
REFERENCE SPECIFICATIONS

MODEL

Product Name: AC servo driver

Part Number : MINAS-A6 series (Multifunction type)

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The maximum value of torque limit setup

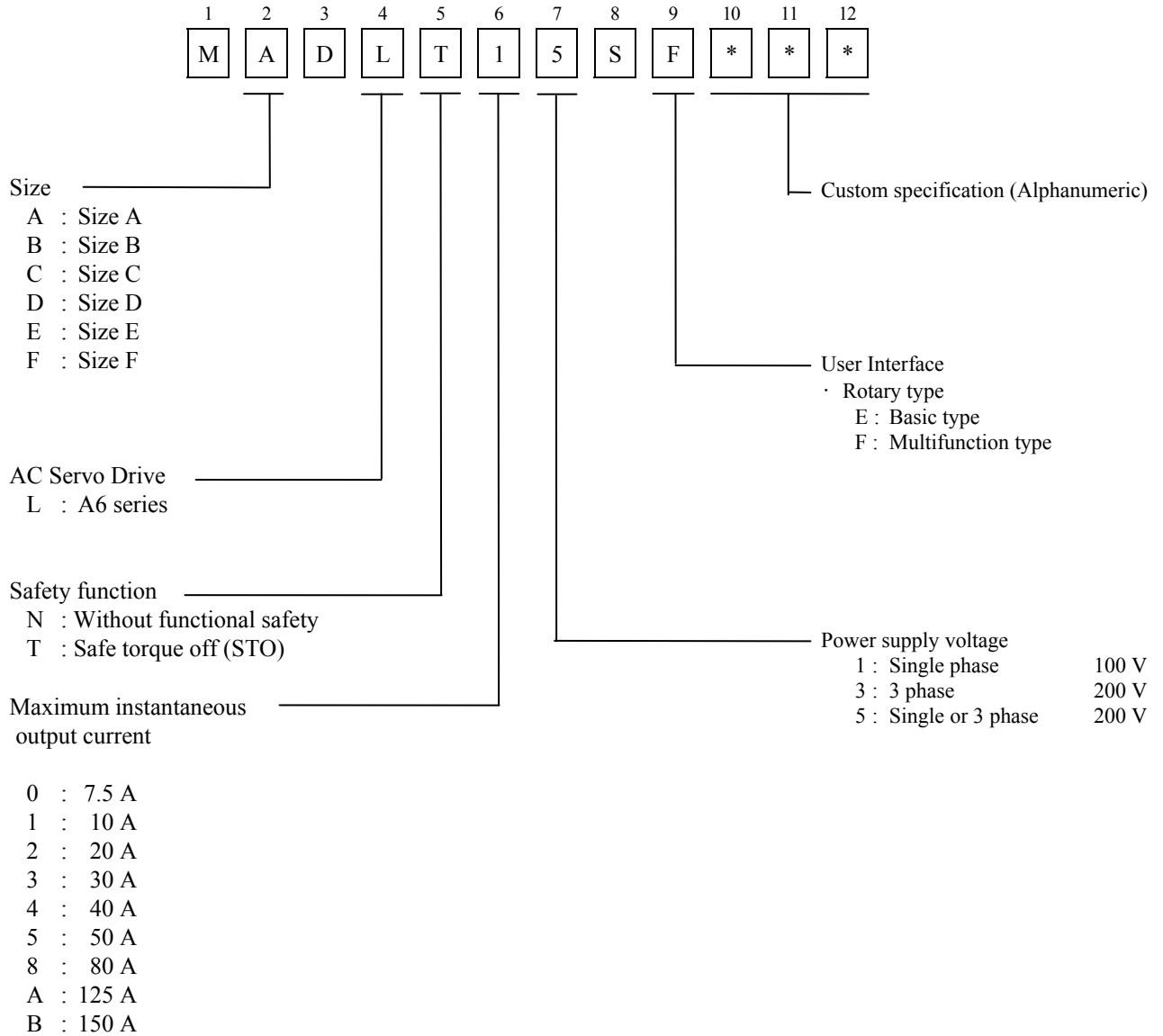
Default value of the parameters

1. Scope

These specifications relate to the servo driver for the AC servo system that is comprised of the AC servo motor manufactured and supplied by Motor Business Unit, Smart Factory Solutions Business Division, Automotive & Industrial amplifier Systems Company, Panasonic Corporation.

2. Model designation code

Notation of the machine designation code is as follows:



3. Product line-up

Servo driver			Motor used				
Model	Size	Power supply input	Model	Voltage specification	Rated output	Rated speed	Encoder specification
MADLT01SF	A	Single 100 V	MSMF5AZL1**	100 V	50 W	3000 r/min	7 cores, 23 bits
			MHMF5AZL1**	100 V	50 W	3000 r/min	7 cores, 23 bits
MADLT11SF	A	Single 100 V	MSMF011L1**	100 V	100 W	3000 r/min	7 cores, 23 bits
			MQMF011L1**	100 V	100 W	3000 r/min	7 cores, 23 bits
			MHMF011L1**	100 V	100 W	3000 r/min	7 cores, 23 bits
MADLT05SF	A	Single / 3 phase 200 V	MSMF5AZL1**	200 V	50 W	3000 r/min	7 cores, 23 bits
			MHMF5AZL1**	200 V	50 W	3000 r/min	7 cores, 23 bits
			MSMF012L1**	200 V	100 W	3000 r/min	7 cores, 23 bits
			MQMF012L1**	200 V	100 W	3000 r/min	7 cores, 23 bits
			MHMF012L1**	200 V	100 W	3000 r/min	7 cores, 23 bits
MADLT15SF	A	Single / 3 phase 200 V	MSMF022L1**	200 V	200 W	3000 r/min	7 cores, 23 bits
			MQMF022L1**	200 V	200 W	3000 r/min	7 cores, 23 bits
			MHMF022L1**	200 V	200 W	3000 r/min	7 cores, 23 bits
MBDLT21SF	B	Single 100 V	MSMF021L1**	100 V	200 W	3000 r/min	7 cores, 23 bits
			MQMF021L1**	100 V	200 W	3000 r/min	7 cores, 23 bits
			MHMF021L1**	100 V	200 W	3000 r/min	7 cores, 23 bits
MBDLT25SF	B	Single / 3 phase 200 V	MSMF042L1**	200 V	400 W	3000 r/min	7 cores, 23 bits
			MQMF042L1**	200 V	400 W	3000 r/min	7 cores, 23 bits
			MHMF042L1**	200 V	400 W	3000 r/min	7 cores, 23 bits
MCDLT31SF	C	Single 100 V	MSMF041L1**	100 V	400 W	3000 r/min	7 cores, 23 bits
			MQMF041L1**	100 V	400 W	3000 r/min	7 cores, 23 bits
			MHMF041L1**	100 V	400 W	3000 r/min	7 cores, 23 bits
MCDLT35SF	C	Single / 3 phase 200 V	MSMF082L1**	200 V	750 W	3000 r/min	7 cores, 23 bits
			MHMF082L1**	200 V	750 W	3000 r/min	7 cores, 23 bits
MDDLTL45SF	D	Single / 3 phase 200 V	MGMF092L1**	200 V	850 W	1500 r/min	7 cores, 23 bits
			MSMF092L1**	200 V	1.0 kW	3000 r/min	7 cores, 23 bits
			MDMF102L1**	200 V	1.0 kW	2000 r/min	7 cores, 23 bits
			MHMF102L1**	200 V	1.0 kW	2000 r/min	7 cores, 23 bits
MDDLTL55SF	D	Single / 3 phase 200 V	MHMF092L1**	200 V	1.0 kW	3000 r/min	7 cores, 23 bits
			MSMF102L1**	200 V	1.0 kW	3000 r/min	7 cores, 23 bits
			MGMF132L1**	200 V	1.3 kW	1500 r/min	7 cores, 23 bits
			MSMF152L1**	200 V	1.5 kW	3000 r/min	7 cores, 23 bits
			MDMF152L1**	200 V	1.5 kW	2000 r/min	7 cores, 23 bits
			MHMF152L1**	200 V	1.5 kW	2000 r/min	7 cores, 23 bits

Servo driver			Motor used				
Model	Size	Power supply input	Model	Voltage specification	Rated output	Rated speed	Encoder specification
MEDLT83SF	E	3 phase 200 V	MGMF182L1**	200 V	1.8 kW	1500 r/min	7 cores, 23 bits
			MSMF202L1**	200 V	2.0 kW	3000 r/min	7 cores, 23 bits
			MDMF202L1**	200 V	2.0 kW	2000 r/min	7 cores, 23 bits
			MHMF202L1**	200 V	2.0 kW	2000 r/min	7 cores, 23 bits
MFDLTA3SF	F	3 phase 200 V	MSMF302L1**	200 V	3.0 kW	3000 r/min	7 cores, 23 bits
			MDMF302L1**	200 V	3.0 kW	2000 r/min	7 cores, 23 bits
			MHMF302L1**	200 V	3.0 kW	2000 r/min	7 cores, 23 bits
MFDLTB3SF	F	3 phase 200 V	MGMF292L1**	200 V	2.9 kW	1500 r/min	7 cores, 23 bits
			MSMF402L1**	200 V	4.0 kW	3000 r/min	7 cores, 23 bits
			MDMF402L1**	200 V	4.0 kW	2000 r/min	7 cores, 23 bits
			MHMF402L1**	200 V	4.0 kW	2000 r/min	7 cores, 23 bits
			MGMF442L1**	200 V	4.4 kW	1500 r/min	7 cores, 23 bits
			MSMF502L1**	200 V	5.0 kW	3000 r/min	7 cores, 23 bits
			MDMF502L1**	200 V	5.0 kW	2000 r/min	7 cores, 23 bits
			MHMF502L1**	200 V	5.0 kW	2000 r/min	7 cores, 23 bits

4. General specifications

4-1 General specification

Basic specifications	Input power supply	100 V	Main circuit power		Single phase 100 - 120 V	+ 10% - 15%	50/60 Hz	
			Control circuit power		Single phase 100 - 120 V	+ 10% - 15%	50/60 Hz	
		200 V	Main circuit power	A - D	Single/3 phase 200 - 240 V	+ 10% - 15%	50/60 Hz	
				E - F	3 phase 200 - 240 V	+ 10% - 15%	50/60 Hz	
			Control circuit power	A - D	Single phase 200 - 240 V	+ 10% - 15%	50/60 Hz	
				E - F	Single phase 200 - 240 V	+ 10% - 15%	50/60 Hz	
	Operation conditions	Temperature		Operation temperature: 0 - 55 degrees C (no freezing) Storage temperature: -20 - 65 degrees C (Max.temperature guarantee : 80 degrees C for 72 hours no condensation*)				
		Humidity		Operation and storage humidity 20 - 85 %RH or less (no condensation*)				
		Height above the sea		Height above the sea level: 1000 meters or less				
		Vibration		5.88 m/s ² or less, 10 - 60 Hz				
Insulation voltage			Resistant to 1500 V AC between primary power supply and ground for a minute (Sensed current: 20 mA)					
Control method			IGBT PWM method, sinusoidal drive					
Encoder feedback			23Bit(resolution:8388608) 7cores-serial absolute encoder					
Control signal	Input		Multi-function input x 10 Function of each multi-function input is assigned by the parameter.					
	Output		Multi-function output x 5 + dedicated output x 1 (alarm output) Function of each multi-function output is assigned by the parameter.					
Analogue signal	Input		3 inputs (16bit A/D x 1, 12bit A/D x 2)					
	Output		2 outputs for analog monitor					
Pulse signal	Input		2 inputs Both open collector and line driver interface can be connected. High speed line driver interface can be connected.					
	Output		4 outputs Line driver output for encoder pulses (A/B/Z signal) or external feedback pulses (EXA/EXB/EXZ signal) open collector output also available for Z or EXZ signal					
Communication	USB		USB interface to connect to computers for parameter setting or status monitoring.					
	RS232		1:1 communication					
	RS485		1: n communication (max 31)					
Safety terminal			A dedicated connector is provided for Functional Safety					
Front panel			5 key switches, 6-digit 7-segment LED					
Regeneration			Size A, B: External regen resistor only Size C - F: Built-in regen resistor (External regen is also available)					
Dynamic brake			Size A - F: Built-in					
Control mode			Selectable from the following 7 modes by parameter: [1]position control [2]velocity control [3]torque control [4]position/velocity control [5]position/torque control [6]velocity/torque control [7]full-closed control					

- Please note that condensation tend to occur when temperature fall.

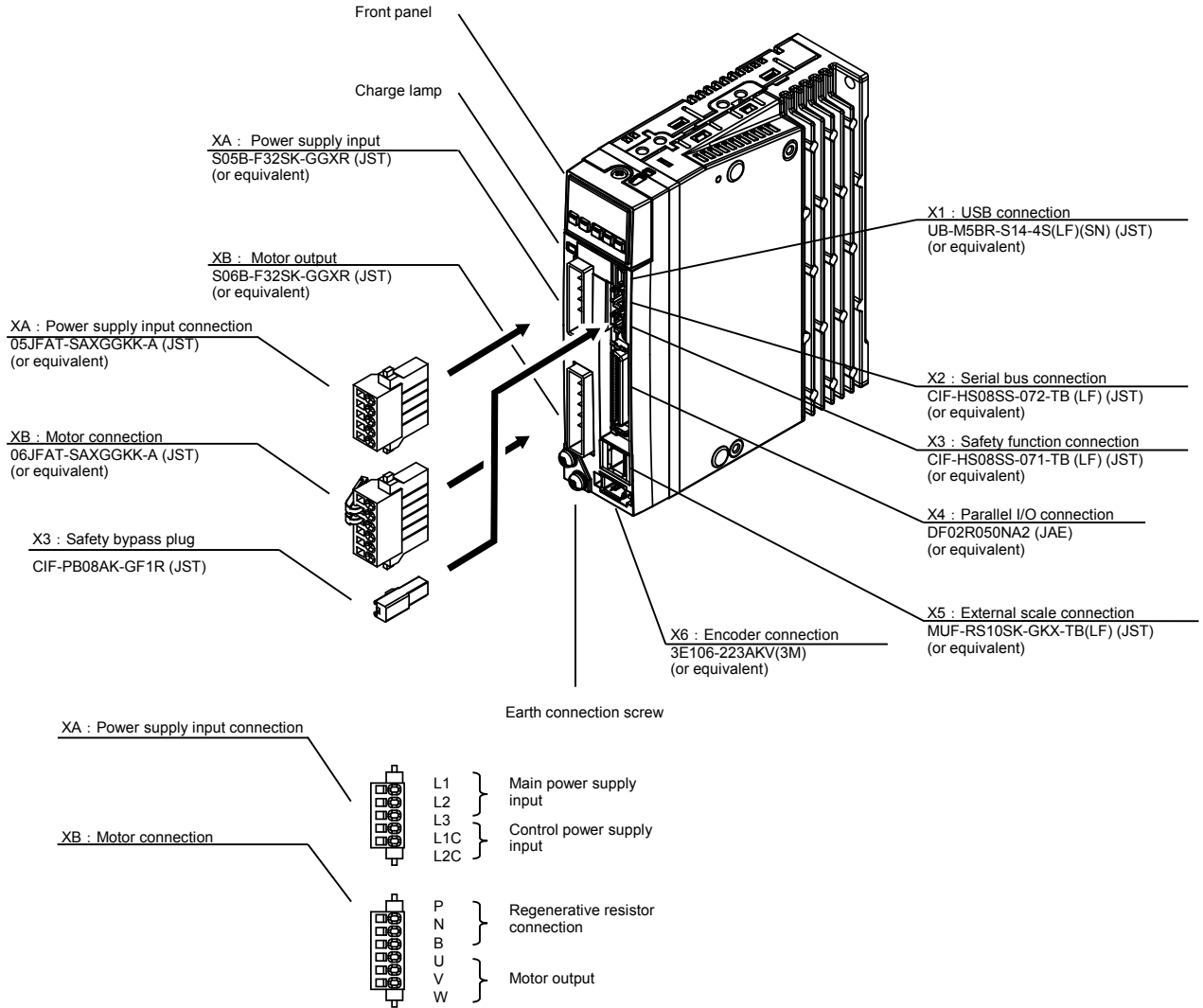
Function	Position control	Digital input		Deviation counter clear, command pulse inhibition, command scaling switch, anti-vibration switch, etc.	
		Digital output		Positioning completion, etc.	
		Pulse input	Max command pulse frequency	500kpps (Optocoupler interface) 8Mpps (Line receiver interface)	
			Command pulse input mode	Differential input. Selectable by parameter. ([1]Positive/Negative pulse [2]A/B quadrature [3]Pulse/Direction)	
			Command pulse scaling (Electronic gear)	Applicable scaling ratio: 1/1000 - 1000 Any value of 1 - 20 ³⁰ can be set for both numerator (which corresponds to encoder resolution) and denominator (which corresponds to command pulse resolution per motor revolution), but the combination has to be within the range shown above.	
			Smoothing Filter	1 st order filter or FIR filter selectable for command input	
		Analog input	Torque limit	Torque can be limited separately in positive/negative direction	
			Torque feed forward	Analog voltage can be used as torque forward input	
		Instantaneous speed observer		Available	
		Anti-vibration control		Available	
	Two-degree-of-freedom control		Available		
	Velocity control	Digital input		Internal command speed selections 1-3, speed-zero clamp, etc.	
		Digital output		At speed, etc.	
		Analog input	Speed command	Speed command can be given by analog voltage. The scale and the polarity can be set by parameters.	
			Torque limit	Torque can be limited separately in positive/negative direction	
			Torque feed forward	Analog voltage can be used as torque forward input.	
		Preset velocity control		Preset velocity is selectable from 8 steps by digital inputs.	
		Soft start/slowdown function		0 - 10s / 1000 r/min Acceleration and deceleration can be set separately. S-curve acceleration/deceleration is also available.	
		Speed zero clamp		Preset velocity command can be clamped to zero by the speed zero clamp input.	
		Instantaneous speed observer		Available	
		Speed command filter		Available	
	Two-degree-of-freedom control		Available		
	Torque Control	Digital input		Speed-zero clamp, torque command, etc.	
		Digital output		At speed, etc.	
		Analog input	Torque command	Torque command can be given by analog voltage. The scale and the polarity can be set by parameters.	
		Speed limit		Speed limit can be set by parameter	
		Two-degree-of-freedom control		Not Available	
Full-closed Control	Digital input		Deviation counter clear, command pulse inhibition, command scaling switch, anti-vibration switch, etc.		
	Digital output		Positioning completion, etc.		
	Pulse input	Max. command pulse frequency	500kpps (Optocoupler interface) 4Mpps (Line receiver interface)		
		Command pulse input mode	Differential input. Selectable by parameter. ([1]Positive/Negative pulse [2]A/B quadrature [3]Pulse/Direction)		
		Command pulse scaling (Electronic gear)	Applicable scaling ratio: 1/1000 - 1000 Any value of 1 - 2030 can be set for both numerator (which corresponds to encoder resolution) and denominator (which corresponds to command pulse resolution per motor revolution), but the combination has to be within the range shown above.		
		Smoothing Filter	1st order filter or FIR filter selectable for command input		
	Analog input	Torque limit	Torque can be limited separately in positive/negative direction		
		Torque feed forward	Analog voltage can be used as torque forward input.		
	External scale scaling		Applicable scaling ratio: 1/40 - 160 Any value of 1 - 2020 can be set for both numerator (which corresponds to encoder resolution) and denominator (which corresponds to external scale resolution), but the combination has to be within the range shown above.		
	Anti-vibration Control		Available		
Two-degree-of-freedom control		Not Available			
Common	Auto-tuning		Identifies the load inertia in real-time and automatically, sets up the gain that meets the stiffness setting when the motor is operating according to the command given by the controlling device and set up support software "PANATERM".		
	Scaling of feedback pulse		Any number of pulses can be set up. (maximum setting number is encoder resolution)		
	Protective function	Hardware error	Overvoltage, undervoltage, over speed, overload, overheat, over current, encoder error, etc.		
		Software error	Following error fault, command pulse scaling error, EEPROM error, etc.		
Alarm data trace back		Tracing back of alarm data is available			

4-2 Specifications by model

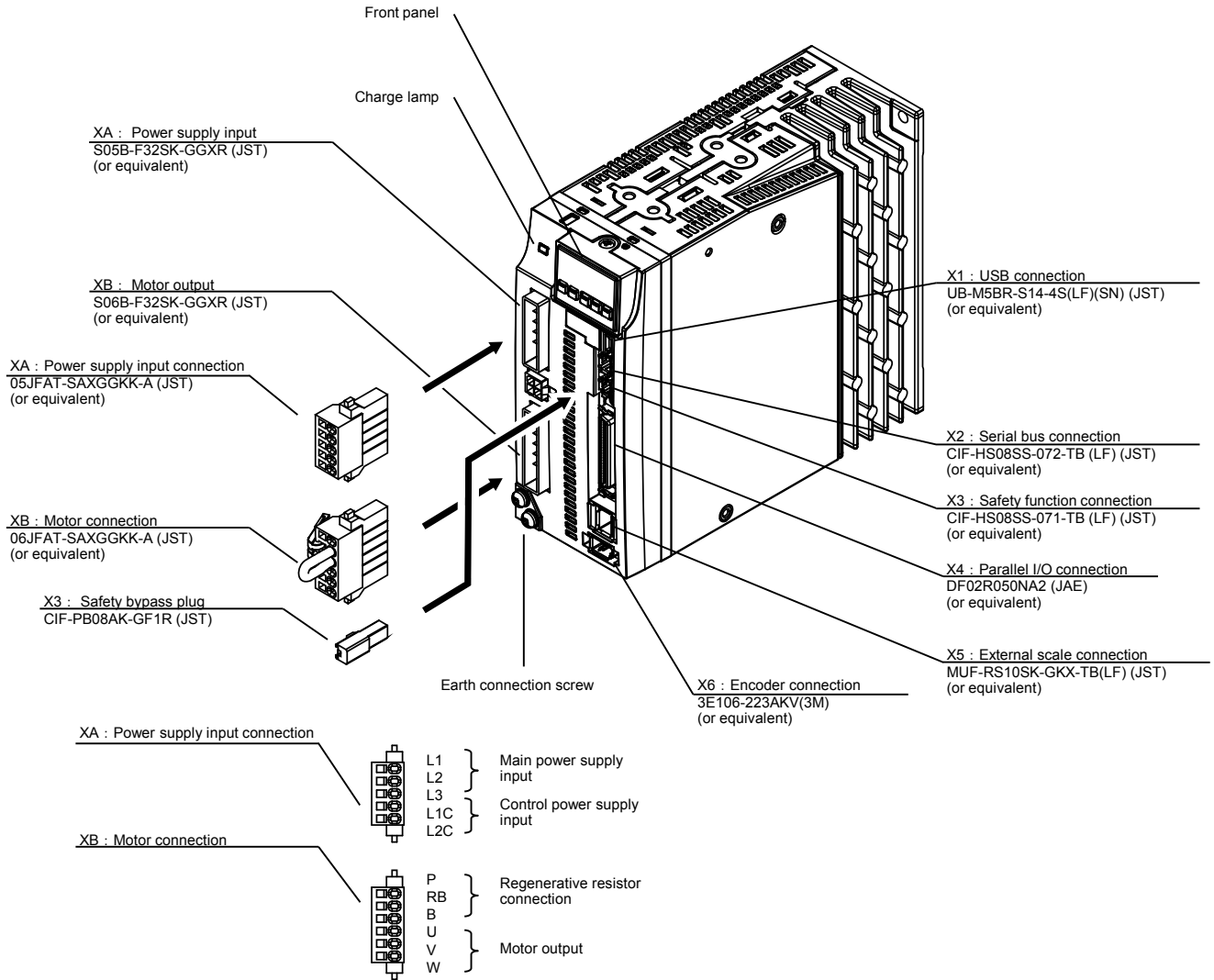
Refer to specification for each model.

5. Appearance and part names

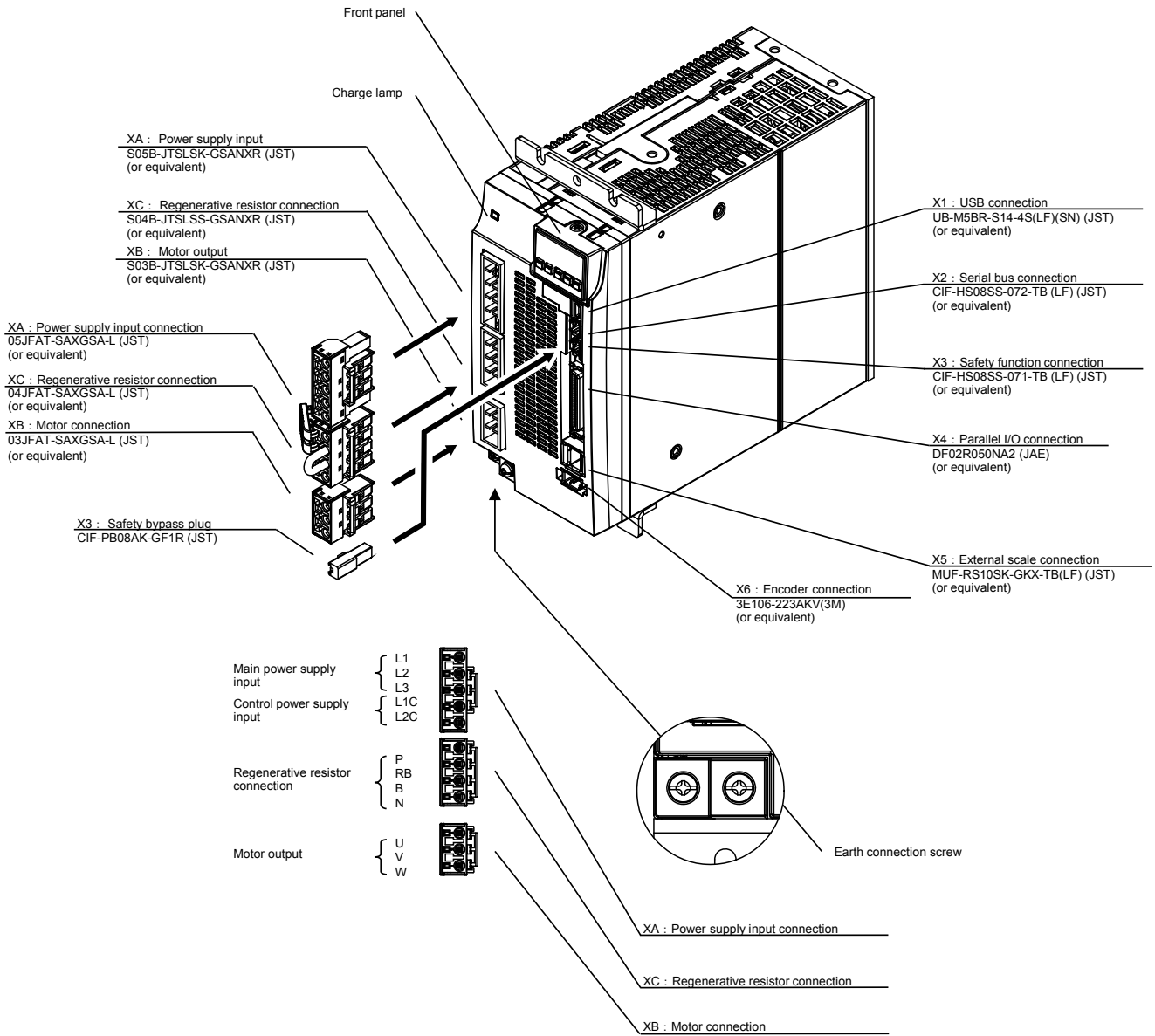
100 V, 200 V size A, B



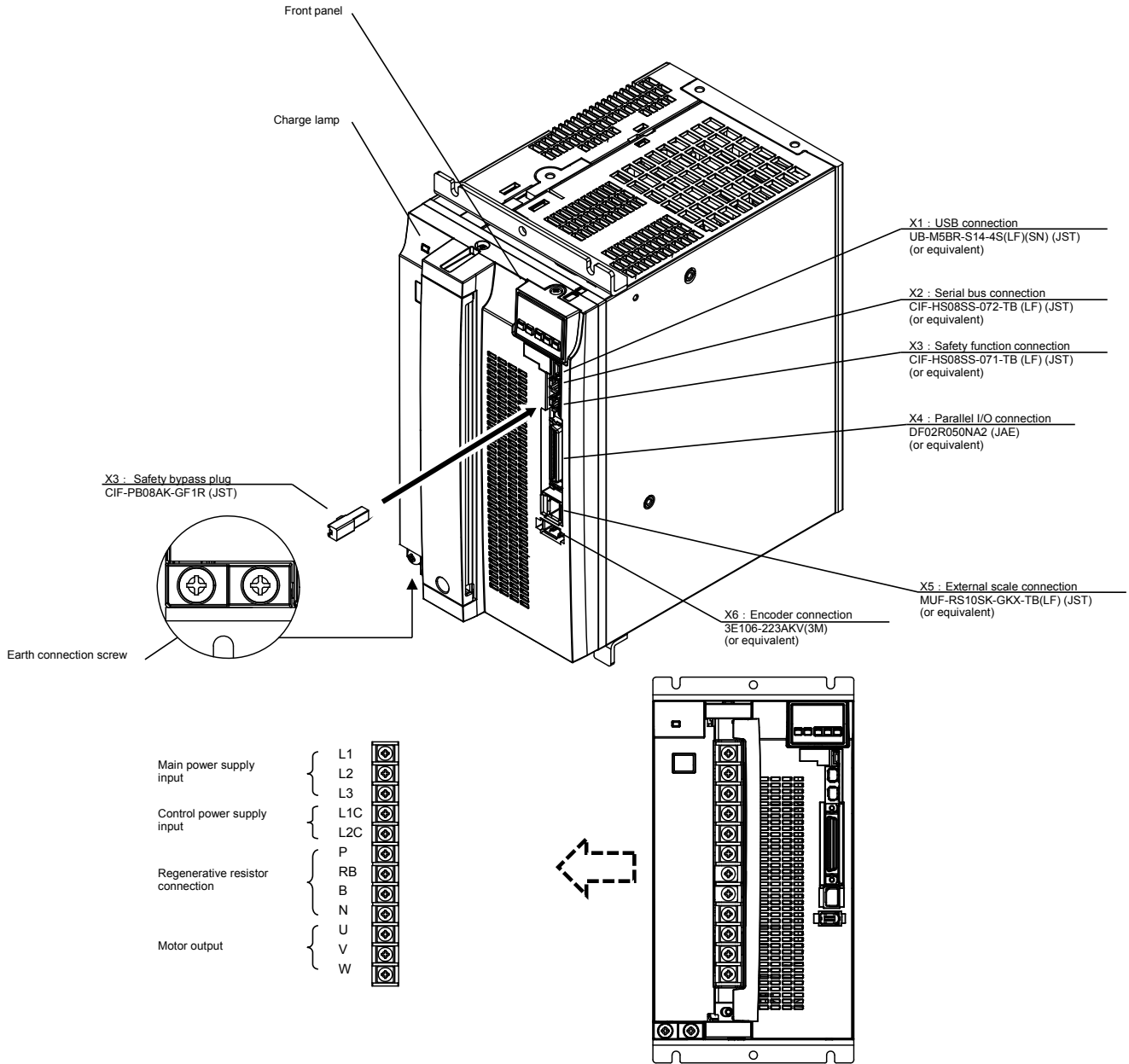
100 V, 200 V size C, D



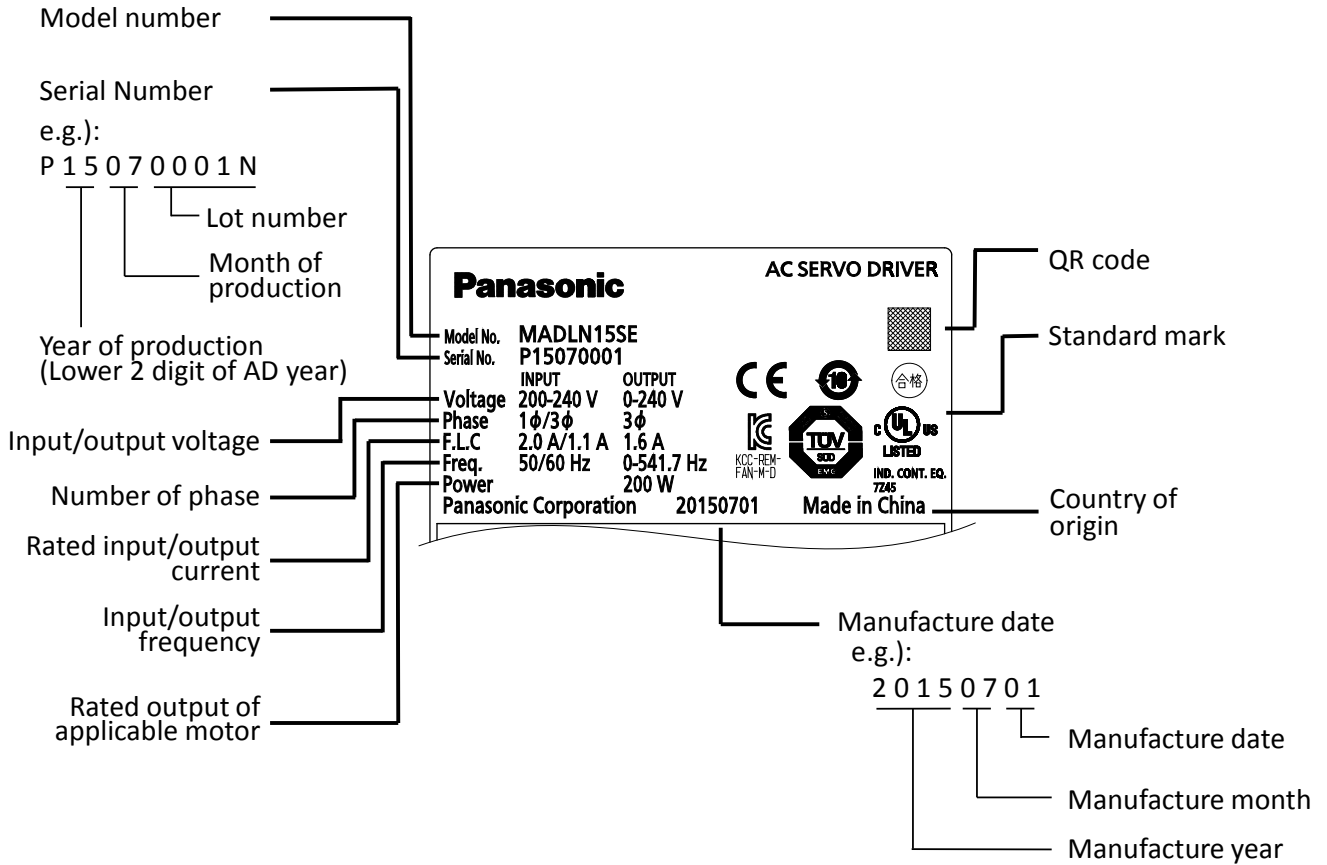
200 V size E



200 V size F





Name plate



6. Configuration of connectors and terminal blocks



6-1 Power connector **XA**, **XB**, **XC**, **XD** and terminal block

[1] Size A, B of 100 V and 200 V system

	Connector pin No.	Terminal symbol	Name	Description	
XA	5	L1	Main power supply input	100 V	Single phase 100-120 V + 10 % - 15 % 50/60 Hz input Use L1 and L3 terminal for single phase input
	4	L2		200 V	Single or 3 phase 200-240 V + 10 % - 15 % 50/60 Hz input
	3	L3			Use L1 and L3 terminal for single phase input
	2	L1C	Control power supply input	100 V	Single phase 100-120 V + 10 % - 15 % 50/60 Hz input
	1	L2C		200 V	Single phase 200-240 V + 10 % - 15 % 50/60 Hz input
XB	6	P	Regen resistor connection	<ul style="list-style-type: none"> When a trip happens due to a regenerative load protection error, connect an external regenerative resistor (prepared by customer) between P and B. Then, specify the external regenerative resistor for the parameter Pr0.16. Do not connect N terminal. 	
	5	N			
	4	B			
	3	U	Motor connection	Connect each phase of the motor winding. U: U phase V: V phase W: W phase	
	2	V			
	1	W			
			Earth	Earth terminal for grounding	



* Tighten the earth screws M4 with the 0.7-0.8 Nm torque respectively.

[2] Size C, D of 100 V and 200 V system

	Connector pin No.	Terminal symbol	Name	Description	
XA	5	L1	Main power supply input	100 V	Single phase 100-120 V + 10 % - 15 % 50/60 Hz input Use L1 and L3 terminal for single phase input
	4	L2		200 V	Single or 3 phase 200 – 240 V + 10 % - 15 % 50/60 Hz input
	3	L3			Use L1 and L3 terminal for single phase input
	2	L1C	Control power supply input	100 V	Single phase 100-120 V + 10 % - 15 % 50/60 Hz input
	1	L2C		200 V	Single phase 200 – 240 V + 10 % - 15 % 50/60 Hz input
XC	4	N	-	• Do not connect.	
	3				
	2	P			
	1				
XB	6	P	Regen resistor connection	<ul style="list-style-type: none"> Normally, short out the circuit between B and RB. (Sizes C, D) When a trip happens due to a regenerative load protection error, open the circuit between B and RB and connect an external regenerative resistor (prepared by customer) between P and B. Then, specify the external regenerative resistor for the parameter Pr0. 16. 	
	5	RB			
	4	B			
	3	U	Motor connection	Connect each phase of the motor winding. U: U phase V: V phase W: W phase	
	2	V			
	1	W			
			Earth	Earth terminal for grounding	

* Tighten the earth screws M4 with the 0.7-0.8 Nm torque respectively.



[3] Size E of 200 V system

	Connector pin No.	Terminal symbol	Name	Description		
XA	5	L1	Main power supply input	200 V	3 phase 200 - 240 V	+ 10 % - 15 % 50/60 Hz input
	4	L2				
	3	L3				
	2	L1C	Control power supply input	200 V	Single phase 200 - 240 V	+ 10 % - 15 % 50/60 Hz input
	1	L2C				
XC	4	P	Regen resistor connection		<ul style="list-style-type: none"> • Normally, short out the circuit between RB and B. • When a trip happens due to a regenerative load protection error, open the circuit between RB and B and connect an external regenerative resistor (prepared by customer) between P and B. Then, specify the external regenerative resistor for parameter Pr0. 16. • Do not connect N terminal. 	
	3	RB				
	2	B				
	1	N				
XB	3	U	Motor connection		Connect each phase of the motor winding. U: U phase V: V phase W: W phase	
	2	V				
	1	W				
			Earth		Earth terminal for grounding	

* Tighten the earth screws M4 with the 0.7-0.8 Nm torque respectively.

[4] Size F of 200V system

Terminal block is used instead of connector.

Terminal No. (Upper to bottom)	Terminal symbol	Name	Description
1	L1	Main power supply input	3 phase 200 - 240 V + 10 % - 15 % 50/60 Hz input
2	L2		
3	L3		
4	L1C	Control power supply input	Single phase 200 - 240 V + 10 % - 15 % 50/60 Hz input
5	L2C		
6	P	Regen resistor connection	<ul style="list-style-type: none"> • Normally, short out the circuit between RB and B. • When a trip happens due to a regenerative load protection error, open the circuit between RB and B and connect an external regenerative resistor (prepared by customer) between P and B. Then, specify the external regenerative resistor for parameter Pr0. 16. • Do not connect N terminal.
7	RB		
8	B		
9	N		
10	U	Motor connection	Connect each phase of the motor winding. U: U phase V: V phase W: W phase
11	V		
12	W		
		Earth	Earth terminal for grounding

* Tighten the earth screws M5 with the 1.4 -1.6 Nm torques respectively.

* Tighten the terminal block screws M5 with the 1.0-1.7 Nm torques respectively.

* Tighten the fixing screw M3 for the terminal block cover with the 0.2 Nm torque.

* If the maximum value of tightening torque is exceeded, the terminal block could be damaged.

6-2 USB connector X1

By connecting to a computer or a controller via USB interface, the following operations are available
parameter reference / change parameter save / load monitoring of status checking alarm status or alarm history

Name	Symbol	Connector pin No	Description
USB signal	VBUS	1	• Communicate with a computer or a controller
	D-	2	
	D+	3	
For manufacturer use	-	4	• Do not connect
Signal ground	GND	5	• Signal ground

6-3 Serial bus connector X2

Name	Symbol	Connector pin No	Description
Signal ground	GND	1	• Signal ground (*Note 1)
NC	-	2	• Do not connect
RS232 signal	TXD	3	• Serial bus transmission and reception data (RS232)
	RXD	4	
RS485 signal	485 -	5	• Serial bus transmission and reception data (RS485)
		6	
	485+	7	
		8	
Frame ground	FG	shell	• Frame ground

Note 1) The signal ground GND is connected with the control circuit ground connected with the connector X4.

6-4 Safety function connector X3

This connection is for functional safety.

Name	Symbol	Connector pin No	Description	Circuit
Reserved	-	1	• Do not connect	-
	-	2		-
Safety input 1	SF1-	3	2 channel inputs with independent circuit to cut off the drive signal to the power module in the servo driver.	i-1
	SF1+	4		
Safety input 2	SF2-	5		
	SF2+	6		
EDM output	EDM-	7	External Device Monitoring (EDM) output to diagnose the functional safety function in the servo driver.	o-1
	EDM+	8		
Frame ground	FG	shell	• Internally connected to the earth terminal.	-

Note 1) The signal ground GND is connected with the control circuit ground connected with the connector X3.

6-5 Parallel I/O connector, **X4****Common digital inputs**

Name	Symbol	Con- nector pin No.	Description	Circuit
Power supply input	COM+	7	<ul style="list-style-type: none"> Connect to the + terminal of an external DC power supply (12 to 24 V) Use a 12 V ($\pm 5\%$) to 24 V ($\pm 5\%$) power supply Insulation is needed against the primary side power supply. Please do not connect them with the same power supply. 	—
Multi-function input 1	SI1	8	<ul style="list-style-type: none"> The function changes according to the parameter settings. See below. 	i-1
Multi-function input 2	SI2	9		
Multi-function input 3	SI3	26		
Multi-function input 4	SI4	27		
Multi-function input 5	SI5	28		
Multi-function input 6	SI6	29		
Multi-function input 7	SI7	30		
Multi-function input 8	SI8	31		
Multi-function input 9	SI9	32		
Multi-function input 10	SI10	33		

Functions allocatable to multi-function inputs

Name	Symbol	Description
Servo ON	SRV-ON	<ul style="list-style-type: none"> When turned ON, the servo is turned on (power is supplied to the motor). When turned OFF, the servo is turned off and the motor power is turned off.
Control mode switch	C-MODE	<ul style="list-style-type: none"> Switches the control modes.
Positive overtravel limit	POT	<ul style="list-style-type: none"> Positive overtravel limit. Make sure to connect this so that the contact point will be opened when the movable module positively exceeded the movable range. When this input is OFF, a positive torque does not occur.
Negative overtravel limit	NOT	<ul style="list-style-type: none"> Negative overtravel limit. Make sure to wire this input to be activated as the work over travels the limit in the negative direction. When this input is OFF, a negative torque does not occur.
Deviation counter clear	CL	<ul style="list-style-type: none"> Clears the position deviation counter.
Command pulse inhibition	INH	<ul style="list-style-type: none"> Ignores the position command pulse.
Preset velocity 1	INTSPD1	<ul style="list-style-type: none"> Preset speed. Allows you to set up to 8 internal velocities by combining INTSPDs 1 - 3.
Preset velocity 2	INTSPD2	
Preset velocity 3	INTSPD3	
Speed zero clamp	ZEROSPD	<ul style="list-style-type: none"> Sets the speed command to zero.
Anti-vibration switch 1	VS-SEL1	<ul style="list-style-type: none"> Switches the applied frequencies for anti-vibration control.
Anti-vibration switch 2	VS-SEL2	
Gain switch	GAIN	<ul style="list-style-type: none"> Input to switch the gains.
Torque limit switch	TL-SEL	<ul style="list-style-type: none"> Switches the torque limits.
Alarm clear	A-CLR	<ul style="list-style-type: none"> Digital input to clear the alarm.
Command scaling switch	VC-SIGN	<ul style="list-style-type: none"> Specifies the sign of the speed command during the speed control.
Torque command sign	TC-SIGN	<ul style="list-style-type: none"> Specifies the sign of the torque command during the torque control.
Command scaling switch 1	DIV1	<ul style="list-style-type: none"> Switches the scaling numerators of the command pulse. Allows you to switch up to 4 numerators by combining DIVs 1, 2.
Command scaling switch 2	DIV2	
Forced alarm input	E-STOP	<ul style="list-style-type: none"> Generates Err87. 0 "Abnormal forced alarm input."
Inertia ratio switch	J-SEL	<ul style="list-style-type: none"> Switches the inertia ratios.

Input signals (command pulse train) and their functions

A suitable interface can be chosen from two kind of interface based on the specification of command pulses.

A. Pulse train interface with line driver

Name	Symbol	Con-necter pin No.	Description	Circuit
Command pulse input 1	PULSH1	44	<ul style="list-style-type: none"> • Input terminal for the position command pulse. It can be selected by setting corresponding parameters. • Disabled in such control modes as the speed control or the torque control, which does not require position commands. • The maximum allowable input frequency is 8 Mpps. 	Di-2
	PULSH2	45		
Command direction input 1	SIGNH1	46		
	SIGNH2	47		

B. Pulse train interface with optocoupler

Name	Symbol	Con-necter pin No.	Description	Circuit
Command pulse input 2	OPC1	1	<ul style="list-style-type: none"> • Input terminal for the position command pulse. It can be selected by setting corresponding parameters. • Disabled in such control modes as the speed control or the torque control, which does not require position commands. • The maximum allowable input frequency is 500 kpps for line driver input, and 200 kpps for open collector input. 	Di-1
	PULS1	3		
	PULS2	4		
Command direction input 2	OPC2	2		
	SIGN1	5		
	SIGN2	6		

Input signals (analog command) and their functions

Name	Symbol	Con- nector pin No.	Description	Circuit
Analog input 1	AI1	14	<ul style="list-style-type: none"> • Analog input with 16 bit resolution. • The function changes according to the control mode. 	Ai-1
Analog input 2	AI2	16	<ul style="list-style-type: none"> • Analog input with 12 bit resolution. • The function changes according to the control mode. 	Ai-2
Analog input 3	AI3	18	<ul style="list-style-type: none"> • Analog input with 12 bit resolution. 	

Functions allocatable to analog inputs

Analog input	Name	Symbol	Description
AI1	Speed command	SPR	• Speed command input in speed control mode.
	Torque command	TRQC	• Torque command input in torque control mode. (without control mode AI1 switch)
	Speed limit	SPL	• Speed limit input in torque control mode.
AI2	Positive torque limit	P-ATL	• Torque limit input in positive direction.
	Torque command	TRQR	• Torque command input in torque control in the speed/torque control mode switch.
AI3	Negative torque limit	N-ATL	• Torque limit input in negative direction.

Output signals (common) and their functions

Name	Symbol	Con- nector pin No.	Description	Circuit
Multi-function output 1	SO1- SO1+	10 11	• The function changes according to the parameter settings. See below.	o-1
Multi-function output 2	SO2- SO2+	34 35		
Multi-function output 4	SO4- SO4+	38 39		
Servo alarm	ALM- ALM+	36 37	• Digital output to indicate alarm status.	
Multi-function output 5	SO5	12	• The function changes according to the parameter settings. See below.	o-3
Multi-function output 6	SO6	40		
Power supply input	COM-	41	<ul style="list-style-type: none"> • Connect to the - terminal of an external DC power supply (12 to 24 V) • The power capacity varies depending on a composition of I/O circuit.0.5A or more is recommended. • Insulation is needed against the primary side power supply Please do not connect them with the same power supply.	—

Functions allocatable to multi-function outputs

Name	Symbol	Description
Servo Alarm	ALM	• Digital output to indicate the driver is in alarm status..
Servo ready	S-RDY	• Digital output to indicate the driver is ready to be enabled.
Motor holding break release	BRK-OFF	• Digital output to provide the timing signal to control the motor holding brake.
Zero speed	ZSP	• Outputs the zero speed detection signals.
Torque limited	TLC	• Outputs the torque limit signal.
In-position	INP	• Outputs the positioning completion signal.
Positioning completion 2	INP2	• Outputs the positioning completion signal 2.
At speed	AT-SPD	• Outputs the at-speed signal.
V-COIN	V-COIN	• Outputs the speed coincidence signal.
Warning output 1	WARN1	• Outputs the warning output signal configured in Pr4. 40 "Warning output selection 1".
Warning output 2	WARN2	• Outputs the warning output signal configured in Pr4. 41 "Warning output selection 2".
Position command ON/OFF	P-CMD	• Outputs meaning positional command applied.
Speed in –limit output	V-LIMIT	• Outputs meaning the speed is limited at torque control mode.
Alarm attribute output	ALM-ATB	• Outputs meaning occur an alarm that can be cleared.
Speed command ON/OFF	V-CMD	• Turns on output transistor when the speed command is applied while the speed is controlled.
Servo on status output	SRV-ST	• Turn on output transistor when servo is on.

Output signals (pulse output) and its function

Name	Symbol	Connector pin No.	Description	Circuit
A phase output	OA+	21	<ul style="list-style-type: none"> • Scaling processed encoder signal or external scale signal (A/B/Z-phase) is output in differential mode. (RS422 equivalent) • Scaling ratio can be set by parameters. • The ground pin of the line driver on the output circuit is not insulated and is connected to signal ground (GND). • The maximum output frequency is 8 Mpps (after quadrature). 	Do-1
	OA-	22		
B phase output	OB+	48		
	OB-	49		
Z phase output	OZ+	23		
	OZ-	24		
Z phase output	CZ	19	<ul style="list-style-type: none"> • Open collector output of Z-phase signal. • Ground of line driver of the output circuit is connected to signal ground (GND); not insulated. 	Do-2

Analog monitor signals and their functions

Name	Symbol	Connector pin No.	Description	Circuit
Analog monitor output	IM	42	<ul style="list-style-type: none"> • Analog signal output for monitoring • Monitoring object changes according to the parameter setting. 	Ao-1
	SP	43		

Others

Name	Symbol	Connector pin No.	Description	Circuit
Frame ground	FG	50, shell	<ul style="list-style-type: none"> • Internally connected to the earth terminal. 	—
Signal ground	GND	13,15, 17,25	<ul style="list-style-type: none"> • Signal ground • Internally insulated from the control signal power supply (COM-). 	—
—	—	20	<ul style="list-style-type: none"> • Do not connect 	—

6-6 External feedback device connector **X5**

Name	Connector pin No	Description
Power supply output for external scale	1	EX5V (*Note 2) (*Note 3)
	2	EX0V (*Note 1)
External scale signal input / output (serial signal)	3	EXPS
	4	/EXPS
External scale signal input (A / B / Z phase signal)	5	EXA
	6	/EXA
	7	EXB
	8	/EXB
	9	EXZ
	10	/EXZ
Frame ground	shell	FG

Note 1) The E0V of the external scale power output is connected with the control circuit ground linked to the connector **X4**.

Note 2) EX5V power supply output for external scale is rated at $5.2\text{ V} \pm 5\%$ and 250 mA at maximum. To use an external scale with a current consumption higher than that, a preparation of an external power supply is required. Some external scales may take longer time in initialization after turning on the power.

Note 3) In case an external power supply is used for the external scale, make sure that the EX5V pin is open and no external power is supplied to the EX5V pin.

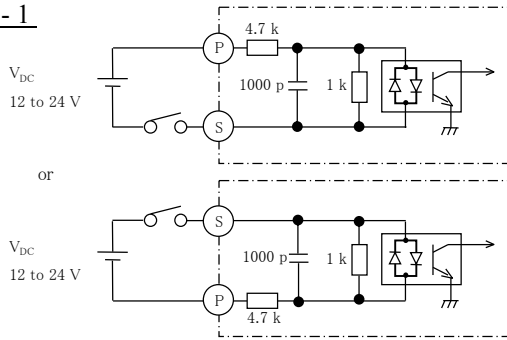
6-7 Encoder connector X6

Name	Connector pin No.	Description
Encoder power supply output	1	E5V
	2	E0V (*Note 1)
—	3	Do not connect.
	4	Do not connect.
Encoder signal I/O (serial signal)	5	PS
	6	/PS
Frame ground	shell	FG

*Note 1) The E0V of the encoder power supply output is connected with the control circuit ground of the connector X4.

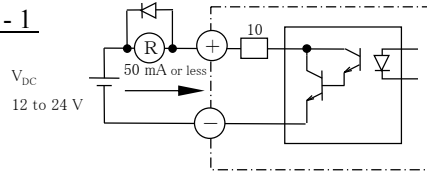
Input and output interface

i - 1



Pins;
 S : (X3) 3, 5
 (X4) 8, 9, 26, 27, 28, 29, 30, 31, 32, 33
 P : (X3) 4, 6
 (X4) 7

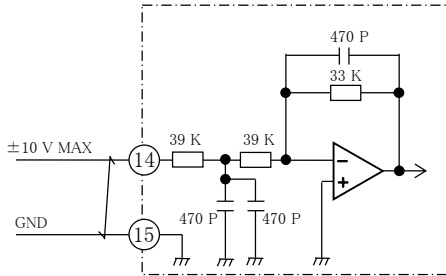
o - 1



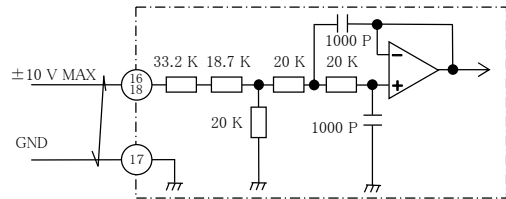
Pins;
 + : (X3) 8
 (X4) 11, 35, 37, 39
 - : (X3) 7
 (X4) 10, 34, 36, 38

Note) To directly run the relay, attach a diode in Parallel with the relay and in the direction shown in the figure above.
 VCE sat = 1.2 V

Ai - 1

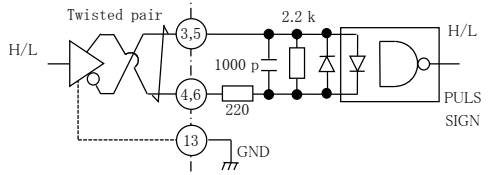


Ai - 2



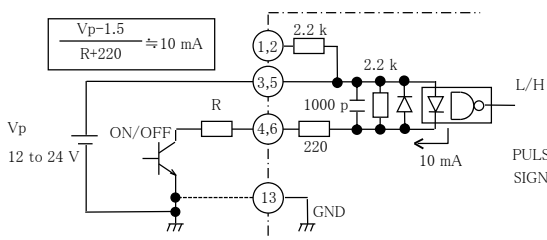
Di - 1

< Line Driver >

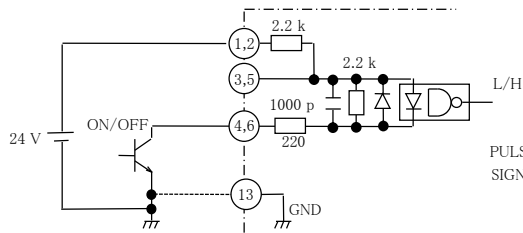


< Open Collector >

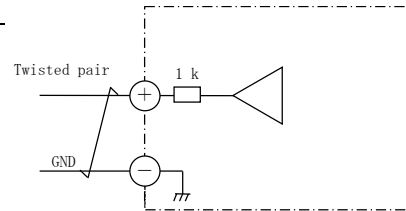
① 12-24 V Powersupply with external resistor



② 24 V Power supply without external resistor

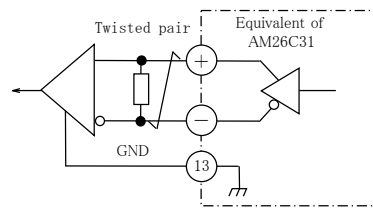


Ao - 1



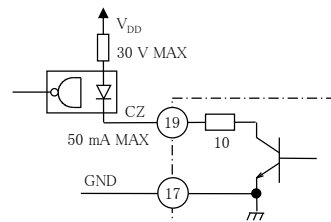
Pins;
 + : (X4) 42, 43
 - : (X4) 13, 17, 25
 Note) Outputting signal amplitude is ±10 V

Do - 1

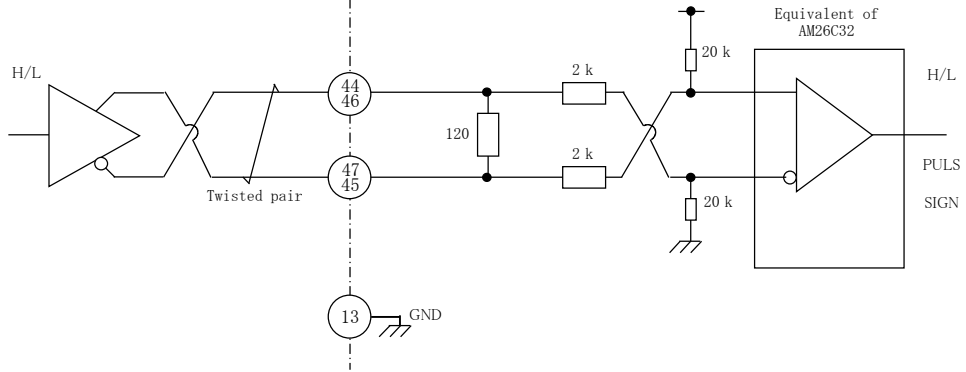


Pins;
 + : 21, 23, 48
 - : 22, 24, 49

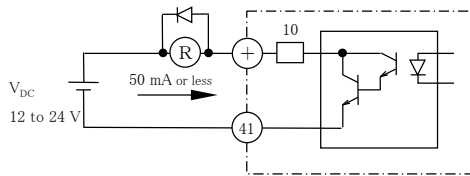
Do - 2



Di - 2



o - 2



Pins:

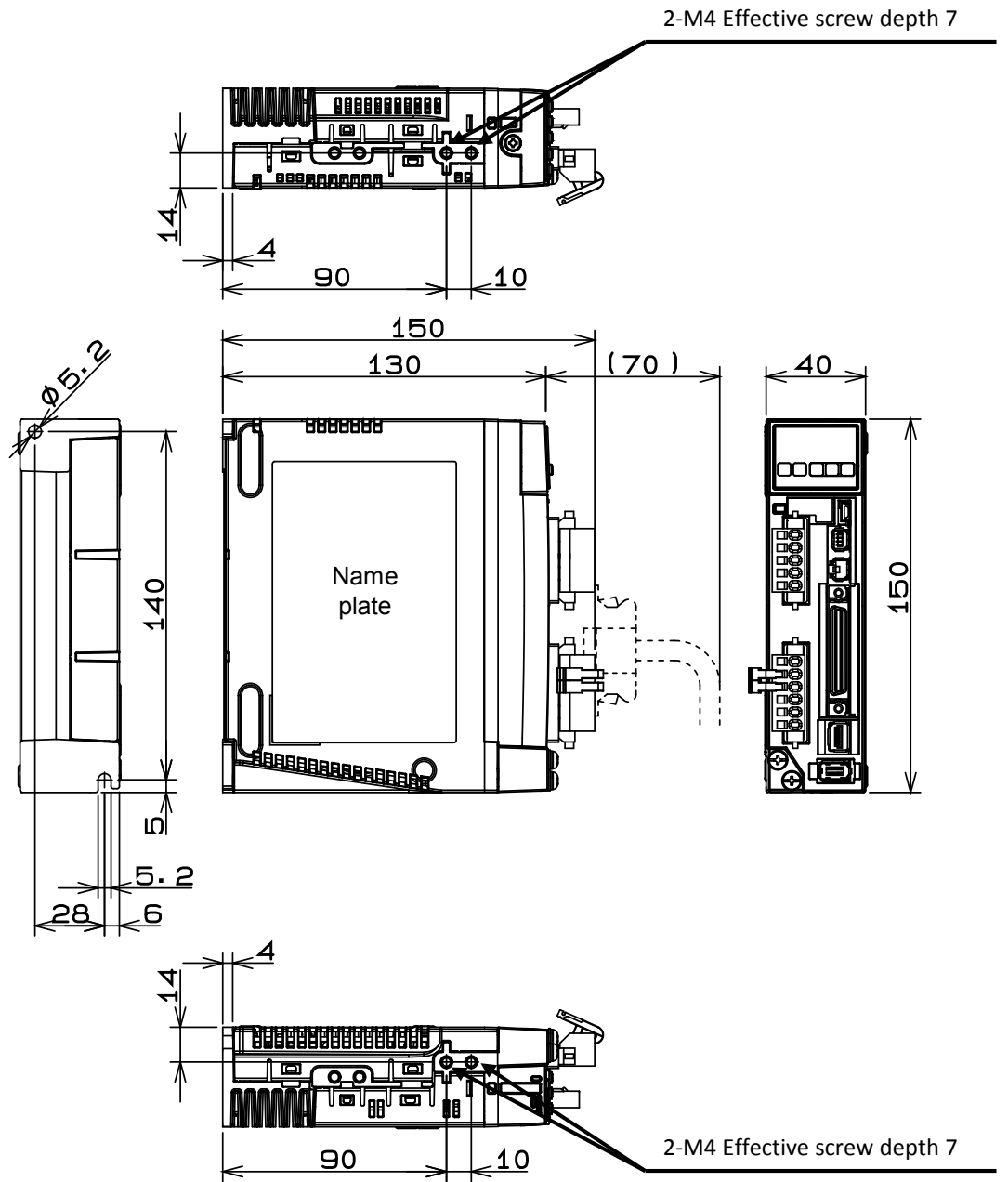
+ : 40, 12

Note) To directly run the relay, attach a diode in Parallel with the relay and in the direction shown in the figure above.

7. Dimensions

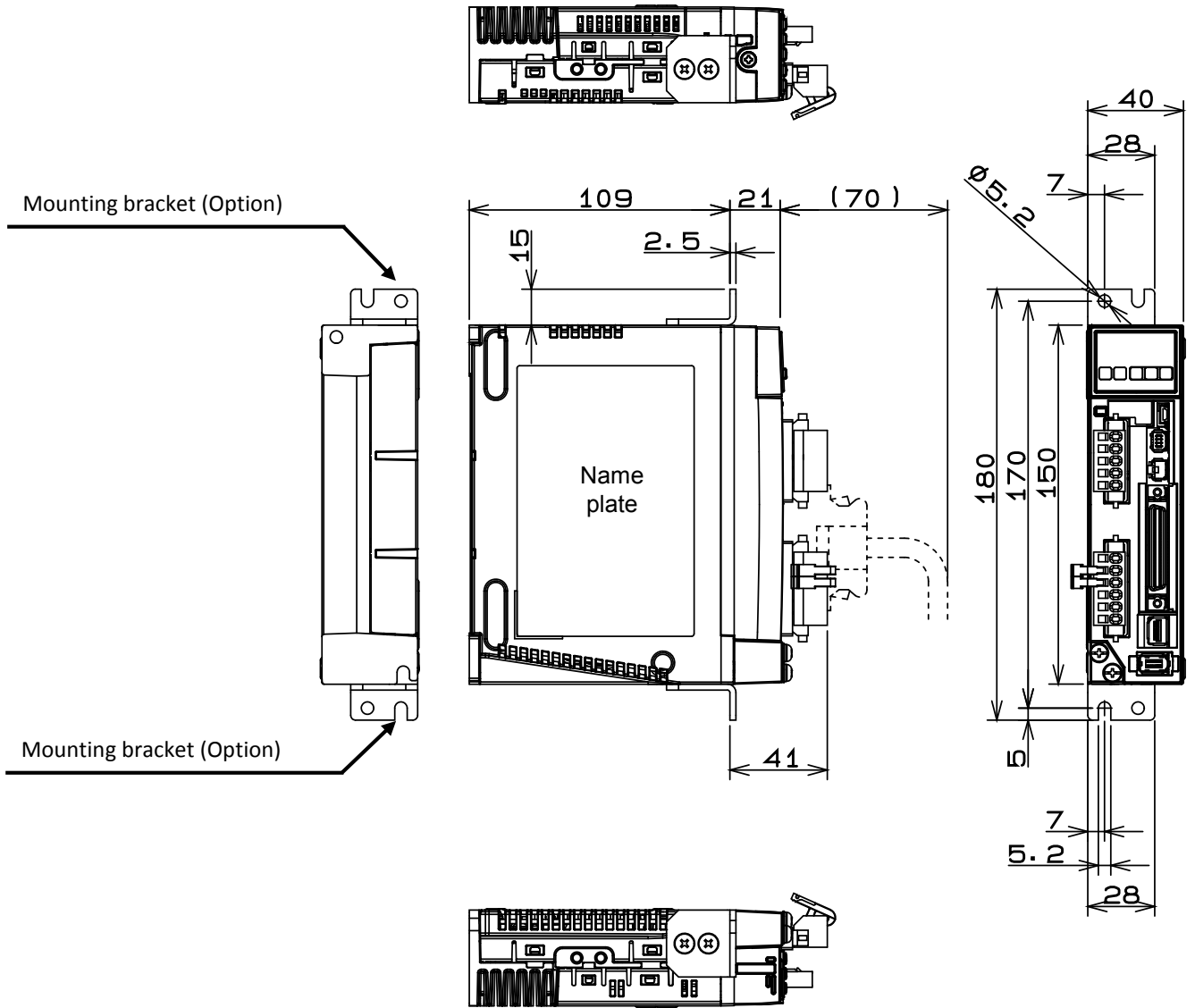
External dimension size A

[Base-mounting TYPE (Standard: Mounting on the back)]



*Please do not use the screw holes of no description of the size value.

[Rack-mounting TYPE (Option: Mounted on the front)]

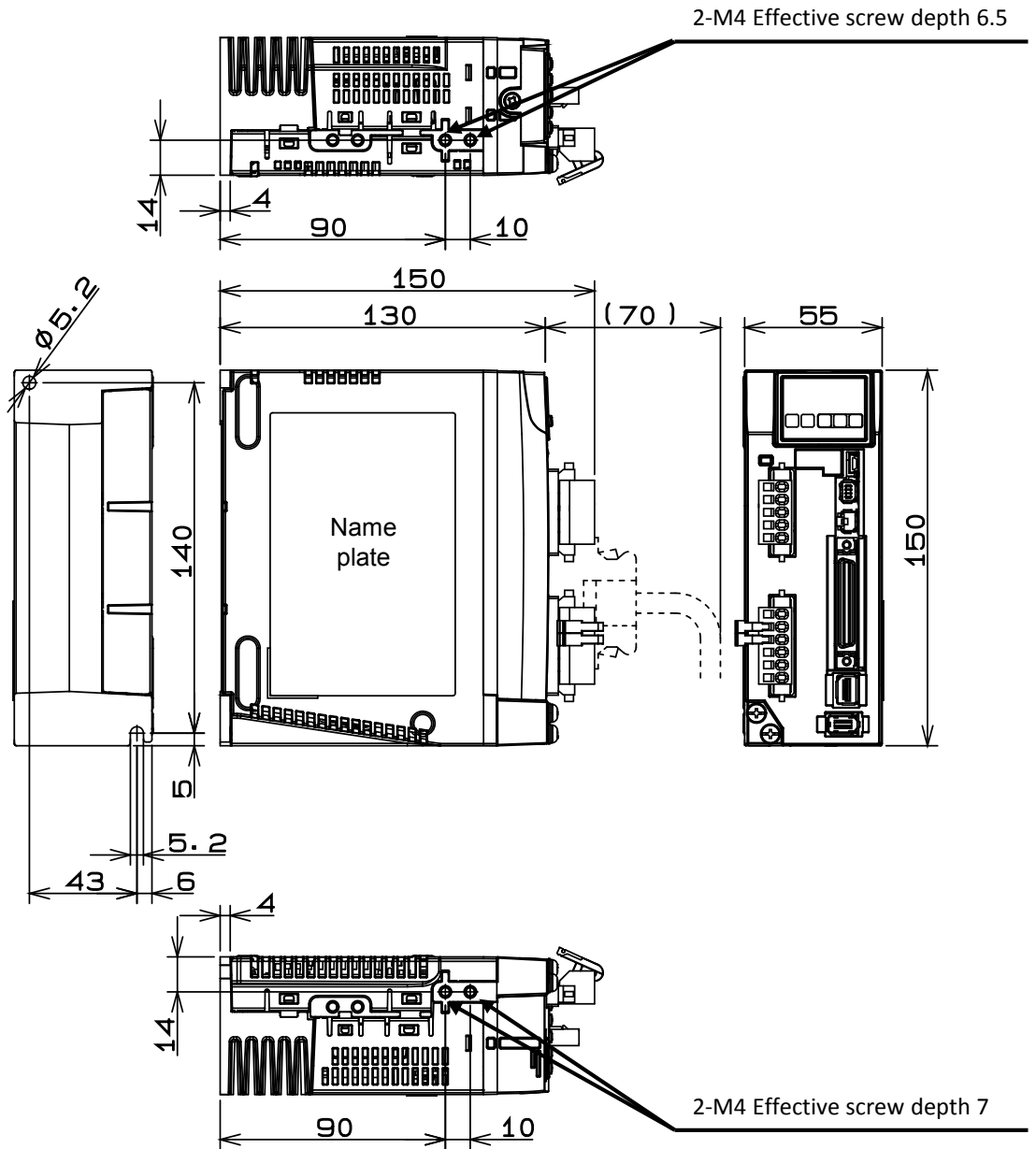


*Please do not use the screw holes of no description of the size value.

*Mounting bracket is optional parts. Mounting bracket does not shipped with the product.

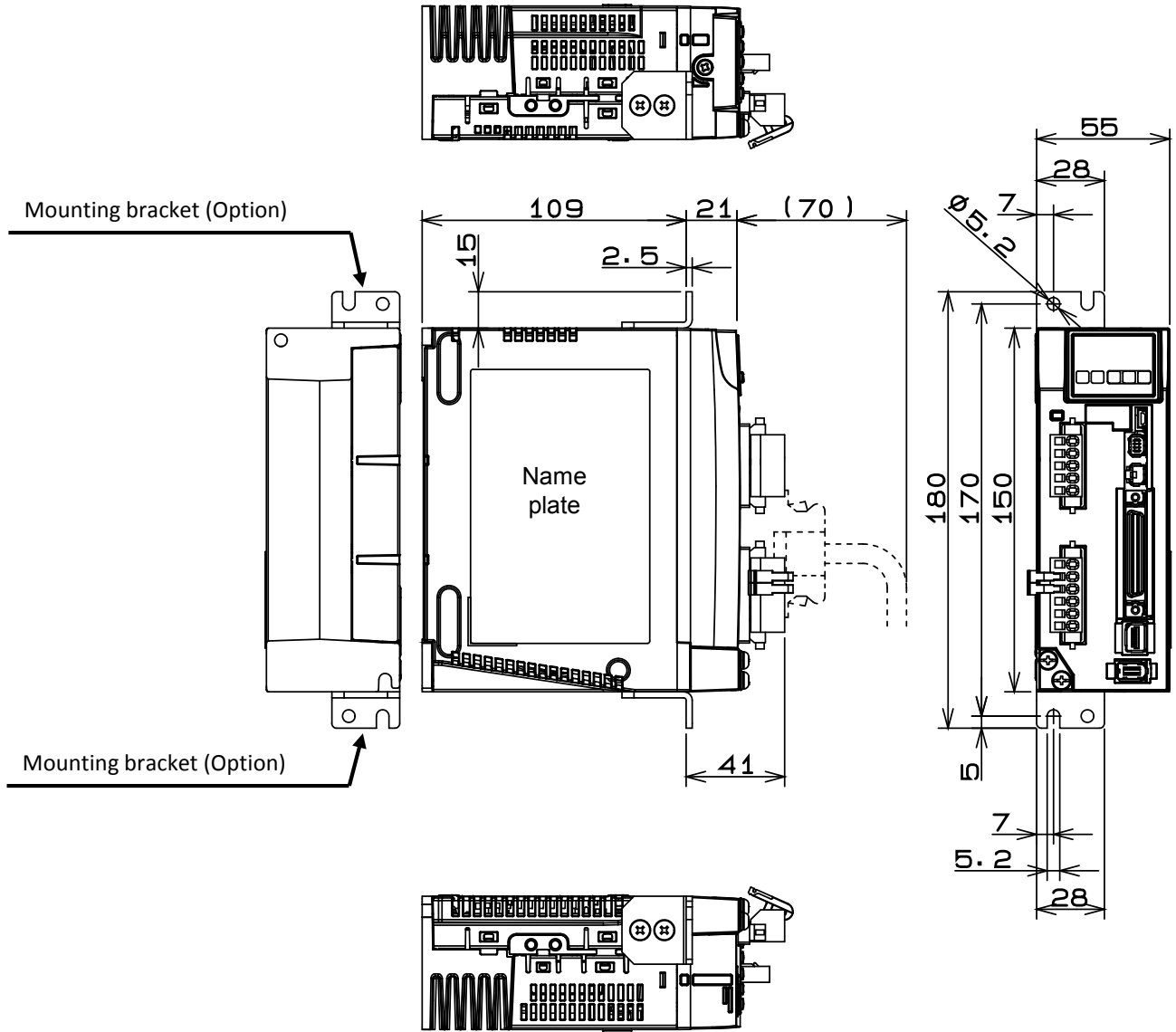
External dimension size B

[Base-mounting TYPE (Standard: Mounting on the back)]



*Please do not use the screw holes of no description of the size value.

[Rack-mounting TYPE (Option: Mounted on the front)]

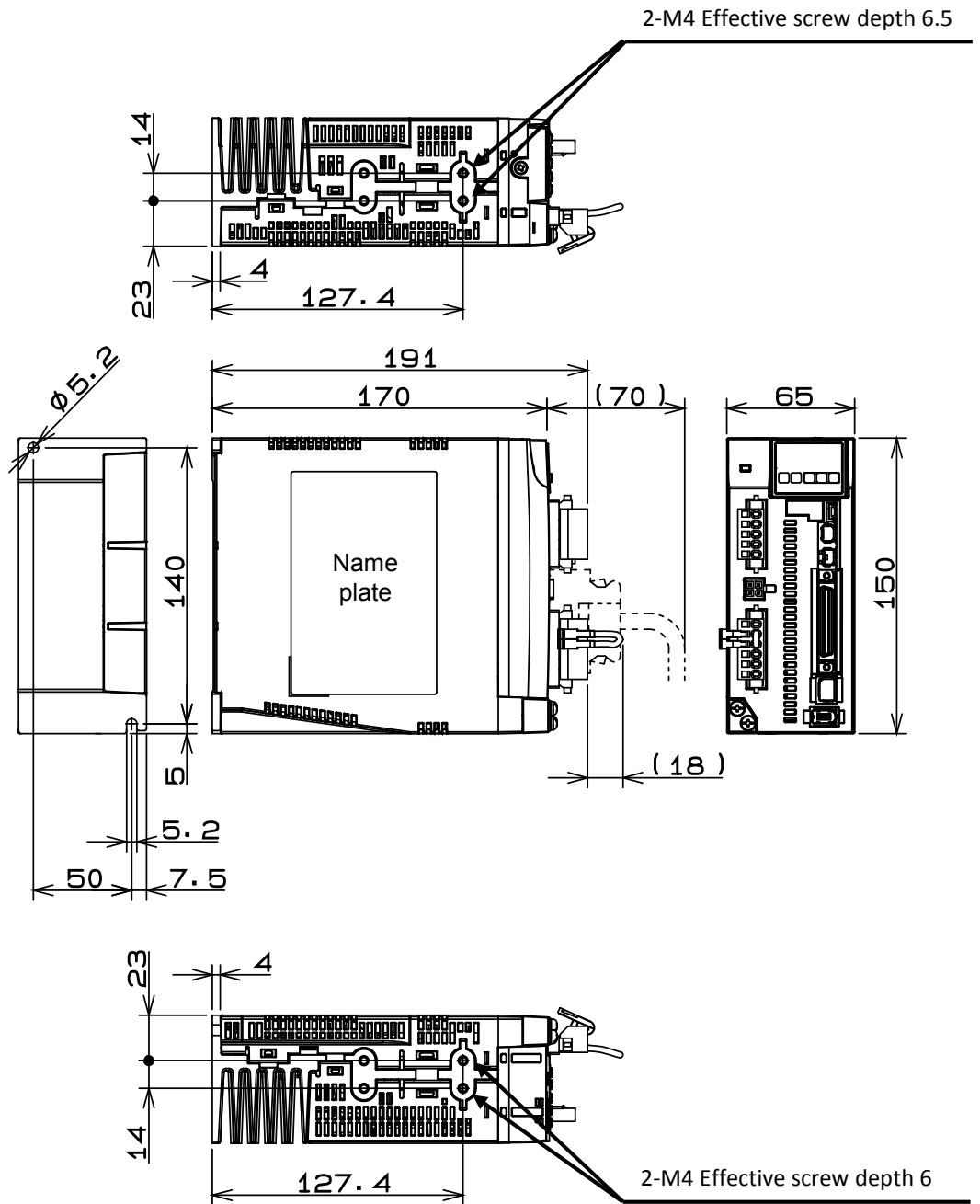


*Please do not use the screw holes of no description of the size value.

*Mounting bracket is optional parts. Mounting bracket does not shipped with the product.

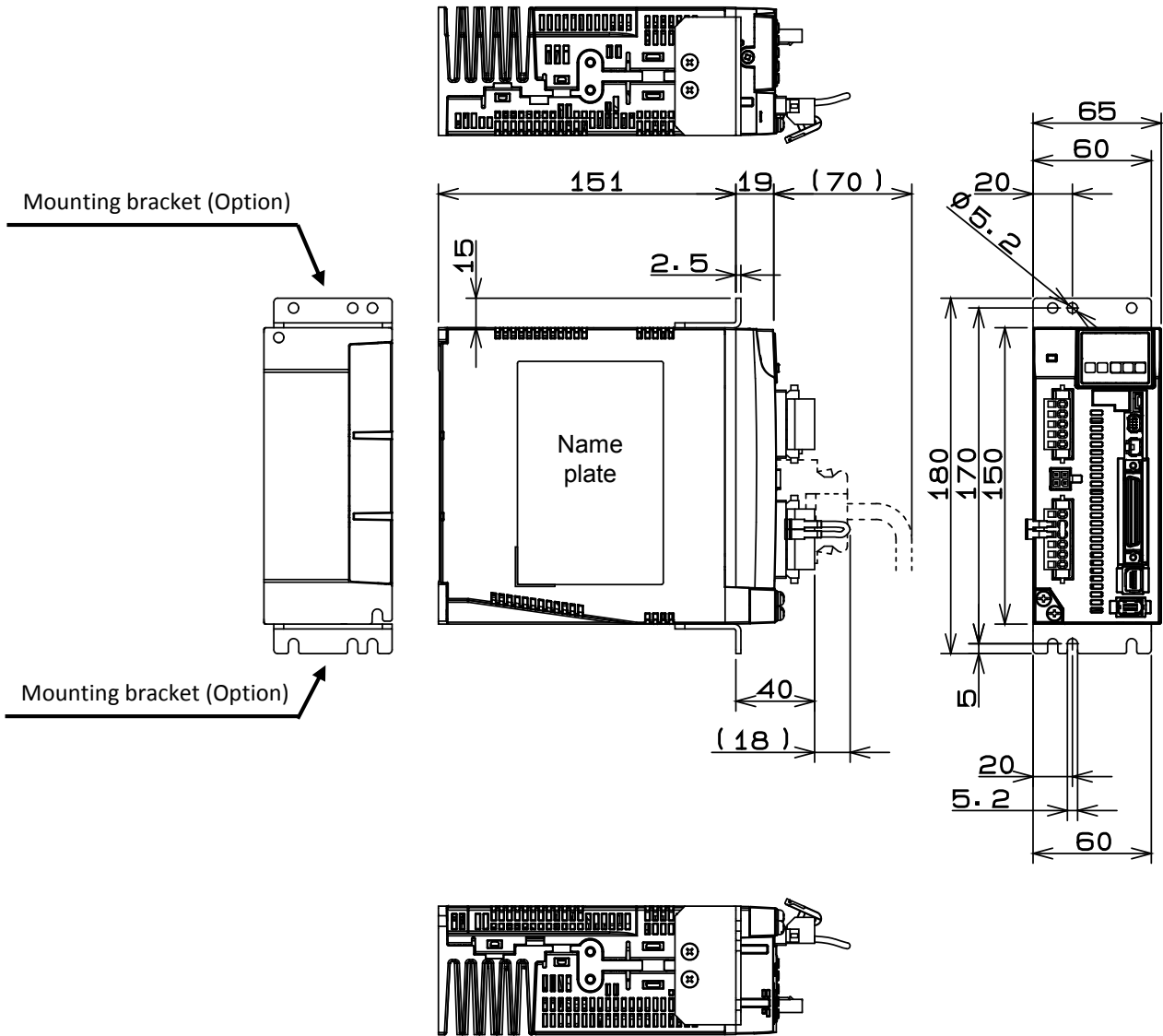
External dimension size C

[Base-mounting TYPE (Standard: Mounting on the back)]



*Please do not use the screw holes of no description of the size value.

[Rack-mounting TYPE (Option: Mounted on the front)]

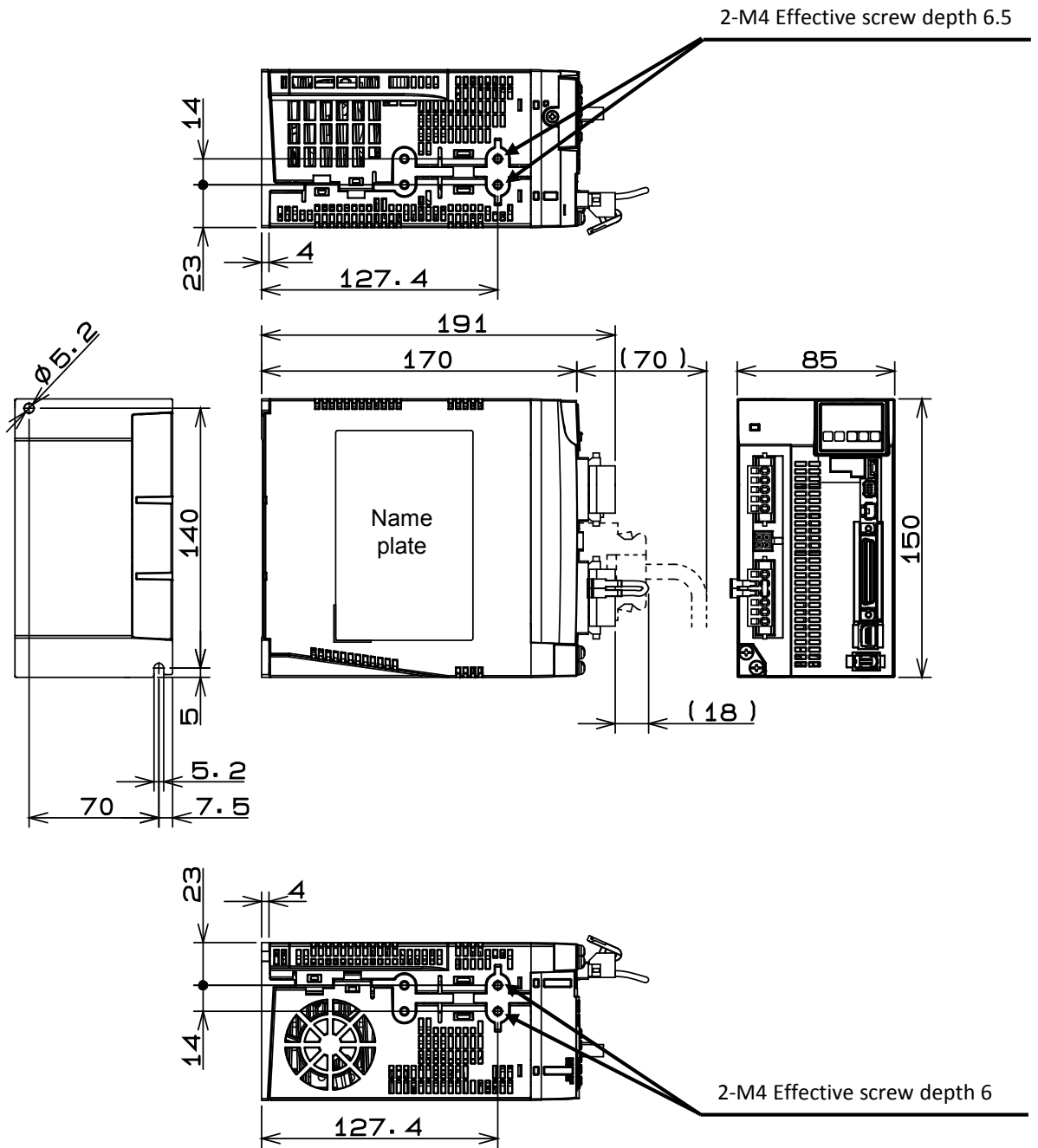


*Please do not use the screw holes of no description of the size value.

*Mounting bracket is optional parts. Mounting bracket does not shipped with the product.

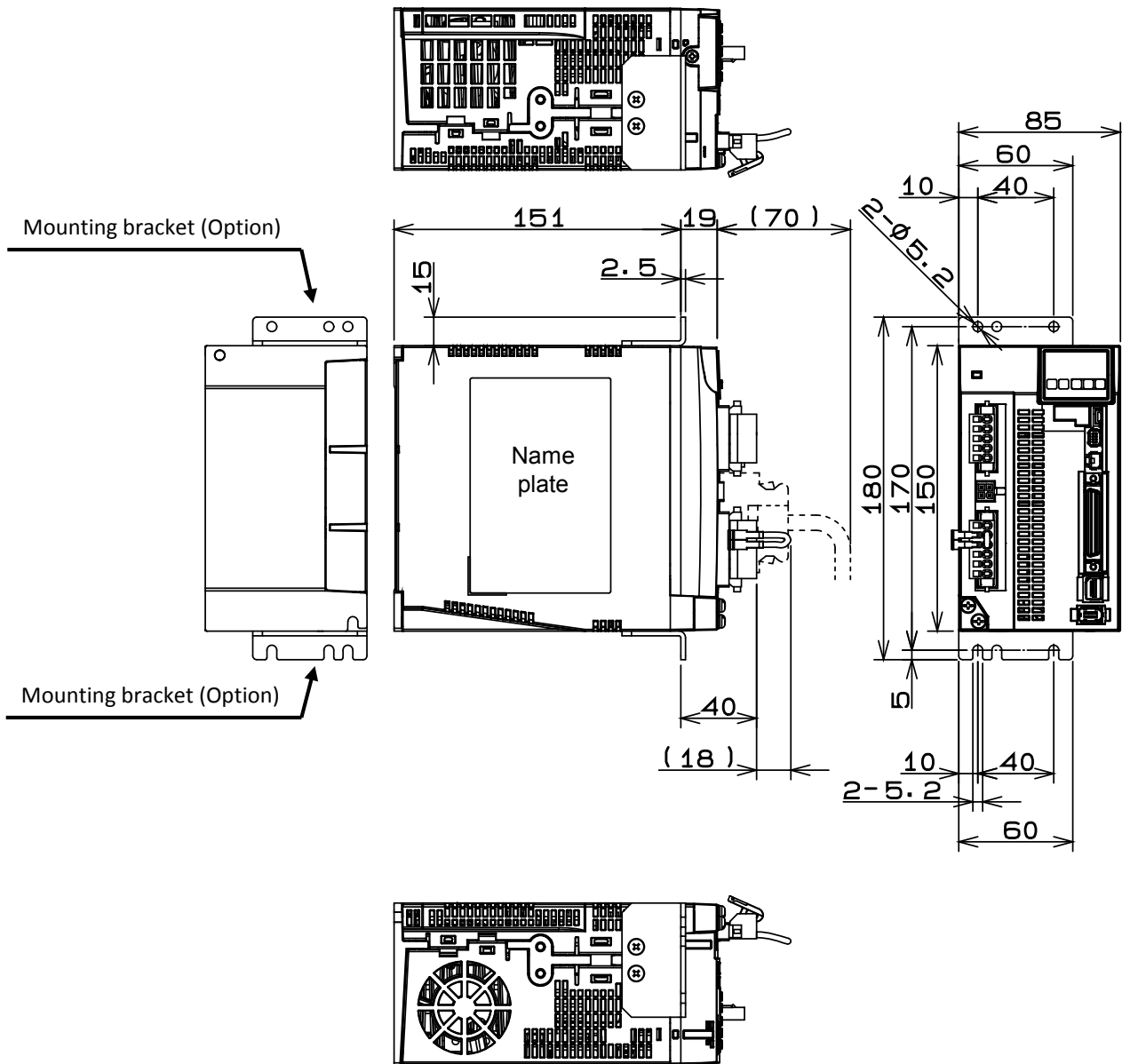
External dimension size D 200V

[Base-mounting TYPE (Standard: Mounting on the back)]



*Please do not use the screw holes of no description of the size value.

[Rack-mounting TYPE (Option: Mounted on the front)]



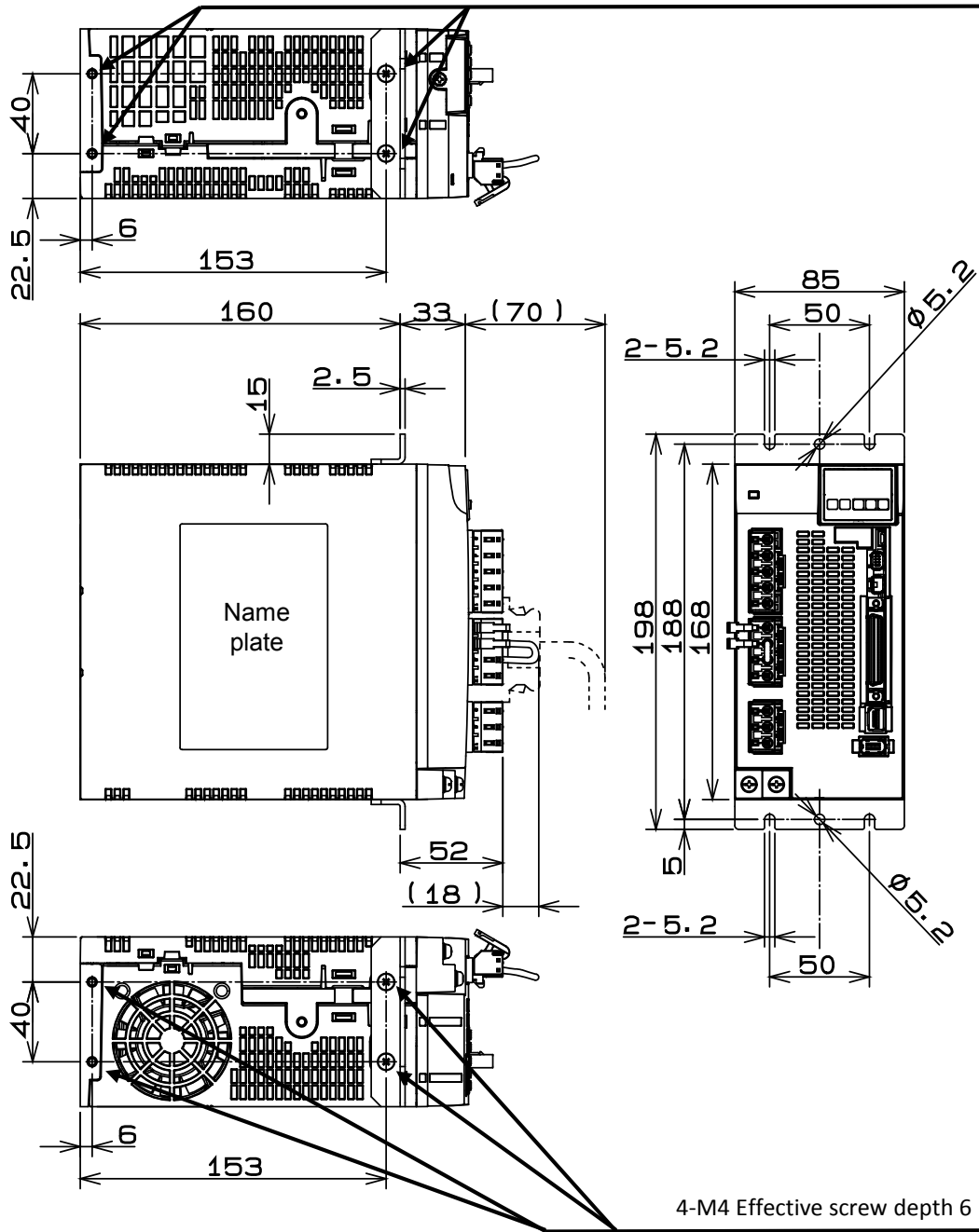
*Please do not use the screw holes of no description of the size value.

*Mounting bracket is optional parts. Mounting bracket does not shipped with the product.

External dimension size E 200V

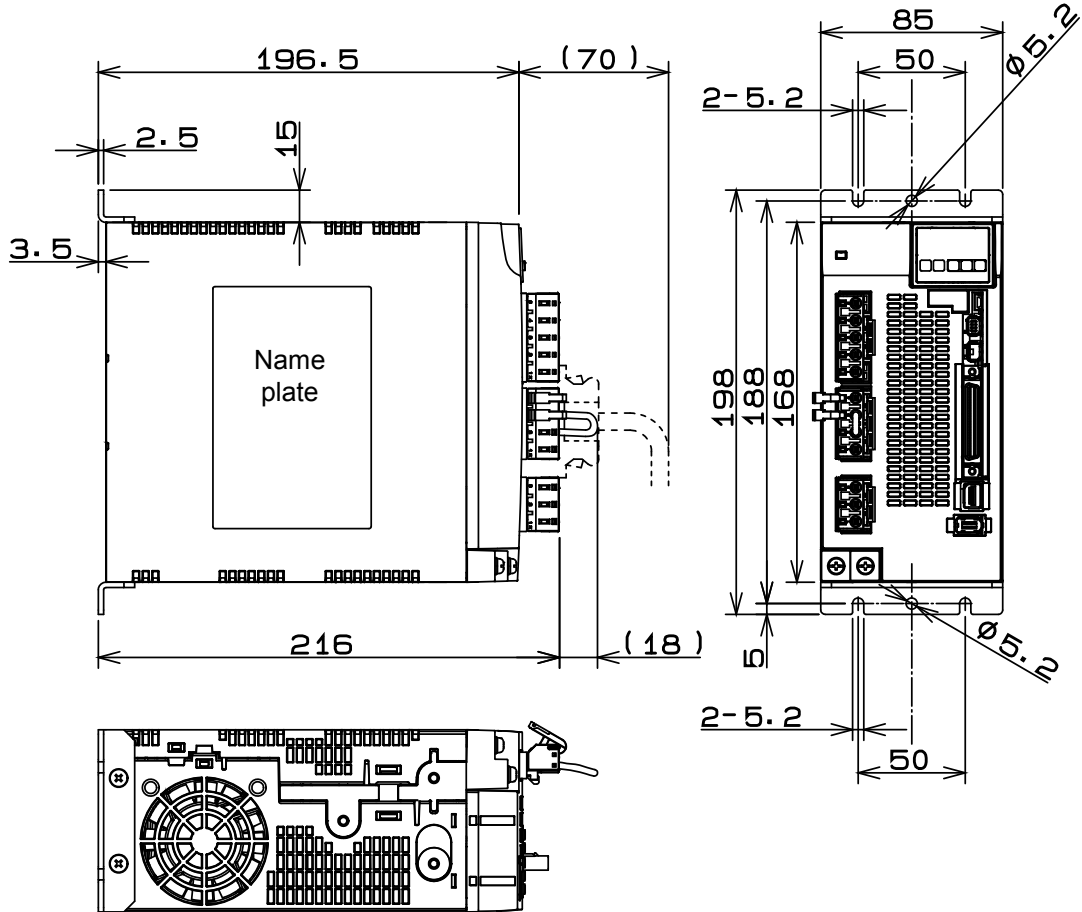
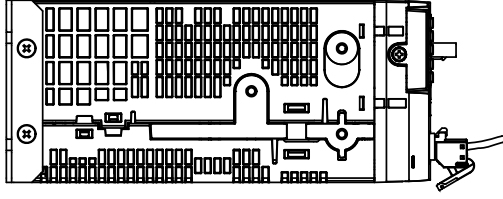
[Rack-mounting TYPE (Standard)]

4-M4 Effective screw depth 6



4-M4 Effective screw depth 6

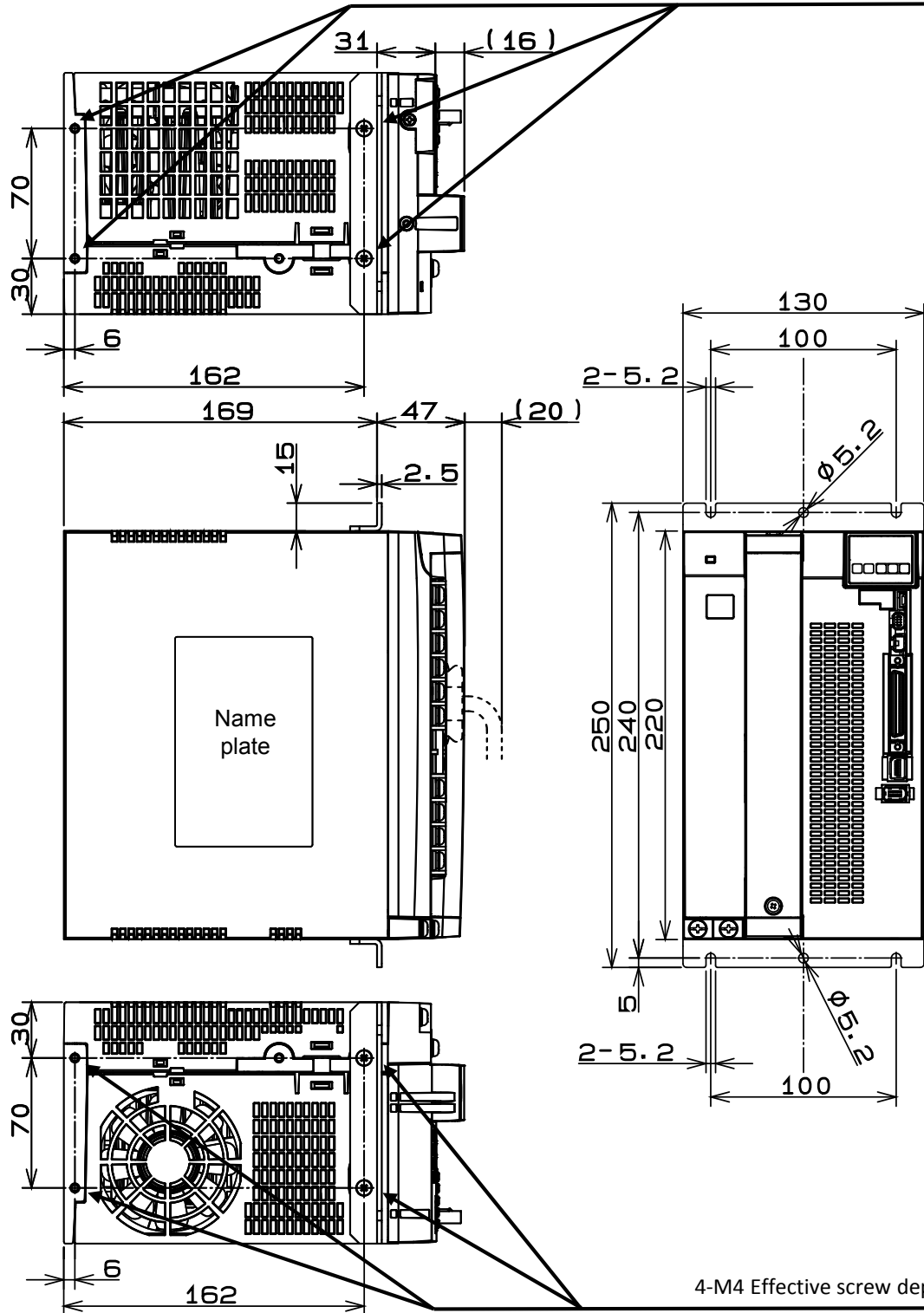
[Base-mounting TYPE (Change from standard)]



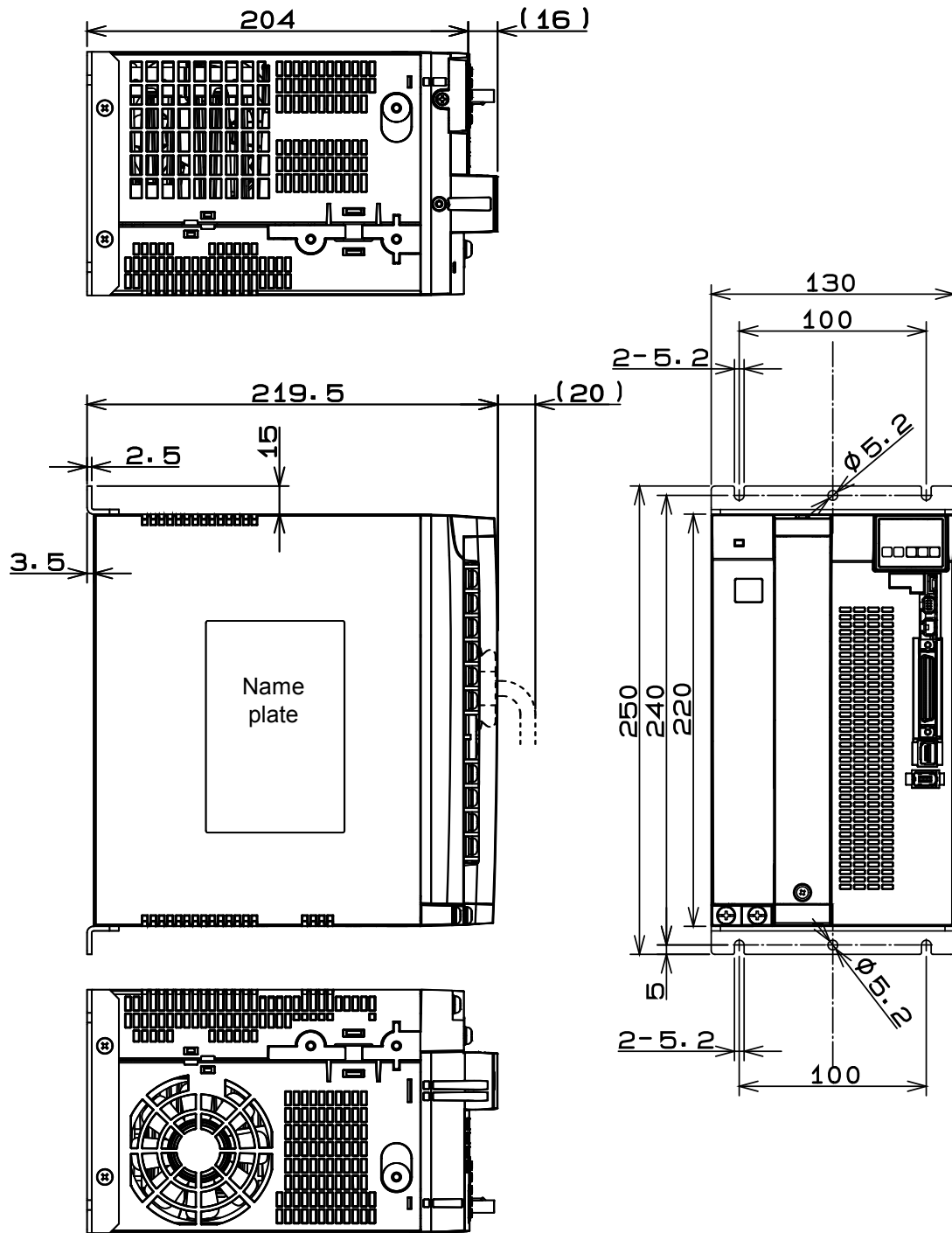
External dimension size F 200V

[Rack-mounting TYPE (Standard)]

4-M4 Effective screw depth 9



[Base-mounting TYPE (Change from standard)]



8. Wiring

8-1 Used cables and maximum cable lengths

Name	Symbol	Maximum cable length	Used cable
Main power supply	L1, L2, L3	—	Refer to specification
Control power supply	L1C, L2C	—	Refer to specification
Motor connection	U, V, W,	20m	Refer to specification
Earth cable	\oplus	—	Refer to specification
Encoder connection	X6	20m	Batch twisted shielded pair Core cable: 0.18mm ² or more
External feedback scale connection	X5	20m	
I/O connection	X4	3m	
Functional safety connection	X3	3m	Core cable: 0.18mm ² or more

8-2 Various connectors

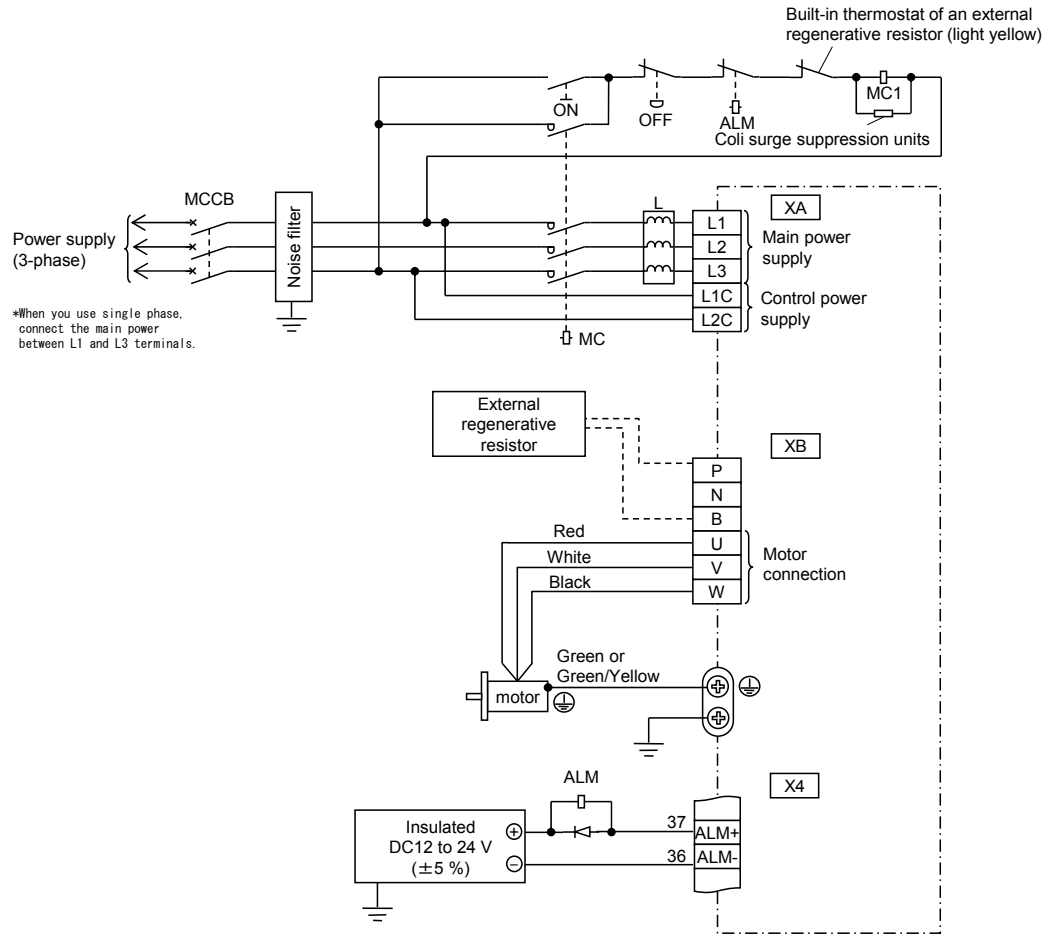
Connector symbol	Part name	Part number	Manufacturer
X2	Connector	2040008-1	Tyco electronics
X3	Connector	2013595-1	
X4	Solder plug (soldering type)	DF02P050F22A1	JAE
	Shell kit	DF02D050B22A	
X5	Connector	MUF-PK10K-X	J.S.T. Mfg.
X6	Connector	3E306-3200-008	3M Company

Please use the above part number connector, or equivalent connector.

8-3 Precautions for wiring

(1) Wiring to power connector and terminal block

100/ 200 V sizes A - B

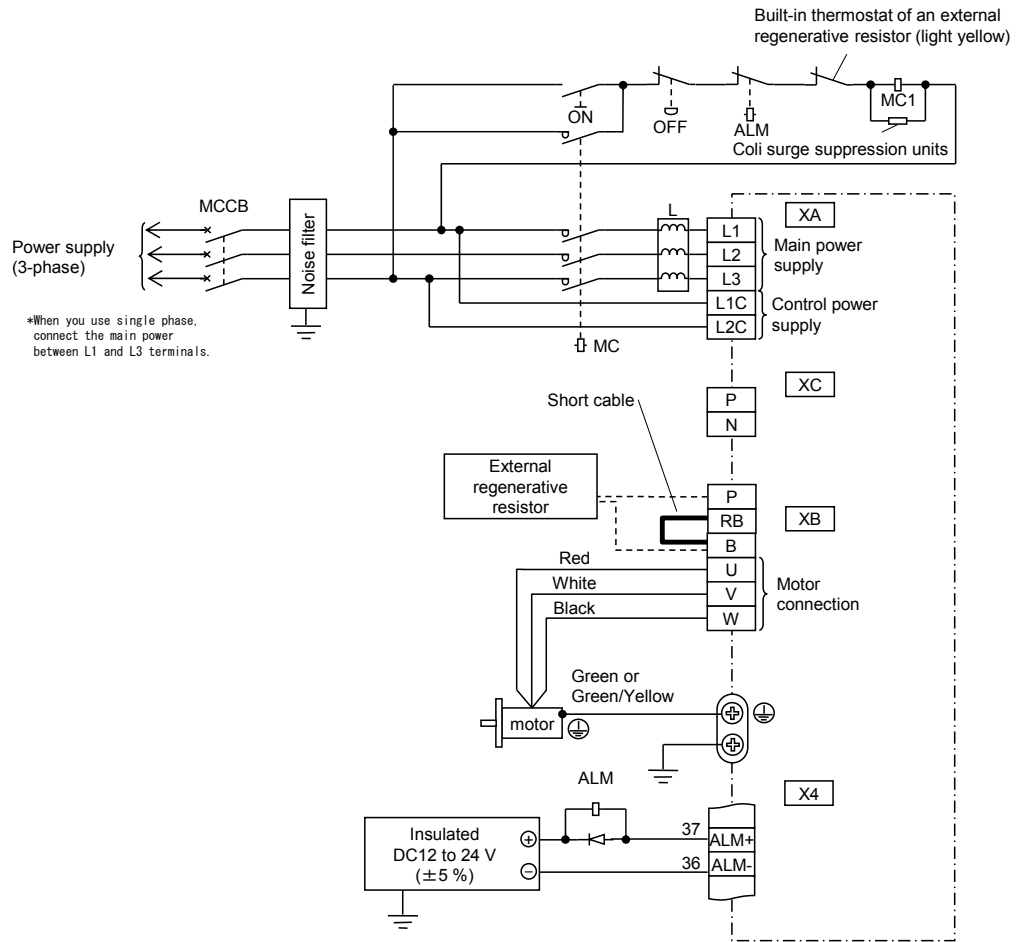


■Connection of regenerative resistor

Size	Shorting cable (Accessories)	Internal regenerative resistor	Connection of the connector XB	
			In case of using the external regenerative resistor	In case of not using the external regenerative resistor
A B	Not attached	Not installed	Between P and B: Connect the external regenerative resistor.	Between P and B: Keep open

- The circuit connected to terminal X1 – X6 are secondary circuits.
- Insulation is needed against the primary side power supply (power supply of the motor brake).
- Please do not connect them with the same power supply.

100/ 200 V sizes C - D

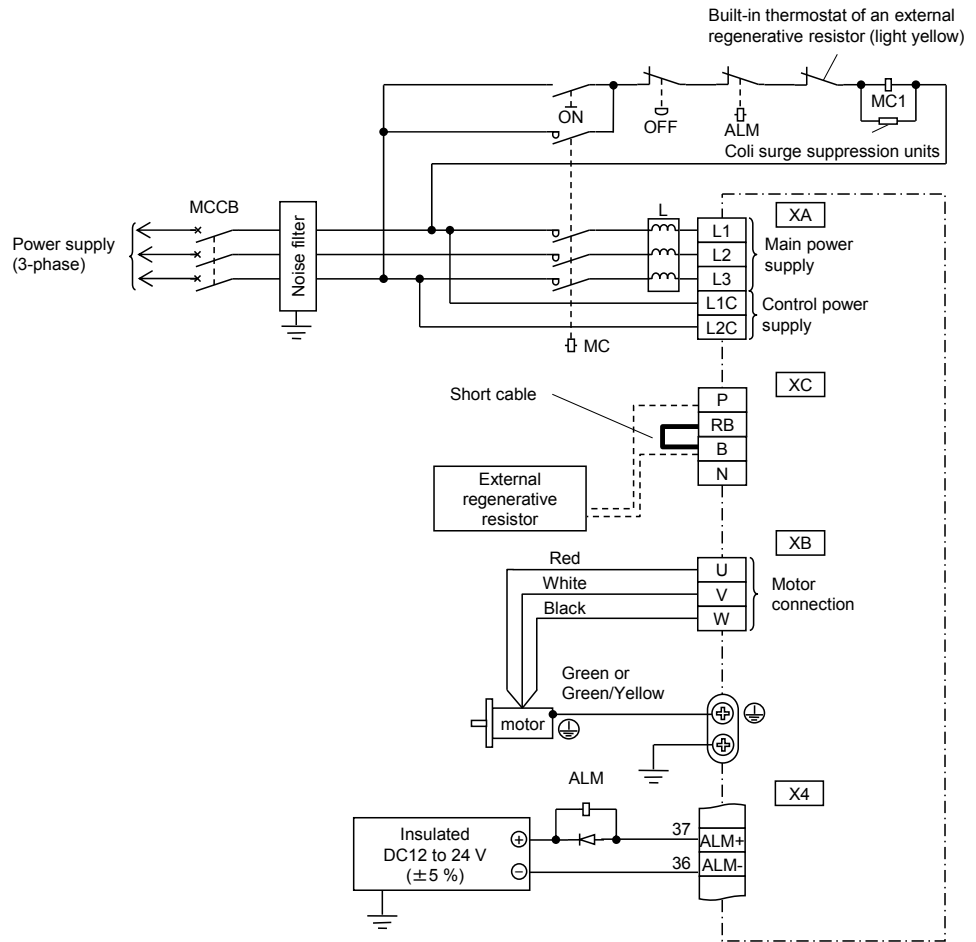


■ Connection of regenerative resistor

Size	Shorting cable (Accessories)	Internal regenerative resistor	Connection of the connector XB	
			In case of using the external regenerative resistor	In case of not using the external regenerative resistor
C D	Supplied	Installed	Between RB and B: Disconnect the short cable Between P and B: Connect the external regenerative resistor	Between RB and B: Connect the shorting cable

- The circuit connected to terminal X1 – X6 are secondary circuits.
Insulation is needed against the primary side power supply (power supply of the motor brake).
Please do not connect them with the same power supply.

200 V size E

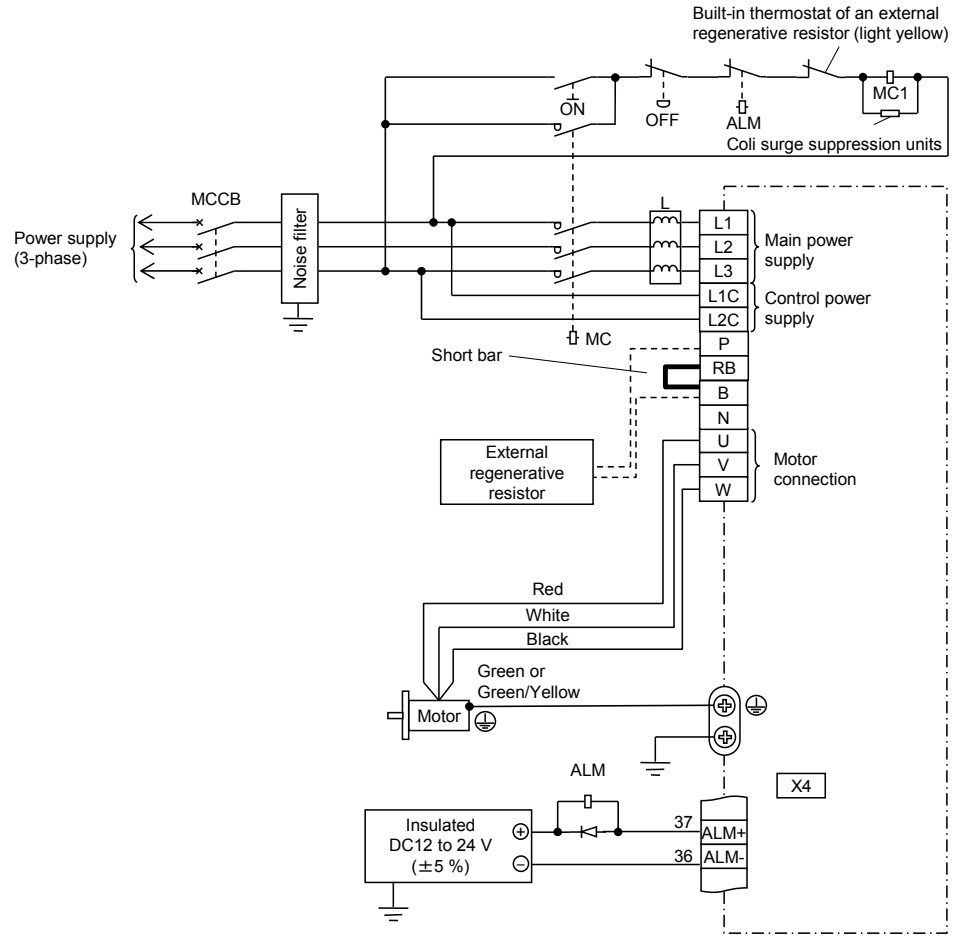


■ Connection of regenerative resistor

Size	Shorting cable (Accessories)	Internal regenerative resistor	Connection of the connector XC	
			In case of using the external regenerative resistor	In case of not using the external regenerative resistor
E	Supplied	Installed	Between RB and B: Disconnect the short cable Between P and B: Connect the external regenerative resistor	Between RB and B: Connect the shorting cable

- The circuit connected to terminal X1 – X6 are secondary circuits. Insulation is needed against the primary side power supply (power supply of the motor brake). Please do not connect them with the same power supply.

200 V size F



■ Connection of regenerative resistor

Size	Short bar (Accessories)	Internal regenerative resistor	Connection of the connector XC	
			In case of using the external regenerative resistor	In case of not using the external regenerative resistor
F	Supplied	Installed	Between RB and B: Disconnect the short bar Between P and B: Connect the external regenerative resistor	Between RB and B: Connect the short bar

- The standard of the ability of the built-in dynamic brake resistor is up to continuousness three times in the stop from the allowance and maximum inertia and the rated speed. Resistor is damaged and the dynamic brake might not work when using it under more critical operating condition.
- The circuit connected to terminal X1 – X6 are secondary circuits. Insulation is needed against the primary side power supply (power supply of the motor brake). Please do not connect them with the same power supply.

- [1] When the servo driver uses single phase power supply for sizes A - D, connect the servo driver to the terminals L1, L3 of main power supply input. Do not connect anything to the terminal L2.
- [2] Surely insert the connector into place until it clicks.
- [3] Make sure to use an insulation coated crimp terminal when connecting to each terminal on the terminal block.
- [4] Terminal block cover is fixed with screws. When wiring to the terminal block, unscrew these screws to uncover the cover. Tighten the cover fixing screw with the torque of 0.2 Nm or less.
- [5] To not use an external regenerative resistor, short out the circuit between terminals RB and B. (For sizes C, D, E, F)When a trip occurs due to the regenerative load protection error No.18.0, externally install a regenerative resistor.
To externally install a regenerative resistor, remove a connection cable between terminals RB, B and then connect the regenerative resistor between terminals P, B.
The products (Sizes A, B) supporting only the external regenerative resistor, connect an external regenerative resistor if necessary.
To use an external regenerative resistor, set Pr.0.16 (external regenerative resistor selection) to 1 or 2.
- [6] Apply the power supply of the voltage indicated on the nameplate.
- [7] Do not reverse-connect the power input terminals (L1, L2, and L3) and the motor output terminals (U, V, and W).
- [8] Do not connect the motor output terminals (U, V, and W) to ground or short out them.
- [9] Because high voltage is applied to the power connectors **[XA]**, **[XB]**, **[XC]**, and **[XD]**, and the terminal block, never touch them on any account. It may cause electric shock.
- [10] Suitable for use on a circuit capable of delivering not more than 5000 rms symmetrical amperes, below the maximum input voltage of the product.
- [11] An AC servomotor, unlike an induction motor, cannot change the rotation direction by exchanging three phases.
Make sure to coincide the motor output terminals (U, V, and W) of the servo driver with the colors (pin number for cannon plugs) of the motor output cables.
- [12] Surely connect the ground terminals of the motor and the servo driver and earth the ground terminal as well as that of the noise filter. In addition, earth the equipment unit. To earth them, ground resistance should be 100 ohm or less for grounding.
When the power supply voltage is over 300 V ground resistance should be 10ohm or less.
Please tight the earth screws by appropriate torque and use correct size earth cable decided in the specifications.
In order to avoid the impact of electrolytic corrosion, do not immediately have any contact between aluminum and copper.
- [13] Attach the surge absorbing circuits for preventing noises to an electromagnetic contactor placed around the servo driver, a coil between relay contact points, and a brake winding of motor with a brake.
- [14] Attach the no fuse breaker. In case of emergency, make sure to power off outside the servo driver. To use an earth leakage circuit breaker, use that in which a high frequency wave countermeasure is taken.
- [15] In order to reduce the terminal noise voltage, install a noise filter.
- [16] Customer is responsible for the power supply of the brake attached to a motor.
- [17] Turn ON the power after the wiring was finished.

* As for external regenerative resistor, we recommend the resistors below:

Size	Input Power Voltage	
	Single phase 100 V	Single/3 phase 200 V
A	DV0P4280	DV0P4281 (100 W or less), DV0P4283 (200 W)
B	DV0P4283	DV0P4283
C	DV0P4282	DV0P4283
D		DV0P4284
E	-	DV0P4284 x 2 in parallel or DV0P4285 x 1
F		DV0P4285 x 2 in parallel

Manufacturer by Iwaki Musen Kenkyusho

Part number	Manu- -facturer's model	Specification			Built-in thermal protector operational temperature
		Resis- -tance value	Rated power (for reference) *		
			Free air	Fan used (1 m/s)	
Ω	[W]	[W]			
DV0P4280	RF70M	50	10	25	140 ± 5 deg. Celsius Contact point B Open/close capacity (resistance load) 1 A 125 VAC, 6000 times 0.5 A 250 VAC, 10000 times
DV0P4281	RF70M	100	10	25	
DV0P4282	RF180B	25	17	50	
DV0P4283	RF180B	50	17	50	
DV0P4284	RF240	30	40	100	
DV0P4285	RH450F	20	52	130	

* Electric power available without running the built-in thermal protector.

For safety, a temperature fuse and a thermal protector are built in.

Configure the circuit so as to turn off the power supply when the thermal protector is running.

The built-in temperature fuse can break according to the radiation condition, the used temperature range, the power supply voltage, and the load change.

Make sure that the surface temperature of regenerative resistor is being kept 100 deg. Celsius or less under bad conditions (high power supply voltage, large load inertia, short deceleration time, etc.) subject to regeneration by embedding the regenerative resistor in equipments and running the equipments.

Attach the regenerative resistor on the incombustibles such as metal.

Install the regenerative resistor so that people can not directly touch it, such as the incombustible to cover it.

Keep the temperature of places, which people can directly touch, below 70 deg. Celsius.

*) Dynamic brake

Servo driver(size A-F) has built-in dynamic brake function to stop motor in an emergency.

Dynamic brake can be operated in the following cases

1. The main power off
2. The servo off
3. Protection action
4. Connector X4 driving ban importation (POT, NOT) action

On the above 1~4 cases, valid or invalid of dynamic brake can be determined by the parameters.

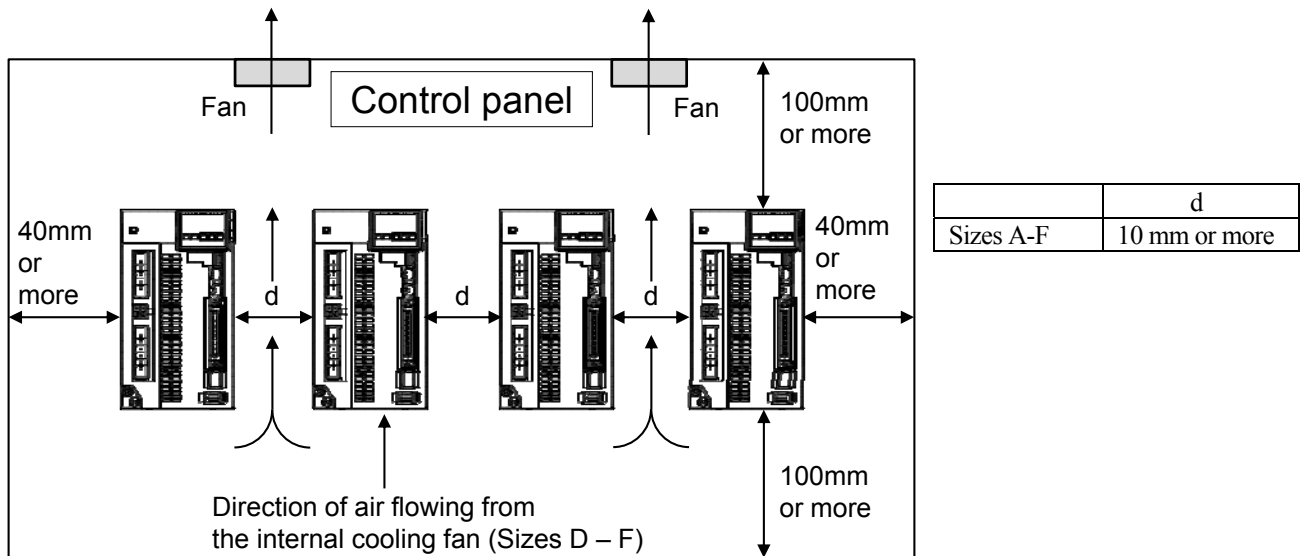
However, when the control power off, dynamic brake of size A-F keep valid condition.

Dynamic brake shall be using in rated short time for emergency stop using. Please note the following points.

1. Do not start / stop the motor by the servo signal (SRV-ON) . Built-in dynamic brake circuit may be damaged.
2. Do not drive the motor with external torque. Motor generates electricity by external torque.
Dynamic brake circuit will be damaged and it is possible that short-circuit current cause smoke or combustion.
3. Allow approx. 10 minutes pause when the dynamic brake is activated during high-speed running.
Resistor is damaged and the dynamic brake might not work when using it under more critical operating condition.

*) Mounting direction and spacing

- To perform effective cooling, allow sufficient ambient space.
- Provide a fan so as to make uniform the temperature in the control panel.
- Each of Sizes D to F is equipped with a cooling fan on the bottom.
- Adhere to environmental conditions for the environment in the control panel.

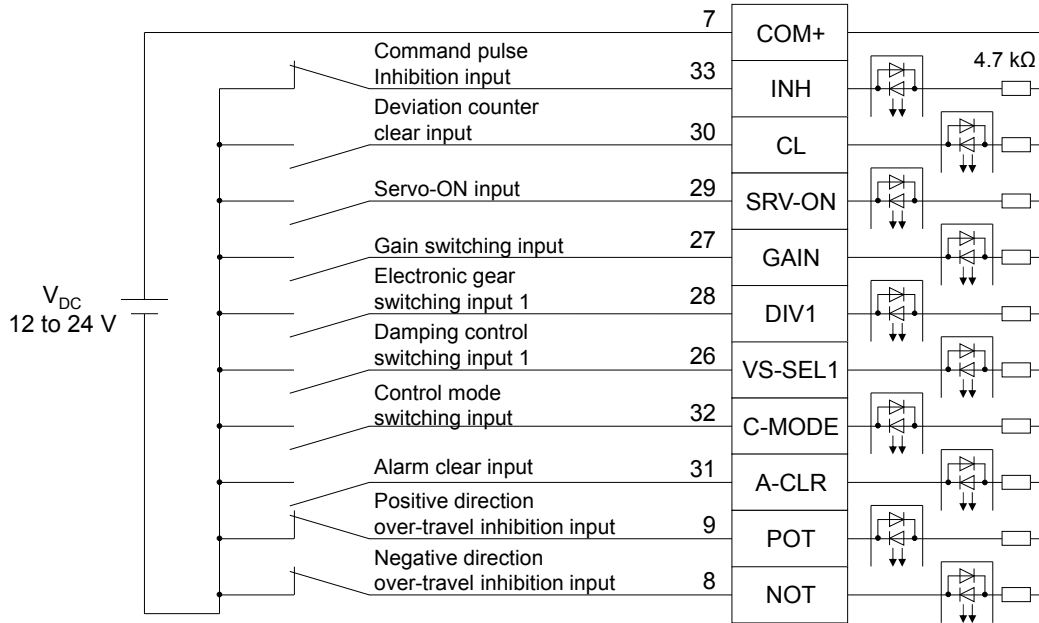


In case the portion to receive a fan is coated, peeling off the coating before installing a fan or using homebuilt brackets with conductive plating provides effective anti-noise measures.

(2) Wiring to connector **X4**

- [1] Customer is responsible for the control signal power supply at 12-24 VDC for external control connected between COM+ and COM-. Insulation is needed against the primary side power supply (power supply of the motor brake).
Please do not connect them with the same power supply.
- [2] Place the servo driver and its peripheral device as nearly as possible (up to 3 m) so as to shorten the wiring.
- [3] Wire the wiring as far away as possible (30 cm or more) from the power lines (L1, L2, L3, L1C, L2C, U, V, W, \oplus). Do not put them in the same duct or bind them together.

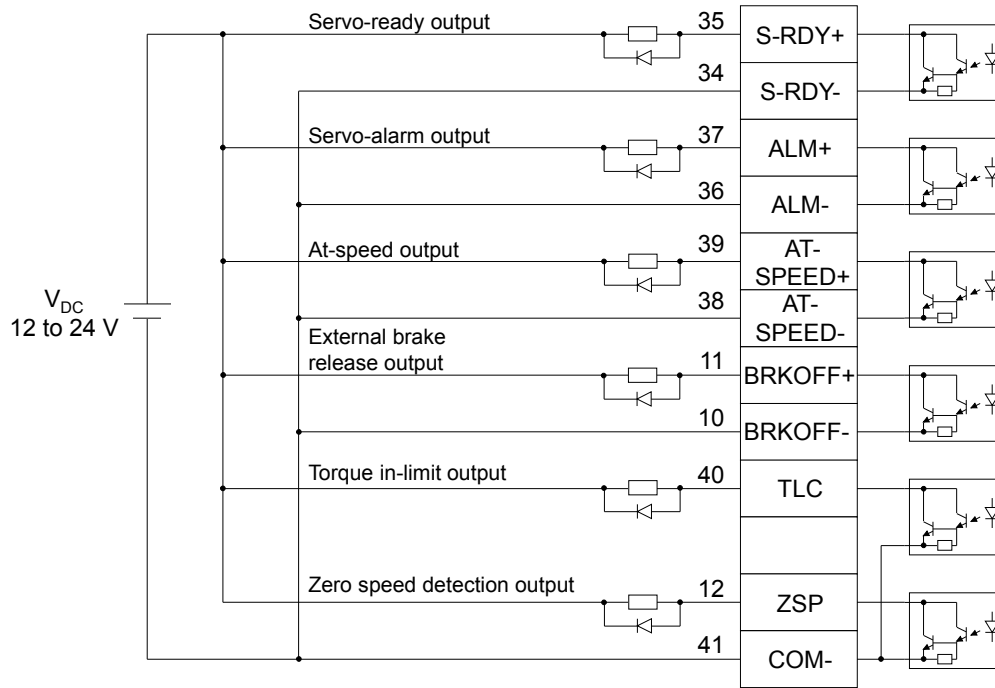
Digital input



The functions of pins 8, 9, 26-33 are allocatable with parameters. The figure above shows the default setting.

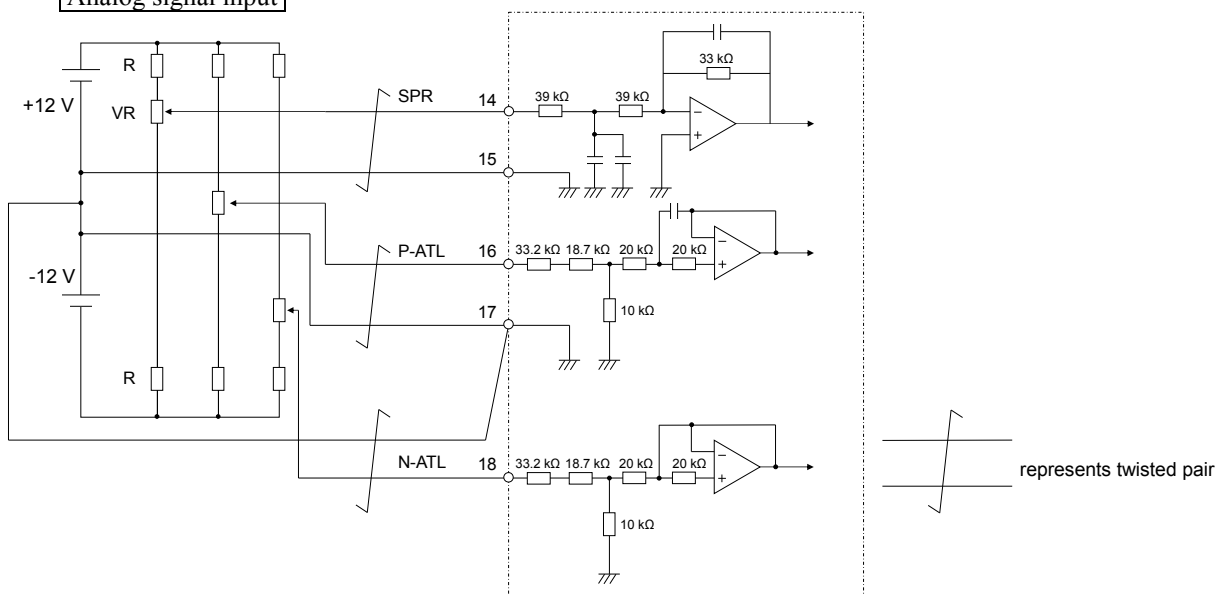
- [4] Be aware of the polarity of the power supply for control signals. The polarity connection contrary to the figure shown above can damage the servo driver.
- [5] To directly drive the relay with each output signal, make sure to attach a diode in parallel to the relay and in the direction as shown in the figure below. The servo driver can be damaged if the diode is not attached or the diode is attached in the opposite direction.
- [6] When a logic circuit such as a gate receives each output signal, take care so that a noise does not impact on the circuit.
- [7] Apply 50 mA or less of current to each output.

Digital output



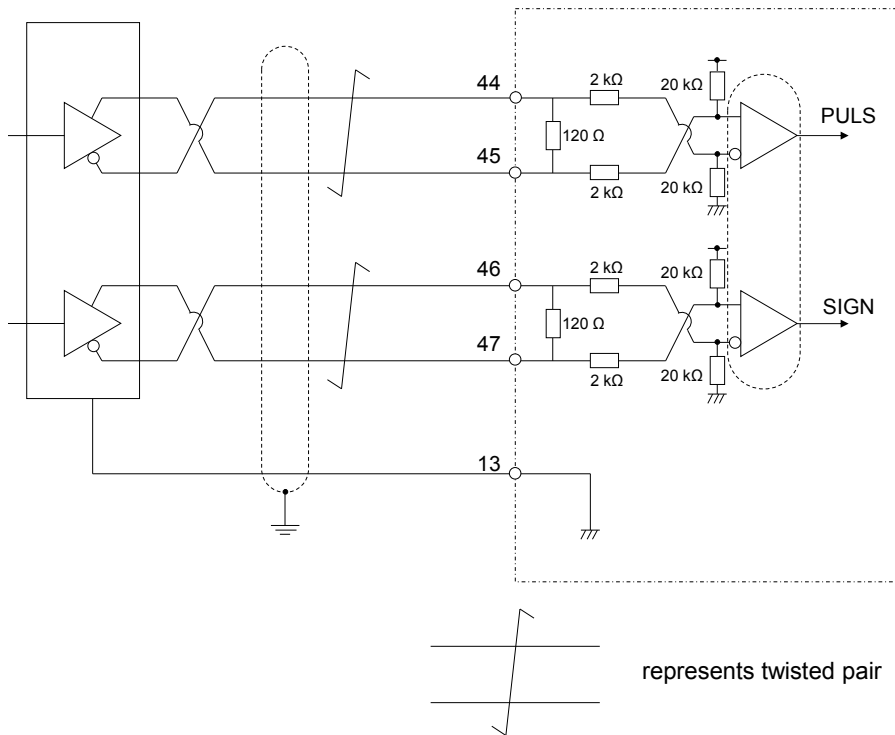
The functions of pins 10, 11, 34, 35, 38, 39 are allocatable with parameters. The figure above shows the default setting.

Analog signal input



Pulse train command

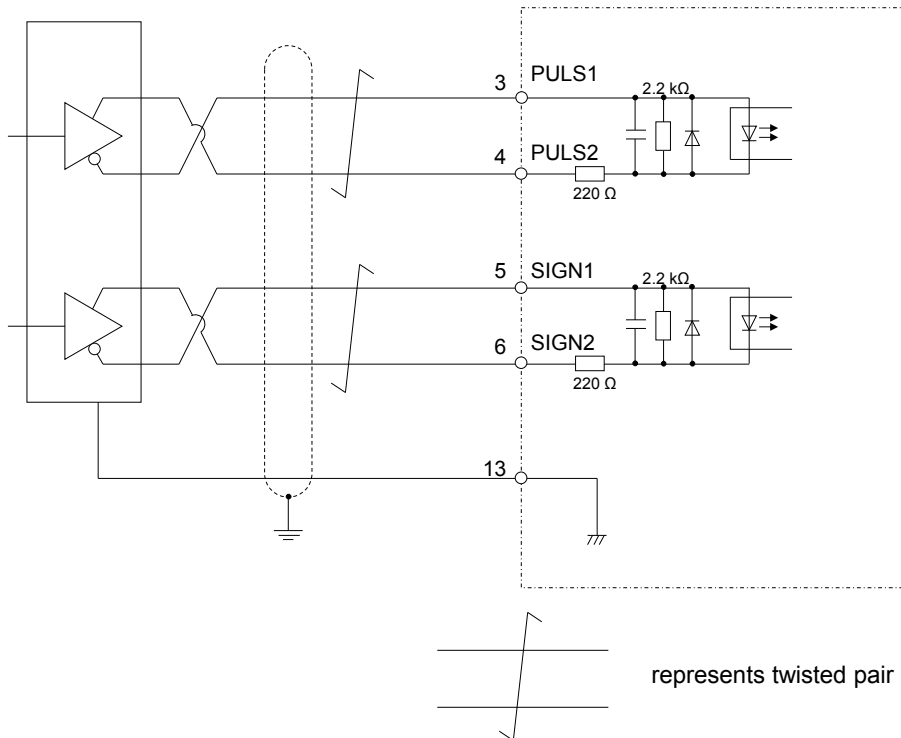
A. Pulse train interface exclusively for line driver



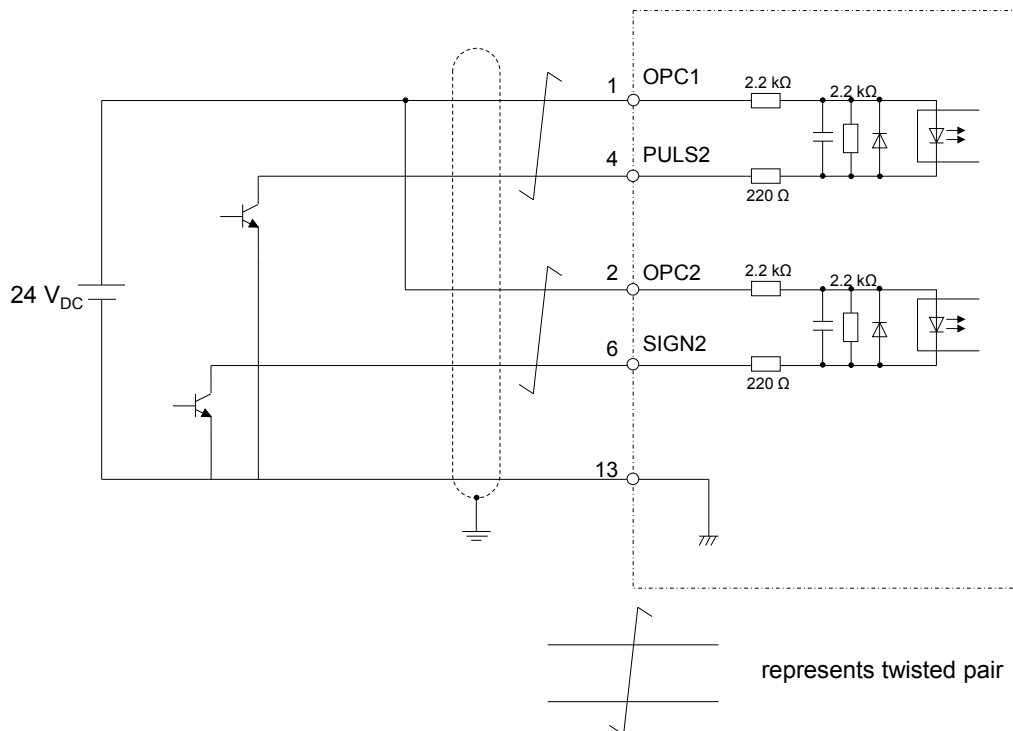
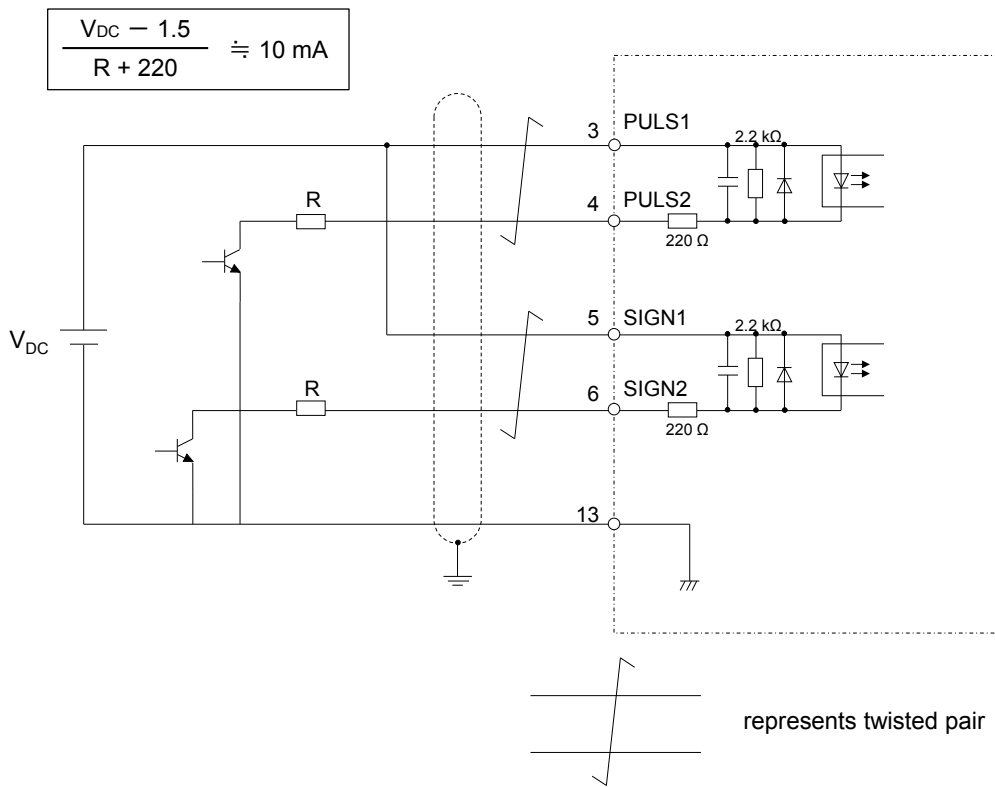
B. Pulse train interface

The pulse train command input can support both line driver and open collector interfaces, but in order to increase the certainty of signal transmissions, we recommend you to use the pulse train command input as an line driver interface as shown in the figure below.
 Be aware that the line driver and open collector interfaces differ from each other in the connection to the servo driver.

● Line driver interface



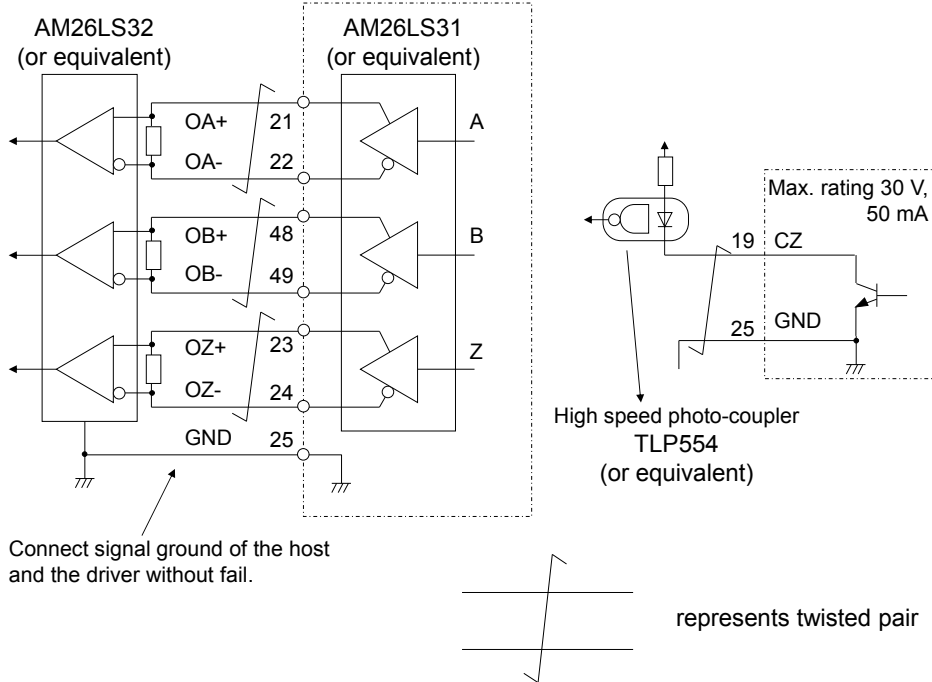
● Open collector interface



Note: Precautions for using the command pulse input as an open collector interface

- Shorten the wire length (up to 1 m).
- Be aware that the maximum pulse frequency of the open collector interface is small (200 kpps) compared with that (500 kpps) of the line driver interface.


Feedback pulse of rotary encoder



Note:

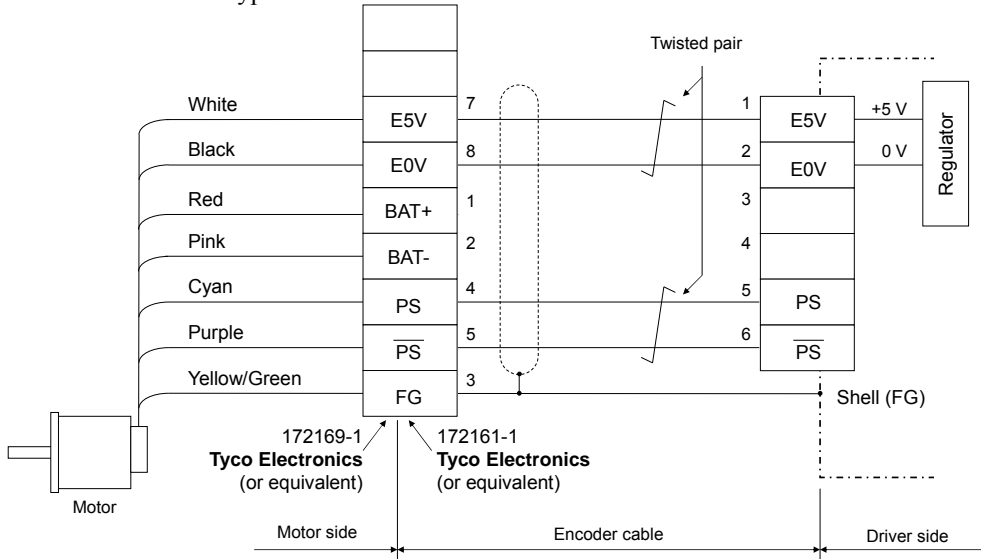
- [1] As well as being output in the line driver, only the Z-phase signals are output to the pin 19 (CZ) in the open collector. When using this CZ signal, be careful not to be subject to the noise impact.
- [2] Use a line receiver (AM26C32 or equivalent) for receiving the output pulses. Then, attach appropriate terminating resistor between inputs of the line receiver.
- [3] In the Z-phase signal output, be aware that the logic of line driver output (OZ) is the reverse of that of the open collector output (CZ).
- [4] Use the pulses at less than or equal to the maximum output frequency 4 Mpps (after quad edge valuation).

(3) Wiring to connector **X6**

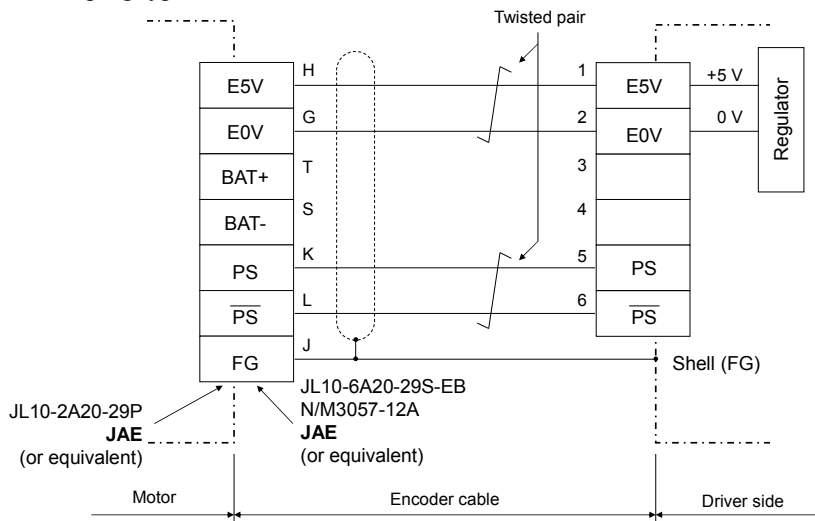
- [1] As for the encoder cable, use the batch shielded twisted wire pairs whose core is 0.18 mm² or more.
- [2] The cable length should be up to 20 m. When the wiring is long, we recommend you to use the double wiring for the 5 V power supply in order to reduce the impact of voltage drop.
- [3] Connect the coat of shielded cable at the motor side to the shield of shielded cable from the encoder.
Make sure to connect the coat of shielded cable at the servo driver side to the shell (FG) of **X6**.
- [4] Wire the wiring as far away as possible (30 cm or more) from the power lines (L1, L2, L3, L1C, L2C, U, V, W, ).
Do not put them in the same duct or bind them together.
- [5] Do not connect anything to the empty pins of **X6**.

In case of using as singleturn encoder

In case of lead wire type:

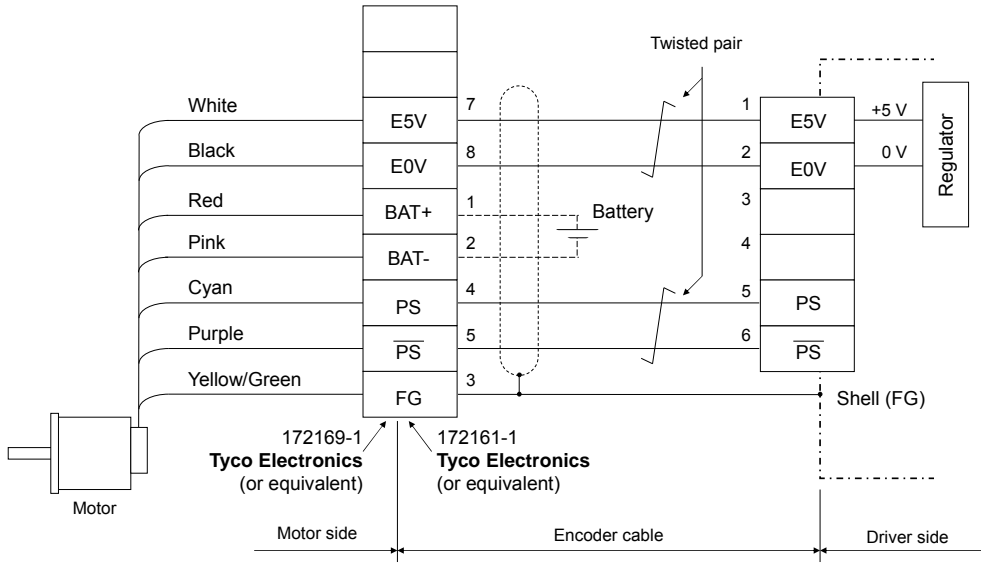


In case of canon plug type:



In case of using as multiturn encoder

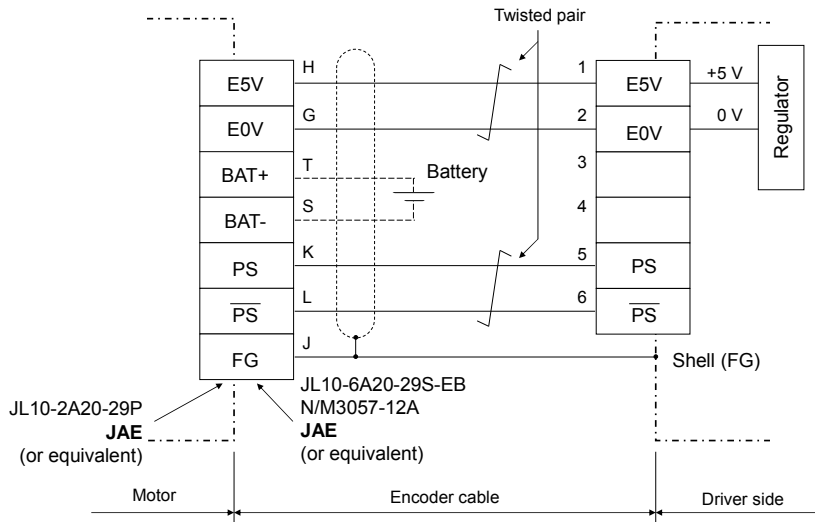
In case of lead wire type:



Connect the battery for absolute encoder to the relay connector between **1P** and **2P** (above figure).

As for the battery holder and the battery connection cable, customer can use the optional cable or prepare them.

In case of canon plug type:

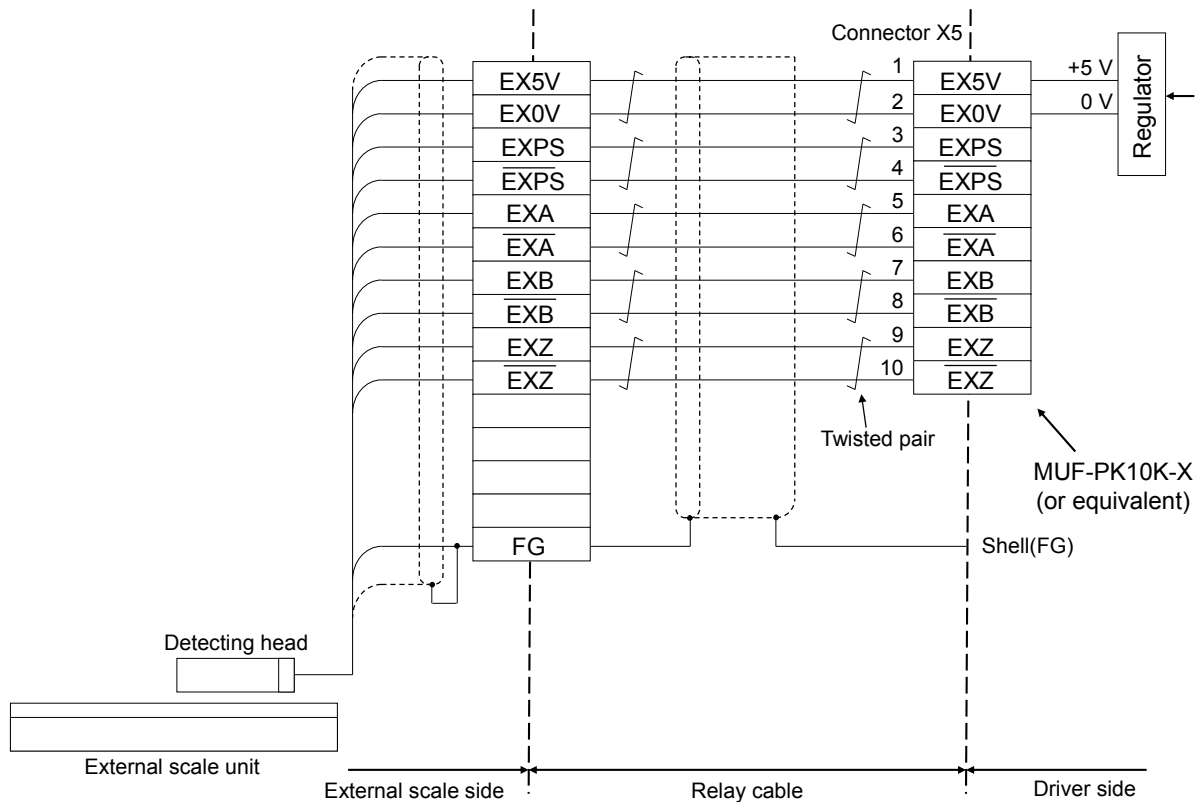


Connect the battery for absolute encoder to the relay connector between **T-pin** and **S-pin** (above figure).

As for the battery holder and the battery connection cable, customer can use the optional cable or prepare them.

(4) Wiring to connector **X5**

- [1] As for the external scale cable, use the batch shielded twisted wire pairs whose core is 0.18mm² or more.
- [2] The cable length should be up to 20 m. When the wiring is long, we recommend you to use the double wiring for the 5 V power supply in order to reduce the impact of voltage drop.
- [3] Connect the coat of shielded cable at the motor side to the shield of shielded cable from the encoder.
Make sure to connect the coat of shielded cable at the servo driver side to the shell (FG) of **X5**.
- [4] Wire the wiring as far away as possible (30 cm or more) from the power lines (L1, L2, L3, L1C, L2C, U, V, W, \oplus). Do not put them in the same duct or bind them together.
- [5] Do not connect anything to the empty pins of **X5**.
- [6] **X5** is capable to supply up to 5V ± 5% 250mA power supply. When using an external scale at more consumption current than this, customer is responsible for the power supply.
Some external scales may take longer time in initialization after turning on the power.
Design the power supply so as to meet the running timing after power-on.



9. Compliance with global standards

9-1 Conforming standards

European EC directive	EMC directive	EN55011 EN61000-6-2 EN61000-6-4 EN61800-3
	Low voltage directive	EN61800-5-1 EN50178
	Machinery directive Functional Safety	ISO13849-1 (PL e, Cat.3) EN61508 (SIL 3) EN62061 (SILCL 3) EN61800-5-2 (SIL 3, STO) IEC61326-3-1 IEC60204-1
UL standard		UL508C (File No. E164620)
CSA standard		C22. 2 No. 14
KC		KN11 KN61000-4-2,3,4,5,6,8,11

IEC : International Electrotechnical Commission
 EN : Europaischen Norman
 EMC : Electromagnetic Compatibility
 UL : Under writers Laboratoris
 CSA : Canadian Standards Association
 KC : Radio Waves Act(South Korea)

9-2 European EC directive

Our products, in order to make it easy for the embedded equipments and devices to be compliant with EC directive, provide the compliance with the standards associated with low voltage directive.

9-2-1 Compliance with EMC directive

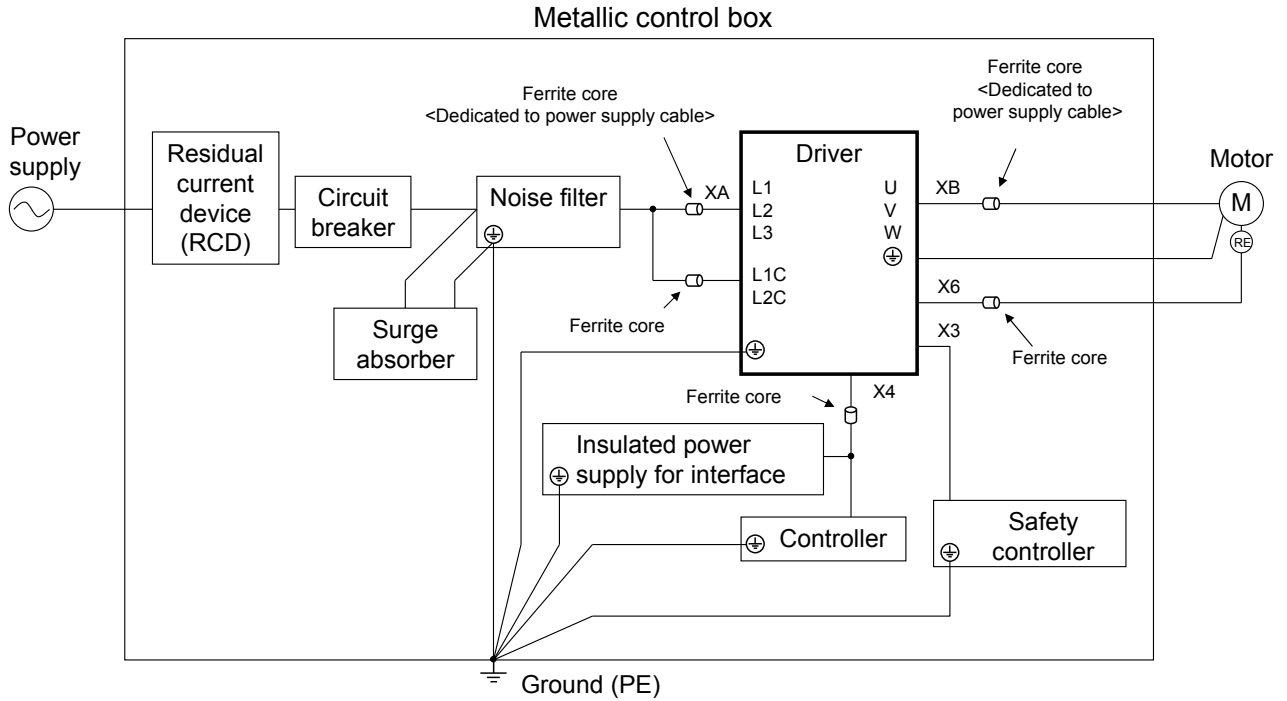
Our servo system determines the model (conditions) such as the installed distance and the wiring of the servo driver and the servomotor and makes the model compliant with the standards associated with EMC directive. When equipments and devices are embedded in practice, wiring and grounding conditions, etc. may be not the same as the model. Thus, it is necessary to measure how the final equipments and devices where the servo driver and the servo motor are embedded are compliant (especially unnecessary radiation noise, noise terminal voltage) with EMC directive.

9-3 Peripheral device configuration

9-3-1 Installation environment

Use the servo driver under the environment of pollution level 2 or 1 defined in IEC60664-1.
 (Example: Installed in the IP54 control panel.)

100 V/200 V type



9-3-2 Power supply

100 V system:	Single phase 100 V - 120 V	+10 % -15%	50/60 Hz
200 V system (Sizes A-D):	Single / 3 phase 200 V - 240 V	+10 % -15%	50/60 Hz
200 V system (Sizes E-F):	3 phase 200 V - 240 V	+10 % -15%	50/60 Hz

- (1) Use it under the environment of overvoltage category III defined in IEC60664-1.
- (2) As for the parallel I/O power supply, use the CE marking conforming product or the 12-24 VDC power supply of insulation type compliant with EN standard (EN60950).

9-3-3 Power supply

Make sure to connect a circuit breaker compliant with IEC standard and UL certification (marked with LISTED, UL) between the power supply and the noise filter.

Integral solid state short circuit protection does not provide branch circuit protection. Branch circuit protection must be provided in accordance with the National Electrical Code and any additional local codes.

9-3-4 Noise filter

To install one noise filter as a whole in the power unit when multiple servo drivers are used, consult the noise filter manufacturer.

9-3-5 Surge absorber

Install the surge absorber in the primary side of the noise filter.

- Please!

To carry out a pressure test of equipments and devices, make sure to detach the surge absorber.

Otherwise, the surge absorber can be damaged.

9-3-6 Ferrite core

Install the noise filters for signal lines in all cables (power supply, motor, encoder, and interface cables).

9-3-7 Grounding

- (1) In order to avoid an electric shock, make sure to connect a protection ground terminal (PE) of the servo driver and the protection ground (PE) of the control panel.
- (2) Do not tighten the connection to the protection ground terminal (PE) along with other parts. The servo driver has two protection ground terminals.

9-4 List of peripheral devices applicable to servo driver

Servo driver	Voltage spec	Power capacity (Rated current)	Electromagnetic contactor (Rated current/ Released heat current)	Circuit breaker (Rated current)	Noise filter	Surge absorber	Noise filter for signals		
							Power cable	Motor cable	
MADL*01**	Single phase 100 V	Approx. 0.4 kVA	20 A	10 A	DV0P4170 (for single phase) / DV0PM20042 / RTHN-5010	DV0P4190 (for single phase) / DV0P1450 (for 3 phase)	DV0P 1460	DV0P 1460	
MADL*11**									
MADL*05**	Single/ 3 phase 200 V	Approx. 0.5 kVA							
MADL*15**									
MBDL*21**	Single phase 100 V	Approx. 0.5 kVA							
MBDL*25**	Single/ 3 phase 200 V	Approx. 0.9 kVA							
MCDL*31**	Single phase 100 V	Approx. 0.9 kVA		15 A	DV0PM20042 / RTHN-5010				
MCDL*35**	Single/ 3 phase 200 V	Approx. 1.3 kVA							
MDDL*45**	Single/ 3 phase 200 V	Approx. 1.8 kVA		30 A	20 A				DV0P4220 / RTHN-5030
MDDL*55**		Approx. 2.3 kVA							
MEDL*83**	3 phase 200 V	Approx. 3.8 kVA	60 A	30 A	DV0PM20043 / RTHN-5050	DV0P1450	RJ8035		
MFDL*A3**		Approx. 4.5 kVA	100 A	50 A	DV0P3410 / RTHN-5050				
MFDL*B3**		Approx. 7.5 kVA							

- Select the specification common to single/ 3 phase 200 V according to the power supply.
- To become compliant with European EC directive, make sure to connect a circuit breaker compliant with IEC standard and UL certification (marked with LISTED) between the power supply and the noise filter.

- Please!

- Select a circuit breaker and a noise filter with the capacity comparable to the power capacity (by taking into account the load condition).
- Terminal block and earth terminal

For wiring, use the copper conductor cable of the temperature rating 75deg. Celsius or more.

For the protection earth terminal, use M4 for Sizes A-E, M5 for Sizes F.

The terminal block can be damaged if the screw tightening torque exceeds the maximum value.

(see the page for explanation of terminal blocks.)

- Use earth cable having a cross section area of 2.0 mm² (AWG 14) or more for an output of 50 W to 2.5 kW, 3.5 mm² (AWG 12) or more for an output of 3.0 kW to 5.0 kW, 13.3 mm² (AWG 6) or more for an output of 6.0 kW to 11.0 kW, or 21.1 mm² (AWG 4) or more for an output of 15 kW.
- For Sizes A - E, use the dedicated connector which came with the product.
In this case, the stripped cable length should be 8-9 mm.
- The tightening torque of connector (X4) with the upper controller should be 0.3 - 0.35 Nm.
The torque which exceeds 0.35 Nm can damage the driver's connector.

	Optional part number	Part number of manufacturer	Manufacturer
Absorber	DV0P1450	R•A•V-781BXZ-4	Okaya Electric Industries
	DV0P4190	R•A•V-781BWZ-4	
	DV0PM20050	R•A•V-801BXZ-4	
Ferrite core	DV0P1460	ZCAT3035-1330	TDK
	—	RJ8035	Konno Kogyousho
Noise filter	DV0P4170	SUP-EK5-ER-6	Okaya Electric Industries
	DV0P4220	3SUP-HU30-ER-6	
	DV0P3410	3SUP-HL50-ER-6B	
	DV0PM20042	3SUP-HU10-ER-6	
	DV0PM20043	3SUP-HU50-ER-6	
	—	FN258L-16-07(29)	Schaffner
	—	FN258L-30-07(33)	
	—	FS5559-60-34	
	—	FS5559-80-34	
	—	FN258-42-07(33)	
	—	RTHN-5010	TDK

9-5 Compliance with UL standard

Certified by the UL508C (file No. E164620) standard by observing the installation conditions 1, 2 below.

[1] Installation environment

Use the servo driver under the environment of pollution level 2 or 1 defined in IEC60664-1.

(Example: Installed in the IP54 control panel.)

Make sure to connect a circuit breaker or fuse compliant with UL certification (marked with LISTED, UL) between the power supply and the noise filter.

For information about rated current of the circuit breaker/ fuse, refer to "9-4 List of peripheral devices applicable to servo driver".

For wiring, use the copper conductor cable of the temperature rating 75deg.Celsius or more.

The terminal block can be damaged if the screw tightening torque exceeds the maximum value.

(see the page for explanation of terminal blocks.)

[2] Short Circuit Current Ratings (SCCR)

This servo driver complies with the power of the following conditions.

- The power supply voltage is less than the maximum input voltage of the product.
- Symmetrical short current of the power supply is less than 5000A.

[3] Protection of branch circuit

Protection of branch circuit, please follow the NEC(National Electrical Code) and standard regional.

[4] Overload protection, overheat protection

The overload protection function of the servo driver works when the effective current will be 115 % or more of the rated current based on the time property. Check that the effective current of the servo driver does not exceed the rated current. Set up the maximum instantaneous allowable current at the Pr0. 13 (first torque limit) and Pr5.22 (second torque limit).

There is no overheat protection in the servo motor. If you need to conform to the NEC, please implement the overheating protection measures.

9-6 Radio waves act (South Korea) precautions

This servo driver is a Class A commercial electromagnetic radio wave generator not designed for home use. The user and distributor should be aware of this fact.

A 급 기기 (업무용 방송통신기자재)

이 기기는 업무용(A 급) 전자파적합기기로서 판매자 또는 사용자는 이 점을 주의하시기 바라며, 가정외의 지역에서 사용하는 것을 목적으로 합니다.

(대상기종 : **Servo Driver**)

9-7 Compliance with SEMI F47 instantaneous stop standard

- This function corresponds to the F47 power supply instantaneous stop standard in the SEMI standard during no/ light load condition.
- Useful when used in the semiconductor manufacturing equipment.



-Warning:

- [1] Not applicable to the driver which has a single phase 100V specification and a 24 VDC specification for control power input.
- [2] Make sure to evaluate and confirm the compliance with F47 power supply instantaneous stop standard with an actual device.



SAFETY PRECAUTIONS

10. Safety precautions

- Danger and damage caused when the safety precautions are ignored are described in the following categories and signs:

 DANGER	Description of this sign indicates “urgent danger that may cause death or serious injury.”
 ATTENTION	Description of this sign indicates “danger that may cause injury or property damage.”

- Rules to keep are categorized and described with the following graphics.

	This graphic indicates “Prohibited” acts that are not permitted.
	This graphic indicates “Mandatory” acts that must be performed forcibly.

DANGER



- (1) Be sure not to store or use the equipment under conditions subjected to vibrations (5. 88 m/s² or heavier) or an impact shock, foreign matters such as dust, metal particles oil mist, liquids such as water, oil and polishing liquid, near flammable objects, in an atmosphere of corrosive gas (such as H₂S, SO₂, NO₂, Cl₂) or in an atmosphere of flammable gas.
- (2) Do not place any flammable objects near a motor, a driver, or a regenerative resistor.
- (3) Do not driver the motor with external torque. Motor generates electricity by external torque. Dynamic brake circuit will be damaged and it is possible that short-circuit current cause smoke or combustion.
- (4) Do not damage or strain the cable, or do not apply excessive stress. Do not place a heavy item on the cable or do not pinch the cable.
- (5) Do not use the equipment with the cable soaked in oil or water.
- (6) Do not install the equipment near a heating object such as a heater or a large wire-wound resistor. (Install a thermal shield, etc. to avoid the influences of heating object.)
- (7) Do not connect the motor directly with a commercial power.
- (8) Do not use the equipment under conditions subject to strong vibrations or an impact shock. Please attach the anti-vibration equipment to servo driver mounting surface If you install the servo driver in the vicinity of the vibration source.
- (9) Be sure not to touch a rotating part of a motor during operation.
- (10) Do not touch the key flutes of motor output shaft with bare hands.
- (11) Be sure not to touch inside a servo driver.
- (12) Motor drive heat sink and peripheral device become very hot. Do not touch them.
- (13) Do not carry out wiring or do not operate the equipment with wet hands.



SAFETY PRECAUTIONS



- (14) Wiringwork is strictly allowed only for an engineer specializing electrical work.
- (15) A motor other than specified is not provided with a protection device. Protect a motor with an overcurrent protection device, a ground-fault interrupter, overheating protection device, and emergency stop device,etc.
- (16) When operating the driver after an earthquake, inspect installation conditions of the driver and the motor and safety of the equipment to make sure that no fault exists.
- (17) After turning off the power, the inside circuit remains charged at a high voltage for a while. When moving, wiring or inspection the equipment, completely shut off the power supply input outside the driver and leave for 15 minutes or longer before working.
- (18) Install and mount the equipment securely to prevent personal injury caused by poor installation or mounting on an earthquake.
- (19) Install an external emergency shutoff circuit to stop operation and interrupt power immediately upon emergency. Emission of smoke or dust may occur due to a fault of a motor or a driver used in combination. For example, if the system is energized with the regenerative control power transistor shorted by failure, overheating of a regenerative resistor installed outside the driver may occur and it may emit smoke and dust. If a regenerative resistor is connected outside a driver, provide a means of detecting overheating such as a thermal protector to shut off power upon detecting abnormal heating.
- (20) Mount the motor, the driver and the peripheral devices on a noncombustible material such as metal.
- (21) Provide correct and secure wiring. Insecure wiring or incorrect wiring may cause runaway or burning of a motor. During wiring work, avoid entry of conductive dust such as wire chippings in an driver.
- (22) Connect cables securely and provide secure insulation on current-carrying parts using insulation aterial.
- (23) Be sure to install a fuseless breaker in a power supply. Be sure to connect grounding terminals and grounding wires. To prevent an electric shock and malfunction, type D grounding (grounding resistance at 100 Ω or lower) or higher grade is recommended.
- (24) Tighten the screws on the terminal block and earth terminal securely at appropriate torque shown in the specifications.
- (25) When building a system by using the safety feature, design it by fully understanding and being compliant with the related safety standards and items described in our operation manual or technical reference.



ATTENTION



- (26) Do not hold cables or motor shaft when carrying the equipment.
- (27) Do not adjust or change drive gains extremely, and do not make operations of the machine instable.
- (28) The equipment may suddenly restart after recovery from shutdown upon a power failure. Keep away from the equipment. Specify settings of the equipment to secure safety for human against such restart operations.
- (29) When the equipment is energized, keep away from the motor and mechanism driven by the motor in case of malfunction.
- (30) Avoid a strong shock to the motor shaft.
- (31) Avoid a strong shock to the product.
- (32) Be sure not to use the electromagnetic contactor installed on the main power supply to start or stop the motor.
- (33) Avoid frequent switching on and off the main power supply of the driver.
- (34) The built-in brake of the motor is used for holding only. Do not use the brake to stop (braking) for securing safety of the equipment.



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- (35) Do not fall or topple over the equipment when carrying or installing.
- (36) Do not climb the motor or do not place a heavy item on the motor.
- (37) Do not block radiation slits of the driver and do not put a foreign matter into the driver.
- (38) Do not use the equipment under direct sunlight. When storing the equipment, avoid direct sunlight and store under conditions of operating temperatures and humidity.
- (39) Be sure not to disassemble or modify the equipment. Disassembling and repair is allowed only for the manufacturer or sales agency authorized by the manufacturer.
- (40) Do not start / stop the motor by the servo signal (SRV-ON). Built-in dynamic brake circuit may be damaged.
- (41) Use a motor and a driver in combination specified by the manufacturer. A customer shall be responsible for verifying performances and safety of combination with other driver.



- (42) A failure of a motor or a combined driver may cause burning of motor, or emission of smoke and dust. Take this into consideration when the application of the machine is clean room related.
- (43) Install the equipment adequately in consideration of output and main unit weight.
- (44) Keep the ambient conditions of an installed motor within a range of allowable ambient temperatures and of allowable humidity.
- (45) Install the equipment by specified procedures and in specified orientation.
- (46) Install the devices by keeping specified distances between a driver and inside control panel or other devices.
- (47) If a motor has an eyebolt, use the eyebolt to carry the motor only. Do not use the eyebolt to carry equipment.
- (48) Connect a relay breaking upon emergency stop in series with a brake control relay.
- (49) For a test run, hold down a motor and disconnect from a mechanical system to verify operations before installing on the equipment.
(A motor must run smoothly at 30 r/min driven with an driver.)
- (50) Verify that an input power supply voltage satisfies the driver specifications before turning on the power and start operation.
An input voltage higher than rated may cause ignition and smoking in the driver, which may cause runaway or burning of a motor in some cases.
- (51) When an alarm status occurs, remove a cause of the problem before restarting.
Careless restarting without removing a cause of problem may cause malfunction or burning of a motor.
- (52) The built-in brake of the motor may not be able to hold due to expiring useful life or a mechanical structure. Install a braking device on the equipment to secure safety.
- (53) Pay attention to heat radiation. The driver generates heat by operating a motor. A driver used in a sealed control box may cause an extreme rise of temperature.
Consider cooling so that an ambient temperature around the driver satisfies an operating range.
- (54) Maintenance and inspection is allowed only for a specializing person.
- (55) Turn off the power when the equipment is not used for a long term.
- (56) The cooling fan in the top side of size H stops for energy saving when driver is servo off. It is not abnormal.
- (57) Allow approx. 10 minutes pause when the dynamic brake is activated during high-speed running.
- (58) Resistor is damaged and the dynamic brake might not work when using it under more critical operating condition.

- Capacitance of the capacitors of power supply rectifier circuit drops over time. To avoid a secondary problem due to a failure, replacement of capacitors is recommended at an interval of approximately 5 years. Commission the manufacturer or sales agency authorized by the manufacturer to replace the parts.
- Be sure to read operating manual (safety guide) that shipped with product before use.



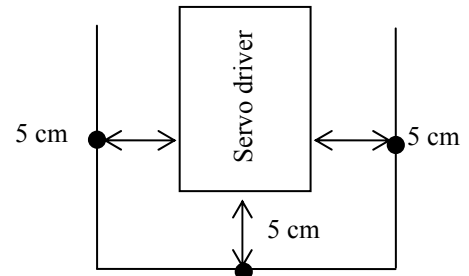
SAFETY PRECAUTIONS

Servo driver's ambient temperature

The driver's service life significantly depends on the ambient temperature.

Make sure that the driver's ambient temperature (at 5 cm distant from the driver) does not exceed the operating temperature range.

Operating temperature range: 0 to 55 °C



We have made the best efforts to ensure quality of this product. However, application of external noise(include radiation) or static electricity, or a defect of the input power supply, wiring or components may cause the servo driver to operate beyond the preset conditions. Therefore, you should exercise thorough caution to ensure safety against an unexpected operation.

11. Life and warranty

11-1 Life expectancy of the driver

The driver has 28000 hours of life expectancy when used continuously under the following conditions,

Definition of the life: Life end shall be defined as the capacitance of the electrolytic capacitor is reduced by 20 % from the ex-factory status.

Condition	[Input power	:	Single phase 100 VAC 50/60 Hz
			:	3 phase 200 VAC 50/60 Hz
		Working temperature.	:	55 degrees C
		Output thrust	:	Constant thrust at rating
		Speed	:	Constant speed at rating

Note that the life varies due to the working conditions.

11-2 Typical life

[1] In-rush current prevention relay

Replace the in-rush current prevention relay when it is activated typically 20000 times. Note that the criteria may vary depending on the environmental and working condition.

[2] Cooling fan

Replace the cooling fan in 10000 to 30000 hours. Note that the criteria may vary depending on the environmental and working condition.

11-3 Warranty period

(1) Warranty period shall be 12 months from the ex-factory date or 18 months from the date of manufacturing.

This Warranty shall be exempted in the following cases,

[1] defects resulting from misuse and/or repair or modification by the customer

[2] defects resulting from drop of the Product or damage during transportation

[3] defects resulting from improper usage of the Product beyond the Specifications

[4] defects resulting from fire, earthquake, lightening, flood, damage from salt, abnormal voltage or other Act of God, or other disaster.

[5] defects resulting from the intrusion of foreign material to the Product, such as water, oil or metallic particles.

This Warranty shall be exempted when the life of the components described in 7-2 exceeds its typical life.

(2) Warranty scope

Panasonic warrants the replacement of the defected parts of the Product or repair of them when the defects of the Product occur during the Warranty Period, and when the defects are under Panasonic responsibility. This Warranty only covers the Product itself and does not cover any damage incurred by such defects.

12. Others

- Precautions for export of this product and the equipment incorporating this product
If the end user or end purpose of this product relates to military affairs, armament and so on, this product may be subject to the export regulations prescribed in "Foreign Exchange and Foreign Trade Control Law". To export this product, take thorough examination, and follow the required export procedure.
- We cannot warrant this product, if it is used beyond the specified operating conditions.
- Compliance with the relevant standards should be considered by the user.
- The final decision on the compatibility with the installations and components at the user's site, in terms of structure, dimensions, characteristics and other conditions, should be made by the user.
- When using this product in your equipment, be careful about the compatibility with the servomotor and the servo driver to be used together.
- For performance improvement or other reasons, some components of this product may be modified in a range that satisfies the specifications given in this document.
- Any specification change shall be based on our authorized specifications or the documents presented by the user. If a specification change may affect the functions and characteristics of this product, we will produce a trial product, and conduct examination in advance. Note that the produce price may be changed with a change in its specifications.
- We have made the best efforts to ensure the product quality. However, complete equipment at customer's site may malfunction due to a failure of this product. Therefore, take precautions by providing fail-safe design at customer's site, and ensure safety within the operating range of the work place.
- Failure of this product depending on its content, may generate smoke of about one cigarette.
Take this into consideration when the application of the machine is clean room related.
- When the equipment runs without connecting the servomotor's shaft electrically to ground, electrolytic corrosion may occur on the motor bearing and the bearing noise may get louder depending on the equipment and installing environment. So, customer is responsible to check and verify it.
- A customer must verify and inspect the equipment. Please be careful when using in an environment with high concentrations of sulphur or sulphuric gases, as sulphuration can lead to disconnection from the chip resistor or a poor contact connection.
- Do not use benzene, thinner, alcohol, and acid or alkaline detergent, because they can discolor and damage the packaging chassis.
- Apply adequate tightening torque to the product mounting screw by taking into consideration strength of the screw and the characteristics of material to which the product is installed. Over-tightening can damage the screw and/or material; under-tightening can result in loosening. Example) Steel screw(M5) into steel section: 2.7-3.3Nm.
- Take care to avoid inputting a supply voltage which significantly exceeds the rated range to the power supply of this product. Failure to heed this caution may result in damage to the internal parts, causing smoking and/or a fire and other trouble.
- When discard batteries, provide insulation using a tape, etc. and discard the batteries abiding by a municipal law.
- When discarding the equipment, process the item as an industrial waste.

13. Specification for each model

Model	MADLT01SF	MADLT11SF	MADLT05SF	MADLT15SF
Power supply input	Single phase 100 V	Single phase 100 V	Single phase/ 3 phase 200 V	Single phase/ 3 phase 200 V
Maximum instantaneous output current	10 A	10 A	10 A	10 A
Maximum continuous output current	5 A	7.5 A	5 A	7.5 A
Rotary encoder feedback signal	Resolution: 8388608 P/r	Resolution: 8388608 P/r	Resolution: 8388608 P/r	Resolution: 8388608 P/r
Regenerative discharge resistor	Externally connected	Externally connected	Externally connected	Externally connected
Auto gain tuning function	Provided	Provided	Provided	Provided
Dynamic brake function	Provided	Provided	Provided	Provided
Absolute system	Available ^{NOTE)}	Available ^{NOTE)}	Available ^{NOTE)}	Available ^{NOTE)}
Ambient temperature main power supply cable	0 - 55 °C	0 - 55 °C	0 - 55 °C	0 - 55 °C
Control power cable	HVSF 0.75 mm ²	HVSF 0.75 mm ²	HVSF 0.75 mm ²	HVSF 0.75 mm ²
	AWG18	AWG18	AWG18	AWG18
Main power supply cable	HVSF 0.75 - 2.0 mm ²	HVSF 0.75 - 2.0 mm ²	HVSF 0.75 - 2.0 mm ²	HVSF 0.75 - 2.0 mm ²
	AWG14 - 18	AWG14 - 18	AWG14 - 18	AWG14 - 18
Ground cable	HVSF 2.0 mm ²	HVSF 2.0 mm ²	HVSF 2.0 mm ²	HVSF 2.0 mm ²
	AWG14	AWG14	AWG14	AWG14
Motor cable	HVSF 0.75 - 2.0 mm ²	HVSF 0.75 - 2.0 mm ²	HVSF 0.75 - 2.0 mm ²	HVSF 0.75 - 2.0 mm ²
	AWG14 - 18	AWG14 - 18	AWG14 - 18	AWG14 - 18
Inrush current (Main power supply) (*1)	Max. 7 A	Max. 7 A	Max. 14 A	Max. 14 A
Inrush current (Control power supply) (*1)	Max. 14 A	Max. 14 A	Max. 28 A	Max. 28 A
Weight	Approx 0.8 kg	Approx 0.8 kg	Approx 0.8 kg	Approx 0.8 kg
Dimensions	Size A	Size A	Size A	Size A

(*1) Current values were calculated on the basis of the power supply input described above, assuming a voltage of 100 V or 200 V.

(Note) The absolute encoder backup battery is externally connected.

<Caution>

The lithium-metal battery is used as a backup battery.

There are restrictions for transportation of the lithium-metal batteries by an international transport rule of dangerous goods etc.

Please inquire in detail through the purchase shop.

Model	MBDLT21SF	MBDLT25SF	MCDLT31SF	MCDLT35SF
Power supply input	Single phase 100 V	Single phase/ 3 phase 200 V	Single phase 100 V	Single phase/ 3 phase 200 V
Maximum instantaneous output current	15 A	15 A	30 A	30 A
Maximum continuous output current	10 A	10 A	20 A	20 A
Rotary encoder feedback signal	Resolution: 8388608 P/r	Resolution: 8388608 P/r	Resolution: 8388608 P/r	Resolution: 8388608 P/r
Regenerative discharge resistor	Externally connected	Externally connected	Built-in	Built-in
Auto gain tuning function	Provided	Provided	Provided	Provided
Dynamic brake function	Provided	Provided	Provided	Provided
Absolute system	Available ^{NOTE)}	Available ^{NOTE)}	Available ^{NOTE)}	Available ^{NOTE)}
Ambient temperature main power supply cable	0 – 55 °C	0 – 55 °C	0 – 55 °C	0 – 55 °C
Control power cable	HVSF 0.75 mm ² AWG18	HVSF 0.75 mm ² AWG18	HVSF 0.75 mm ² AWG18	HVSF 0.75 mm ² AWG18
Main power supply cable	HVSF 0.75 - 2.0 mm ² AWG14 - 18	HVSF 0.75 - 2.0 mm ² AWG14 - 18	HVSF 0.75 - 2.0 mm ² AWG14 - 18	HVSF 0.75 - 2.0 mm ² AWG14 - 18
Ground cable	HVSF 2.0 mm ² AWG14	HVSF 2.0 mm ² AWG14	HVSF 2.0 mm ² AWG14	HVSF 2.0 mm ² AWG14
Motor cable	HVSF 0.75 - 2.0 mm ² AWG14 - 18	HVSF 0.75 - 2.0 mm ² AWG14 - 18	HVSF 0.5 - 2.0 mm ² AWG14 - 18	HVSF 0.75 - 2.0 mm ² AWG14 - 18
Inrush current (Main power supply) (*1)	Max. 7 A	Max. 14 A	Max. 15 A	Max. 29 A
Inrush current (Control power supply) (*1)	Max. 14 A	Max. 28 A	Max. 14 A	Max. 28 A
Weight	Approx 1.0 kg	Approx 1.0 kg	Approx 1.6 kg	Approx 1.6 kg
Dimensions	Size B	Size B	Size C	Size C

(*1) Current values were calculated on the basis of the power supply input described above, assuming a voltage of 100 V or 200 V.

(Note) The absolute encoder backup battery is externally connected.

<Caution>

The lithium-metal battery is used as a backup battery.

There are restrictions for transportation of the lithium-metal batteries by an international transport rule of dangerous goods etc.

Please inquire in detail through the purchase shop.

Model	MDDL45SF	MDDL55SF	MEDLT83SF
Power supply input	Single phase/ 3 phase 200 V	Single phase/ 3 phase 200 V	3 phase 200V
Maximum instantaneous output current	30 A	50 A	75 A
Maximum continuous output current	30 A	40 A	64 A
Rotary encoder feedback signal	Resolution: 8388608 P/r	Resolution: 8388608 P/r	Resolution: 8388608 P/r
Regenerative discharge resistor	Built-in	Built-in	Built-in
Auto gain tuning function	Provided	Provided	Provided
Dynamic brake function	Provided	Provided	Provided
Absolute system	Available ^{NOTE)}	Available ^{NOTE)}	Available ^{NOTE)}
Ambient temperature main power supply cable	0 – 55 °C	0 – 55 °C	0 – 55 °C
Control power cable	HVSF 0.75 mm ²	HVSF 0.75 mm ²	HVSF 0.75 mm ²
	AWG18	AWG18	AWG18
Main power supply cable	HVSF 2.0 mm ²	HVSF 2.0 mm ²	HVSF 2.0 mm ²
	AWG14	AWG14	AWG14
Ground cable	HVSF 2.0 mm ²	HVSF 2.0 mm ²	HVSF 2.0 mm ²
	AWG14	AWG14	AWG14
Motor cable	HVSF 2.0 mm ²	HVSF 2.0 mm ²	HVSF 2.0 mm ²
	AWG14	AWG14	AWG14
Inrush current (Main power supply) (*1)	Max. 29 A	Max. 29 A	Max. 29 A
Inrush current (Control power supply) (*1)	Max. 28 A	Max. 28 A	Max. 14 A
Weight	Approx 1.8 kg	Approx 1.8 kg	Approx 2.7 kg
Dimensions	Size D	Size D	Size E

(*1) Current values were calculated on the basis of the power supply input described above, assuming a voltage of 200 V.

(Note) The absolute encoder backup battery is externally connected.

<Caution>

The lithium-metal battery is used as a backup battery.

There are restrictions for transportation of the lithium-metal batteries by an international transport rule of dangerous goods etc.

Please inquire in detail through the purchase shop.

Model	MFDLTSF	MFDLTSF
Power supply input	3 phase 200 V	3 phase 200 V
Maximum instantaneous output current	100 A	150 A
Maximum continuous output current	90 A	120 A
Rotary encoder feedback signal	Resolution: 8388608 P/r	Resolution: 8388608 P/r
Regenerative discharge resistor	Built-in	Built-in
Auto gain tuning function	Provided	Provided
Dynamic brake function	Provided	Provided
Absolute system	Available ^(NOTE)	Available ^(NOTE)
Ambient temperature main power supply cable	0 – 55 °C	0 – 55 °C
Control power cable	HVSF 0.75 mm ²	HVSF 0.75 mm ²
	AWG18	AWG18
Main power supply cable	HVSF 3.5 mm ²	HVSF 3.5 mm ²
	AWG12	AWG12
Ground cable	HVSF 3.5 mm ²	HVSF 3.5 mm ²
	AWG12	AWG12
Motor cable	HVSF 3.5 mm ²	HVSF 3.5 mm ²
	AWG12	AWG12
Inrush current (Main power supply) (*1)	Max. 22 A	Max. 22 A
Inrush current (Control power supply) (*1)	Max. 14 A	Max. 14 A
Weight	Approx 4.8 kg	Approx 4.8 kg
Dimensions	Size F	Size F

(*1) Current values were calculated on the basis of the power supply input described above, assuming a voltage of 200 V.

(Note) The absolute encoder backup battery is externally connected.

<Caution>

The lithium-metal battery is used as a backup battery.

There are restrictions for transportation of the lithium-metal batteries by an international transport rule of dangerous goods etc.

Please inquire in detail through the purchase shop.

■ The maximum value of torque limit setup

No.SX-DSV03025

Size	Model	Applicable motor	The maximum value of torque limit setup	Size	Model	Applicable motor	The maximum value of torque limit setup		
A	MADLT01SF	MSMF5AZL1**	300	D	MDDL55SF	MHMF092L1**	350		
		MHMF5AZL1**	350			MSMF102L1**	300		
	MADLT11SF	MSMF011L1**	300			MGMF132L1**	281		
		MQMF011L1**	350			MSMF152L1**	300		
		MHMF011L1**	350			MDMF152L1**	300		
	MADLT05SF	MSMF5AZL1**	300			MHMF152L1**	300		
		MHMF5AZL1**	350			E	MEDLT83SF	MGMF182L1**	251
		MSMF012L1**	300					MSMF202L1**	300
		MQMF012L1**	350	MDMF202L1**	300				
	MHMF012L1**	350	MHMF202L1**	300					
	MADLT15SF	MSMF022L1**	300	F	MFDLTA3SF	MSMF302L1**	300		
		MQMF022L1**	350			MDMF302L1**	300		
		MHMF022L1**	350			MHMF302L1**	300		
	B	MBDLT21SF	MSMF021L1**	300	MFDLTB3SF	MGMF292L1**	245		
			MQMF021L1**	350		MSMF402L1**	300		
			MHMF021L1**	350		MDMF402L1**	300		
MBDLT25SF		MSMF042L1**	300	MHMF402L1**		300			
		MQMF042L1**	350	MGMF442L1**		250			
		MHMF042L1**	350	MSMF502L1**		300			
C		MCDLT31SF	MSMF041L1**	300		MDMF502L1**	300		
			MQMF041L1**	350		MHMF502L1**	300		
			MHMF041L1**	350		/			
	MCDLT35SF	MSMF082L1**	300						
		MHMF082L1**	350						
	D	MDDL45SF	MGMF092L1**	264					
MSMF092L1**			300						
MDMF102L1**			300						
MHMF102L1**			300						

PARAMETER				MODEL		MINAS-A6 (SF) series common															
Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value						
0	0	Reference direction	1	1	12	Torque feed forward gain	100.0	1	43	For manufacturer use	250	1	74	For manufacturer use	Size A-C 0.84 Size D-F 1.26						
	1	Control mode	0		13	Torque feed forward filter	0.00		44	For manufacturer use	100.0		75	For manufacturer use	250	2	26	Notch depth 5	0		
	2	RTAT mode	1		14	Second gain enable	1		45	For manufacturer use	100.0		76	For manufacturer use	100.0		27	Anti-vibration width configuration 1	0.00		
	3	Mechanical stiffness for RTAT	Size A-C 13 Size D-F 11		15	Gain switching mode for position	0		46	For manufacturer use	0.0		77	For manufacturer use	100.0		28	Anti-vibration width configuration 2	0.00		
	4	Inertia ratio	250		16	Gain switching delay for position	1.0		47	For manufacturer use	Size A-C 48.0 Size D-F 32.0		78	For manufacturer use	0.0		29	Anti-vibration width configuration 3	0.00		
	5	Command pulse mode	0		17	Gain switching level for position	0		48	For manufacturer use	Size A-C 27.0 Size D-F 18.0		2	0	Adaptive filter mode		0	30	Anti-vibration width configuration 4	0.00	
	6	Command pulse counting direction	0		18	Gain switching hysteresis for position	0		49	For manufacturer use	Size A-C 21.0 Size D-F 31.0			1	1st notch frequency		5000	31	For manufacturer use	0	
	7	Command pulse input mode setting	1		19	Position loop gain switching time	1.0		50	For manufacturer use	Size A-C 0.84 Size D-F 1.26			2	Notch width 1		2	32	For manufacturer use	0	
	8	Command pulse resolution	10000		20	Gain switching mode for velocity	0		51	For manufacturer use	250			3	Notch depth 1		0	33	For manufacturer use	0	
	9	First command division/multiplication numerator	0		21	Gain switching delay for velocity	0.0		52	For manufacturer use	100.0			4	2nd notch frequency		5000	34	For manufacturer use	0	
	10	Command scaling denominator	10000		22	Gain switching level for velocity	0		53	For manufacturer use	100.0			5	Notch width 2		2	35	For manufacturer use	0	
	11	Number of output pulses per motor revolution	2500		23	Gain switching hysteresis for velocity	0		54	For manufacturer use	0.0			6	Notch depth 2		0	36	For manufacturer use	0	
	12	Output pulse logic / select output source	0		24	Gain switching mode for torque	0		55	For manufacturer use	Size A-C 48.0 Size D-F 32.0			7	Third notch frequency		5000	37	For manufacturer use	0	
	13	Torque limit 1	500		25	Gain switching delay for torque	0.0		56	For manufacturer use	Size A-C 27.0 Size D-F 18.0			8	Notch width 3		2	3	0	Velocity command type	0
	14	Max position deviation	100000		26	Gain switching level for torque	0		57	For manufacturer use	Size A-C 21.0 Size D-F 31.0			9	Notch depth 3		0		1	Velocity command direction source	0
	15	Absolute encoder setting	1		27	Gain switching hysteresis for torque	0		58	For manufacturer use	Size A-C 0.84 Size D-F 1.26			10	Notch frequency 4		5000		2	Input gain of speed command	500
	16	Regen resistor configuration	Size A,B 3 Size C-F 0		28	For manufacturer use	100.0		59	For manufacturer use	250			11	Notch width 4		2		3	Reversal of speed command input	1
	17	External regenerative resistor selection	0		29	For manufacturer use	100.0		60	For manufacturer use	100.0			12	Notch depth 4		0		4	1st speed	0
18	For manufacturer use	0	30	For manufacturer use	0.0	61	For manufacturer use	100.0	13	Anti-vibration filter switching mode	0	5		2nd speed	0						
1	0	Position loop gain 1	Size A-C 48.0 Size D-F 32.0	31	For manufacturer use	Size A-C 48.0 Size D-F 32.0	62	For manufacturer use	0.0	14	Anti-vibration frequency 1	0.0		6	3rd speed	0					
	1	Velocity loop proportional gain 1	Size A-C 27.0 Size D-F 18.0	32	For manufacturer use	Size A-C 27.0 Size D-F 18.0	63	For manufacturer use	Size A-C 48.0 Size D-F 32.0	15	Anti-vibration filter configuration 1	0.0		7	4th speed	0					
	2	Velocity loop integral time constant 1	Size A-C 21.0 Size D-F 31.0	33	For manufacturer use	Size A-C 21.0 Size D-F 31.0	64	For manufacturer use	Size A-C 27.0 Size D-F 18.0	16	Anti-vibration frequency 2	0.0		8	5th speed	0					
	3	Velocity detection filter 1	0	34	For manufacturer use	Size A-C 0.84 Size D-F 1.26	65	For manufacturer use	Size A-C 21.0 Size D-F 31.0	17	Anti-vibration filter configuration 2	0.0		9	6th speed	0					
	4	Torque filter 1	Size A-C 0.84 Size D-F 1.26	35	For manufacturer use	250	66	For manufacturer use	Size A-C 0.84 Size D-F 1.26	18	Anti-vibration frequency 3	0.0	10	7th speed	0						
	5	Position loop gain 2	Size A-C 48.0 Size D-F 32.0	36	For manufacturer use	100.0	67	For manufacturer use	250	19	Anti-vibration filter configuration 3	0.0	11	8th speed	0						
	6	Velocity loop proportional gain 2	Size A-C 27.0 Size D-F 18.0	37	For manufacturer use	100.0	68	For manufacturer use	100.0	20	Anti-vibration frequency 4	0.0	12	Acceleration time	0						
	7	Velocity loop integral time constant 2	Size A-C 21.0 Size D-F 31.0	38	For manufacturer use	0.0	69	For manufacturer use	100.0	21	Anti-vibration filter configuration 4	0.0	13	Deceleration time	0						
	8	Velocity detection filter 2	0	39	For manufacturer use	Size A-C 48.0 Size D-F 32.0	70	For manufacturer use	0.0	22	First order filter time constant for position command	Size A-C 9.2 Size D-F 13.9	14	S-curve accel/decel time	0						
	9	Torque filter 2	Size A-C 0.84 Size D-F 1.26	40	For manufacturer use	Size A-C 27.0 Size D-F 18.0	71	For manufacturer use	Size A-C 48.0 Size D-F 32.0	23	FIR filter time constant for position command	1.0	15	Speed zero clamp select	0						
	10	Velocity feed forward gain	100.0	41	For manufacturer use	Size A-C 21.0 Size D-F 31.0	72	For manufacturer use	Size A-C 27.0 Size D-F 18.0	24	5th notch frequency	5000	16	Speed zero clamp level	30						
11	Velocity feed forward filter	0.00	42	For manufacturer use	Size A-C 0.84 Size D-F 1.26	73	For manufacturer use	Size A-C 21.0 Size D-F 31.0	25	Notch width 5	2	17	Selection of torque command	0							
												18	Torque command direction selection	0							

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.

Ex) Pr6.24 Disturbance observer filter ... Value of Panterm : 0.53 / Value of parameter-file : 53

*2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"

PARAMETER				MODEL	MINAS-A6 (SF) series common														
Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value				
3	19*1	Input gain of torque command	3.0	4	20	For manufacturer use	0	5	8	LV trip selection at main power AC off	1	5	39	Modbus response waiting time	0				
	20	Input reversal of torque command	0		21	Analog monitor output type	0		9	Main power AC off detecting time	70		40	Modbus communication timeout time	0	6	14	Immediate stop time for alarm	200
	21	Speed limit value 1	0		22	Analog input 1 (AI1) offset setup	0		10	Alarm action	0		41	For manufacturer use	0	15	15	2nd overspeed level	0
	22	Speed limit value 2	0		23*1	Analog input 1 (AI1) filter	0.00		11	Immediate stop torque limit	0		42	Modbus broadcast setting	0	16	16	For manufacturer use	0
	23	External scale selection	0		24*1	Analog input 1 (AI1) overvoltage setup	0.0		12	Overload level	0		43	No use	-	17	17	Front panel parameter write selection	0
	24	Numerator of external scale division	0		25*1	Analog input 2 (AI2) offset setup	0		13	Overspeed level	0		44	No use	-	18*1	18	Start-up wait	0.0
	25	Denominator of external scale division	10000		26*1	Analog input 2 (AI2) filter	0.00		14	Motor movable range	1.0		45*1	Quadrant projection positive direction compensation value	0.0	19	19	Encoder Z-phase setting	0
	26	Reversal of external scale direction	0		27*1	Analog input 2 (AI2) overvoltage setup	0.0		15	Control input signal read setting	0		46*1	Quadrant projection negative direction compensation value	0.0	20	20	Z-phase setup of external scale	0
	27	External scale Z-phase disconnection detection	0		28	Analog input 3 (AI3) offset setup	0		16	Alarm clear input (A-CLR) setting	0		47*1	Quadrant projection compensation delay time	0	21	21	Serial absolute external scale Z phase setup	0
28	Hybrid deviation excess setup	16000	29*1	Analog input 3 (AI3) filter	0.00	17	Counter clear input (CL) setting	3	48*1	Quadrant projection compensation filter setting L	0.00	22	22	A/B-phase external scale pulse output selection	0				
29	Hybrid deviation clear setup	0	30*1	Analog input 3 (AI3) overvoltage setup	0.0	18	Command pulse prohibition input (INH) disable setting	1	49*1	Quadrant projection compensation filter setting H	0.00	23	23	Disturbance torque compensation gain	0				
4	0	SI1 input assignment	8553090	31	In-position range	10	19	Command pulse prohibition input (INH) read setting	0	50	For manufacturer use	0	24*1	24	Disturbance observer filter	0.53			
	1	SI2 input assignment	8487297	32	In-position output configuration	0	20	Position units	0	51	For manufacturer use	0	25	25	No use	-			
	2	SI3 input assignment	9539850	33	INP hold time	0	21	Torque limit selection	1	52	For manufacturer use	0	26	26	No use	-			
	3	SI4 input assignment	394758	34	Zero speed	50	22*7	Torque limit 2	500	53	For manufacturer use	0	27	27	Warning latch time	5			
	4	SI5 input assignment	4108	35	Speed coincidence range	50	23	Torque limit switch setup 1	0	54	For manufacturer use	0	28	28	Special function selection	0			
	5	SI6 input assignment	197379	36	At-speed	1000	24	Torque limit switch setup 2	0	55	For manufacturer use	0	29	29	No use	-			
	6	SI7 input assignment	3847	37	Stop time mechanical brake operation setting	0	25*2	Positive torque limit for external input	500	0	Analog torque feed forward conversion gain	0.0	30	30	For manufacturer use	0			
	7	SI8 input assignment	263172	38	Run time mechanical brake operation setting	0	26*7	Negative torque limit for external input	500	1	No use	-	31	31	Real time auto-gain tuning estimated speed	1			
	8	SI9 input assignment	328965	39	Brake clear speed setting	30	27*1	Input gain of analog torque limit	3.0	2	Excessive speed deviation	0	32	32	Real time auto-gain tuning customize	0			
	9	SI10 input assignment	3720	40	Warning output selection 1	0	28	LED Initial display	1	3	No use	-	33	33	For manufacturer use	1000			
	10	SO1 output assignment	197379	41	Warning output selection 2	0	29	Baud rate of RS232	2	4	JOG speed	300	34*1	34	Hybrid vibration suppressor gain	0.0			
	11	SO2 output assignment	131586	42	Positioning completion range 2	10	30	Baud rate of RS485	2	5	Position gain 3 valid time	0.0	35*1	35	Hybrid vibration suppressor filter	0.10			
	12	SO3 output assignment	65793	5	0	2nd command frequency division multiplication	0	31	Axis number	1	6	Position gain 3 scaling factor	100	36	36	Dynamic brake operation input	0		
	13	SO4 output assignment	328964		1	3rd command frequency division multiplication	0	32	Maximum command pulse input setting	4000	7	Torque command addition	0	37	37	Oscillation detection threshold	0.0		
	14	SO5 output assignment	460551		2	Command scaling numerator 4	0	33	Enable pulse regeneration output limit	0	8	Positive torque compensation	0	38	38	Warning mask setting	4		
	15	SO6 output assignment	394758		3	Output pulse scaling denominator	0	34	For manufacturer use	4	9	Negative torque compensation	0	39	39	For manufacturer use	0		
	16	Analog monitor 1 type	0		4	Overtravel input configuration	1	35	Front panel lock	0	10	Function expansion settings 1	16	40	40	No use	-		
	17	Analog monitor 1 output gain	0		5	Overtravel action	0	36	For manufacturer use	0	11	Current response setup	100	41	41	Anti-vibration depth 1	0		
	18	Analog monitor 2 types	4		6	Servo off action	0	37	Modbus connection setting	0	12	No use	-	42*1	42	Two-stage torque filter time constant	0.00		
19	Analog monitor 2 output gain	0	7	Sequence at main power AC off	0	38	Modbus communication setting	0	13	2nd inertia ratio	250	43	43	Two-stage torque filter Attenuation term	0				

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.

Ex) Pr6.24 Disturbance observer filter ... Value of Panaterm : 0.53 / Value of parameter-file : 53

*2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"

PARAMETER	MODEL	MINAS-A6 (SF) series common
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Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value						
6	45	No use	-	6	76	Number of load estimation	0	7	30	For manufacturer use	0	7	61	No use	-	7	92	For manufacturer use	0		
	46	No use	-		7	0	For manufacturer use		0	31	For manufacturer use		0	62	No use		-	93	For manufacturer use	0	
	47	Function expansion settings 2	1		1	1	For manufacturer use		0	32	For manufacturer use		0	63	No use		-	8	0	For manufacturer use	0
	48	Adjust filter	Size A 1.1 / B-C 1.2 / D-F 1.7		2	2	No use		-	33	For manufacturer use		0	64	No use		-	1	1	For manufacturer use	100
	49	Command response / tuning filter damping	15		3	3	For manufacturer use		0	34	For manufacturer use		0	65	No use		-	2	2	For manufacturer use	0
	50	Viscous friction compensation gain	0.0		4	4	For manufacturer use		0	35	For manufacturer use		0	66	No use		-	3	3	For manufacturer use	0
	51	Immediate cessation completion wait time	0		5	5	For manufacturer use		0	36	For manufacturer use		0	67	No use		-	4	4	For manufacturer use	100
	52	For manufacturer use	0		6	6	For manufacturer use		0	37	For manufacturer use		0	68	No use		-	5	5	For manufacturer use	0
	53	For manufacturer use	0		7	7	For manufacturer use		0	38	For manufacturer use		0	69	No use		-	6	6	No use	-
	54	For manufacturer use	0		8	8	For manufacturer use		0	39	For manufacturer use		0	70	No use		-	7	7	No use	-
	55	No use	-		9	9	For manufacturer use		0	40	No use		-	71	No use		-	8	8	No use	-
	56	No use	-		10	10	For manufacturer use		0	41	For manufacturer use		0	72	No use		-	9	9	No use	-
	57	Torque saturation anomaly detection time	0		11	11	For manufacturer use		0	42	No use		-	73	No use		-	10	10	For manufacturer use	0
	58	No use	-		12	12	For manufacturer use		0	43	No use		-	74	No use		-	11	11	No use	-
	59	No use	-		13	13	For manufacturer use		0	44	No use		-	75	No use		-	12	12	For manufacturer use	0
	60	Anti-vibration depth 2	0		14	14	Main power turn-off warning detection time		0	45	No use		-	76	No use		-	13	13	For manufacturer use	0
	61	Resonance frequency 1	0.0		15	15	For manufacturer use		0	46	No use		-	77	No use		-	14	14	For manufacturer use	0
	62	Resonance damping ratio 1	0		16	16	For manufacturer use		0	47	No use		-	78	No use		-	15	15	For manufacturer use	0
	63	Antiresonant frequency 1	0.0		17	17	No use		-	48	No use		-	79	No use		-	16	16	No use	-
	64	Anti resonance damping ratio 1	0		18	18	No use		-	49	No use		-	80	No use		-	17	17	No use	-
	65	Response frequency 1	0.0		19	19	No use		-	50	No use		-	81	No use		-	18	18	No use	-
	66	Resonance frequency 2	0.0		20	20	For manufacturer use		0	51	No use		-	82	No use		-	19	19	For manufacturer use	0
	67	Resonance damping ratio 2	0		21	21	For manufacturer use		1	52	No use		-	83	No use		-	14	0	For manufacturer use	0
	68	Antiresonant frequency 2	0.0		22	22	For manufacturer use		0	53	No use		-	84	No use		-	1	1	For manufacturer use	0
	69	Anti resonance damping ratio 2	0		23	23	For manufacturer use		0	54	No use		-	85	No use		-	2	2	For manufacturer use	0
	70	Response frequency 2	0.0		24	24	For manufacturer use		0	55	No use		-	86	No use		-	3	3	For manufacturer use	0
	71	Anti-vibration depth 3	0		25	25	For manufacturer use		0	56	No use		-	87	For manufacturer use		0	4	4	For manufacturer use	0
	72	Anti-vibration depth 4	0		26	26	For manufacturer use		0	57	No use		-	88	No use		-	5	5	For manufacturer use	0
	73	Load estimation filter	0.00		27	27	For manufacturer use		0	58	No use		-	89	No use		-	6	6	For manufacturer use	0
74	Torque compensating frequency 1	0.0	28	28	For manufacturer use	0	59	No use	-	90	No use	-	7	7	For manufacturer use	0					
75	Torque compensating frequency 2	0.0	29	29	For manufacturer use	0	60	No use	-	91	For manufacturer use	0	8	8	For manufacturer use	0					

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.

Ex) Pr6.24 Disturbance observer filter ... Value of Panaterm : 0.53 / Value of parameter-file : 53

*2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"

PARAMETER

MODEL MINAS-A6 (SF) series common

Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value					
14	9	For manufacturer use	0	15	10	No use	-	56	5	Block action data 002	0	56	36	Block action command 018	0					
	10	For manufacturer use	0		11	No use	-		6	Block action command 003	0		37	Block action data 018	0	68	Block action command 034	0		
	11	For manufacturer use	0		12	No use	-		7	Block action data 003	0		38	Block action command 019	0	69	Block action data 034	0		
	12	For manufacturer use	0		13	No use	-		8	Block action command 004	0		39	Block action data 019	0	70	Block action command 035	0		
	13	For manufacturer use	0		14	No use	-		9	Block action data 004	0		40	Block action command 020	0	71	Block action data 035	0		
	14	For manufacturer use	0		15	No use	-		10	Block action command 005	0		41	Block action data 020	0	72	Block action command 036	0		
	15	For manufacturer use	0		16	For manufacturer use	2		11	Block action data 005	0		42	Block action command 021	0	73	Block action data 036	0		
	16	For manufacturer use	0		17	For manufacturer use	4		12	Block action command 006	0		43	Block action data 021	0	74	Block action command 037	0		
	17	For manufacturer use	0		18	No use	-		13	Block action data 006	0		44	Block action command 022	0	75	Block action data 037	0		
	18	For manufacturer use	0		19	No use	-		14	Block action command 007	0		45	Block action data 022	0	76	Block action command 038	0		
	19	For manufacturer use	0		20	No use	-		15	Block action data 007	0		46	Block action command 023	0	77	Block action data 038	0		
	20	For manufacturer use	0		21	No use	-		16	Block action command 008	0		47	Block action data 023	0	78	Block action command 039	0		
	21	For manufacturer use	0		22	No use	-		17	Block action data 008	0		48	Block action command 024	0	79	Block action data 039	0		
	22	For manufacturer use	0		23	No use	-		18	Block action command 009	0		49	Block action data 024	0	80	Block action command 040	0		
	23	For manufacturer use	0		24	No use	-		19	Block action data 009	0		50	Block action command 025	0	81	Block action data 040	0		
	24	For manufacturer use	0		25	No use	-		20	Block action command 010	0		51	Block action data 025	0	82	Block action command 041	0		
	25	For manufacturer use	0		26	No use	-		21	Block action data 010	0		52	Block action command 026	0	83	Block action data 041	0		
	26	For manufacturer use	0		27	No use	-		22	Block action command 011	0		53	Block action data 026	0	84	Block action command 042	0		
	27	For manufacturer use	0		28	No use	-		23	Block action data 011	0		54	Block action command 027	0	85	Block action data 042	0		
	28	For manufacturer use	0		29	No use	-		24	Block action command 012	0		55	Block action data 027	0	86	Block action command 043	0		
	29	For manufacturer use	0		30	For manufacturer use	6		25	Block action data 012	0		56	Block action command 028	0	87	Block action data 043	0		
	15	0	For manufacturer use		0	31	For manufacturer use		5	26	Block action command 013		0	57	Block action data 028	0	88	Block action command 044	0	
		1	No use		-	32	No use		-	27	Block action data 013		0	58	Block action command 029	0	89	Block action data 044	0	
		2	No use		-	33	For manufacturer use		0	28	Block action command 014		0	59	Block action data 029	0	90	Block action command 045	0	
		3	No use		-	34	For manufacturer use		0	29	Block action data 014		0	60	Block action command 030	0	91	Block action data 045	0	
		4	No use		-	35	For manufacturer use		0	30	Block action command 015		0	61	Block action data 030	0	92	Block action command 046	0	
		5	No use		-	56	0		Block action command 000	0	31		Block action data 015	0	62	Block action command 031	0	93	Block action data 046	0
		6	No use		-		1		Block action data 000	0	32		Block action command 16	0	63	Block action data 031	0	94	Block action command 47	0
		7	No use		-		2		Block action command 001	0	33		Block action data 016	0	64	Block action command 032	0	95	Block action data 047	0
8		No use	-	3	Block action data 001		0	34	Block action command 017	0	65	Block action data 032	0	96	Block action command 048	0				
9		No use	-	4	Block action command 002		0	35	Block action data 017	0	66	Block action command 033	0	97	Block action data 048	0				

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.

Ex) Pr6.24 Disturbance observer filter ... Value of Panaterm : 0.53 / Value of parameter-file : 53

*2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"

PARAMETER				MODEL		MINAS-A6 (SF) series common												
Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value			
56	98	Block action command 049	0	57	1	Block action data 064	0	57	32	Block action command 080	0	57	63	Block action data 095	0			
	99	Block action data 049	0		2	Block action command 065	0		33	Block action data 080	0		64	Block action command 096	0	94	Block action command 111	0
	100	Block action command 050	0		3	Block action data 065	0		34	Block action command 081	0		65	Block action data 096	0	95	Block action data 111	0
	101	Block action data 050	0		4	Block action command 066	0		35	Block action data 081	0		66	Block action command 097	0	96	Block action command 112	0
	102	Block action command 051	0		5	Block action data 066	0		36	Block action command 082	0		67	Block action data 097	0	97	Block action data 112	0
	103	Block action data 051	0		6	Block action command 067	0		37	Block action data 082	0		68	Block action command 098	0	98	Block action command 113	0
	104	Block action command 052	0		7	Block action data 067	0		38	Block action command 083	0		69	Block action data 098	0	99	Block action data 113	0
	105	Block action data 052	0		8	Block action command 068	0		39	Block action data 083	0		70	Block action command 099	0	100	Block action command 114	0
	106	Block action command 053	0		9	Block action data 068	0		40	Block action command 084	0		71	Block action data 099	0	101	Block action data 114	0
	107	Block action data 053	0		10	Block action command 069	0		41	Block action data 084	0		72	Block action command 100	0	102	Block action command 115	0
	108	Block action command 054	0		11	Block action data 069	0		42	Block action command 085	0		73	Block action data 100	0	103	Block action data 115	0
	109	Block action data 054	0		12	Block action command 070	0		43	Block action data 085	0		74	Block action command 101	0	104	Block action command 116	0
	110	Block action command 055	0		13	Block action data 070	0		44	Block action command 086	0		75	Block action data 101	0	105	Block action data 116	0
	111	Block action data 055	0		14	Block action command 071	0		45	Block action data 086	0		76	Block action command 102	0	106	Block action command 117	0
	112	Block action command 056	0		15	Block action data 071	0		46	Block action command 087	0		77	Block action data 102	0	107	Block action data 117	0
	113	Block action data 056	0		16	Block action command 072	0		47	Block action data 087	0		78	Block action command 103	0	108	Block action command 118	0
	114	Block action command 057	0		17	Block action data 072	0		48	Block action command 088	0		79	Block action data 103	0	109	Block action data 118	0
	115	Block action data 057	0		18	Block action command 073	0		49	Block action data 088	0		80	Block action command 104	0	110	Block action command 119	0
	116	Block action command 058	0		19	Block action data 073	0		50	Block action command 089	0		81	Block action data 104	0	111	Block action data 119	0
	117	Block action data 058	0		20	Block action command 074	0		51	Block action data 089	0		82	Block action command 105	0	112	Block action command 120	0
	118	Block action command 059	0		21	Block action data 074	0		52	Block action command 090	0		83	Block action data 105	0	113	Block action data 120	0
	119	Block action data 059	0		22	Block action command 075	0		53	Block action data 090	0		84	Block action command 106	0	114	Block action command 121	0
	120	Block action command 060	0		23	Block action data 075	0		54	Block action command 091	0		85	Block action data 106	0	115	Block action data 121	0
	121	Block action data 060	0		24	Block action command 076	0		55	Block action data 091	0		86	Block action command 107	0	116	Block action command 122	0
	122	Block action command 061	0		25	Block action data 076	0		56	Block action command 092	0		87	Block action data 107	0	117	Block action data 122	0
	123	Block action data 061	0		26	Block action command 077	0		57	Block action data 092	0		88	Block action command 108	0	118	Block action command 123	0
	124	Block action command 062	0		27	Block action data 077	0		58	Block action command 093	0		89	Block action data 108	0	119	Block action data 123	0
	125	Block action data 062	0		28	Block action command 078	0		59	Block action data 093	0		90	Block action command 109	0	120	Block action command 124	0
	126	Block action command 063	0		29	Block action data 078	0		60	Block action command 094	0		91	Block action data 109	0	121	Block action data 124	0
	127	Block action data 063	0		30	Block action command 079	0		61	Block action data 094	0		92	Block action command 110	0	122	Block action command 125	0
57	0	Block action command 064	0	31	Block action data 079	0	62	Block action command 095	0	93	Block action data 110	0	123	Block action data 125	0			
												124	Block action command 126	0				

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.
 Ex) Pr6.24 Disturbance observer filter ... Value of Panaterm : 0.53 / Value of parameter-file : 53

*2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"

PARAMETER

MODEL MINAS-A6 (SF) series common

Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value			
57	125	Block action data 126	0	58	28	Block action command 142	0	58	59	Block action data 157	0	58	90	Block action command 173	0			
	126	Block action command 127	0		29	Block action data 142	0		60	Block action command 158	0		91	Block action data 173	0	122	Block action command 189	0
	127	Block action data 127	0		30	Block action command 143	0		61	Block action data 158	0		92	Block action data 174	0	123	Block action data 189	0
58	0	Block action command 128	0	31	Block action data 143	0	62	Block action command 159	0	93	Block action command 174	0	124	Block action command 190	0			
	1	Block action data 128	0	32	Block action command 144	0	63	Block action data 159	0	94	Block action data 175	0	125	Block action data 190	0			
	2	Block action command 129	0	33	Block action data 144	0	64	Block action command 160	0	95	Block action data 175	0	126	Block action command 191	0			
	3	Block action data 129	0	34	Block action command 145	0	65	Block action data 160	0	96	Block action command 176	0	127	Block action data 191	0			
	4	Block action command 130	0	35	Block action data 145	0	66	Block action command 161	0	97	Block action data 176	0	59	0	Block action command 192	0		
	5	Block action data 130	0	36	Block action command 146	0	67	Block action data 161	0	98	Block action command 177	0		1	Block action data 192	0		
	6	Block action command 131	0	37	Block action data 146	0	68	Block action command 162	0	99	Block action data 177	0		2	Block action command 193	0		
	7	Block action data 131	0	38	Block action command 147	0	69	Block action data 162	0	100	Block action command 178	0		3	Block action data 193	0		
	8	Block action command 132	0	39	Block action data 147	0	70	Block action command 163	0	101	Block action data 178	0		4	Block action command 194	0		
	9	Block action data 132	0	40	Block action command 148	0	71	Block action data 163	0	102	Block action command 179	0		5	Block action data 194	0		
	10	Block action command 133	0	41	Block action data 148	0	72	Block action command 164	0	103	Block action data 179	0		6	Block action command 195	0		
	11	Block action data 133	0	42	Block action command 149	0	73	Block action data 164	0	104	Block action command 180	0		7	Block action data 195	0		
	12	Block action command 134	0	43	Block action data 149	0	74	Block action command 165	0	105	Block action data 180	0		8	Block action command 196	0		
	13	Block action data 134	0	44	Block action command 150	0	75	Block action data 165	0	106	Block action command 181	0		9	Block action data 196	0		
	14	Block action command 135	0	45	Block action data 150	0	76	Block action command 166	0	107	Block action data 181	0		10	Block action command 197	0		
	15	Block action data 135	0	46	Block action command 151	0	77	Block action data 166	0	108	Block action command 182	0		11	Block action data 197	0		
	16	Block action command 136	0	47	Block action data 151	0	78	Block action command 167	0	109	Block action data 182	0		12	Block action command 198	0		
	17	Block action data 136	0	48	Block action command 152	0	79	Block action data 167	0	110	Block action command 183	0		13	Block action data 198	0		
	18	Block action command 137	0	49	Block action data 152	0	80	Block action command 168	0	111	Block action data 183	0		14	Block action command 199	0		
	19	Block action data 137	0	50	Block action command 153	0	81	Block action data 168	0	112	Block action command 184	0		15	Block action data 199	0		
20	Block action command 138	0	51	Block action data 153	0	82	Block action command 169	0	113	Block action data 184	0	16		Block action command 200	0			
21	Block action data 138	0	52	Block action command 154	0	83	Block action data 169	0	114	Block action command 185	0	17		Block action data 200	0			
22	Block action command 139	0	53	Block action data 154	0	84	Block action command 170	0	115	Block action data 185	0	18		Block action command 201	0			
23	Block action data 139	0	54	Block action command 155	0	85	Block action data 170	0	116	Block action command 186	0	19		Block action data 201	0			
24	Block action command 140	0	55	Block action data 155	0	86	Block action command 171	0	117	Block action data 186	0	20	Block action command 202	0				
25	Block action data 140	0	56	Block action command 156	0	87	Block action data 171	0	118	Block action command 187	0	21	Block action data 202	0				
26	Block action command 141	0	57	Block action data 156	0	88	Block action command 172	0	119	Block action data 187	0	22	Block action command 203	0				
27	Block action data 141	0	58	Block action command 157	0	89	Block action data 172	0	120	Block action command 188	0	23	Block action data 203	0				

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.

Ex) Pr6.24 Disturbance observer filter ... Value of Panatorm : 0.53 / Value of parameter-file : 53

*2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"

PARAMETER

MODEL

MINAS-A6 (SF) series common

Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value					
59	24	Block action command 204	0	59	55	Block action data 219	0	59	86	Block action command 235	0	59	117	Block action data 250	0					
	25	Block action data 204	0		56	Block action command 220	0		87	Block action data 235	0		118	Block action command 251	0	60	20	Block action acceleration 04	0	
	26	Block action command 205	0		57	Block action data 220	0		88	Block action command 236	0		119	Block action data 251	0		21	Block action acceleration 05	0	
	27	Block action data 205	0		58	Block action command 221	0		89	Block action data 236	0		120	Block action command 252	0		22	Block action acceleration 06	0	
	28	Block action command 206	0		59	Block action data 221	0		90	Block action command 237	0		121	Block action data 252	0		23	Block action acceleration 07	0	
	29	Block action data 206	0		60	Block action command 222	0		91	Block action data 237	0		122	Block action command 253	0		24	Block action acceleration 08	0	
	30	Block action command 207	0		61	Block action data 222	0		92	Block action command 238	0		123	Block action data 253	0		25	Block action acceleration 09	0	
	31	Block action data 207	0		62	Block action command 223	0		93	Block action data 238	0		124	Block action command 254	0		26	Block action acceleration 10	0	
	32	Block action command 208	0		63	Block action data 223	0		94	Block action command 239	0		125	Block action data 254	0		27	Block action acceleration 11	0	
	33	Block action data 208	0		64	Block action command 224	0		95	Block action data 239	0		126	Block action command 255	0		28	Block action acceleration 12	0	
	34	Block action command 209	0		65	Block action data 224	0		96	Block action command 240	0		127	Block action data 255	0		29	Block action acceleration 13	0	
	35	Block action data 209	0		66	Block action command 225	0		97	Block action data 240	0		60	0	Block action velocity 00		0	30	Block action acceleration 14	0
	36	Block action command 210	0		67	Block action data 225	0		98	Block action command 241	0			1	Block action velocity 01		0	31	Block action acceleration 15	0
	37	Block action data 210	0		68	Block action command 226	0		99	Block action data 241	0			2	Block action velocity 02		0	32	Block action deceleration 00	0
	38	Block action command 211	0		69	Block action data 226	0		100	Block action command 242	0			3	Block action velocity 03		0	33	Block action deceleration 01	0
	39	Block action data 211	0		70	Block action command 227	0		101	Block action data 242	0			4	Block action velocity 04		0	34	Block action deceleration 02	0
	40	Block action command 212	0		71	Block action data 227	0		102	Block action command 243	0			5	Block action velocity 05		0	35	Block action deceleration 03	0
	41	Block action data 212	0		72	Block action command 228	0		103	Block action data 243	0	6		Block action velocity 06	0		36	Block action deceleration 04	0	
	42	Block action command 213	0		73	Block action data 228	0		104	Block action command 244	0	7		Block action velocity 07	0	37	Block action deceleration 05	0		
	43	Block action data 213	0		74	Block action command 229	0		105	Block action data 244	0	8		Block action velocity 08	0	38	Block action deceleration 06	0		
	44	Block action command 214	0		75	Block action data 229	0		106	Block action command 245	0	9		Block action velocity 09	0	39	Block action deceleration 07	0		
	45	Block action data 214	0		76	Block action command 230	0		107	Block action data 245	0	10		Block action velocity 10	0	40	Block action deceleration 08	0		
	46	Block action command 215	0		77	Block action data 230	0		108	Block action command 246	0	11		Block action velocity 11	0	41	Block action deceleration 09	0		
	47	Block action data 215	0		78	Block action command 231	0		109	Block action data 246	0	12		Block action velocity 12	0	42	Block action deceleration 10	0		
	48	Block action command 216	0		79	Block action data 231	0		110	Block action command 247	0	13		Block action velocity 13	0	43	Block action deceleration 11	0		
	49	Block action data 216	0		80	Block action command 232	0		111	Block action data 247	0	14		Block action velocity 14	0	44	Block action deceleration 12	0		
50	Block action command 217	0	81	Block action data 232	0	112	Block action command 248	0	15	Block action velocity 15	0	45		Block action deceleration 13	0					
51	Block action data 217	0	82	Block action command 233	0	113	Block action data 248	0	16	Block action acceleration 00	0	46		Block action deceleration 14	0					
52	Block action command 218	0	83	Block action data 233	0	114	Block action command 249	0	17	Block action acceleration 01	0	47	Block action deceleration 15	0						
53	Block action data 218	0	84	Block action command 234	0	115	Block action data 249	0	18	Block action acceleration 02	0	48	For manufacturer use	0						
54	Block action command 219	0	85	Block action data 234	0	116	Block action command 250	0	19	Block action acceleration 03	0	49	Block action origin offset	0						
												50	Block action positive direction software limit	0						

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.

Ex) Pr6.24 Disturbance observer filter ... Value of Panaterm : 0.53 / Value of parameter-file : 53

*2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"

PARAMETER	MODEL	MINAS-A6 (SF) series common
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Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value				
60	51	Block action negative direction software limit	0	61	13	For manufacturer use	0	62	12	For manufacturer use	0	62	43	For manufacturer use	0	62	74	For manufacturer use	0
	52	Block action origin return velocity (high speed)	0		14	For manufacturer use	0		13	For manufacturer use	0		44	For manufacturer use	0		75	For manufacturer use	0
	53	Block action origin return velocity (low speed)	0		15	For manufacturer use	0		14	For manufacturer use	0		45	For manufacturer use	0		76	For manufacturer use	0
	54	Block action origin return acceleration and deceleration	0		16	For manufacturer use	0		15	For manufacturer use	0		46	For manufacturer use	0		77	For manufacturer use	0
	55	Set invalidate block action origin return	0		17	For manufacturer use	0		16	For manufacturer use	0		47	For manufacturer use	0		78	For manufacturer use	0
	56	For manufacturer use	0		18	For manufacturer use	0		17	For manufacturer use	0		48	For manufacturer use	0		79	For manufacturer use	0
	57	For manufacturer use	0		19	For manufacturer use	0		18	For manufacturer use	0		49	For manufacturer use	0		80	For manufacturer use	0
	58	For manufacturer use	0		20	For manufacturer use	0		19	For manufacturer use	0		50	For manufacturer use	0		81	For manufacturer use	0
	59	For manufacturer use	0		21	For manufacturer use	0		20	For manufacturer use	0		51	For manufacturer use	0		82	For manufacturer use	0
	60	For manufacturer use	0		22	For manufacturer use	0		21	For manufacturer use	0		52	For manufacturer use	0		83	For manufacturer use	0
	61	For manufacturer use	0		23	For manufacturer use	0		22	For manufacturer use	0		53	For manufacturer use	0		84	For manufacturer use	0
	62	For manufacturer use	0		24	For manufacturer use	0		23	For manufacturer use	0		54	For manufacturer use	0		85	For manufacturer use	0
	63	For manufacturer use	0		25	For manufacturer use	0		24	For manufacturer use	0		55	For manufacturer use	0		86	For manufacturer use	0
	64	For manufacturer use	0		26	For manufacturer use	0		25	For manufacturer use	0		56	For manufacturer use	0		87	For manufacturer use	0
	65	For manufacturer use	0		27	For manufacturer use	0		26	For manufacturer use	0		57	For manufacturer use	0		88	For manufacturer use	0
	66	For manufacturer use	0		28	For manufacturer use	0		27	For manufacturer use	0		58	For manufacturer use	0		89	For manufacturer use	0
	67	For manufacturer use	0		29	For manufacturer use	0		28	For manufacturer use	0		59	For manufacturer use	0		90	For manufacturer use	0
	68	For manufacturer use	0		30	For manufacturer use	0		29	For manufacturer use	0		60	For manufacturer use	0		91	For manufacturer use	0
61	0	For manufacturer use	0	31	For manufacturer use	0	30	For manufacturer use	0	61	For manufacturer use	0	92	For manufacturer use	0				
	1	For manufacturer use	0	62	0	For manufacturer use	0	31	For manufacturer use	0	62	For manufacturer use	0	93	For manufacturer use	0			
	2	For manufacturer use	0		1	For manufacturer use	0	32	For manufacturer use	0	63	For manufacturer use	0	94	For manufacturer use	0			
	3	For manufacturer use	0		2	For manufacturer use	0	33	For manufacturer use	0	64	For manufacturer use	0	95	For manufacturer use	0			
	4	For manufacturer use	0		3	For manufacturer use	0	34	For manufacturer use	0	65	For manufacturer use	0	96	For manufacturer use	0			
	5	For manufacturer use	0		4	For manufacturer use	0	35	For manufacturer use	0	66	For manufacturer use	0	97	For manufacturer use	0			
	6	For manufacturer use	0		5	For manufacturer use	0	36	For manufacturer use	0	67	For manufacturer use	0	98	For manufacturer use	0			
	7	For manufacturer use	0		6	For manufacturer use	0	37	For manufacturer use	0	68	For manufacturer use	0	99	For manufacturer use	0			
	8	For manufacturer use	0		7	For manufacturer use	0	38	For manufacturer use	0	69	For manufacturer use	0	100	For manufacturer use	0			
	9	For manufacturer use	0		8	For manufacturer use	0	39	For manufacturer use	0	70	For manufacturer use	0	101	For manufacturer use	0			
	10	For manufacturer use	0		9	For manufacturer use	0	40	For manufacturer use	0	71	For manufacturer use	0	102	For manufacturer use	0			
	11	For manufacturer use	0		10	For manufacturer use	0	41	For manufacturer use	0	72	For manufacturer use	0	103	For manufacturer use	0			
12	For manufacturer use	0	11		For manufacturer use	0	42	For manufacturer use	0	73	For manufacturer use	0	104	For manufacturer use	0				

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.

Ex) Pr6.24 Disturbance observer filter ... Value of Panaterm : 0.53 / Value of parameter-file : 53

*2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"

PARAMETER

MODEL MINAS-A6 (SF) series common

Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value	Cate	Pr.	Parameter	Default value
62	105	For manufacturer use	0												
	106	For manufacturer use	0												
	107	For manufacturer use	0												
	108	For manufacturer use	0												
	109	For manufacturer use	0												
	110	For manufacturer use	0												
	111	For manufacturer use	0												
	112	For manufacturer use	0												
	113	For manufacturer use	0												
	114	For manufacturer use	0												
	115	For manufacturer use	0												
	116	For manufacturer use	0												
	117	For manufacturer use	0												
	118	For manufacturer use	0												
	119	For manufacturer use	0												
	120	For manufacturer use	0												
	121	For manufacturer use	0												
	122	For manufacturer use	0												
	123	For manufacturer use	0												
	124	For manufacturer use	0												
	125	For manufacturer use	0												
	126	For manufacturer use	0												
	127	For manufacturer use	0												

*1 When checking directly value of parameter-file with a text data etc., it does not show the decimal point.
 Ex) Pr6.24 Disturbance observer filter ... Value of Panaterm : 0.53 / Value of parameter-file : 53
 *2 The maximum torque limit value (Pr.0.13,Pr.5.22,Pr.5.25,Pr.5.26) varies by the applicable motor.Refer to "The maximum value of torque limit setup"