



IMPULSE[®]G+ & VG+ *Series 4*

Adjustable Frequency/Vector Crane Controls

INSTRUCTION MANUAL



MAGNETEK
MATERIAL HANDLING



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WARNING

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

***DANGER, WARNING, CAUTION, and NOTE* Statements**

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



DANGER

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



WARNING

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



CAUTION

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

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

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Appendix A: Parameter Listing

IMPULSE®•G+ & VG+ Series 4 Parameter Listing A-3

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Chapter **1**

Introduction

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WARNING

Do not touch any circuitry components while the main AC power is on. In addition, wait until the red "CHARGE" LED is out before performing any service on that unit. It may take as long as 5 minutes for the charge on the main DC bus capacitors to drop to a safe level.

Do not check signals during operation.

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

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

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

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

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

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

The drive is suitable for circuits capable of delivering not more than 100,000 RMS symmetrical Amperes. Install adequate branch circuit short circuit protection per applicable codes. Failure to do so may result in equipment damage and/or personal injury.

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

How to Use This Manual

This manual provides technical information on IMPULSE®•G+ and VG+ Series 4 parameter settings, drive functions, troubleshooting, and installation details. Use this manual to expand drive functionality and to take advantage of higher performance features. This manual is available for download on the Magnetek Material Handling document center website at www.magnetekmh.com.

The IMPULSE®•G+ and VG+ Series 4 drives share a common power section, and similar parameters. The parameters and performance differ because the VG+ drives includes a PG-X3 encoder feedback card allowing the drive to perform Flux Vector control of the motor. The G+ drives operate in V/f or Open Loop Vector control methods, appropriate for traverse or standard hoist motions. The VG+ drives are typically applied to the non-mechanical load brake hoist motion, and can be applied to traverse motions where torque control or a wide speed control range is required.

Many IMPULSE®•G+ and VG+ Series 4 parameter functions are common between the two drive classes. The functions that differ are noted with a “Model” column; this column designates which parameters are available for a given function. Functions may also be control method dependent; these differences are noted in the function and parameter details. Table 1-1 below notes which drives can operate in a particular control method.

Table 1-1: Control Methods by Model

Drive Model	Control Method (A01-02)	Speed Control Range	Motion (A01-03)
G+	V/f (0)	40:1	Traverse (0) Standard Hoist (1)
G+	Open Loop Vector (2)	200:1	Traverse (0) Standard Hoist (1)
VG+	Flux Vector (3)	1500:1	Traverse (0) NLB Hoist (2)

The instructions in the following chapters apply to most IMPULSE®•G+ & VG+ Series 4 crane, hoist, and monorail applications. However, carefully evaluate each specific situation and ensure that the National Electric Code (NEC) codes and local wiring practices are followed.

These chapters explain how to install the IMPULSE®•G+ & VG+ Series 4 and, to some extent, the components that it interconnects. It explains how to: assess the drive’s environment, mount the drive, and wire the drive circuits. It is important to develop a “plan of attack” for both the mounting and wiring since each task has an effect on the other one. IMPULSE®•G+ & VG+ Series 4 Wiring Practices is included to provide assistance and reference.

NOTE: *If the IMPULSE®•G+ & VG+ Series 4 is part of a Magnetek motor control panel, reference the control drawings, disregard this chapter, and turn to Chapter 4.*

Introduction

Assessing the System Requirements

It is important to know how the drive will be utilized before working on installation and wiring. Please know the requirements for the following components:

- Speed control method(s) - i.e. stepped, stepless, infinitely variable
- Braking method(s) - coast to stop, decel to stop, No Load Brake (NLB) Hoist
- Power source voltage, number of phases, and kVA rating
- Power source location
- Wire size
- Grounding location and method
- Control wiring sources - i.e. cab, pendant, radio

Assessing the Drive Environment

When choosing a location for IMPULSE®•G+ & VG+ Series 4, perform the following steps:

1. Ensure that a three-phase 200 to 240 VAC 50/60 Hz power supply is available for a 230 VAC-rated drive, a three-phase 380 to 480 VAC 50/60 Hz power supply is available for a 460 VAC-rated drive, and a 500 to 600 VAC 50/60 Hz power supply is available for a 575 VAC-rated drive.
2. Ensure the encoder is supplied with +5 VDC or 12 VDC.
3. If the RMS encoder current requirement is greater than 200 mA, provide an auxiliary power supply to the encoder.
4. Ensure that the drive-to-motor wiring distance is less than 150 ft. unless appropriate reactors, filters, and/or inverter duty motor is used.
5. Ensure that the drive circuit wiring is protected or isolated from:
 - Ambient temperatures outside the range of +14°F to +140°F (-10°C to +60°C) at 2 kHz carrier frequency.
 - Rain or moisture
 - Corrosive gases or liquids
 - Direct sunlight
 - Severe mechanical vibration
6. Ensure that the drive is housed in an appropriate NEMA-rated enclosure.
7. For severe-duty applications (long lifts, for example) or with 75-HP-or-greater motors, ensure that the drive control system (including dynamic braking resistors) is adequately cooled, even though the ambient temperature limit is not exceeded. For more information, contact Magnetek.

IMPULSE®•G+ & VG+ Series 4 General Specifications

Table 1-2: Specification Values and Information - Heavy Duty

230 V			460 V			575 V		
Model (-G+/VG+S4)	Rated Output Current (A)	Output Capacity (kVA)	Model (-G+/VG+S4)	Rated Output Current (A)	Output Capacity (kVA)	Model (-G+/VG+S4)	Rated Output Current (A)	Output Capacity (kVA)
2003	3.2	1.2	4001	1.8	1.4	5001	1.7	1.7
2005	5.0	1.9	4003	3.4	2.6	5003	3.5	3.5
2007	6.9	2.6	4004	4.8	3.7	5004	4.1	4.1
2008	8.0	3.0	4005	5.5	4.2	5006	6.3	6.3
2011	11.0	4.2	4007	7.2	5.5	5009	9.8	9.8
2014	14.0	5.3	4009	9.2	7.0	5012	12.5	12.5
2017	17.5	6.7	4014	14.8	11.3	5017	17.0	17.0
2025	25.0	9.5	4018	18.0	13.7	5022	22.0	22.0
2033	33.0	12.6	4024	24.0	18.3	5027	27.0	27.0
2047	47.0	17.9	4031	31.0	24.0	5032	32.0	32.0
2060	60.0	23.0	4039	39.0	30.0	5041	41.0	41.0
2075	75.0	29.0	4045	45.0	34.0	5052	52.0	52.0
2085	85.0	32.0	4060	60.0	48.0	5062	62.0	62.0
2115	115	44.0	4075	75.0	57.0	5077	77.0	77.0
2145	145	55.0	4091	91.0	69.0	5099	99.0	99.0
2180	180	69.0	4112	112	85.0	5130	130	129
2215	215	82.0	4150	150	114	5172	172	171
2283	283	108	4180	180	137	5200	200	199
2346	346	132	4216	216	165	--	--	--
2415	415	158	4260	260	198	--	--	--
--	--	--	4304	304	232	--	--	--
--	--	--	4370	370	282	--	--	--
--	--	--	4450	450	343	--	--	--
--	--	--	4605	605	461	--	--	--
--	--	--	4810	810	617	--	--	--
--	--	--	41090	1090	831	--	--	--

Table 1-3: Specifications for 230 V, 460 V, and 575 V

Specification	Specification Value and Information for All Models
Certification	UL, cUL, CSA, CE, RoHS
Crane Duty Classification	Rated for CMAA Crane Duty Class A - F only (or equivalent)
Rated input power supply volts & freq	3-phase 200 to 240 VAC 50/60 Hz for a 230 VAC-rated drive 3-phase 380 to 480 VAC 50/60 Hz for a 460 VAC-rated drive 3-phase 500 to 600 VAC 50/60 Hz for a 575 VAC-rated drive
Control Voltage	120 VAC (50/60 Hz) standard 42–48 VAC (50/60 Hz) 24 VAC (50/60 Hz) 24 VDC
Allowable input and control voltage fluctuation	+10% or -15% of nominal
Allowable input frequency fluctuation	±5% of nominal
Allowable control frequency fluctuation	±3 Hz of nominal
Control method	Fully digital, V/f, open loop vector, or flux vector control; sine-wave, pulse-width-modulated
Maximum output voltage (VAC)	3-phase 200 to 240 VDC (proportional to input voltage) 3-phase 380 to 480 VDC (proportional to input voltage) 3-phase 500 to 600 VDC (proportional to input voltage)
Rated frequency (Hz)	150 Hz standard (400 Hz optional, consult factory and equipment manufacturer)
Output speed control range	FLV: 1500:1; OLV: 200:1; V/f: 40:1
Output frequency accuracy	0.01%—with digital reference command 0.1%—with analog reference command; 10 bits/10 V
Frequency reference resolution	Digital: 0.01 Hz; analog: 0.03 Hz (at 60 Hz)
Output frequency resolution	0.01 Hz
Overload capacity	150% of drive rated load for 1 min
Remote frequency reference sources	0–10 VDC (20k Ω); 4–20 mA (250 Ω); ±10 VDC serial (RS-485)
Accel/decel times	0.1 to 6000.0 sec—4 sets; 8 parameters are independently adjustable
Braking torque	150% or more with dynamic braking
DC Link Choke	Models 2085 to 2415 and 4045 to 41090 come with a built-in DC link choke.
Internal Braking Transistor	Models 2003 to 2115, 4001 to 4060, and 5001 to 5041 come with an internal braking transistor (B1 and B2 terminals).
Motor overload protection	UL recognized electronic thermal overload relay; field-programmable
Overcurrent protection level (OC1)	200% of drive rated current
Circuit protection	Ground fault and blown-fuse protection
Overvoltage protection level	230 VAC class: Stops when DC bus voltage exceeds approx. 410 VDC 460 VAC class: Stops when DC bus voltage exceeds approx. 820 VDC 575 VAC class: Stops when DC bus voltage exceeds approx. 1040 VDC
Undervoltage protection level	230 VAC class: Stops when DC bus voltage falls below approx. 190 VDC 460 VAC class: Stops when DC bus voltage falls below approx. 380 VDC 575 VAC class: Stops when DC bus voltage falls below approx. 475 VDC

* 2kHz carrier frequency

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

Specification	Specification Value and Information for All Models
Heatsink overtemperature	Thermostat trips at 105°C (221°F)
Torque limit selection	Separate functions for FORWARD, REVERSE, REGEN; all selectable from 0–300%
Stall prevention	Separate functions for accel, decel, at-speed, and constant horsepower region
Other protection features	VG+ : Speed deviation, overspeed, mechanical brake failure, lost output phase, failed-oscillator, PG-disconnect, roll-back detection, micro controller watchdog, internal braking transistor failure, torque output limit, motor overcurrent, inverter overcurrent, input phase loss. G+ : Lost output phase, micro-controller watchdog, internal braking resistor failure, motor overcurrent, inverter overcurrent, input phase loss.
DC bus voltage indication	Charge LED is on until DC bus voltage drops below 50 VDC
Location	Indoors; requires protection from moisture, corrosive gases, and liquids
Ambient operating temperature	-10° to 60°C (14° to 140°F)* -10° to 65°C (14° to 149°F)**
Storage temperature	-20°C to +70°C (-4°F to 158°F)
Humidity	95% relative humidity or less and free of condensation
Vibration	10 to 20 Hz at 9.8 m/s ² 20 to 55 Hz at 5.9 m/s ² (Models 2003 to 2180, 4001 to 4150, and 5001 to 5077) or 20 to 55 Hz at 2.0 m/s ² (Models 2215 to 2415, 4180 to 4605, and 5099 to 5200)
Elevation	1000 m or lower, up to 3000 m with derating.
Orientation	Install the drive vertically to maintain maximum cooling effects.

* 2kHz carrier frequency

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

AC Reactor Specifications

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

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

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

Table 1-4: 230 V Class

Model Number	230 V Part Number	Maximum Amps of Reactor
2003-G+/VG+S4	REA230-1	4
2005-G+/VG+S4	REA230-1	4
2007-G+/VG+S4	REA230-2	8
2008-G+/VG+S4	REA230-2	8
2011-G+/VG+S4	REA230-3	12
2014-G+/VG+S4	REA230-3	12
2017-G+/VG+S4	REA230-5	18
2025-G+/VG+S4	REA230-7.5	25
2033-G+/VG+S4	REA230-10	35
2047-G+/VG+S4	REA230-15	45
2060-G+/VG+S4	REA230-20	55
2075-G+/VG+S4	REA230-25	80
2085-G+/VG+S4	REA230-30	80
2115-G+/VG+S4	REA230-40	100
2145-G+/VG+S4	REA230-50	130
2180-G+/VG+S4	REA230-60	160
2215-G+/VG+S4	REA230-75	200
2283-G+/VG+S4	REA230-100	250
2346-G+/VG+S4	REA230-125	320
2415-G+/VG+S4	REA230-150	400

Table 1-5: 460 V Class

Model Number	460 V Part Number	Maximum Amps of Reactor
4001-G+/VG+S4	REA460-1	2
4003-G+/VG+S4	REA460-2	4
4004-G+/VG+S4	REA460-3	6
4005-G+/VG+S4	REA460-5	8
4007-G+/VG+S4	REA460-5	8
4009-G+/VG+S4	REA460-5	8
4014-G+/VG+S4	REA460-7.5	12
4018-G+/VG+S4	REA460-10	18
4024-G+/VG+S4	REA460-15	25
4031-G+/VG+S4	REA460-20	35
4039-G+/VG+S4	REA460-25	35
4045-G+/VG+S4	REA460-30	45
4060-G+/VG+S4	REA460-40	55
4075-G+/VG+S4	REA460-50	80
4091-G+/VG+S4	REA460-60	80
4112-G+/VG+S4	REA460-75	100
4150-G+/VG+S4	REA460-100	130
4180-G+/VG+S4	REA460-150	200
4216-G+/VG+S4	REA460-150	200
4260-G+/VG+S4	REA460-200	250
4304-G+/VG+S4	REA460-250	320
4370-G+/VG+S4	REA460-300	400
4450-G+/VG+S4	REA460-400	500
4605-G+/VG+S4	REA460-500	600
4810-G+/VG+S4	Consult Factory	Consult Factory
41090-G+/VG+S4	Consult Factory	Consult Factory

Table 1-6: 575 V Class

Model Number	600 V Part Number	Maximum Amps of Reactor
5001-G+/VG+S4	REA575-1	2
5003-G+/VG+S4	REA575-2	4
5004-G+/VG+S4	REA575-3	4
5006-G+/VG+S4	REA575-5	8
5009-G+/VG+S4	REA575-10	12
5012-G+/VG+S4	REA575-10	12
5017-G+/VG+S4	REA575-15	18
5022-G+/VG+S4	REA575-20 & 25	25
5027-G+/VG+S4	REA575-30	35
5032-G+/VG+S4	REA575-30	35
5041-G+/VG+S4	REA575-40	45
5052-G+/VG+S4	REA575-50	55
5062-G+/VG+S4	REA575-60	80
5077-G+/VG+S4	REA575-75	80
5099-G+/VG+S4	REA575-100	100
5130-G+/VG+S4	REA575-150	160
5172-G+/VG+S4	REA575-200	200
5200-G+/VG+S4	REA575-200	200

S4IF Interface Specifications

IMPULSE®•G+ & VG+ Series 4 is designed to interface with user input and output devices through the S4IF interface board. This eliminates the need for an additional interface relay or isolation circuitry. The S4IF comes in 24 VDC, 24 VAC (50/60 Hz), 42 to 48 VAC (50/60 Hz), and 120 VAC (50/60 Hz) options.

The S4IF has eight optically isolated input terminals which can be used to connect the user input device to the drive. The eight terminals are multi-function terminals, and are used for speed control and other controls.

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

NOTE: The 250 VAC relays must be derated to 48 VAC to comply with CE.

Table 1-7: S4IF Ratings

S4IF Model	S1-S8	
	Voltage	Frequency
S4IF-120A60*	120 VAC	50/60 Hz
S4IF-48A60	42–48 VAC	50/60 Hz
S4IF-24A60	24 VAC	50/60 Hz
S4IF-24D00	24 VDC	--

* Not certified for CE compliance.

S4I and S4IO Option Specifications

IMPULSE®•G+ & VG+ Series 4 is compatible with AC digital input (S4I) and AC digital input/output (S4IO) options. The options expand the I/O capability of the drives, without the need for interface relays or isolation circuitry.

The S4I has four optically isolated input terminals. The S4IO has four optically isolated input terminals and four dry contact form A relays.

Table 1-8: S4I Ratings

S4I Model	I1-I4	
	Voltage	Frequency
S4I-120A60*	120 VAC	50/60 Hz
S4I-48A60	42–48 VAC	50/60 Hz
S4I-24A60	24 VAC	50/60 Hz

* Not certified for CE compliance.

Table 1-9: S4IO Ratings

S4IO Model	I1-I4		O1-O6	
	Voltage	Frequency	Voltage (max)	Current (max)
S4IO-120A60*	120 VAC	50/60 Hz	250 VAC (48VAC for CE)/ 30 VDC	1.0 A
S4IO-48A60	42–48 VAC	50/60 Hz		
S4IO-24A60	24 VAC	50/60 Hz		

* Not certified for CE compliance.

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Chapter **2**

Installation

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WARNING

- When preparing to mount the IMPULSE®•G+ & VG+ Series 4 drive, lift it by its base. Never lift the drive by the front cover, as doing so may cause drive damage or personal injury.
- Mount the drive on nonflammable material.
- The IMPULSE®•G+ & VG+ Series 4 drive generates heat. For the most effective cooling possible, mount it vertically. For more details, refer to the “IMPULSE®•G+ & VG+ Series 4 Dimensions/Heat Loss-Open Chassis” in this chapter.
- When mounting units in an enclosure, install a fan or other cooling device to keep the enclosure temperature below 65°C (149°F)*.

Failure to observe these warnings may result in equipment damage.

This chapter explains the following:

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

In addition, this section will cover information on the components that interconnect with IMPULSE®•G+ & VG+ Series 4.

Choosing a Location

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

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

* 2 kHz carrier frequency

IMPULSE®•G+ & VG+ Series 4 System Components And External Devices

Standard IMPULSE®•VG+ Series 4 Drive Components

- PG-X3 Line Driver Encoder Card

Optional Drive Components

- DI-A3 Digital DC Input Card
- DO-A3 Digital Output Card
- AI-A3 Analog Input Card
- AO-A3 Analog Output Card
- S4I-xxxA60 Control Digital AC Input Card
- S4IO-xxxA60 Control Digital AC Input/Output Card
- PS-A10L 24 VDC Control Power Unit for 230 V models
- PS-A10H 24 VDC Control Power Unit for 460 V and 575 V models
- PG-B3 Open Collector Encoder Card
- SI-EN3 EtherNet/IP
- SI-EM3 Modbus TCP/IP
- SI-EP3 PROFINET
- SI-P3 PROFIBUS-DP

As-Required Drive Components

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

Required External Devices

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

Long Time Storage

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

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

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

Capacitor Storage and their Reforming Process

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

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

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

Inverter Bus Capacitor Reforming Procedure:

1. Connect the inverter inputs L1 and L2 to a variac.
2. Make sure the variac voltage setting is turned down so that when input power is applied to the variac, the output of the variac will be at or near 0 volts.
3. Apply power to the variac, listening for abnormal sounds and watching for abnormal visual indications in the drive. If the variac has an output current indication, make sure the current is very near zero with zero or a steady output voltage applied.
4. Slowly turn the variac up, increasing the variac's output voltage to nominal rated input voltage over a time period of 2 to 3 minutes. In other words, ramp the voltage up at a rate of approximately 75 to 100 volts/minute for 230 VAC units, 150 to 200 volts/minute for 460 VAC units, and 225 to 300 volts/minute for 575 VAC.
5. Let the output voltage remain at rated voltage for 30 to 60 minutes while keeping close watch for abnormal signs within the inverter. While increasing the variac's output voltage, the current will momentarily increase as current is necessary to charge the capacitors.
6. Once 30 to 60 minutes elapse, remove power.

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

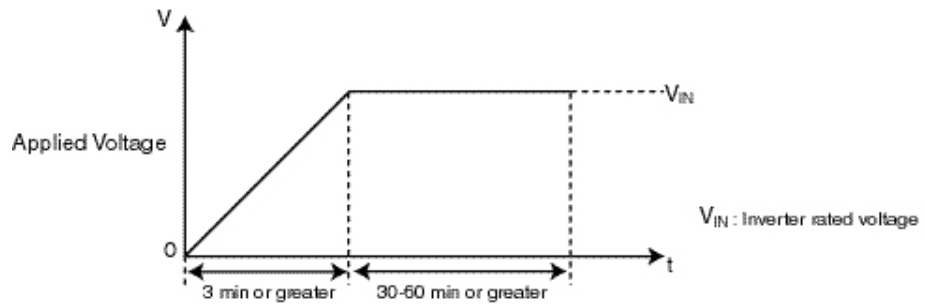
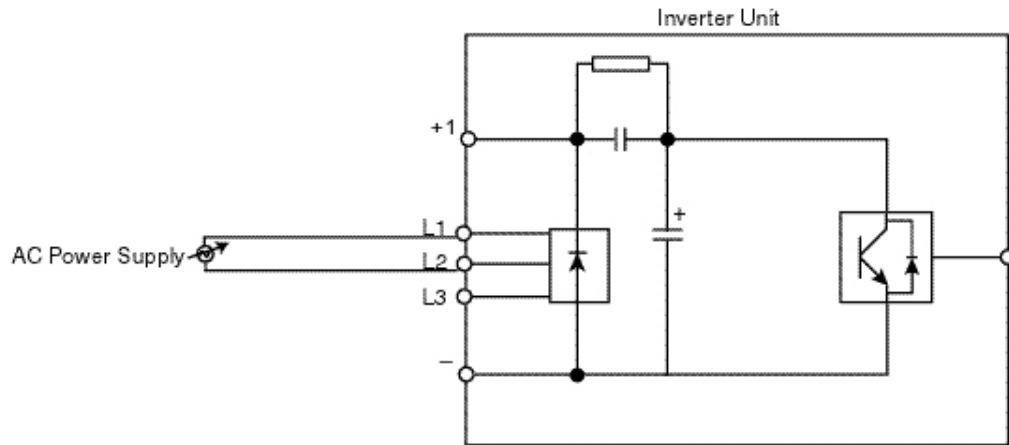


Figure 2-1: Long Time Storage

Installing the Drive

To install IMPULSE®•G+ & VG+ Series 4:

1. Ensure the drive will be used in a proper environment. Refer to page 1-5.
2. Review “IMPULSE®•G+ & VG+ Series 4 Terminal Block Configuration” on page 3-12.
3. Determine the sizes and connection locations for the drive components and external devices that need to be wired. Locate the ground.
4. Determine the proper drive orientation on the subpanel to maintain proper cooling (see Figure 2-2).

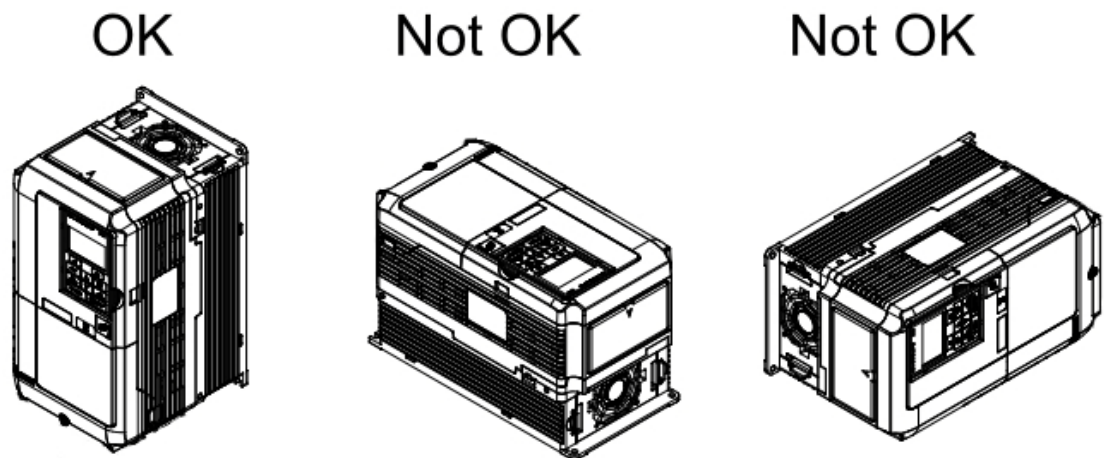


Figure 2-2: Correct Installation Orientation

5. Ensure that the air can flow freely around the heat sink as shown in Figure 2-3.

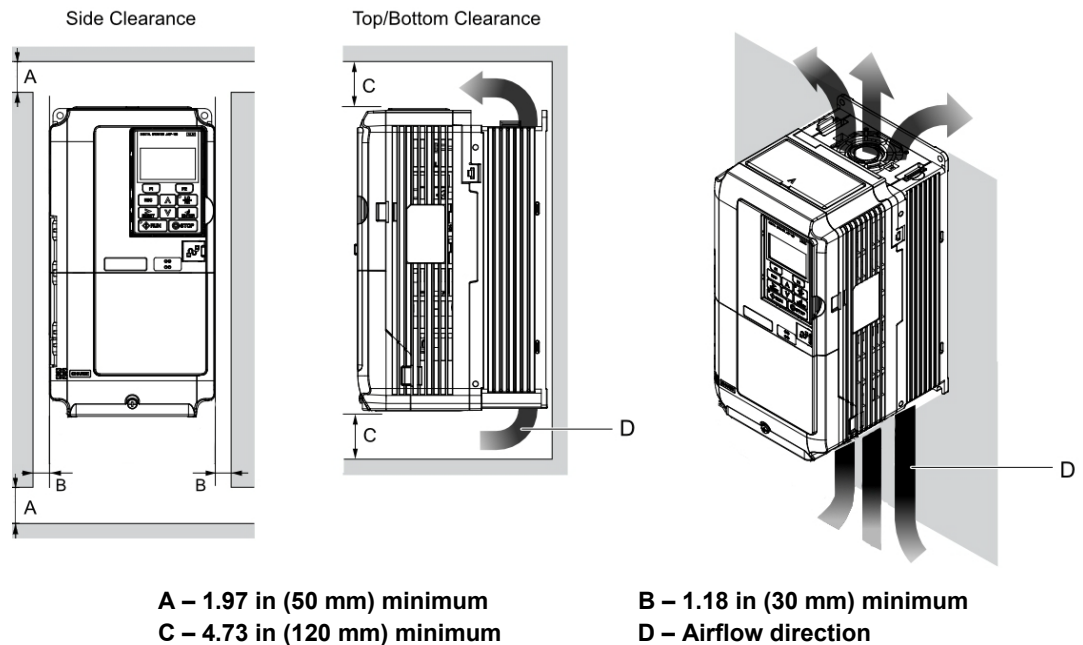


Figure 2-3: Correct Installation Spacing

NOTE:

- Allowable intake air temperature: 14° to 140°F (-10° to +60°C) at 2 kHz carrier frequency.
 - If necessary, a heater or air conditioner must be used to maintain the temperature range listed above.
6. Lay out the wire runs. Size the wire according to Tables 3-1, 3-2, and 3-3, and in accordance with NEC Table 610-14(a).
 - Ensure that the drive control circuit and power circuit wires are perpendicular to each other at any point they cross.
 - Keep power and control festoon wiring in separate cables.
 - Separate control drive circuit and power circuit wiring on the terminal block strip.
 7. Obtain the appropriate hardware for mounting.
 8. Mount the subpanel or surface to which you are mounting the drive (contact Magnetek if advice is needed in regards to mounting drives, especially for larger drives).
 9. Fasten the drive and components to the subpanel.
 10. Remove the terminal cover.
 11. Follow the wiring practices outlined in Chapter 3.

Multiple Drive Installation (Side-by-Side Installation)

Models 2003 to 2075, 4001 to 4039, and 5001 to 5027 can take advantage of Side-by-Side installation.

When mounting drives with the minimum clearing of 0.08 inches (2 mm) according to Figure 2-4, set parameter L08-35 to 1 while considering derating.

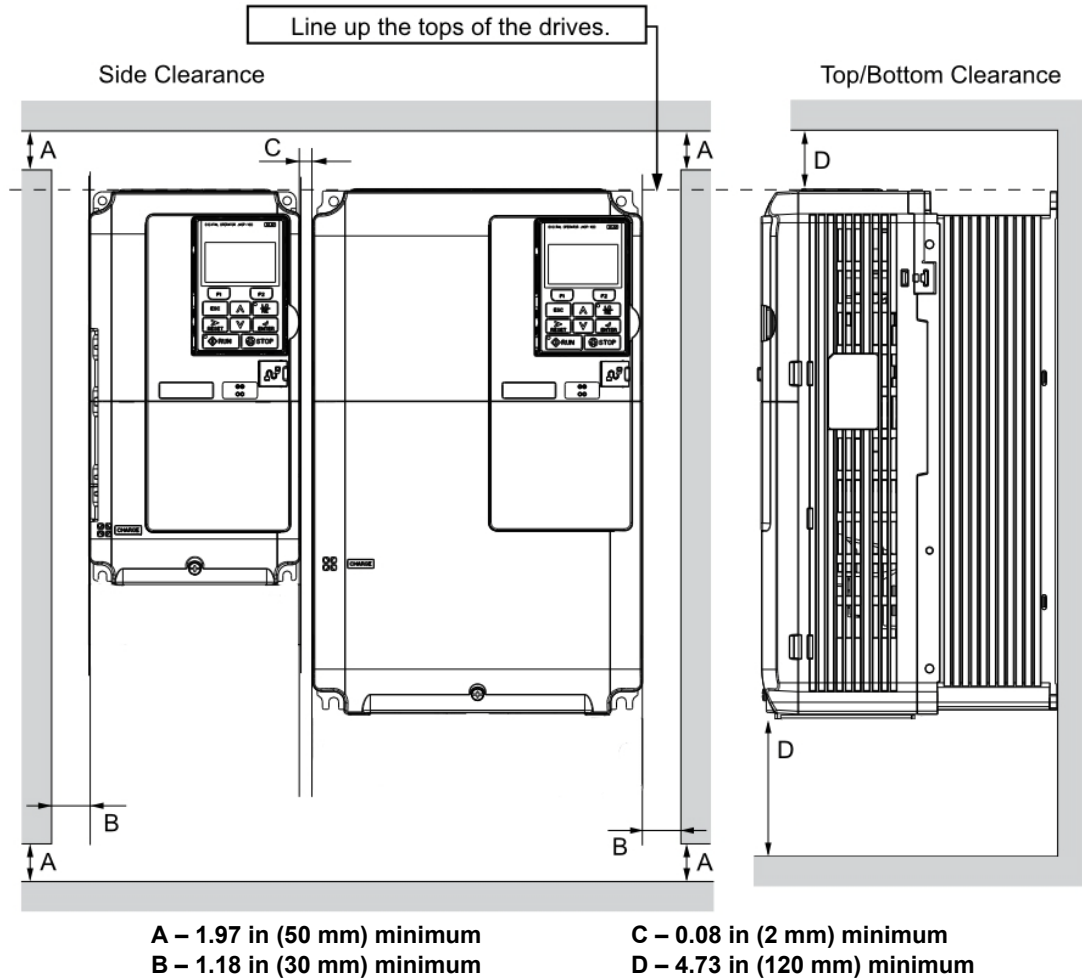


Figure 2-4: Space Between Drives (Side-by-Side Mounting)

NOTE: Align the tops of the drives when installing drives of different heights in the same enclosure panel. Leave space between the tops and bottoms of stacked drives for easier cooling fan replacement.

Drive Derating Data

Temperature Derating

To ensure the maximum performance life, the drive output current must be derated when the drive is installed in areas with high ambient temperature or if drives are mounted side-by-side in a cabinet. In order to ensure reliable drive overload protection, set parameters L08-12 and L08-35 according to the installation conditions. Contact Magnetek for derating curves.

IP00/Open-Chassis Enclosure

Drive operation between -10°C to $+60^{\circ}\text{C}$ (14°F to 140°F) allows CMAA Class F continuous current without derating.

Side-by-Side Mounting

Drive operation between -10°C and 30°C (14°F to 86°F) allows CMAA Class F continuous current without derating. Operation between 30°C and 50°C (86°F to 122°F) requires output current derating.

Dimensions for IP00/Open Chassis Enclosures

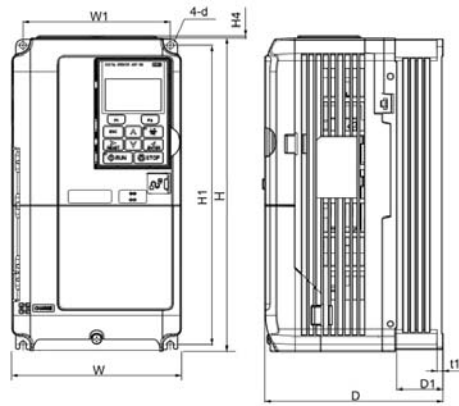


Figure 2-5

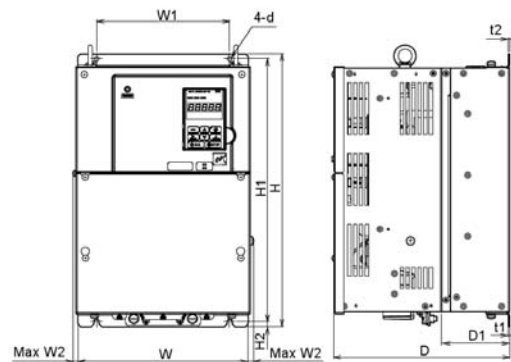


Figure 2-6

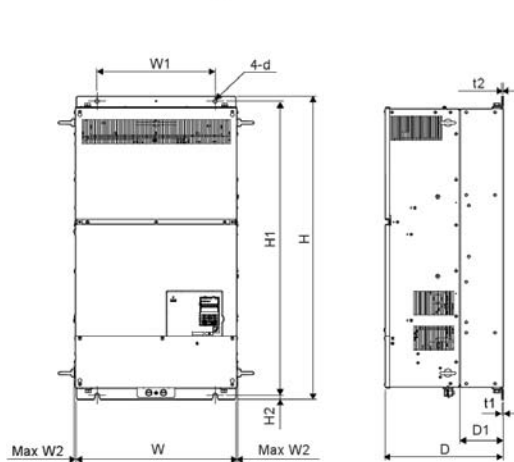


Figure 2-7

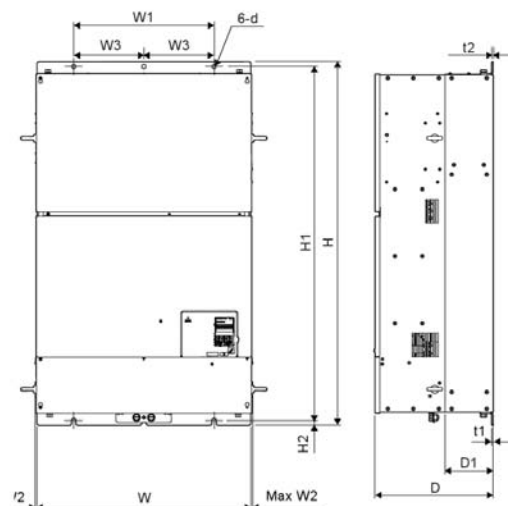


Figure 2-8

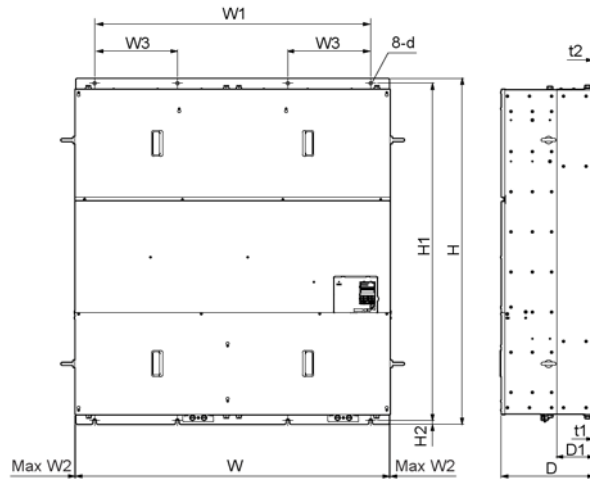


Figure 2-9

Table 2-1: Enclosure Dimensions - 230 V Drives

Drive Model Number (-G+VG+S4)	Figure	Dimensions (in)											Wt. (lbs)	Total Loss (W)*	
		W	H	D	W1	W2	H1	H2	H4	D1	t1	t2			d
2003	2-5	5.51	10.24	5.79	4.80	--	9.76	--	0.06	1.50	0.20	--	M5	7.3	59
2005		5.51	10.24	5.79	4.80	--	9.76	--	0.06	1.50	0.20	--	M5	7.3	72
2007		5.51	10.24	5.79	4.80	--	9.76	--	0.06	1.50	0.20	--	M5	7.5	84
2008		5.51	10.24	5.79	4.80	--	9.76	--	0.06	1.50	0.20	--	M5	7.5	95
2011		5.51	10.24	5.79	4.80	--	9.76	--	0.06	1.50	0.20	--	M5	7.5	122
2014		5.51	10.24	6.46	4.80	--	9.76	--	0.06	2.17	0.20	--	M5	8.2	137
2017		5.51	10.24	6.46	4.80	--	9.76	--	0.06	2.17	0.20	--	M5	8.2	168
2025		5.51	10.24	6.57	4.80	--	9.76	--	0.06	2.17	0.20	--	M5	9.3	287
2033		5.51	10.24	6.57	4.80	--	9.76	--	0.06	2.17	0.20	--	M5	9.3	319
2047		7.09	11.81	7.36	6.30	--	11.18	--	0.06	2.95	0.20	--	M5	13.0	410
2060		8.66	13.78	7.76	7.56	--	13.19	--	0.06	3.07	0.20	--	M6	20.1	558
2075		8.66	13.78	7.76	7.56	--	13.19	--	0.06	3.07	0.20	--	M6	22.0	681
2085	2-6	10.00	15.75	10.16	7.68	0.31	15.16	0.30	--	3.94	0.09	0.09	M6	50.7	721
2115		10.98	17.72	10.16	8.66	0.31	17.13	0.30	--	3.94	0.09	0.09	M6	61.7	912
2145		12.95	21.65	11.14	10.24	0.31	21.06	0.30	--	4.33	0.09	0.09	M6	90.4	1122
2180		12.95	21.65	11.14	10.24	0.31	21.06	0.30	--	4.33	0.09	0.09	M6	92.6	1354
2215		17.72	27.76	12.99	12.80	0.39	26.77	0.49	--	5.12	0.13	0.13	M10	167.6	1980
2283		17.72	27.76	12.99	12.80	0.39	26.77	0.49	--	5.12	0.13	0.13	M10	176.4	2524
2346		19.69	31.50	13.78	14.57	0.39	30.43	0.51	--	5.12	0.18	0.18	M12	216.1	3347
2415		19.69	31.50	13.78	14.57	0.39	30.43	0.51	--	5.12	0.18	0.18	M12	218.3	3626

* Total Loss is specified for continuous operation.

Table 2-2: Enclosure Dimensions - 460 V Drives

Drive Model Number (-G+/VG+S4)	Figure	Dimensions (in)													Wt. (lbs)	Total Loss (W)*
		W	H	D	W1	W2	W3	H1	H2	H4	D1	t1	t2	d		
4001	2-5	5.51	10.24	5.79	4.80	--	--	9.76	--	0.06	1.50	0.20	--	M5	7.5	61
4003		5.51	10.24	5.79	4.80	--	--	9.76	--	0.06	1.50	0.20	--	M5	7.5	70
4004		5.51	10.24	5.79	4.80	--	--	9.76	--	0.06	1.50	0.20	--	M5	7.5	87
4005		5.51	10.24	6.46	4.80	--	--	9.76	--	0.06	2.17	0.20	--	M5	7.9	101
4007		5.51	10.24	6.46	4.80	--	--	9.76	--	0.06	2.17	0.20	--	M5	8.2	108
4009		5.51	10.24	6.46	4.80	--	--	9.76	--	0.06	2.17	0.20	--	M5	8.2	130
4014		5.51	10.24	6.57	4.80	--	--	9.76	--	0.06	2.17	0.20	--	M5	9.0	221
4018		5.51	10.24	6.57	4.80	--	--	9.76	--	0.06	2.17	0.20	--	M5	9.0	247
4024		7.09	11.81	6.57	6.30	--	--	11.18	--	0.06	2.17	0.20	--	M5	12.6	323
4031		7.09	11.81	7.36	6.30	--	--	11.18	--	0.06	2.95	0.20	--	M5	13.2	403
4039		8.66	13.78	7.76	7.56	--	--	13.19	--	0.06	3.07	0.20	--	M6	19.2	509
4045		2-6	10.00	15.75	10.16	7.68	0.31	--	15.16	0.30	--	3.94	0.09	0.09	M6	50.7
4060	10.98		17.72	10.16	8.66	0.31	--	17.13	0.30	--	3.94	0.09	0.09	M6	59.5	701
4075	12.95		20.08	10.16	10.24	0.31	--	19.49	0.30	--	4.13	0.09	0.13	M6	86.0	817
4091	12.95		20.08	10.16	10.24	0.31	--	19.49	0.30	--	4.13	0.09	0.13	M6	86.0	1022
4112	12.95		21.65	11.14	10.24	0.31	--	21.06	0.30	--	4.33	0.09	0.09	M6	99.2	1325
4150	12.95		21.65	11.14	10.24	0.31	--	21.06	0.30	--	4.33	0.09	0.09	M6	101.4	1920
4180	17.72		27.76	12.99	12.80	0.39	--	26.77	0.49	--	5.12	0.13	0.13	M10	174.2	2313
4216	19.69		31.50	13.78	14.57	0.39	--	30.43	0.51	--	5.12	0.18	0.18	M12	211.6	3075
4260	19.69		31.50	13.78	14.57	0.39	--	30.43	0.51	--	5.12	0.18	0.18	M12	224.9	3178
4304	19.69		31.50	13.78	14.57	0.39	--	30.43	0.51	--	5.12	0.18	0.18	M12	235.9	4060
4370	2-7	19.69	37.40	14.57	14.57	0.31	--	36.34	0.51	--	5.31	0.18	0.18	M12	275.6	4742
4450	2-8	26.38	44.88	14.57	17.32	0.24	8.66	43.70	0.59	--	5.91	0.18	0.18	M12	476.2	5358
4605		26.38	44.88	14.57	17.32	0.24	8.66	43.70	0.59	--	5.91	0.18	0.18	M12	487.2	5875
4810	2-9	49.21	54.33	14.57	43.70	0.24	13.00	52.95	0.59	--	5.91	0.18	0.18	M12	1201.5	9367
41090		49.21	54.33	14.57	43.70	0.24	13.00	52.95	0.59	--	5.91	0.18	0.18	M12	1223.6	10781

* Total Loss is specified for continuous operation.

Table 2-3: Enclosure Dimensions - 575 V Drives

Drive Model Number (-G+/VG+S4)	Figure	Dimensions (in)											Wt. (lbs)	Total Loss (W)*	
		W	H	D	W1	W2	H1	H2	H4	D1	t1	t2			d
5001	2-5	5.51	10.24	5.79	4.80	--	9.76	--	0.06	1.50	0.20	--	M5	7.5	48.7
5003		5.51	10.24	5.79	4.80	--	9.76	--	0.06	1.50	0.20	--	M5	7.5	81.9
5004		5.51	10.24	6.46	4.80	--	9.76	--	0.06	2.17	0.20	--	M5	8.2	80.0
5006		5.51	10.24	6.46	4.80	--	9.76	--	0.06	2.17	0.20	--	M5	8.2	115.1
5009		5.51	10.24	6.57	4.80	--	9.76	--	0.06	2.17	0.20	--	M5	9.0	160.3
5012		7.09	11.81	7.36	6.30	--	11.18	--	0.06	2.95	0.20	--	M5	13.2	212.2
5017		7.09	11.81	7.36	6.30	--	11.18	--	0.06	2.95	0.20	--	M5	13.2	284.8
5022		8.66	13.78	7.76	7.56	--	13.19	--	0.06	3.07	0.20	--	M6	19.2	381.1
5027		8.66	13.78	7.76	7.56	--	13.19	--	0.06	3.07	0.20	--	M6	19.2	465.1
5032		2-6	10.98	17.72	10.16	8.66	0.31	17.13	0.30	--	3.94	0.09	0.09	M6	59.5
5041	10.98		17.72	10.16	8.66	0.31	17.13	0.30	--	3.94	0.09	0.09	M6	59.5	688.5
5052	12.95		21.65	11.14	10.24	0.31	21.06	0.30	--	4.33	0.09	0.09	M6	99.2	1606.5
5062	12.95		21.65	11.14	10.24	0.31	21.06	0.30	--	4.33	0.09	0.09	M6	99.2	1836.5
5077	12.95		21.65	11.14	10.24	0.31	21.06	0.30	--	4.33	0.09	0.09	M6	99.2	1619.0
5099	17.72		27.76	12.99	12.80	0.39	26.77	0.49	--	5.12	0.13	0.13	M10	174.2	1750
5130	17.72		27.76	12.99	12.80	0.39	26.77	0.49	--	5.12	0.13	0.13	M10	174.2	2146
5172	19.69		31.50	13.78	14.57	0.39	30.43	0.51	--	5.12	0.18	0.18	M12	235.9	2762
5200	19.69		31.50	13.78	14.57	0.39	30.43	0.51	--	5.12	0.18	0.18	M12	235.9	3422

* Total Loss is specified for continuous operation.

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Chapter **3**

Wiring

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IMPULSE®•G+ & VG+ Series 4 Wiring Practices



WARNING

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

- Ensure that the encoder wiring is less than 300 feet unless fiber optic cables are used.
- Ensure that the encoder wiring is isolated from the power wiring.
- Ensure that the encoder wiring shield is grounded only at the drive end.
- Connect the incoming three-phase AC source to terminals R/L1, S/L2, T/L3.
- Connect the Motor leads to terminals U/T1, V/T2, W/T3.
- Install a line reactor between the output of the drive in applications that require a disconnecting means between the drive's output and motor. Use a "make before break" auxiliary contact with the disconnect means and the hardware base block of the drive.
- Use hard contacts between the PLC output and the drive 120/24/48 VAC input card. If using a solid state output from a PLC (TRIAC) to a 120/24/48 VAC input card, use a 5K Ω , 5W resistor between the signal and X2.
- If the power source is 500 kVA or greater, or more than 10 times the inverter kVA rating, ensure that there is at least 3% impedance between the power source and the drive input. To accomplish this, a DC reactor can be installed between inverter terminals 1 and 2, or an AC line reactor can be used on the input of the drive. Excessive peak currents could damage the input power supply circuit if there is not enough impedance provided.
- Comply with "Suggested Circuit Protection Specifications" on page 3-6.
- Use time delay fuses, which are sized at 150% of drive's continuous rated input current, for wiring protection.
- Use appropriate R-C or MOV type surge absorbers across the coil of all contactors and relays in the system. Failure to do so could result in noise-related, nuisance fault incidents.
- Use external dynamic braking resistors for all applications.
- Do not ground the drive with any large-current machines.
- Before using any welding or high-current machines near the crane, disconnect all line and ground wiring.
- Do not let the wiring leads come in contact with the drive enclosure.
- Do not connect power factor correction capacitors to the drive input or output; use a sine wave filter.
- When possible, hard-wire the drive and motor. Do not use sliding collector bars (e.g., festoon cable).
- If there is a user input device or interface board that is remote, use shielded cable between the drive input terminals and the interface output terminals or user input device(s).
- Before turning on the drive, check the output circuit (U/T1, V/T2 and W/T3) for possible short circuits and ground faults.
- Increase the wire size by one gauge for every 250 feet (76.2 meters) between the drive and motor; suggested for center driven cranes, trolleys, and bridges (voltage drop is significant at low frequencies).
- When using more than one transformer for the drive's power, properly phase each transformer.

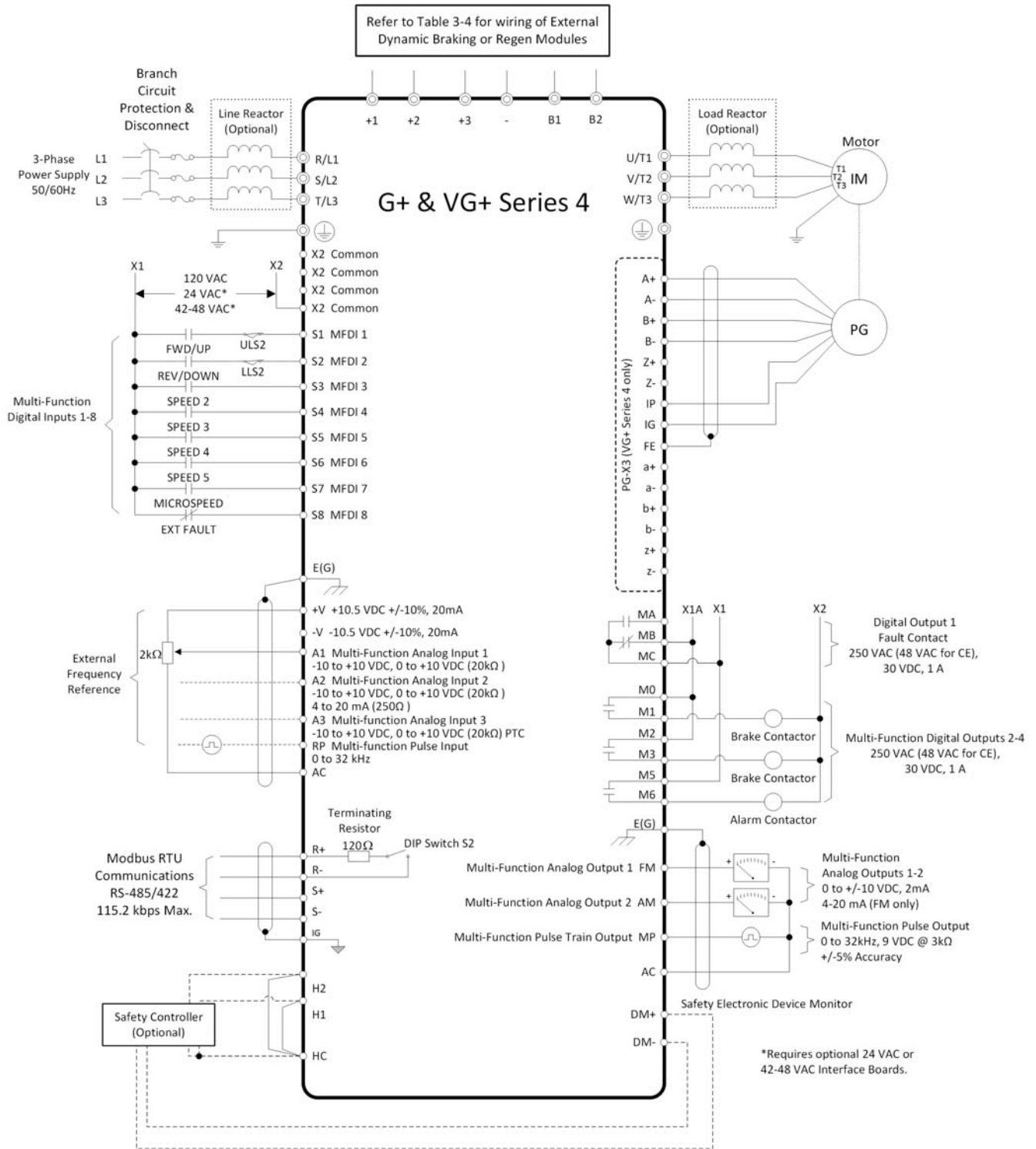
- To reverse the direction of rotation, program B03-04 = 1 (exchange phases), or interchange any two motor leads (changing R/L1, S/L2, or T/L3 will not affect the shaft rotation direction) as well as encoder phasing (F01-02 = 0/1 or swapping A and \bar{A} wires).
- Use shielded cable for all low-level DC speed reference signals (0 to 10 VDC, 4 to 20 mA). Ground the shield only at the drive side.
- Please observe National Electrical Code (NEC) guidelines when wiring electrical devices.
- IMPORTANT: All wire connections must have strain relief, and must not apply downward pressure to the terminals on the drive.

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



CAUTION

Do NOT connect external dynamic braking units to drive braking resistor terminal "B2". Connect positive external dynamic braking unit terminal(s) to drive terminal "+3" and negative external dynamic braking unit terminal(s) to drive terminal "-". When drive terminal "+3" is unavailable, use terminal "B1".



<1> Set L08-55 to 0 when using an external dynamic braking option.

Figure 3-1: IMPULSE® G+ & VG+ Series 4 Typical Connection Diagram

Suggested Circuit Protection Specifications and Wire Size

In order to comply with most safety standards, some circuit protective devices should be used between the incoming three-phase power supply and the IMPULSE®•G+ & VG+ Series 4. These devices can be thermal, magnetic, or molded-case breakers (MCCB); or “slow-blow” type fuses such as “CCMR” or “J.”



CAUTION

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

Table 3-1: Wire Sizing for 230 V Class

Model # (-G+/VG+S4)	Continuous HD Input Amps	Time Delay Input Fuse (A)	Time Delay Input Fuse Class	Inverse Time Molded/Case Circuit Breaker (A) ³	Recommended Gauge (AWG) ^{1, 4}		
					Power Circuit Wiring	Control Wiring	Ground Copper ²
2003	2.9	5	CC	15	14 to 10	18 to 16	14 to 10
2005	5.8	10	CC	15	14 to 10	18 to 16	14 to 10
2007	7.0	12	CC	15	14 to 10	18 to 16	14 to 10
2008	7.5	15	CC	15	14 to 10	18 to 16	14 to 10
2011	11.0	20	CC	20	14 to 10	18 to 16	14 to 10
2014	15.6	25	CC	30	14 to 10	18 to 16	14 to 10
2017	18.9	30	CC	35	12 to 10	18 to 16	12 to 10
2025	28.0	40	J	50	10 to 6	18 to 16	10 to 8
2033	37.0	50	J	70	8 to 6	18 to 16	10 to 8
2047	52.0	60	J	90	6 to 4	18 to 16	8 to 6
2060	68.0	80	J	110	4 to 2	18 to 16	6 to 4
2075	80.0	125	J	150	4 to 2	18 to 16	6 to 4
2085	82.0	125	J	150	2 to 1/0	18 to 16	6 to 4
2115	111	175	J	200	2 to 1/0	18 to 16	4
2145	136	200	J	250	1/0 to 2/0	18 to 16	4 to 2
2180	164	250	J	300	1/0 to 2/0	18 to 16	4 to 1/0
2215	200	300	J	350	250 2-2/0	18 to 16	3 to 300
2283	271	400	J	450	350 2-3/0	18 to 16	2 to 300
2346	324	500	J	600	400 2-250	18 to 16	1 to 350
2415	394	600	J	700	400 2-250	18 to 16	1 to 350

1) NFPA 70 National Electric Code 2011. 430.122(a) and Table 610-14(a) 40°C, 60-minute, copper 50°C ambient

2) NFPA 70 National Electric Code 2011. Table 250.122.

3) NFPA 70 National Electric Code 2011. Table 430.52 (selected based on motor FLA).

4) NFPA 40 National Electric Code 2011. Table 315(b)(2)(a).

Table 3-2: Wire Sizing for 460 V Class

Model # (-G+/VG+S4)	Continuous HD Input Amps	Time Delay Input Fuse (A)	Time Delay Input Fuse Class	Inverse Time Molded/Case Circuit Breaker (A) ³	Recommended Gauge (AWG) ^{1, 4}		
					Power Circuit Wiring	Control Wiring	Ground Copper ²
4001	1.8	2	CC	15	14 to 10	18 to 16	14 to 12
4003	3.2	6	CC	15	14 to 10	18 to 16	14 to 12
4004	4.4	8	CC	15	14 to 10	18 to 16	14 to 10
4005	6.0	9	CC	15	14 to 10	18 to 16	14 to 10
4007	8.2	15	CC	15	14 to 10	18 to 16	14 to 10
4009	10.4	20	CC	15	14 to 10	18 to 16	14 to 10
4014	15.0	25	CC	30	12 to 6	18 to 16	14 to 10
4018	20	30	CC	40	10 to 6	18 to 16	12 to 10
4024	29	35	J	50	8 to 6	18 to 16	10 to 8
4031	39	45	J	60	8 to 6	18 to 16	10 to 6
4039	44	50	J	70	6 to 4	18 to 16	8 to 6
4045	43	60	J	80	6 to 4	18 to 16	8 to 6
4060	58	80	J	100	4 to 2	18 to 16	6
4075	71	100	J	125	4 to 2	18 to 16	6 to 4
4091	86	125	J	175	2 to 1/0	18 to 16	6 to 4
4112	105	150	J	225	1/0 to 2/0	18 to 16	4
4150	142	200	J	300	3/0 to 4/0	18 to 16	4 to 2
4180	170	250	J	350	250 2-2/0	18 to 16	4 to 300
4216	207	300	J	400	250 2-2/0	18 to 16	2 to 350
4260	248	350	J	500	350 2-3/0	18 to 16	2 to 350
4304	300	400	J	600	350 2-4/0	18 to 16	1 to 350
4370	346	500	J	700	500 2-250	18 to 16	1 to 1/0
4450	410	700	L	900	500 2-300 4-3/0	18 to 16	1/0 to 300
4605	584	800	L	1200	2-400 4-250 4-3/0	18 to 16	2/0 to 300
4810	830	1400	L	1500	4/0 x 4P x 2	18 to 16	3/0 to 300
41090	1031	1600	L	2000	300 x 4P x 2	18 to 16	4/0 to 300

1) NFPA 70 National Electric Code 2011. 430.122(a) and Table 610-14(a) 40°C, 60-minute, copper 50°C ambient

2) NFPA 70 National Electric Code 2011. Table 250.122.

3) NFPA 70 National Electric Code 2011. Table 430.52 (selected based on motor FLA).

4) NFPA 40 National Electric Code 2011. Table 315(b)(2)(a).

Table 3-3: Wire Sizing for 575 V Class

Model # (-G+/VG+S4)	Continuous HD Input Amps	Time Delay Input Fuse (A)	Time Delay Input Fuse Class	Inverse Time Molded/Case Circuit Breaker (A) ³	Recommended Gauge (AWG) ^{1, 4}		
					Power Circuit Wiring	Control Wiring	Ground Copper ²
5001	1.9	3	CC	15	14 to 10	18 to 16	14 to 10
5003	3.6	5	CC	15	14 to 10	18 to 16	14 to 10
5004	5.1	7	CC	15	14 to 10	18 to 16	14 to 10
5006	8.3	10	CC	15	14 to 10	18 to 16	12 to 10
5009	12	15	CC	20	14 to 10	18 to 16	12 to 8
5012	16	20	CC	25	10 to 8	18 to 16	12 to 8
5017	23	25	CC	35	10 to 8	18 to 16	10 to 6
5022	31	35	J	45	10 to 6	18 to 16	10 to 6
5027	38	45	J	50	10 to 6	18 to 16	10 to 6
5032	33	50	J	60	10 to 6	18 to 16	6
5041	44	60	J	80	8 to 4	18 to 16	6
5052	54	70	J	100	6 to 4	18 to 16	4
5062	66	90	J	125	4	18 to 16	4
5077	80	100	J	150	4	18 to 16	4
5099	108	125	J	200	2	18 to 16	4 to 300
5130	129	175	J	250	1/0	18 to 16	4 to 300
5172	158	225	J	350	2/0	18 to 16	1 to 350
5200	228	300	J	450	3/0	18 to 16	1 to 350

1) NFPA 70 National Electric Code 2011. 430.122(a) and Table 610-14(a) 40°C, 60-minute, copper 50°C ambient

2) NFPA 70 National Electric Code 2011. Table 250.122.

3) NFPA 70 National Electric Code 2011. Table 430.52 (selected based on motor FLA).

4) NFPA 40 National Electric Code 2011. Table 315(b)(2)(a).

Power Circuit Wiring Procedures

To wire the power circuit for IMPULSE®•G+ & VG+ Series 4:

1. Run the three-phase power supply wires through an appropriate enclosure hole.
2. Refer to “Suggested Circuit Protection Specifications and Wire Size” on page 3-6, connect the three-phase power supply wires to a circuit protection system.
3. Connect the three-phase power supply wires from the circuit protection Terminals R/L1, S/L2, and T/L3.
4. From Terminals U/T1, V/T2, and W/T3, connect the power output wires to the motor. If a load reactor is used, connect these output wires to the reactor input instead; then connect the reactor output to the motor.

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

Table 3-4: Main Circuit Terminal Wiring

Terminal	Drive Model			Function
	230 V Class	2003 to 2075	2085 to 2115	
460 V Class	4001 to 4039	4045 to 4060	4075 to 41090	
575 V Class	5001 to 5027	5032 to 5041	5052 to 5200	
R/L1	Main circuit power supply input <i>NOTE: 6-pulse operation only</i>			Connects line power to the drive
S/L2				
T/L3				
U/T1	Drive Output			Connects to the motor
V/T2				
W/T3				
B1	Braking Resistor		Not Available	Available for connecting a braking resistor or a braking resistor unit option
B2				
+2	DC link choke connection (+1, +2) (remove the bar between +1 and +2) DC power supply input (+1, -)	Not Available		For connecting: <ul style="list-style-type: none"> • the drive to a DC power supply (terminals +1 and - are not UE/CE or UL approved) • dynamic braking options • a DC link choke
+1		DC power supply input (+1, -)	DC power supply input (+1, -)	
--				
+3	Not available Same as B1 on models: 2003 to 2115 4001 to 4060 5001 to 5041			
⊕	For 230 V class: 100Ω or less For 460 V class: 10Ω or less For 575 V class: 10Ω or less			Grounding terminal

Main Circuit Connection Diagram

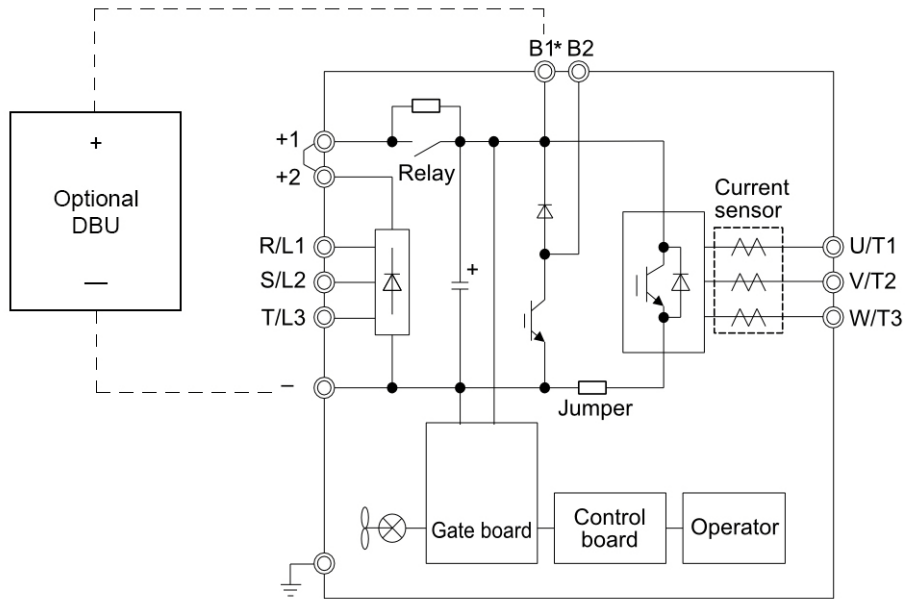


Figure 3-2: Connecting Main Circuit Terminals
 (2003 to 2075)
 (4001 to 4039)
 (5001 to 5027)

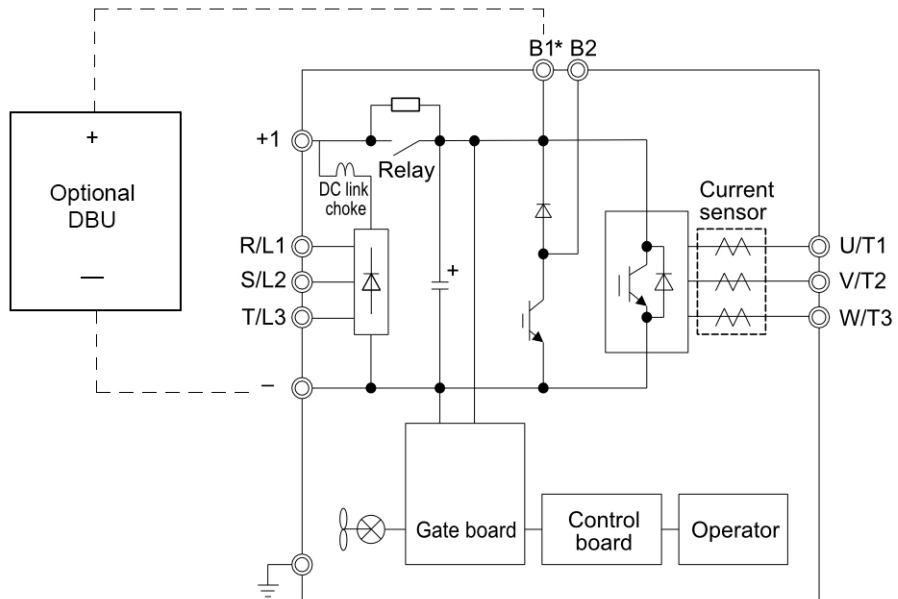


Figure 3-3: Connecting Main Circuit Terminals
 (2085 and 2115)
 (4045 and 4060)
 (5032 and 5041)

* Connect optional DBU to terminals B1 and -

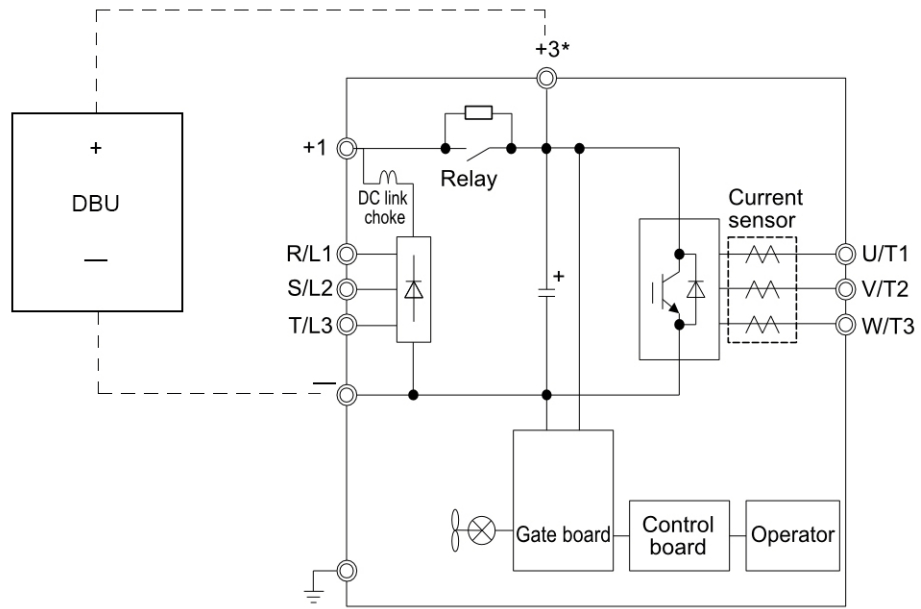


Figure 3-4: Connecting Main Circuit Terminals
 (2145 to 2180)
 (4075 to 4112)
 (5052 to 5077)

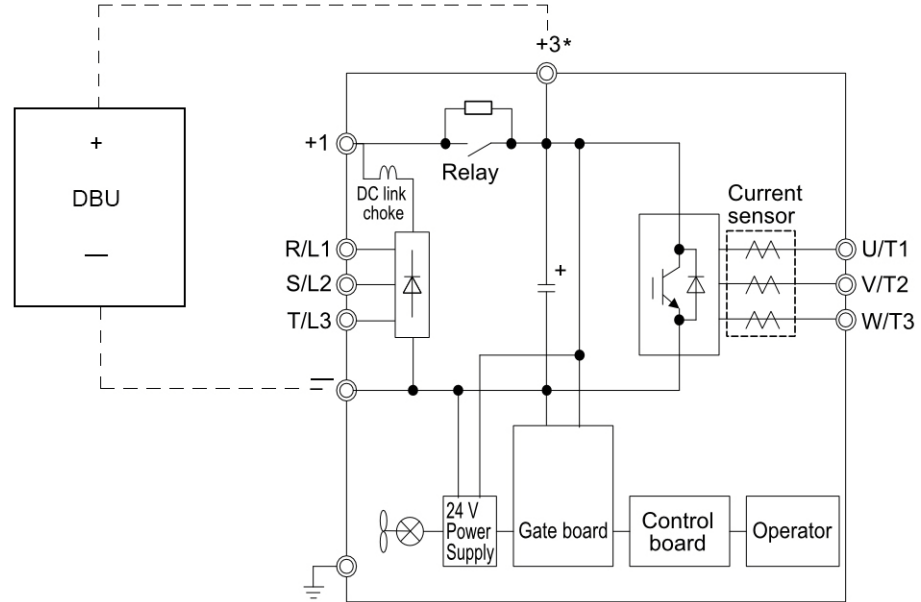
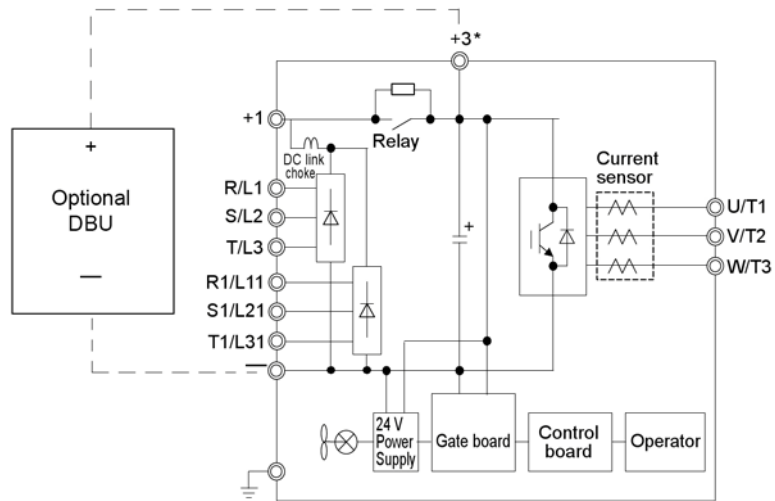


Figure 3-5: Connecting Main Circuit Terminals
 (2215 to 2415)
 (4150 to 4605)
 (5099 to 5200)

* Connect optional DBU to terminals +3 and -



**Figure 3-6: Connecting Main Circuit Terminals
4810 and 41090**

* Connect optional DBU to terminals +3 and -

Terminal Block Configuration

Figure 3-7 and Figure 3-8 show the different main circuit terminal arrangements for the drive capacities.

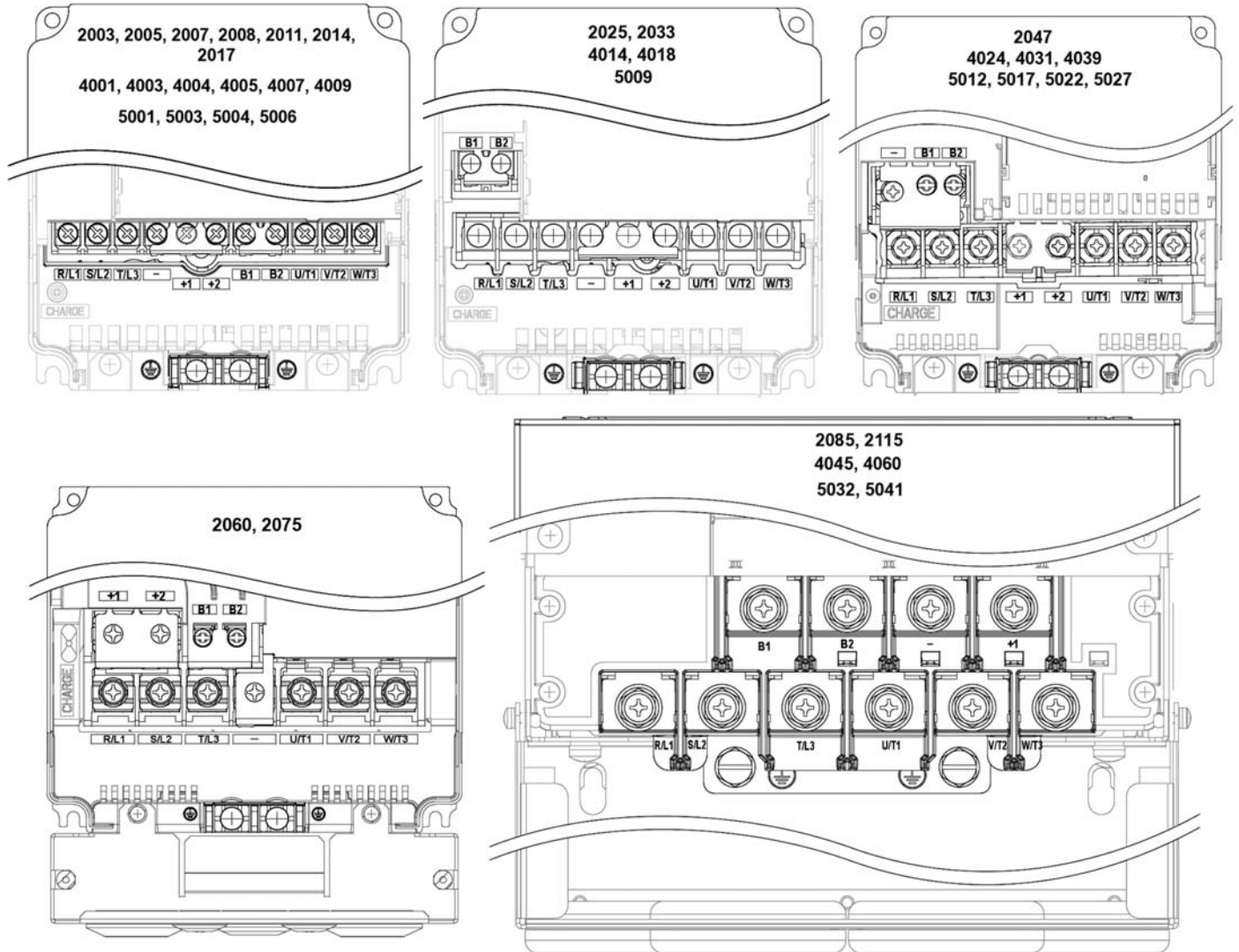
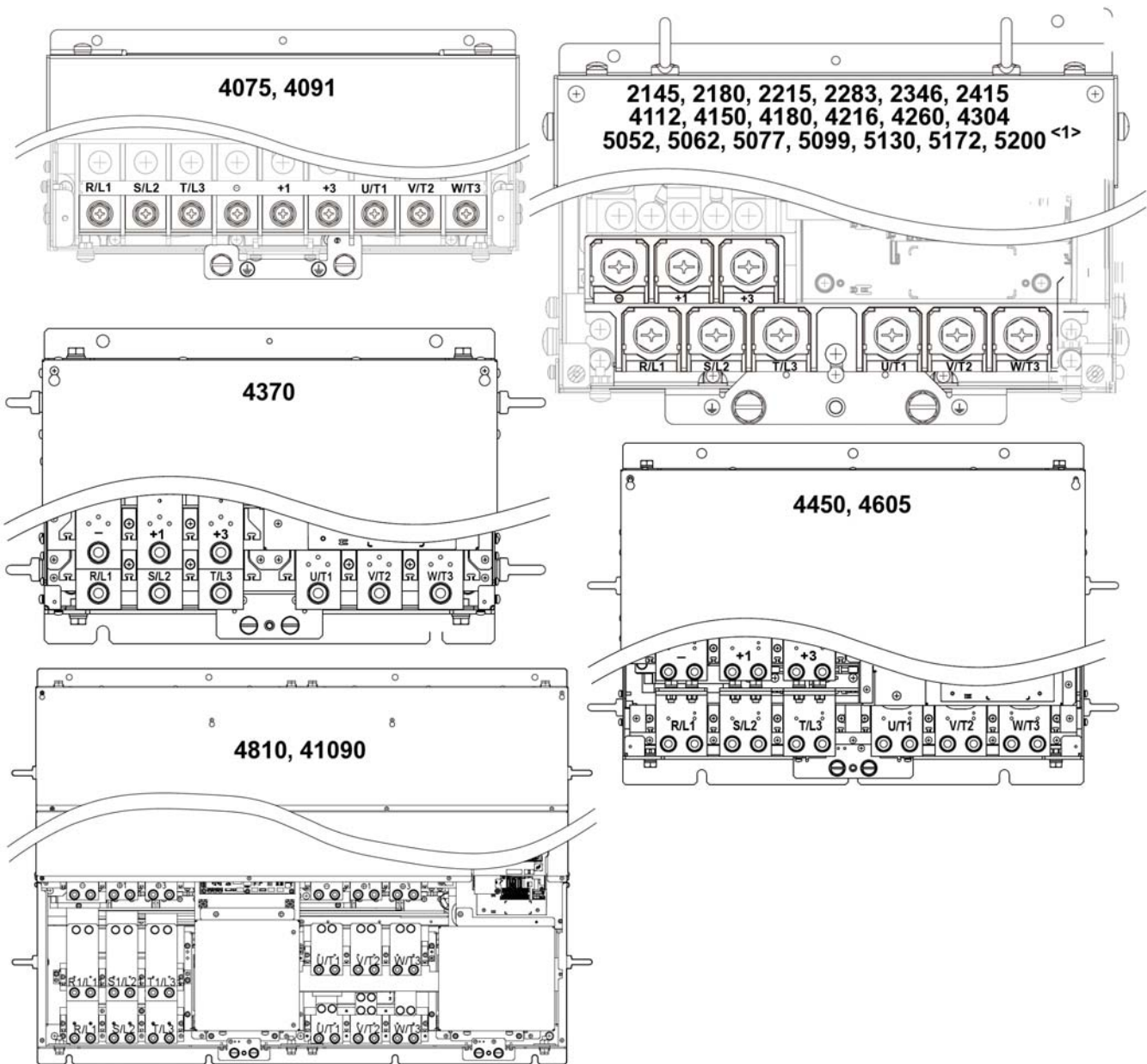


Figure 3-7: Main Circuit Terminal Block Configuration



<1> Terminal block design differs slightly for models 2215 to 2415, 4180 to 4304, and 5099 to 5200.

Figure 3-8: Main Circuit Terminal Block Configuration (continued)

Insulation Barrier

Insulation barriers are packaged with drive models 4370 through 41090 to provide added protection between terminals. Magnetek recommends using the provided insulation barriers to ensure proper wiring. Refer to Figure 3-9 for instructions on placement of the insulation barriers.

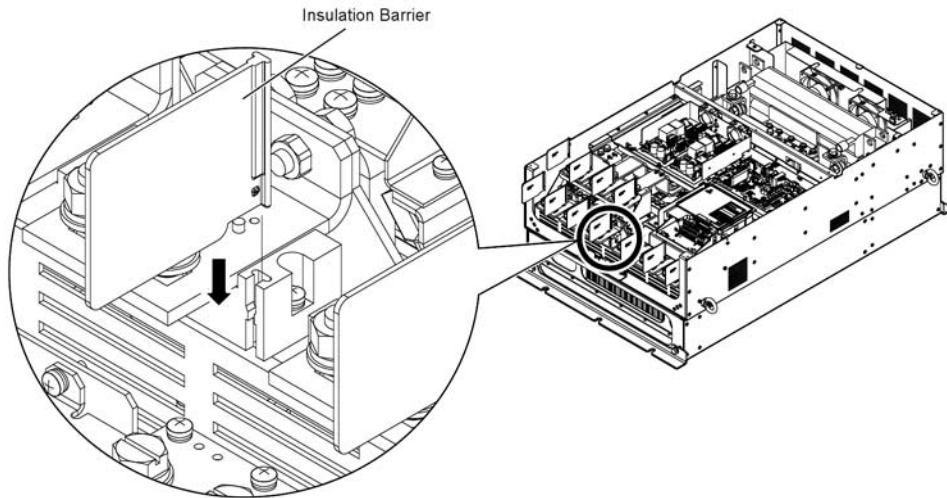


Figure 3-9: Installing Insulation Barriers

Grounding

5. Connect terminal G to the common panel ground. Use ground wiring as specified in “Suggested Circuit Protection and Wire Size” on page 3-6, and keep the length as short as possible.
- Ground Resistance:
 - For 230V class: 100Ω or less
 - For 460V class: 10Ω or less
 - For 575V class: 10Ω or less
 - Never run the IMPULSE®•G+ & VG+ Series 4 drive ground wires in common with welding machines, or other high-current electrical equipment.
 - When more than one drive is used for the same system, ground each directly or daisy-chain to the ground pole. Do not loop the ground wires.

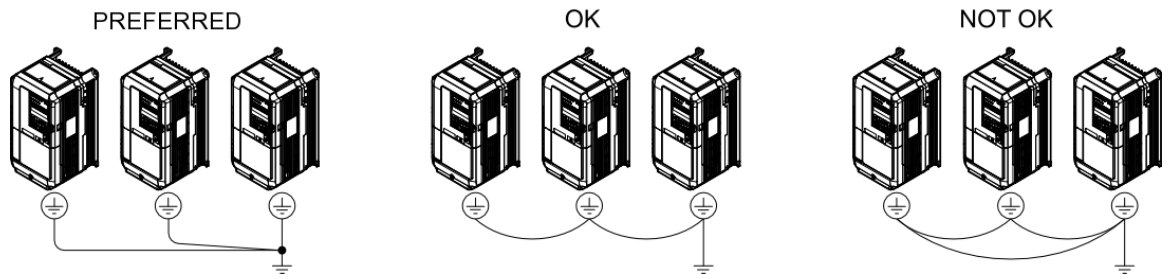


Figure 3-10: Grounding



Figure 3-11: Motor Grounding

Interface Circuit Board

S4IF DIP Switches and Jumper

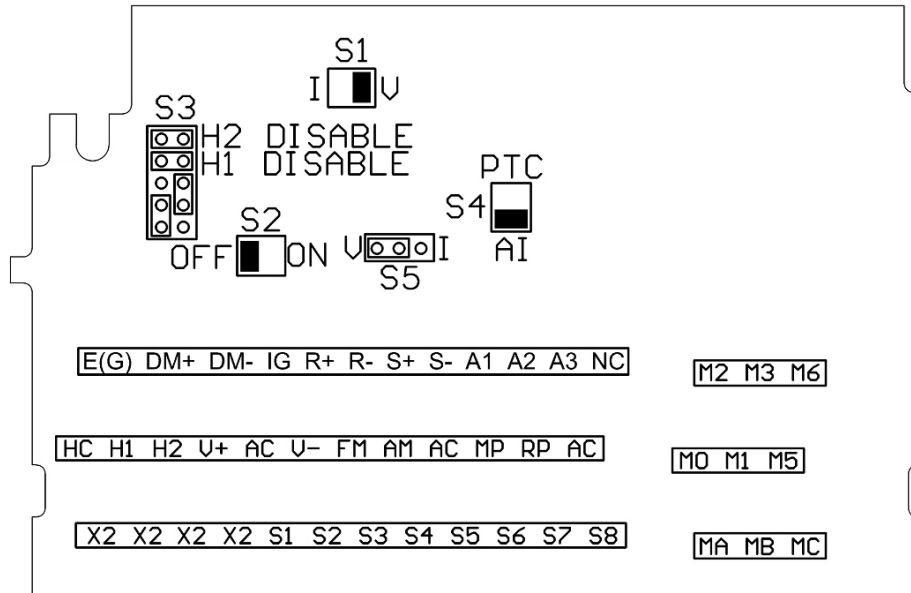


Figure 3-12: S4IF DIP Switches and Jumper Locations for 120 VAC, 42–48 VAC, and 24 VAC)

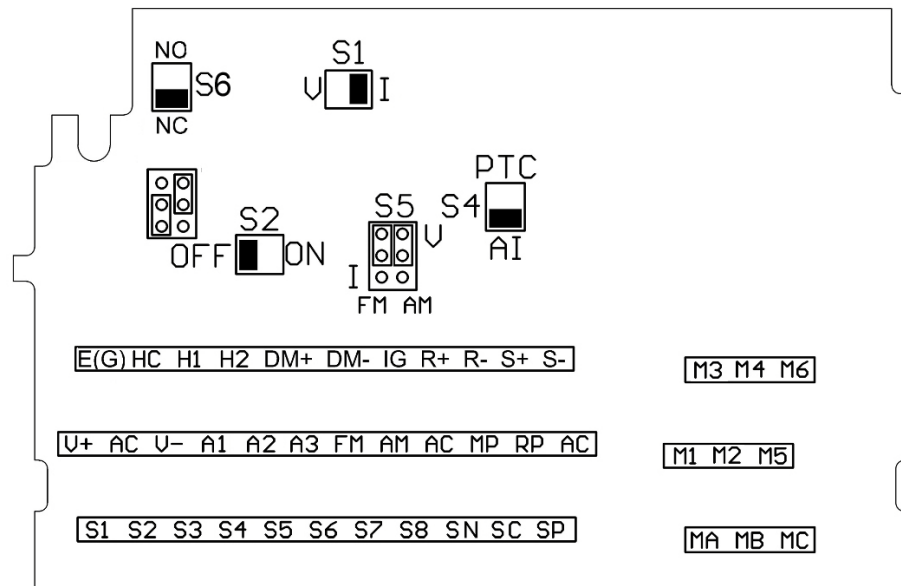


Figure 3-13: S4IF DIP Switches and Jumper Locations for 24 VDC

Table 3-5: Terminal and Wire Specifications

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

Dip Switches

DIP Switches are described in this section. The functions of the DIP switches are shown in the table below.

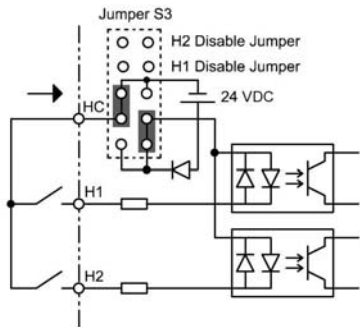
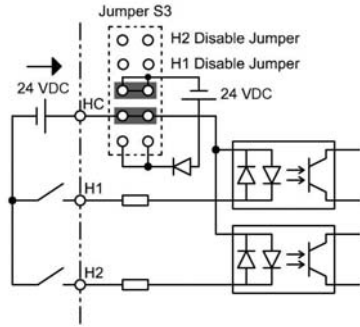
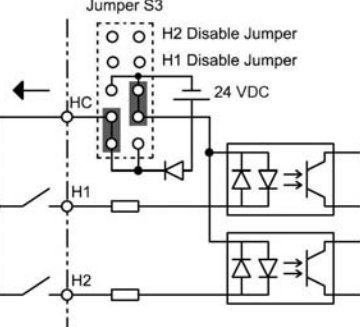
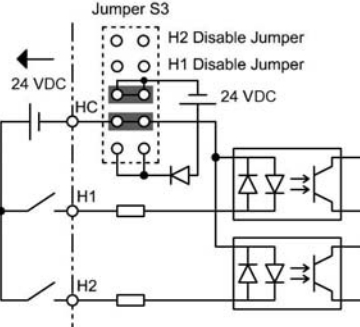
Table 3-6: DIP Switches

Name	Function	Setting
S1	Input method for analog input A2	V: 0 to 10 VDC or -10 to 10 VDC (internal resistance: 20 Ω) (default) I: 4-20mA (internal resistance: 250 Ω)
S2	RS-485 and RS-422 terminating resistance	OFF: No terminating resistance (default) ON: Terminating resistance of 120 Ω
S3	Hardware Base Block Configuration	See page 3-19 for setting details
S4	Analog 3/PTC input select	AI: A3 is used as Analog Input 3 (default) PTC: A3 is used with a Positive Temperature Coefficient (PTC) thermistor
S5	Output method for analog output FM	V: 0 to 10 VDC or -10 VDC to 10 VDC (default) I: 4 to 20 mA

Sinking/Sourcing Mode Selection for Safe Disable Inputs

Use jumper S3 on the Interface Board to select between Sink mode, Source mode, or external power for the Safe Disable inputs H1 and H2 (as shown in Table 3-7). Jumper S3 is also used to disable the Safe Disable inputs H1 and H2, with the jumpers in place the Safe Disable inputs are disabled. Remove H1 and H2 disable jumpers if external Safe Disable functionality is to be used. Refer to Figure 3-12 for locating jumper S3.

Table 3-7: Safe Disable Input Sink/Source/External Power Supply Selection

Mode	Drive Internal Power Supply	External 24 VDC Power Supply
Sinking Mode		
		

(Default)

Control Circuit Terminals

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

Terms:

- Multi-Function Digital Input (MFDI)
- Multi-Function Digital Output (MFDO)
- Multi-Function Analog Input (MFAI)
- Multi-Function Analog Output (MFAO)

Table 3-8: Control Circuit Terminals

Classification	Terminal	Signal Function	Description	Signal Level
Digital Input Signals	S1	MFDI 1	Programmable Multi-function digital inputs (H01-01 to H01-08)	Photo-coupler isolation 120 VAC
	S2	MFDI 2		
	S3	MFDI 3		
	S4	MFDI 4		
	S5	MFDI 5		
	S6	MFDI 6		
	S7	MFDI 7		
	S8	MFDI 8		
		X2	MFDI Common	Common for control signal
Analog Input Signals	+V	Power supply for analog inputs	Positive supply for analog inputs	+10.5 VDC, 20 mA
	-V	Power supply for analog inputs	Negative supply for analog inputs	-10.5 VDC, 20 mA
	A1	MFAI 1	Multi-function analog input (H03-02)	-10 to +10 V (20kΩ) 0 to +10 V (20kΩ)
	A2	MFAI 2	Multi-function analog input (H03-10)	-10 to +10 V (20kΩ) 0 to +10 V (20kΩ) 4 to 20 mA (250Ω)
	A3	MFAI 3	Multi-function analog input (H03-06)	-10 to +10 V (20kΩ) 0 to +10 V (20kΩ)
	AC	Analog Common	Common for analog signal	0 V
	E(G)	Ground for shielded lines and option cards	Earth ground	-
Digital Output Signals	M0	MFDO 1	Multi-function digital output (H02-01)	Form A Relay: 250 VAC (48 VAC for CE), 1 A 30 VDC, 1 A
	M1			
	M2	MFDO 2	Multi-function digital output (H02-02)	Form A Relay: 250 VAC (48 VAC for CE), 1 A 30 VDC, 1 A
	M3			
	M5	MFDO 3	Multi-function digital output (H02-03)	Form A Relay: 250 VAC (48 VAC for CE), 1 A 30 VDC, 1 A
	M6			
	MA	Fault annunciate Terminals MA-MC: N/O Terminals MB-MC: N/C	Terminals MA & MC N/O; closed at major faults Terminals MB & MC N/C open at major faults	Form C Relay: 250 VAC (48 VAC for CE), 1 A 30 VDC, 1 A
	MB			
MC				

Classification	Terminal	Signal Function	Description	Signal Level
Analog Output Signal	FM	MFAO 1	Multi-function analog output (H04-01 to H04-03)	-10 to +10V, 2 mA 0 to +10V, 2 mA 4 to 20 mA
	AC	Analog Common	Analog signal common	0V
	AM	MFAO 2	Multi-function analog output 2 (H04-04 to H04-06)	-10 to +10V, 2 mA 0 to +10V, 2 mA
Pulse I/O Signal	RP	Multi-Function Pulse Train Input	Pulse input frequency reference (H06-01)	Input Freq.: 0 to 32 kHz Duty Cycle: 30 to 70% High level: 3.5 to 13.2 VDC Low Level: 0 to 0.8 VDC Input Impedance: 3kΩ
	MP	Pulse train output (Output frequency)	Pulse output frequency (H06-06)	32 kHz (max)
RS-485/422	R+	Receive (+)	For 2-wire RS-485, jumper R+ and S+ and jumper R- and S-	RS-485/422 Line Driver 115.2 kbps (max)
	R-	Receive (-)		
	S+	Transmit (+)		
	S-	Transmit (-)		
	IG	Shield connection	Serial Communication Shield	0V
Safe Disable	H1	Safe Disable input 1	• One or both open: Motor Output Disabled • Both closed: normal operation • Off time of at least 1ms	24 VDC, 8 mA Internal Impedance: 3.3kΩ
	H2	Safe Disable input 2		
	HC	Safe Disable common		-
	DM+	Safety monitor output	Outputs the status of the Safe Disable function. Closed when both Safe Disable channels are closed.	48 VDC, 8 mA
	DM-	Safety monitor output common		-

S4IF Control Circuit Terminal Diagrams

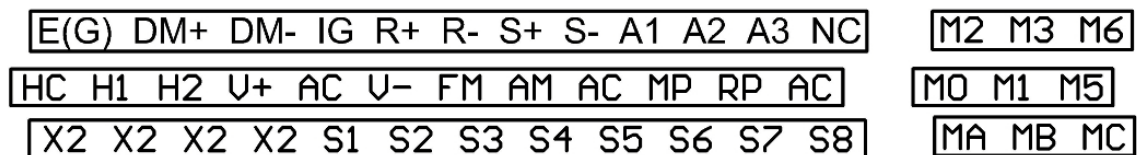


Figure 3-14: S4IF Control Circuit Terminal Diagram (120 VAC, 42–48 VAC, 24 VAC)

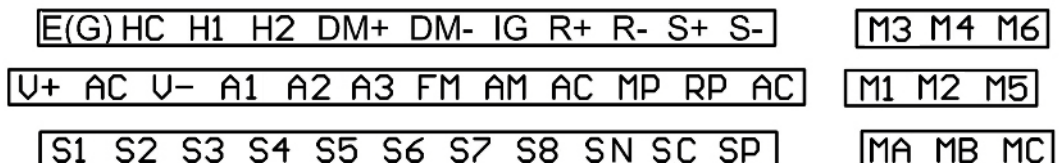


Figure 3-15: S4IF Control Circuit Terminal Diagram (24 VDC)

Safe Torque Off

The Safe Disable inputs provide a stop function in compliance with “Safe Torque Off” as defined in IEC/EN 61800-5-2. Safe Disable inputs have been designed to meet the requirements of the ISO/EN 13849-1, Category 3 PLd, and IEC/EN 61508, SIL2.

Inputs/Outputs		Two Safe Disable inputs and one EDM output according to ISO/EN 13849-1 Cat. 3 PLd, IEC/EN 61508 SIL2.
Operation Time		Time from input open to drive output stop is less than 1 ms.
Failure Probability	Demand Rate Low	PFD = $5.15E^{-5}$
	Demand Rate High/Continuous	PFH = $1.2E^{-9}$
Performance Level		The Safe Disable inputs satisfy all requirements of Performance Level (PL) d according to ISO/EN 13849-1 (DC from EDM considered).

Safe Torque Off disable the drive power section for mechanical maintenance, E-stops, or redundancy safety monitor controller intervention. The feature provides safe removal of motor torque without removal of power to the drive. This is a standard feature on the IMPULSE®•G+ & VG+ Series 4. A Safe Disable Status Monitor for error detection in the safety circuit is also provided.

The Safe Disable circuit (Figure 3-16) consists of two independent input channels (H1 and H2) that can block the output transistors and provide a monitoring output channel (DM+ and DM-) to indicate the status of those input channels.

The input can use the internal 24VDC power supply of the drive or an external power supply, and it will support Sink mode or Source mode. The mode selected for the digital input terminals S1 to S8 by jumper S3 will also be used for the Safe Disable inputs.

NOTE: Terminals H1, H2, DM+, and DM- on 575V class models are designed to the functionality, but are not certified to IEC/EN 61800-5-1, ISO/EN 13849 Cat. 3, IEC/EN 61508 SIL2, Insulation coordination: class 1.

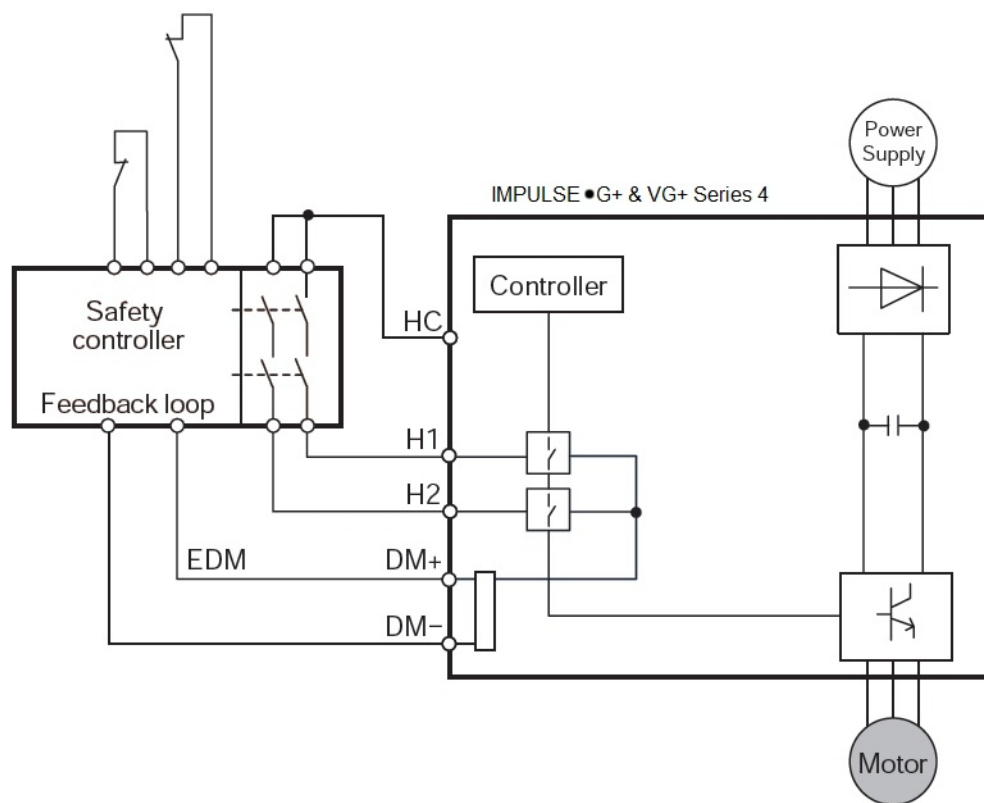


Figure 3-16: Safe Torque Off Block Diagram

Wiring the Encoder Circuit

A shaft-mounted encoder is required to provide speed and shaft position feedback to IMPULSE®•VG+ Series 4. Without an encoder, a flux vector control cannot operate properly.

Before you wire the encoder circuit, refer to the specification tables 3-10 and 3-11 on page 3-25 and “Suggested Circuit Protection Specifications and Wire Size” on page 3-6.

Encoder Circuit Wiring Procedures

Table 3-9: Encoder Specifications

Power supply	+12 VDC (+5 VDC by CN3 jumper); if current demand is greater than 200 mA (consult factory if inrush currents exceed 200 mA), an auxiliary power supply must be equipped - contact Magnetek to purchase
Output Type	Quadrature (A and B channels; Z is not required)
Type of output circuit	High-speed, differential line drive (open collector interface is optional).
Maximum Input Frequency	300 kHz
Mounting method	Encoder must be direct-coupled to motor shaft, using a zero-backlash-type coupling.

To wire the encoder circuit for IMPULSE®•VG+ Series 4 (assuming the cover and keypad are detached):

1. Direct-couple the encoder to the motor shaft, using a zero-backlash-type coupling.
NOTE: Do not connect the encoder to the motor with roller chain or gear drive. If unable to direct-couple the encoder, use a timing belt to drive the encoder. (Contact Magnetek for encoder kits.) Also, do not connect the encoder to the low-speed shaft of a speed reducer.
2. Connect the encoder to the PG-X3 Encoder Interface Card. Refer to Figure 3-17: “PG-X3 Encoder Card Wiring” on page 3-25.
NOTE: Use twisted-pair, shielded cable W100W impedance (Magnetek R-20/6, R-22/6, Belden 9730, or Brand Rex T-11651). Strip the encoder wires .25 in. (5.5 mm). Keep the wiring length less than 300 feet (for cable lengths greater than 300 feet, contact Magnetek for information on available fiber optic cable).
3. Ground the shielded cable to Terminal FE of the PG-X3 Encoder Interface Card (ground only one end of the shielded cable).
NOTE: For LakeShore encoders, the shield connection is not considered “Ground.” The shield should be grounded.
4. Whenever possible, the encoder cable should be wired in a continuous run between the motor and drive. If it cannot be a direct run, the splice should be in its own junction box and isolated from the power wires.

Encoder Wiring Diagrams and Information

Encoder 1: Install in option port CN5-C

Encoder 2: Install in option port CN5-B.

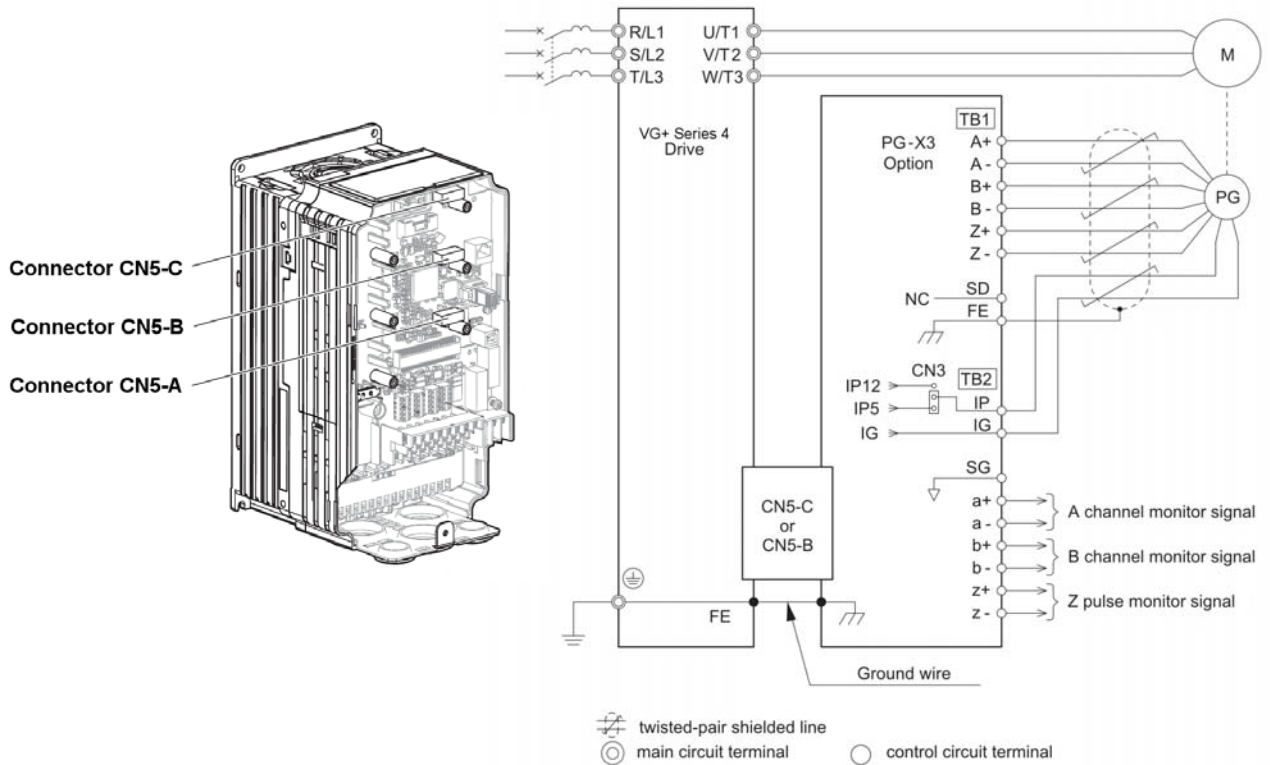


Figure 3-17: PG-X3 Encoder Card Wiring

Table 3-10: Encoder Wiring

Encoder Signal	Wire Color	PG-X3 Terminal
+5 to 15 VDC	Red	IP
0V	Black	IG
A+	Blue	A+
A-	Gray	A-
B+	Green	B+
B-	Yellow	B-
Shield	--	FE

Table 3-11: PG-X3 Line Driver Encoder Interface Card Specifications

Power supply to encoder:	Dual; +5 VDC or +12 VDC; 200 mA maximum
Encoder input signal:	RS-422-level, line-driver-type
Pulse monitor output signal (repeater):	RS-422-level, line-driver-type or open collector
Pulse phases accepted:	Phases A and B (both + and -)
Maximum input frequency:	300 kHz

NOTE: See PG-B3 Open Collector Encoder Card manual for wiring and terminal descriptions.

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Chapter **4**

Getting Started

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Overview

With its easy-to-use keypad and X-Press Programming, the IMPULSE®•G+ & VG+ Series 4 makes it easy to get up and running right away. In addition to explaining the keypad and X-Press Programming, this chapter explains how to view the scroll settings, get into the programming mode, and program speeds.

Checks Before Powering

After mounting and interconnections are completed, verify:

- Correct connections.
- Correct input power supply (no voltage drop or imbalance, source kVA \leq 500, unless a line reactor is used).
- No short circuit conditions.
- No loose screw terminals (check especially for loose wire clippings).
- Proper load conditions.

Precautions

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



DANGER

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

Using the Keypad

With five 16-character lines available, the keypad display makes it possible to monitor drive operation, change parameter settings, and view fault codes. In addition, the parameter description is included on the top line of the display. The keypad enables you to:

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

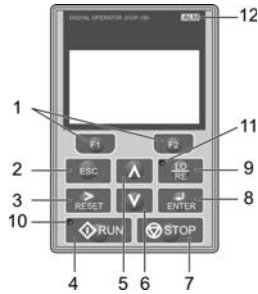


WARNING

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

Keypad LED and Button Functions

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



1		The functions assigned to F1 and F2 vary depending on the current displayed menu. The name of each function appears in the lower half of the display window.
2		<ul style="list-style-type: none"> Returns to the previous display Moves the cursor one space to the left. Pressing and holding this button will return to the Frequency Reference Display.
3		<ul style="list-style-type: none"> Moves the cursor to the right. Resets the drive to clear a fault situation.
4		Starts the drive when in LOCAL mode.
5		Scrolls up to display the next item, selects parameter numbers, and increments setting values.
6		Scrolls down to display the previous item, selects parameter numbers, and decrements setting values.
7		Stops drive operation. *1
8		<ul style="list-style-type: none"> Enters parameter values and settings. Selects a menu item to move between displays.
9		<ul style="list-style-type: none"> Displays the phone number for the Magnetek Service department. Switches drive control between the operator (LOCAL) and an external source (REMOTE) for the Run command and frequency reference. *2 Pressing the key three times resets the maintenance timer, U01-52.
10		Lit while the drive is operating the motor. Flashing when the drive has a phantom fault.
11		Lit while the operator is selected to run the drive (LOCAL mode).
12		Off during normal operation (no fault or alarm). Illuminated when the drive detects an alarm or error. Flashes when an alarm occurs, when an oPE is detected, or when a fault or error occurs during Auto-Tuning.

*1 The STOP key has highest priority. Pressing the STOP key will always cause the drive to stop the motor, even if a Run command is active at any external Run command source.

*2 The LO/RE key can only switch between LOCAL and REMOTE when the drive is stopped. To enable the LO/RE key to switch between LOCAL and REMOTE, set parameter O02-01 to 1.

Parameters

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

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

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

The drive can be programmed to allow personnel with limited crane system knowledge to program only certain parameters, called **User Parameters**. To select these parameters, see "User Parameters (A02-01 through 32)" on page 4-16.

Two other features to be aware of are **Initialize Parameters** (A01-05) and **User Defaults** (O02-03). Both of these features are related and revert back to previously saved parameter settings. This is especially helpful when a number of programming changes were made, but the previous settings may still be needed. To program these features, see "Initialize Parameters (A01-05)" on page 4-15 and "User Defaults (O02-03)" on page 5-124.

Parameter Modes

All parameters are organized under four modes:

Operation Mode

Drive operation is enabled. Drive status LED is lit.

Programming Mode

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

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

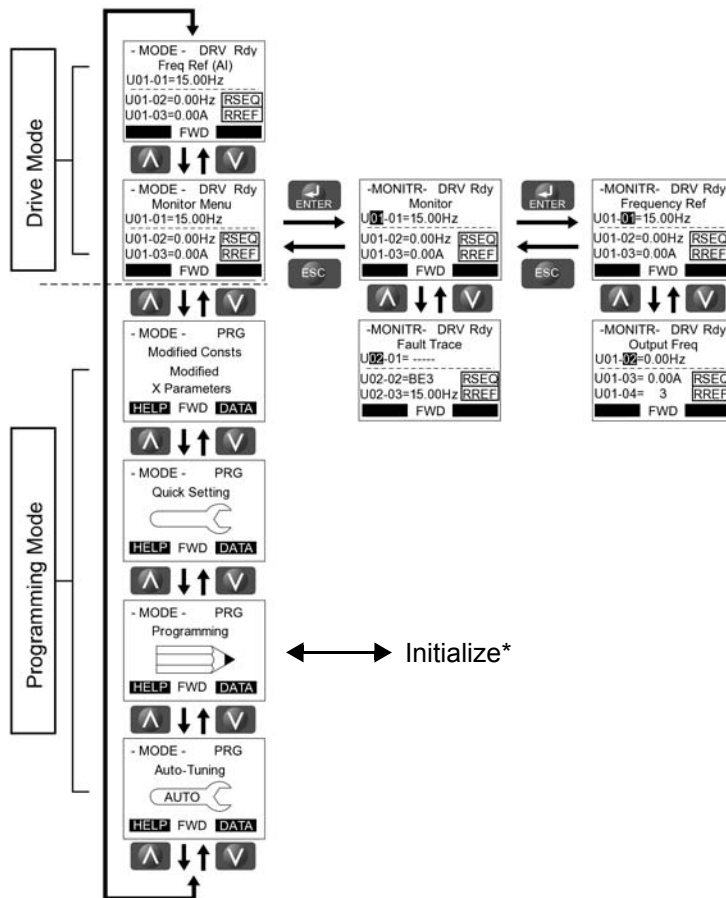
Auto-Tuning Mode

Automatically calculates and sets motor parameters to optimize drive performance.

Modified Constants Mode

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

IMPULSE®•G+ & VG+ Series 4 Menu Structure



*Refer to parameter list on page 4-8.

Figure 4-1: IMPULSE®•G+ & VG+ Menu Structure



Group	Function
Monitor	U01 Monitor
	U02 Fault Trace
	U03 Fault History
	U04 Maintenance
	U06 Control Monitor
Initialize	A01 Initialization Parameters
	A02 User-Defined Parameters
Application	B01 Preset References
	B02 Reference Limits
	B03 Sequence/Reference Source
	B05 Acceleration/Deceleration
	B08 Jump Frequencies
	C01 Quick Stop
	C01 Reverse Plug Simulation
	C02 Micro-Speed
C03 End of Travel Limits	
Special Function	C03 Phantom Stop
	C03 Load Sharing/Torque Following
	C03 Klixon
	C03 Hook Height Measurement
	C03 Electronic Programmable Limit Switches (EPLS)
	C04 Load Float
	C05 Load Check II
	C06 Swift-Lift/Ultra-Lift
	C07 Torque Limit
	C07 Anti-Shock
	C08 No-Load Brake Hoist
	C08 Brake Answerback
	C09 Digital Input Option Set-Up
Tuning	C10 Weight Measurement
	C11 Slack Cable Detection
	C11 Snap Shaft Detection
	C12 Delay Timers and Timer Functions
	C12 Inching Control
	C13 Indexing Control
	D01 DC Injection Braking
	D02 Motor Slip Compensation
	D03 Torque Compensation
	D04 Automatic Speed Regulator Tuning
	D05 Torque Control
D08 Dwell Function	
D09 S-Curve Acceleration/Deceleration	
D10 Carrier Frequency	
D11 Hunting Prevention	
Motor	E01 V/f Pattern 1
	E02 Motor Set-up
	E03 Test Mode
Options	F01 Encoder (PG-X3) Option Set-up
	F02 Analog Input (AI-A3) Option Set-up
	F04 Analog Output (AO-A3) Option Set-up
	F05 Digital Output (DO-A3 or S4IO) Option Set-up
	F06 Communication Option Card Set-Up
	F07 Ethernet Option Card Set-Up
	Terminal
H02 Digital Outputs	
H03 Analog Inputs	
H04 Analog Outputs	
H05 Serial Communication Set-up	
H06 Pulse Train Input/Output Set-up	
Protection	L01 Motor Overload
	L02 Power Loss Ride Thru
	L03 Stall Prevention
	L04 Reference Detection
	L05 Test Mode
	L06 Torque Detection
	L08 Hardware Protection
	L09 Automatic Fault Reset
	Operator
O02 Operator Key	
O03 Maintenance	
O04 Copy Function	

Initialization Set-up

Parameter Access Level (A01-01)

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

Table 4-1: Parameter Access Level Settings

Setting	Description
0	Operation Only Access to only parameters A01-01, A01-06, and all U monitor parameters.
1	User Parameters Accesses parameters selected by OEM or installer (A02-01 to A02-32). These User Parameters can be accessed using the Setup Mode of the digital operator.
2	Advanced Level For advanced programming in special applications. All parameters can be viewed and edited.

Control Method Selection (A01-02)

Select the control method best suited for your application.

Table 4-2: Control Method Selection Settings

Setting	Description	Model
0	V/f Control for Induction Motors (V/f) Use this mode for simple speed control and for multiple motor applications with low demands to dynamic response or speed accuracy. This control method is also used when the motor parameters are unknown and Auto-Tuning cannot be performed. The speed control range is 40:1.	G+
2	Open Loop Vector Control (OLV) Use this mode for general, variable-speed applications that require precise speed control, quick torque response, and high torque at low speed without using a speed feedback signal from the motor (a speed control range of 200:1).	G+
3	Flux Vector Control (FLV) Use this mode for general, variable-speed applications that require precise speed control down to zero speed, quick torque response or precise torque control, and a speed feedback signal from the motor. The speed control range is up to 1500:1.	VG+

NOTE: An auto-tune should be performed for all Flux Vector and Open Loop Vector applications. Refer to the Auto-Tuning section on page 4-17.

X-Press Programming™

X-Press Programming™ automatically configures several commonly used parameters and features when Control Method (A01-02), Motion (A01-03), or Speed Reference (A01-04) are programmed. These parameters are also added to the Quick-Set menu for fast parameter modification. Reference tables 4-6, 4-7, and 4-8 for X-Press™ Programming defaults.

Motion (A01-03)

Set this parameter to match the motion of application. See X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14) for details.

Table 4-3: Select Motion Settings

Setting	Description	Model
0	Traverse	G+/VG+
1	Standard Hoist - G+ Default	G+
2	Hoist NLB - VG+ Default	VG+
4	Braketronic	G+/VG+

Speed Reference (A01-04)

This parameter will automatically define the input terminals for the selections listed below. See X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14) for details.

Table 4-4: Speed Reference Settings

Setting	Description
0	2-SPD Multi-Step — Defines Terminal S3 = 2nd speed.
1	3-SPD Multi-Step — Defines Terminals S3 and S4 as speeds 2 and 3 respectively (default).
2	5-SPD Multi-Step — Defines Terminals S3-S6 as speeds 2–5.
3	2-Step Infinitely Variable — Terminals S1 and S2 use B01-01 and speed hold. Terminal S3 = Accelerate.
4	3-Step Infinitely Variable — Terminals S1 and S2 use B01-01. Terminal S3 = Speed Hold. Terminal S4 = Accelerate.
5	Uni-Polar Analog — Terminals S1 and S2 = A directional input. Terminal A1 = 0-10V. Terminal A2 = 4-20mA (when using Terminal A2, set H03-02 to 1F and H03-10 to 0).
6	Bi-Polar Analog — Terminal S1 = Run Command. Terminal A1 = direction and frequency -10 to +10VDC.
7	Industrial Coms Sets all terminals to “Not Used”. Speed and Run commands come from optional communication card.
8	RS485/RDSI Coms Sets all terminals to “Not Used.” Speed and Run commands come from serial communications.



WARNING

When changing A01-03 or A01-04, MFDI, MFDO, and speed reference parameters will be overwritten by X-Press Programming™ (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14). All parameter settings must be verified for proper operation.

Table 4-5: X-Press Programming I/O Quick Reference

A01-04 =	0	1	2	3	4	5	6
Terminal S1	FWD	FWD	FWD	FWD	FWD	FWD	FWD
Terminal S2	REV	REV	REV	REV	REV	REV	REV
Terminal S3	Step 2	Step 2	Step 2	Accel	Hold	--	--
Terminal S4	--	Step 3	Step 3	--	Accel	--	--
Terminal S5	--	--	Step 4	--	--	--	--
Terminal S6	--	--	Step 5	--	--	--	--
Terminal S7	--	--	--	--	--	--	--
Terminal S8	--	--	--	--	--	--	--
Terminal A1	--	--	--	--	--	FREF	FREF
Terminal M0/M1	Brake	Brake	Brake	Brake	Brake	Brake	Brake
Terminal M2/M3	Brake (NLB), otherwise not used						
Terminal M5/M6	Fault Annunciate (NLB), otherwise not used						

Parameters Changed by X-Press Programming

Table 4-6: Traverse (A01-03= 0) for G+ and VG+S4 Models

Parameter	Description	A01-04 =								
		0 2-Speed Multi- Step	1 3-Speed Multi- Step	2 5-Speed Multi- Step	3 2-Step Infinitely Variable	4 3-Step Infinitely Variable	5 Uni- Polar Analog	6 Bi-Polar Analog	7 Indus- trial Coms	8 RS485/ RDSI Coms
B01-01	Speed 1	20.00	15.00	6.00	6.00	6.00	0.00	0.00	15.00	0.00
B01-02	Speed 2	60.00	30.00	15.00	0.00	0.00	0.00	0.00	30.00	0.00
B01-03	Speed 3	0.00	60.00	30.00	0.00	0.00	0.00	0.00	60.00	0.00
B01-04	Speed 4	0.00	0.00	45.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-05	Speed 5	0.00	0.00	60.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-06–16	Speed 6–16	0.00	0.00	0.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-17	Jog Ref	6.00	6.00	6.00	6.00	6.00	6.00	6.00	6.00	6.00
B01-18	Ref Priority	0	0	0	0	0	1	1	0	1
B02-03	Ref. Lower Limit	2.0	2.0	2.0	2.0	2.0	2.0	2.0	2.0	2.0
B03-01	Freq. Ref. Select	1	1	1	1	1	1	1	3	2
B03-02	Run Cmd Select	1	1	1	1	1	1	1	3	2
B03-03	Stopping Method	0	0	0	0	0	0	0	0	0
B05-01	Accel Time 1	5.0	5.0	5.0	5.0	5.0	5.0	5.0	5.0	5.0
B05-02	Decel Time 1	5.0	5.0	5.0	5.0	5.0	5.0	5.0	5.0	5.0
C01-01	Quick Stop	0	0	0	0	0	0	0	0	0
C03-07	Action @ LL1/UL2	2	2	2	2	2	2	2	2	2
C08-10	Load Float Time	0	0	0	0	0	0	0	0	0
C13-12	Index Brake Ctrl	0	0	0	0	0	0	0	0	0
D09-01	S-Curve Accel at Start	1.50	1.50	1.50	1.50	1.50	1.50	1.50	1.50	1.50
D09-02	S-Curve Accel at End	1.50	1.50	1.50	1.50	1.50	1.50	1.50	1.50	1.50
D09-03	S-Curve Decel at Start	1.50	1.50	1.50	1.50	1.50	1.50	1.50	1.50	1.50
E01-03	V/f Selection	00	00	00	00	00	00	00	00	00
H01-01	Terminal S1 Select	80	80	80	80	80	80	80	80	0F
H01-02	Terminal S2 Select	81	81	81	81	81	81	81	81	0F
H01-03	Terminal S3 Select	00	00	00	05	04	0F	0F	0F	0F
H01-04	Terminal S4 Select	0F	01	01	0F	05	0F	0F	0F	0F
H01-05	Terminal S5 Select	0F	0F	02	0F	0F	0F	0F	0F	0F
H01-06	Terminal S6 Select	0F	0F	03	0F	0F	0F	0F	0F	0F
H01-07	Terminal S7 Select	0F	0F	0F	0F	0F	0F	0F	0F	0F
H01-08	Terminal S8 Select	0F	0F	0F	0F	0F	0F	0F	0F	0F
H02-01	Terminal M0/M1 Select	000	000	000	000	000	000	000	000	000
H02-02	Terminal M2/M3 Select	00F	00F	00F	00F	00F	00F	00F	00F	00F
H02-03	Terminal M5/M6 Select	00F	00F	00F	00F	00F	00F	00F	00F	00F
H03-01	Terminal A1 Signal Level	0	0	0	0	0	0	1	0	0
H03-02	Terminal A1 Select	0	0	0	0	0	0	0	0	0
H03-06	Terminal A3 Select	1F	1F	1F	1F	1F	1F	1F	1F	1F
H03-10	Terminal A2 Select	1F	1F	1F	1F	1F	1F	1F	1F	1F

Table 4-7: Hoist - Standard Hoist (A01-03 = 1) for G+S4 Models

Parameter	Description	A01-04 =								
		0 2-Speed Multi- Step	1 3-Speed Multi- Step	2 5-Speed Multi- Step	3 2-Step Infinitely Variable	4 3-Step Infinitely Variable	5 Uni- Polar Analog	6 Bi-Polar Analog	7 Indus- trial Coms	8 RS485/ RDSI Coms
B01-01	Speed 1	20.00	15.00	6.00	6.00	6.00	0.00	0.00	15.00	0.00
B01-02	Speed 2	60.00	30.00	15.00	0.00	0.00	0.00	0.00	30.00	0.00
B01-03	Speed 3	0.00	60.00	30.00	0.00	0.00	0.00	0.00	60.00	0.00
B01-04	Speed 4	0.00	0.00	45.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-05	Speed 5	0.00	0.00	60.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-06–16	Speed 6–16	0.00	0.00	0.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-17	Jog Ref	6.00	6.00	6.00	6.00	6.00	6.00	6.00	6.00	6.00
B01-18	Ref Priority	0	0	0	0	0	1	1	0	1
B02-03	Ref. Lower Limit	2.0	2.0	2.0	2.0	2.0	2.0	2.0	2.0	2.0
B03-01	Freq. Ref. Select	1	1	1	1	1	1	1	3	2
B03-02	Run Cmd Select	1	1	1	1	1	1	1	3	2
B03-03	Stopping Method	1	1	1	1	1	1	1	1	1
B05-01	Accel Time 1	5.0	5.0	5.0	5.0	5.0	5.0	5.0	5.0	5.0
B05-02	Decel Time 1	3.0	3.0	3.0	3.0	3.0	3.0	3.0	3.0	3.0
C01-01	Quick Stop	0	0	0	0	0	0	0	0	0
C03-07	Action @ LL1/UL2	1	1	1	1	1	1	1	1	1
C08-10	Load Float Time	0	0	0	0	0	0	0	0	0
C13-12	Index Brake Ctrl	0	0	0	0	0	0	0	0	0
D09-01	S-Curve Accel at Start	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50
D09-02	S-Curve Accel at End	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50
D09-03	S-Curve Decel at Start	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50
E01-03	V/f Selection	04	04	04	04	04	04	04	04	04
H01-01	Terminal S1 Select	80	80	80	80	80	80	80	80	0F
H01-02	Terminal S2 Select	81	81	81	81	81	81	81	81	0F
H01-03	Terminal S3 Select	00	00	00	05	04	0F	0F	0F	0F
H01-04	Terminal S4 Select	0F	01	01	0F	05	0F	0F	0F	0F
H01-05	Terminal S5 Select	0F	0F	02	0F	0F	0F	0F	0F	0F
H01-06	Terminal S6 Select	0F	0F	03	0F	0F	0F	0F	0F	0F
H01-07	Terminal S7 Select	0F	0F	0F	0F	0F	0F	0F	0F	0F
H01-08	Terminal S8 Select	0F	0F	0F	0F	0F	0F	0F	0F	0F
H02-01	Terminal M0/M1 Select	000	000	000	000	000	000	000	000	000
H02-02	Terminal M2/M3 Select	00F	00F	00F	00F	00F	00F	00F	00F	00F
H02-03	Terminal M5/M6 Select	00F	00F	00F	00F	00F	00F	00F	00F	00F
H03-01	Terminal A1 Signal Level	0	0	0	0	0	0	1	0	0
H03-02	Terminal A1 Select	0	0	0	0	0	0	0	0	0
H03-06	Terminal A3 Select	1F	1F	1F	1F	1F	1F	1F	1F	1F
H03-10	Terminal A2 Select	1F	1F	1F	1F	1F	1F	1F	1F	1F

Table 4-8: Hoist NLB (A01-03 = 2) for VG+S4 Models

Parameter	Description	A01-04 =								
		0 2-Speed Multi- Step	1 3-Speed Multi- Step	2 5-Speed Multi- Step	3 2-Step Infinitely Variable	4 3-Step Infinitely Variable	5 Uni- Polar Analog	6 Bi-Polar Analog	7 Indus- trial Coms	8 RS485/ RDSI Coms
B01-01	Speed 1	20.00	15.00	6.00	6.00	6.00	0.00	0.00	15.00	0.00
B01-02	Speed 2	60.00	30.00	15.00	0.00	0.00	0.00	0.00	30.00	0.00
B01-03	Speed 3	0.00	60.00	30.00	0.00	0.00	0.00	0.00	60.00	0.00
B01-04	Speed 4	0.00	0.00	45.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-05	Speed 5	0.00	0.00	60.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-06–16	Speed 6–16	0.00	0.00	0.00	0.00	0.00	0.00	0.00	0.00	0.00
B01-17	Jog Ref	6.00	6.00	6.00	6.00	6.00	6.00	6.00	6.00	6.00
B01-18	Ref Priority	0	0	0	0	0	1	1	0	1
B02-03	Ref. Lower Limit	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0	0.0
B03-01	Freq. Ref. Select	1	1	1	1	1	1	1	3	2
B03-02	Run Cmd Select	1	1	1	1	1	1	1	3	2
B03-03	Stopping Method	6	6	6	6	6	6	6	6	6
B05-01	Accel Time 1	5.0	5.0	5.0	5.0	5.0	5.0	5.0	5.0	5.0
B05-02	Decel Time 1	3.0	3.0	3.0	3.0	3.0	3.0	3.0	3.0	3.0
C01-01	Quick Stop	1	1	1	1	1	1	1	1	1
C03-07	Action @ LL1/UL2	2	2	2	2	2	2	2	2	2
C08-10	Load Float Time	10	10	10	10	10	10	10	10	10
C13-12	Index Brake Ctrl	2	2	2	2	2	2	2	2	2
D09-01	S-Curve Accel at Start	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50
D09-02	S-Curve Accel at End	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50
D09-03	S-Curve Decel at Start	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50	0.50
E01-03	V/f Selection	0F	0F	0F	0F	0F	0F	0F	0F	0F
H01-01	Terminal S1 Select	80	80	80	80	80	80	80	80	0F
H01-02	Terminal S2 Select	81	81	81	81	81	81	81	81	0F
H01-03	Terminal S3 Select	00	00	00	05	04	0F	0F	0F	0F
H01-04	Terminal S4 Select	0F	01	01	0F	05	0F	0F	0F	0F
H01-05	Terminal S5 Select	0F	0F	02	0F	0F	0F	0F	0F	0F
H01-06	Terminal S6 Select	0F	0F	03	0F	0F	0F	0F	0F	0F
H01-07	Terminal S7 Select	0F	0F	0F	0F	0F	0F	0F	0F	0F
H01-08	Terminal S8 Select	0F	0F	0F	0F	0F	0F	0F	0F	0F
H02-01	Terminal M0/M1 Select	000	000	000	000	000	000	000	000	000
H02-02	Terminal M2/M3 Select	000	000	000	000	000	000	000	000	000
H02-03	Terminal M5/M6 Select	078	078	078	078	078	078	078	078	078
H03-01	Terminal A1 Signal Level	0	0	0	0	0	0	1	0	0
H03-02	Terminal A1 Select	0	0	0	0	0	0	0	0	0
H03-06	Terminal A3 Select	1F	1F	1F	1F	1F	1F	1F	1F	1F
H03-10	Terminal A2 Select	1F	1F	1F	1F	1F	1F	1F	1F	1F

Initialize Parameters (A01-05)


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



Table 4-9: Initialize Parameter Settings

Setting	Description
0	No Initialization (factory default)
1110	User Default (defaults) Resets parameters to the values saved by the user as User Settings. User Settings are stored when parameter O02-03 is set to "1: Set defaults". <i>NOTE: User Initialization resets all parameters to a user-defined set of default values previously saved to the drive. Set parameter O02-03 to 2 to clear the user-defined default values.</i>
5432	Cntrl Int→Term Moves the parameters stored in the control board and copies them to the terminal board.
5550	Control Init (OPE04 Reset) An oPE04 error appears on the digital operator when a interface card with settings saved to its built-in memory is installed in a drive that has edited parameters. Set A01-05 to 5550 to use the parameter settings saved to the terminal board (S4IF) memory.
7770	Swap Setup Prepares all modified and user parameters for terminal board (S4IF) replacement.
8880	Swap Exe Finalizes terminal board (S4IF) swap process once A01-05 = 7770 has been executed and the new terminal board (S4IF) has been installed.

NOTE: Performing a 7770 initialization will clear a parameter set stored in the digital operator.

Password Entry (A01-06)

This parameter enables the user to set a password that inhibits the programming of the parameters. This function is useful when used in conjunction with the access level parameter A01-01. To set the password, enter a password number in parameter A01-07 and press the  key. If A01-06 is not the same as A01-07, A01-01 cannot be changed once A01-01 is set to 0 or 1. When A01-06 is the same as A01-07, A01-01 can be changed.

To create a password, when A01-06 is displayed, press the  and  key simultaneously to set A01-07.

User Parameters (A02-01 through 32)

The user can select up to 32 parameters for quick-access programming. By setting the user access level (A01-01) to “User Program”, only the parameters selected in function A2 can be accessed by the user. To assign a parameter as a user parameter, go to the A2 level in the initialize menu. Once the A2 parameters are set and A01-01 is programmed to “User Program”, only the parameters visible in the program menu will be assigned to an A2 parameter.

The A2 group is pre-loaded with the settings listed in table 4-10, based on A01-03.

Table 4-10: Application Quick Set

A01-03	0	1	2
Favorite	Traverse	Std Hoist	NLB Hoist
--	B01-01: Speed 1	B01-01: Speed 1	B01-01: Speed 1
A02-01	B01-02: Speed 2	B01-02: Speed 2	B01-02: Speed 2
A02-02	B01-03: Speed 3	B01-03: Speed 3	B01-03: Speed 3
A02-03	B01-04: Speed 4	B01-04: Speed 4	B01-04: Speed 4
A02-04	B01-05: Speed 5	B01-05: Speed 5	B01-05: Speed 5
A02-05	B03-04: Change Rotation	B03-04: Change Rotation	B03-04: Change Rotation
A02-06	B05-01: Accel Time 1	B05-01: Accel Time 1	B05-01: Accel Time 1
A02-07	B05-02: Decel Time 1	B05-02: Decel Time 1	B05-02: Decel Time 1
A02-08	C01-03: Reverse Plug	C02-01: MicroSpd Gain 1	C01-01: Quick Stop
A02-09	C01-04: Rev-Plg Dec Time	C03-01: UL1 Speed	C01-02: Quick Stop Time
A02-10	C01-05: Rev-Plg Acc Time	C03-04: LL1 Speed	C02-01: MicroSpd Gain 1
A02-11	C02-01: MicroSpd Gain 1	C06-01: Swift-Lift	C03-01: UL1 Speed
A02-12	E01-03: V/f Selection	C06-02: SwiftLift FWDSpd	C03-04: LL1 Speed
A02-13	E02-01: Motor Rated FLA	C06-03: SwiftLift REVSpd	C06-01: Ultra-Lift
A02-14	H01-06: Terminal S6 Select	C06-04: SL FWD Current/Torque	C06-02: UltraLift FWDSpd
A02-15	H01-07: Terminal S7 Select	C06-05: SL REV Current/Torque	C06-03: UltraLift REVSpd
A02-16	H01-08: Terminal S8 Select	C06-06: SL Enabling Spd	C06-04: UL FWD Torque
A02-17	H02-03: Terminal M5/M6 Select	E01-03: V/F Selection	C06-05: UL REV Torque
A02-18	H03-02: Terminal A1 Function Select	E01-04: Max Frequency	C08-03: Min Brk Rel Trq
A02-19	H04-02: Terminal FM Gain	E02-01: Motor Rated FLA	C08-10: Load Float Time
A02-20	--	H01-06: Terminal S6 Select	C08-11: Brake Set Delay
A02-21	--	H01-07: Terminal S7 Select	C08-14: Brake Hold Speed
A02-22	--	H01-08: Terminal S8 Select	F01-01: PG1 Pulses/Rev
A02-23	--	H02-03: Terminal M5/M6 Select	F01-05: PG1 #Gear Teeth2
A02-24	--	H03-02: Terminal A1 Function Select	H01-06: Terminal S6 Select
A02-25	--	H04-02: Terminal FM Gain	H01-07: Terminal S7 Select
A02-26	--	--	H01-08: Terminal S8 Select
A02-27	--	--	H02-03: Terminal M5/M6 Select
A02-28	--	--	H03-02: Terminal A1 Function Select
A02-29	--	--	H04-02: Terminal FM Gain
A02-30	--	--	--
A02-31	--	--	--
A02-32	--	--	--

Auto-Tuning



CAUTION

The brake output is not energized during Auto-Tune. The brake must be manually released before tuning and set when Auto-Tuning is complete. Ensure no load is on the hook, and that the hook is near the floor.

The IMPULSE®•G+ & VG+ Series 4 can adapt to nearly all motors manufactured worldwide with its automatic tuning function. The inverter asks the user for minimal motor information, and then guides the user through a quick simple tuning process. Ideally, perform a standard Auto-Tune with the motor uncoupled from the load. When the motor cannot be decoupled, perform a static or non-rotating Auto-Tune.

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

Table 4-11: Auto-Tuning Parameter Settings

Parameter	Display	Description	Default	Model
T01-01	Tuning Mode Sel	Selects Tuning Method	0	G+/VG+
	0	Standard Tuning (Rotational Auto-Tuning)		
	1	Tune-No Rotate1 (Stationary Auto-Tuning 1)**		
	2	Term Resistance (Stationary Auto-Tuning for Line-to-Line Resistance)		
	4	Tune-No Rotate2 (Stationary Auto-Tuning 2)		
T01-02	Motor Rated Power	Sets the motor rated power as specified on the motor nameplate (note: HP = kW/0.746)	Model dependent	G+/VG+
T01-03	Rated Voltage	Sets the motor rated voltage as specified on the motor nameplate	Model dependent	G+/VG+
T01-04	Rated Current	Set the motor rated full-load current (FLA) as specified on the motor nameplate	Model dependent	G+/VG+
T01-05	Rated Frequency	Set the rated frequency of the motor as specified on the motor nameplate	60.0 Hz	G+/VG+
T01-06	Number of Poles	Sets the number of motor poles as specified on the motor nameplate	4	G+/VG+
T01-07	Rated Speed	Sets the rated speed of the motor as specified on the motor nameplate	1750 RPM	G+/VG+
T01-08	PG Pulses/Rev	Set the number of pulses per revolution for the PG being used (pulse generator or encoder)	1024 PPR	G+

* If the value is not known, leave at default.

** See page 4-19 for Non-Rotational Auto-Tune instructions.

Parameter	Display	Description	Default	Model
T01-09*	No-Load Current	Sets the no-load current for the motor. After setting the motor capacity to T01-02 and the motor rated current to T01-04, this parameter will automatically display the no-load current for a standard 4 pole motor. Enter the no-load current as indicated on the motor test report or motor nameplate.	--	G+
T01-10*	Motor Rated Slip	Sets the motor rated slip. After setting the motor capacity to T01-02, this parameter will automatically display the motor slip for a 4 pole motor. Enter the motor slip as indicated on the motor test report or motor nameplate.	--	G+

* If the value is not known, leave at default.

** See page 4-19 for Non-Rotational Auto-Tune instructions.

Standard Auto-Tune (T01-01 = 0) Instructions

This is a rotational Auto-Tuning method for the IMPULSE®•VG+ Series 4 drive which allows for Auto-Tuning on an unloaded or decoupled motor.

This method requires that the motor be unloaded or decoupled from the load with the brake disengaged.

The instructions below will provide a step-by-step procedure to complete the non-rotational segment of this Auto-Tune function:

1. In preparation for the Auto-Tune, the crane should be unloaded with minimal attachments. This Auto-Tuning method requires free rotation of the unloaded motor, so decoupling the motor from the load may be necessary.
2. Ensure the brake is not set during the Auto-Tuning process.
3. Using the keypad, browse to the "Auto-Tuning" menu.
4. Choose "Standard Tuning" (T01-01 = 0) for the Tuning Mode.
5. Enter the nameplate motor characteristics (T01-02 – T01-08) until the "Tuning Ready?" screen is reached.
6. Press the green "RUN" key to start the Auto-Tune. It will take up to a few minutes to complete. During this time, the current will ramp up and down and a high pitched frequency may be audible coming from the motor; this is normal. The motor will then begin a rotational cycle, which will complete in one minute or less.
7. When the Auto-Tune has completed, the keypad display will display an "End Tune Successful" message. Press the "ESC" key twice to exit.

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

Non-Rotational Auto-Tune (T01-01 = 1) Instructions

A non-rotational Auto-Tuning method has been implemented into the IMPULSE®•VG+ Series 4 drive which allows for Auto-Tuning without decoupling the motor.

This method will require a short movement of the crane subsequent to the non-rotational Auto-Tune process which allows the drive to calibrate the Motor Rated Slip and No-Load Current.

The instructions below will provide a step-by-step procedure to complete the non-rotational segment of this Auto-Tune function:

1. In preparation for the Auto-Tune, the crane should be unloaded with minimal hook attachments. For Traverse motion, ensure freedom of travel for Step #6.
2. Using the keypad, browse to the “Auto-Tuning” menu.
3. Choose “Tune-No Rotate1” (T01-01 = 1) for the Tuning Mode.
4. Enter the nameplate motor characteristics (T01-02 ~ T01-09) until the “Tuning Ready?” screen is reached.
5. Press the green “RUN” key to start the Auto-Tune. It will take up to a few minutes to complete. During this time, the current will ramp up and down and a high pitched frequency may be audible coming from the motor; this is normal. When the Auto-Tune has completed, the keypad display will display an “End Tune Successful” message. Press the “ESC” key twice to exit.
6. Run the motor to at least 30% of the Rated Frequency (T01-05). For example, if the Rated Frequency is 60 Hz, the motor must run to at least 18 Hz. In a hoisting motion, the motor must be run in the Up/Raising direction.

NOTE: In hoisting motions, remove any loads or spreader bars.

7. When the short run and adjustments have been completed, the motor will stop, and the keypad will display “TMDN Tune Complete”. The Auto-Tune is now complete and the drive is ready for normal operation.

Terminal Resistance Auto-Tune (T01-01 = 2) Instructions

This is a non-rotational Auto-Tuning method for the IMPULSE®•G+ Series 4 drive which allows for Auto-Tuning without decoupling the motor.

This method is recommended for motors configured with the V/f control method when the motor horsepower and motor rated current are known.

The instructions below will provide a step-by-step procedure to complete the non-rotational segment of this Auto-Tune function:

1. In preparation for the Auto-Tune, the crane should be unloaded with minimal hook attachments.
2. Using the keypad, browse to the “Auto-Tuning” menu.
3. Choose “Term Resistance” (T01-01 = 2) for the Tuning Mode.
4. Enter the nameplate motor characteristics for Motor Horsepower and Motor Rated Current (T01-02 and T01-04) until the “Tuning Ready?” screen is reached.
5. Press the green “RUN” key to start the Auto-Tune. It will take up to a few minutes to complete. During this time, the current will ramp up and down and a high pitched frequency may be audible coming from the motor; this is normal. When the Auto-Tune has completed, the keypad display will display an “End Tune Successful” message. Press the “ESC” key twice to exit.

Non-Rotational 2 Auto-Tune (T01-01 = 4) Instructions

This is a non-rotational Auto-Tuning method for the IMPULSE®•VG+ Series 4 drive which allows for Auto-Tuning without decoupling the motor.

This method is recommended when the motor cannot be decoupled, and the Motor Rated Slip is known. If the Motor Rated Slip is not known, then the Non-Rotational 1 (T01-01 = 1) is recommended.

The instructions below will provide a step-by-step procedure to complete the non-rotational segment of this Auto-Tune function:

1. In preparation for the Auto-Tune, the crane should be unloaded with minimal hook attachments.
2. Using the keypad, browse to the “Auto-Tuning” menu.
3. Choose “Tune-No Rotate2” (T01-01 = 4) for the Tuning Mode.
4. Enter the nameplate motor characteristics (T01-02 ~ T01-10) until the “Tuning Ready?” screen is reached.
5. Press the green “RUN” key to start the Auto-Tune. It will take up to a few minutes to complete. During this time, the current will ramp up and down and a high pitched frequency may be audible coming from the motor; this is normal. When the Auto-Tune has completed, the keypad display will display an “End Tune Successful” message. Press the “ESC” key twice to exit.

Chapter **5**

Programming Advanced Features

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Introduction

This chapter features parameters that are available only when the Series 4 drive is in Advanced mode.

Application

- B1 Preset References
- B2 Reference Limits
- B3 Sequence/Reference Source
- B5 Acceleration/Deceleration
- B8 Jump Frequencies

Preset Reference

Table 5-1: Preset Reference Parameter Settings

Parameter	Display	Function	Range**	Default
B01-01	Reference 1	Sets the Speed 1 frequency.	0.00–E01-04 Hz	15.00*
B01-02	Reference 2	Sets the Speed 2 frequency.	0.00–E01-04 Hz	30.00*
B01-03	Reference 3	Sets the Speed 3 frequency.	0.00–E01-04 Hz	60.00*
B01-04	Reference 4	Sets the Speed 4 frequency.	0.00–E01-04 Hz	0.00*
B01-05	Reference 5	Sets the Speed 5 frequency.	0.00–E01-04 Hz	0.00*
B01-06	Reference 6	Sets the Speed 6 frequency.	0.00–E01-04 Hz	0.00*
B01-07	Reference 7	Sets the Speed 7 frequency.	0.00–E01-04 Hz	0.00*
B01-08	Reference 8	Sets the Speed 8 frequency.	0.00–E01-04 Hz	0.00*
B01-09	Reference 9	Sets the Speed 9 frequency.	0.00–E01-04 Hz	0.00*
B01-10	Reference 10	Sets the Speed 10 frequency.	0.00–E01-04 Hz	0.00*
B01-11	Reference 11	Sets the Speed 11 frequency.	0.00–E01-04 Hz	0.00*
B01-12	Reference 12	Sets the Speed 12 frequency.	0.00–E01-04 Hz	0.00*
B01-13	Reference 13	Sets the Speed 13 frequency.	0.00–E01-04 Hz	0.00*
B01-14	Reference 14	Sets the Speed 14 frequency.	0.00–E01-04 Hz	0.00*
B01-15	Reference 15	Sets the Speed 15 frequency.	0.00–E01-04 Hz	0.00*
B01-16	Reference 16	Sets the Speed 16 frequency.	0.00–E01-04 Hz	0.00*
B01-17	Jog Reference	Jog Control and Inching Control frequency reference.	0.00–E01-04 Hz	6.00
B01-18	Ref Priority 0 Digital Ref Only 1 Analog Ref Only 2 Higher RefSelect	Determines whether the digital or analog frequency reference is used. <i>NOTE: When using Higher Reference Select, Infinitely Variable should NOT be used for a Speed Reference setting in parameter A01-04. The two functions are not intended to work in conjunction.</i>	0–2	0*

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Consult Magnetek for frequencies above 150 Hz.

Table 5-2: Multi-Step Speed Processing by Multi-Function Digital Input (B01-01–B01-16)

Speed Reference	Forward/Reverse Terminal S1 or S2	Multi-Step Speed 2 H01-01-08 = 0	Multi-Step Speed 3 H01-01-08 = 1	Multi-Step Speed 4 H01-01-08 = 2	Multi-Step Speed 5 H01-01-08 = 3	Fwd/Rev Jog Fwd/Rev Inch H01-01-08 = 15, 16, 17, 18
STOP	Off	–	–	–	–	Off
B01-01 Speed Ref 1	On	Off	Off	Off	Off	Off
B01-02 Speed Ref 2	On	On	Off	Off	Off	Off
B01-03 Speed Ref 3	On	On	On	Off	Off	Off
B01-04 Speed Ref 4	On	On	On	On	Off	Off
B01-05 Speed Ref 5	On	On	On	On	On	Off
B01-06 Speed Ref 6	On	Off	On	Off	Off	Off
B01-07 Speed Ref 7	On	Off	On	On	Off	Off
B01-08 Speed Ref 8	On	Off	Off	On	Off	Off
B01-09 Speed Ref 9	On	Off	On	On	On	Off
B01-10 Speed Ref 10	On	Off	Off	On	On	Off
B01-11 Speed Ref 11	On	Off	Off	Off	On	Off
B01-12 Speed Ref 12	On	On	Off	Off	On	Off
B01-13 Speed Ref 13	On	On	On	Off	On	Off
B01-14 Speed Ref 14	On	Off	On	Off	On	Off
B01-15 Speed Ref 15	On	On	Off	On	Off	Off
B01-16 Speed Ref 16	On	On	Off	On	On	Off

Reference Limits

These parameters limit the frequency range as a percentage of maximum output frequency (E01-04). If the lower limit is below the DC Inj Start Freq (D01-01), then operation will continue according to B03-05.

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

Table 5-3: Reference Limit Parameter Settings

Parameter	Display	Function	Range	Default
B02-01	Ref Upper Limit	Sets as a percentage of the maximum output frequency (E01-04), which determines the maximum frequency at which the drive is able to run.	0.0–110.0%	100.0*
B02-02	Ref Lower Limit	Sets as a percentage of the maximum output frequency (E01-04), which determines the minimum master frequency reference only.	0.0–110.0%	0.0
B02-03	Ref1 Lower Limit	Sets as a percentage of the maximum output frequency (E01-04), which determines the minimum frequency at which the drive is able to run.	0.0–110.0%	2.0*
B02-04	Alt Upper Limit	Alternate of B02-01 set by MFDI=59.	0.0–110.0%	0.0

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

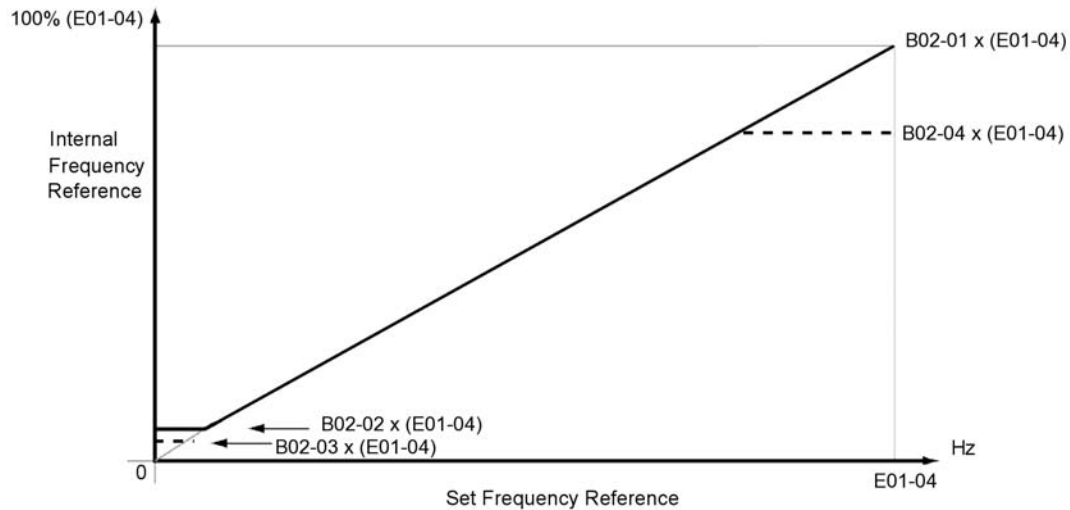


Figure 5-1: Setting Frequency Upper and Lower Limits

Sequence/Reference Source

B03-01 and B03-02 determine the source from where the frequency reference and RUN command are generated.

Table 5-4: Sequence/Reference Source Parameter Settings

Parameter	Display	Function	Range	Default
B03-01	Ref Source 1	Source from where the frequency reference is generated.	0-4	1*
	0 Operator	Digital Operator		
	1 Terminals	Terminals or Analog Input <ul style="list-style-type: none"> • S4-IF Interface Card • S4-I AC Digital Input Option • S4-IO Digital Input/Output Option • DI-A3 Digital Input Option (not used for B03-02) 		
	2 Serial Com	Serial communication <ul style="list-style-type: none"> • RS485/422 Serial Communications (R+, R-, S+, S-) 		
	3 Option PCB	Industrial Communication Option card (Port CN5-A) <ul style="list-style-type: none"> • EtherNet/IP • Modbus TCP/IP • PROFINET • PROFIBUS-DP 		
4 Pulse Input	Pulse input via Terminal RP(H06-01)			
B03-02	Run Source 1	Source from where the RUN command is generated.	0-3	1*
	0 Operator	Digital Operator		
	1 Terminals	Terminals <ul style="list-style-type: none"> • S4-IF Interface Card • S4-I AC Digital Input Option • S4-IO Digital Input/Output Option • DI-A3 Digital Input Option (not used for B03-02) 		
	2 Serial Com	Serial communication <ul style="list-style-type: none"> • RS485/422 Serial Communications (R+, R-, S+, S-) 		
	3 Option PCB	Industrial Communication Option card (Port CN5-A) <ul style="list-style-type: none"> • EtherNet/IP • Modbus TCP/IP • PROFINET • PROFIBUS-DP 		

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

Stop Method

B03-03 selects the stopping method suitable for the particular application.

Table 5-5: Stop Method Parameter Settings

Parameter	Display	Function	Range	Default	Model
B03-03	Stopping Method	Determines stop method.	0, 1, 4, 6	G+: 0* VG+: 6*	
	0 <i>Decel to Stop</i>	(Fig 5-2)			G+/VG+
	1 <i>Coast to Stop</i>	(Fig 5-3)			G+/VG+
	4 <i>Decel with timer (Traverse mode only)</i>	(Fig 5-4)			G+/VG+
	6 <i>No Load Brake</i>	See No-Load Brake Parameter Group C8.			VG+

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

Decel to Stop (B03-03=0)

Upon removal of the FWD or REV run command, the motor decelerates at a rate determined by the time set in deceleration time 1 (B05-02) and DC injection braking is applied after the DC injection start frequency D01-01 has been reached. If the deceleration time is set too short or the load inertia is too large, an overvoltage fault (OV) or deviation (DEV) may occur during deceleration. In this case, increase the deceleration time or install an optional braking transistor and/or braking resistor.

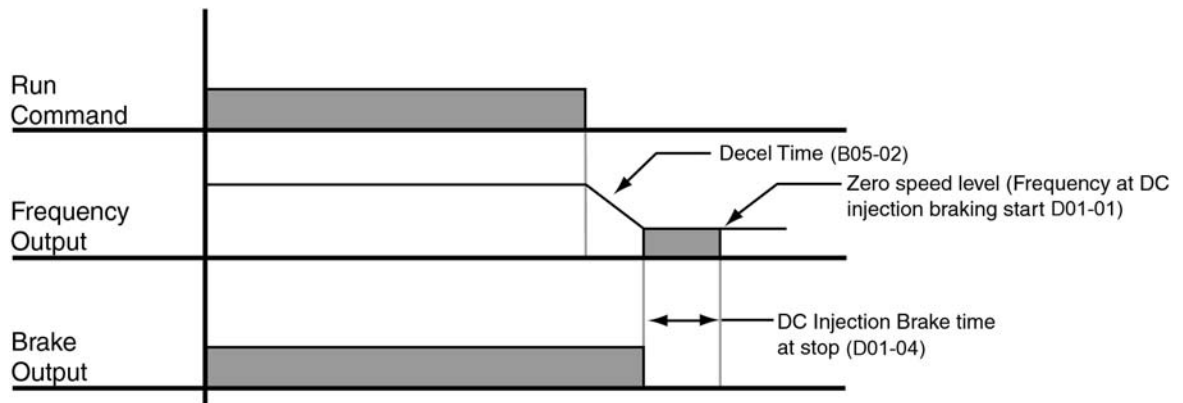


Figure 5-2: Decel to Stop

Coast to Stop (B03-03=1)

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

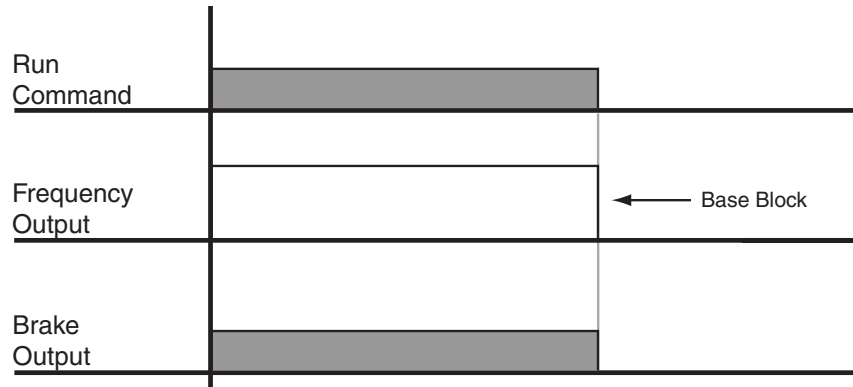


Figure 5-3: Coast to Stop

Decel w/Timer (B03-03=4)

NOTE: This option is only available in traverse motion.

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

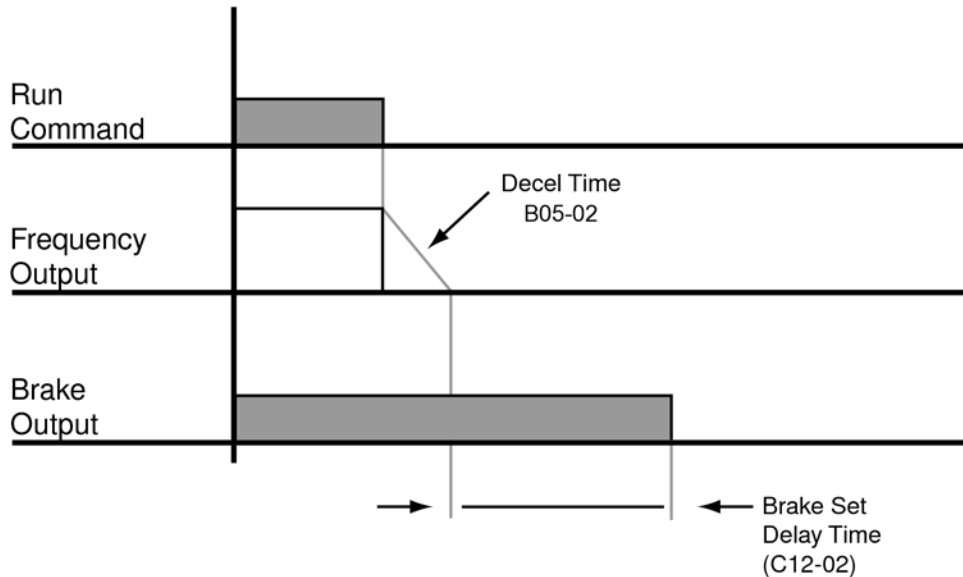


Figure 5-4: Decel w/Timer

Motor Rotation Change

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

Table 5-6: Motor Rotation Parameter Settings

Parameter	Display	Function	Range	Default
B03-04	Change Rotation	Reverse motor direction	0, 1	0
	0 <i>Standard</i>			
	1 <i>SwitchPhaseOrder</i>	Switch phase order (reverses the direction of the motor)		

NOTE: To reverse the direction of rotation, program B03-04 = 1 (exchange phases), or interchange any two motor leads (changing R/L1, S/L2, or T/L3 will not affect the shaft rotation direction) as well as encoder phasing (F01-02 = 0/1 or swapping A and \bar{A} wires).

Zero-Speed Operation

This parameter sets the drive behavior when the frequency reference is below the Zero Speed level.

Table 5-7: Zero-Speed Operation Parameter Settings

Parameter	Display	Function	Range	Default	Model
B03-05	Zero-Speed Oper	Operation Selection at Zero Speed.	0–3	0	
	0 <i>RUN at Freq Ref</i>	Operate according to the Frequency Reference			VG+
	1 <i>STOP</i>	Coast when the Frequency Reference is below E01-09			VG+
	2 <i>RUN at Min Freq</i>	Output the Frequency set in E01-09			VG+
	3 <i>RUN at Zero RPM</i>	Operate at zero speed			VG+

Input Scan Time

B03-06 selects the microprocessor scan time for reading the status of the input control terminals. Set B03-06 to “0” when a quicker response is needed from the control circuit terminal.

Table 5-8: Input Scan Time Parameter Settings

Parameter	Display	Function	Range	Default
B03-06	Cntl Input Scans	Selects the terminal scan time	0, 1	1
	0 <i>1 Scan</i>	1 ms		
	1 <i>2 Scans</i>	2 ms		

LO/RE Run Select

If the run reference/speed reference is switched between serial mode and drive terminal mode, B03-07 determines action after the switch.

Table 5-9: LO/RE Run Select Parameter Settings

Parameter	Display	Function	Range	Default
B03-07	LO/RE RUN Sel	Determines action after switching Run/Speed reference source.	0, 1	0
	0 <i>Cycle Extrn RUN</i>	If the run command is present at the time when the Run/Speed reference source is switched, it requires the run command to be removed and reapplied from the new source to resume the normal operation.		
	1 <i>Accept Extrn RUN</i>	If the run command is present at the time when the Run/Speed reference source is switched, it does not require the run command from the new source to be removed. The normal operation will continue.		
B03-08	RUN CMD at PRG	Allows the Run Method to be changed via the Local/Remote key while the drive/motor are running.	0–2	0
	0 <i>Run Disabled@PRG</i>			
	1 <i>Run Enabled@PRG</i>			
	2 <i>PRG Only @ Stop</i>			
B03-10	AllowRun@PowerUp	Determines how the drive will start if an external run command is active when the drive is powered up.	0, 1	0
	0 <i>Cycle Ext Run</i>	Disregarded. A new Run command must be issued after power up.		
	1 <i>Accept Ext Run</i>	Allowed. Motor will start immediately after power up if a Run command is already enabled.		
B03-15	Ref Source 2	Determines what the drive will use for Frequency Reference. Enabled by MFDI programmed to IF.	0–4	0
	0 <i>Operator</i>	Digital Operator		
	1 <i>Terminals</i>	Terminals or Analog Input <ul style="list-style-type: none"> • S4-IF Interface Card • S4-I AC Digital Input Option • S4-IO Digital Input/Output Option • DI-A3 Digital Input Option (not used for B03-02) 		
	2 <i>Serial Com</i>	Serial communication <ul style="list-style-type: none"> • RS485/422 Serial Communications (R+, R-, S+, S-) 		
	3 <i>Option PCB</i>	Industrial Communication Option card (Port CN5-A) <ul style="list-style-type: none"> • EtherNet/IP • Modbus TCP/IP • PROFINET • PROFIBUS-DP 		
4 <i>Pulse Input</i>	Pulse input via Terminal RP(H06-01)			

Parameter	Display	Function	Range	Default
B03-16	Run Source 2	Determines what the drive will use for Run Reference. Enabled by MFDI programmed to IF.	0–3	0
	0 <i>Operator</i>	Digital Operator		
	1 <i>Terminals</i>	Terminals <ul style="list-style-type: none"> • S4-IF Interface Card • S4-I AC Digital Input Option • S4-IO Digital Input/Output Option • DI-A3 Digital Input Option (not used for B03-02) 		
	2 <i>Serial Com</i>	Serial communication <ul style="list-style-type: none"> • RS485/422 Serial Communications (R+, R-, S+, S-) 		
3 <i>Option PCB</i>	Industrial Communication Option card (Port CN5-A) <ul style="list-style-type: none"> • EtherNet/IP • Modbus TCP/IP • PROFINET • PROFIBUS-DP 			
B03-21	PG Start Sel	Allows the drive to start when the Frequency Reference is between D01-01 and E01-09.	0, 1	0
	0 <i>RejectRunCmd</i>			
	1 <i>AcceptRunCmd</i>			

Acceleration/Deceleration

Acceleration time sets the time necessary for the output frequency to accelerate from 0 Hz to maximum output frequency (E01-04). Deceleration time sets the time necessary for the output frequency to decelerate from the maximum output frequency (E01-04) to 0 Hz.

Table 5-10: Acceleration/Deceleration Parameter Settings

Parameter	Display	Function	Range	Default
B05-01	Accel Time 1	Sets acceleration time.	0.0–25.5 sec**	5.0*
B05-02	Decel Time 1	Sets deceleration time.	0.0–25.5 sec**	3.0*
B05-03	Accel Time 2	Acceleration time 2 enabled when H01-xx = 1A.	0.0–25.5 sec**	10.0
B05-04	Decel Time 2	Deceleration time 2 enabled when H01-xx = 1A.	0.0–25.5 sec**	10.0

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Range is extended to 0.0–6000.00 when B05-16 = 1.

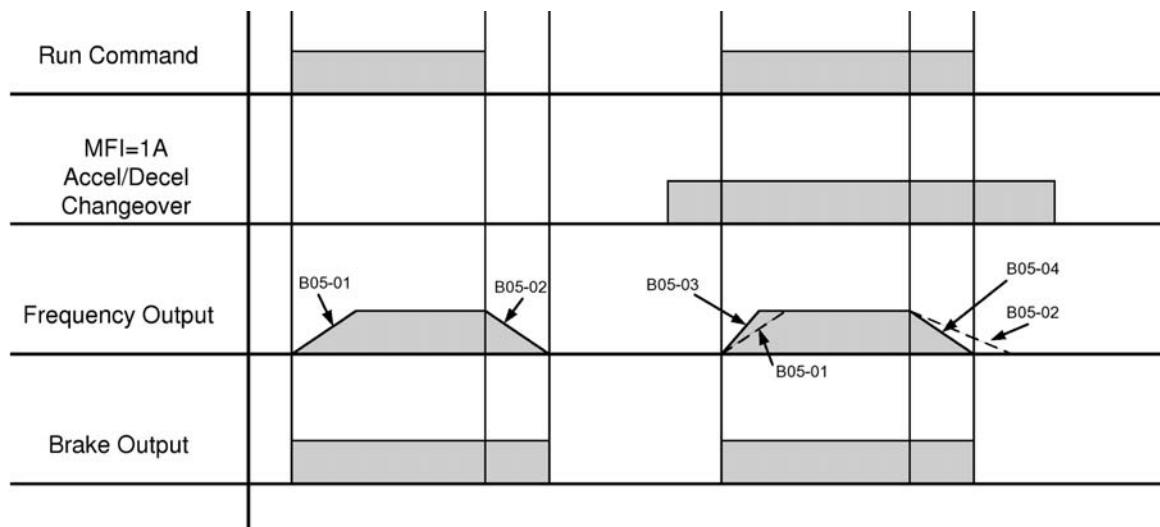


Figure 5-5: Normal Accel/Decel Time and Multiple Accel/Decel Changeover

NOTE: Assume the constant B03-03 is set to "0" (Decel to Stop).

Accel/Decel Time Switching Frequency

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

Table 5-11: Accel/Decel Time Switching Frequency Parameter Settings

Parameter	Display	Function	Range	Default
B05-05	Acc Time N Chg	Sets Acceleration time at Acc/Dec Switch Frequency (B05-10)	0.0–25.5 sec	2.0
B05-06	Dec Time N Chg	Sets Deceleration time at Acc/Dec Switch Frequency (B05-10)	0.0–25.5 sec	2.0
B05-08	Fast Stop Time	Sets deceleration time for complete stop at external fault. See “External Fault Response Selection” on page 5-96.	0.0–25.5 sec	0.5
B05-10	Acc/Dec SW Freq	Determines acceleration/ deceleration time settings	0.0–E01-04	0.0
B05-11	SW Freq. Compare	Determines when Acceleration Time and Deceleration Time at Speed Switch Hz is enabled;	0, 1	1
	0 Lower SW Freq	0: B05-05/B05-06 enabled, U01-02 < B05-10		
	1 Upper SW Freq	1: B05-05/B05-06 enabled, U01-02 > B05-10		
B05-12	Accel Time 3	Acceleration time 3 enabled when H01-xx = 1B.	0.0–25.5 sec*	3.0
B05-13	Decel Time 3	Deceleration time 3 enabled when H01-xx = 1B.	0.0–25.5 sec*	3.0
B05-14	Accel Time 4	Acceleration time 4 enabled when H01-xx = 1C.	0.0–25.5 sec*	3.0
B05-15	Decel Time 4	Deceleration time 4 enabled when H01-xx = 1C.	0.0–25.5 sec*	3.0
B05-16	Acc/Dec Ext Rang	Enables extended range of Acc/ Dec Params: B05-01–B05-04, B05-12–B05-15, C03-02, C03-03, C03-05 and C03-06	0, 1	0
	0 Disabled	Range = 0.0–25.5		
	1 Enabled	Range = 0.0–6000.0		

* Range is extended to 0.0–6000.00 when B05-16 = 1.

Jump Frequencies

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

Table 5-12: Jump Frequencies Parameter Settings

Parameter	Display	Function	Range	Default
B08-01	Jump Freq 1	First of three jump frequencies.	0.0–150.0 Hz	0.0
B08-02	Jump Freq 2	Second of three jump frequencies.	0.0–150.0 Hz	0.0
B08-03	Jump Freq 3	Third of three jump frequencies.	0.0–150.0 Hz	0.0
B08-04	Jump Bandwidth	Jump frequency reference bandwidth.	0.0–20.0 Hz	1.0

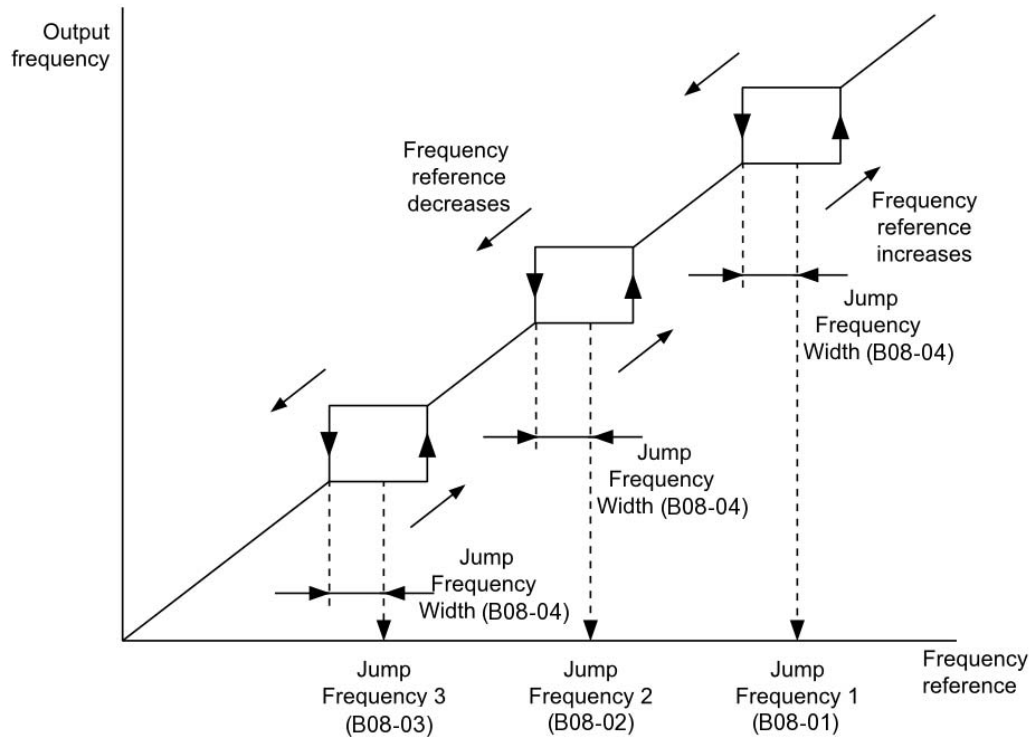


Figure 5-6: Jump Frequencies

Field Forcing

The Field Forcing function compensates the delaying influence of the motor time constant when changing the excitation current reference and improves motor responsiveness. Field Forcing is ineffective during DC Injection Braking.

Table 5-13: Field Forcing Parameter Settings

Parameter	Display	Function	Range	Default
B09-03	Field Forcing Selection	Enables or disables the Field Forcing Function.	0, 1	0
	0 Disabled			
	1 Enabled			
B09-06	Field Forcing Limit	Sets the maximum level at which the Field Forcing function can boost the excitation current reference. The value is set as a percentage of the motor no load current. This parameter does not normally need to be changed.	100–400%	200

Special Functions

Table 5-14: Special Function Usage

Access Level (A01-01)	Advanced (2)					
Motion (A01-02)	Traverse (0)			Standard Hoist (1)		NLB Hoist (2)
Function/Control Method (A01-03)	V/f (0)	OLV (2)	FLV (3)	V/f (0)	OLV (2)	FLV (3)
C1: Quick Stop™	○	○	○	○	○	○
C1: Reverse Plug Simulation™	○	○	○	×	×	○
C2: Micro-Speed™	○	○	○	○	○	○
C3: End of Travel Limits	○	○	○	○	○	○
C3: Phantom Stop	○	○	○	○	○	○
C3: Load Sharing/Torque Following	×	×	○	×	×	○
C3: Klixon	○	○	○	○	○	○
C3: Hook Height Measurement	×	×	○	×	×	○
C3: EPLS	×	×	○	×	×	○
C4: Load Float	×	×	○	×	×	○
C5: Load Check II™	×	×	×	○	○	○
C6: Swift-Lift™/Ultra-Lift™	×	×	×	○	○	○
C7: Torque Limit	×	○	○	×	○	○
C7: Anti-Shock	×	×	×	×	×	○
C8: No-Load Brake Hoist	○	○	○	○	○	○
C8: Brake Answerback	○	○	○	○	○	○
C9: Digital Input Option Set-up	○	○	○	○	○	○
C10: Weight Measurement	×	×	×	○	○	○
C11: Slack Cable Detection	×	×	×	○	○	○
C11: Snap Shaft Detection	×	×	×	×	×	○
C12: Brake Delay Timers	○	○	○	×	×	×
C12: On/Off Delay Timers	○	○	○	○	○	○
C12: Maintenance Timer	○	○	○	○	○	○
C13: Inching Control	○	○	○	○	○	○
C13: Index Control	×	×	○	×	×	○

○: Available for the Motion selected

×: Not available for the Motion selected

Quick Stop™

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

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

Table 5-15: Quick Stop Parameter Settings

Parameter	Display	Function	Range	Default
C01-01*	Quick Stop 0 Disabled 1 Enabled	Determines whether Quick Stop is enabled	0, 1	0
C01-02	Quick Stop Time	Deceleration time during Quick Stop function.	0.0–25.5 sec	1.0

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

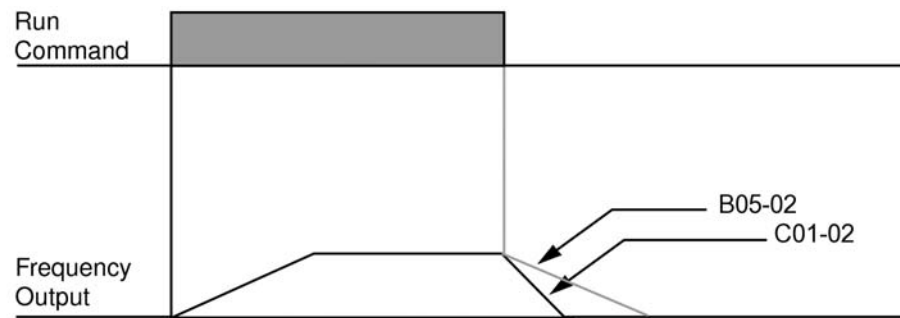


Figure 5-7: Quick Stop

Reverse Plug Simulation™

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

NOTE: Reverse Plug Simulation is not available in MLB (standard) Hoist.

Table 5-16: Reverse Plug Simulation

Parameter	Display	Function	Range	Default
C01-03	Reverse Plug 0 Disabled 1 Enabled	Determines whether Reverse Plug Simulation is enabled.	0, 1	0
C01-04	Rev-Plg Dec Time	Deceleration time during Reverse Plug Simulation.	0.0–25.5 sec	2.0
C01-05	Rev-Plg Acc Time	Acceleration time during Reverse Plug Simulation.	0.0–25.5 sec	0.0

NOTE: A setting of 0.0 in C01-05 will cause B05-01 to be used during acceleration.

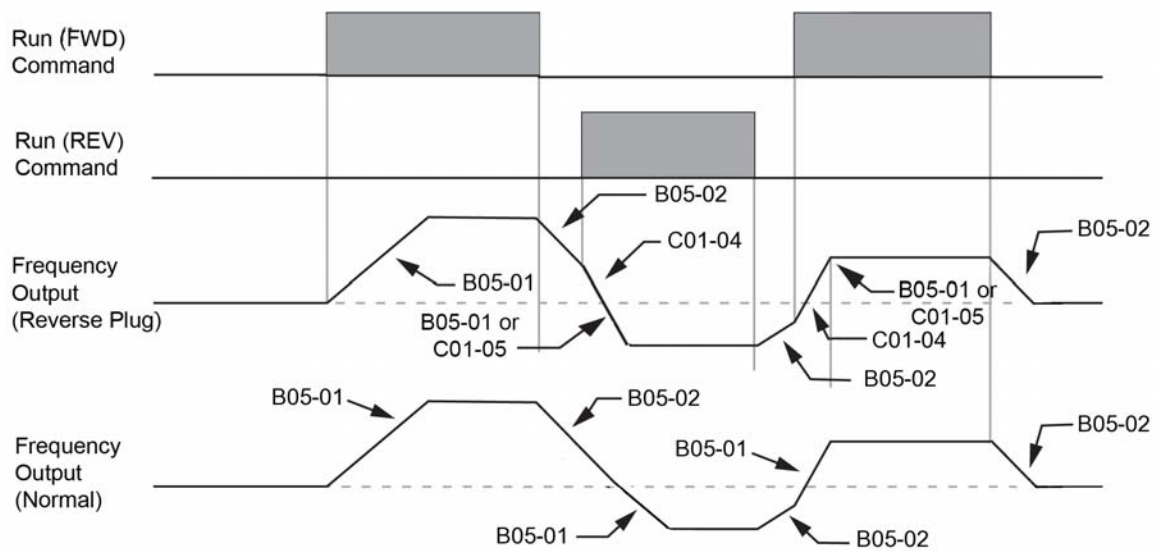


Figure 5-8: Reverse Plug Simulation

Micro-Speed™

Micro-Speed provides a reduced speed range operation for precise positioning. Enabled by a Multi-Function Input, it multiplies the normal speed reference by the Micro-Speed Gain. Two Micro-Speed Gains are available: Gain 1 (C02-01) and Gain 2 (C02-02). They can be adjusted and enabled independently.

Table 5-17: Micro-Speed Parameter Settings

Parameter	Display	Function	Range	Default
C02-01	MicroSpd Gain 1	The multiplier of the Analog or Digital Speed Reference to achieve slow-speed operation. Multi Function Digital Input = E	Hoist: 0.01–1.00 Traverse: 0.01–2.55	1.00
C02-02	MicroSpd Gain 2	An alternate multiplier of the Analog or Digital Speed Reference to achieve slow-speed operation. Multi Function Digital Input = 10	Hoist: 0.01–1.00 Traverse: 0.01–2.55	1.00

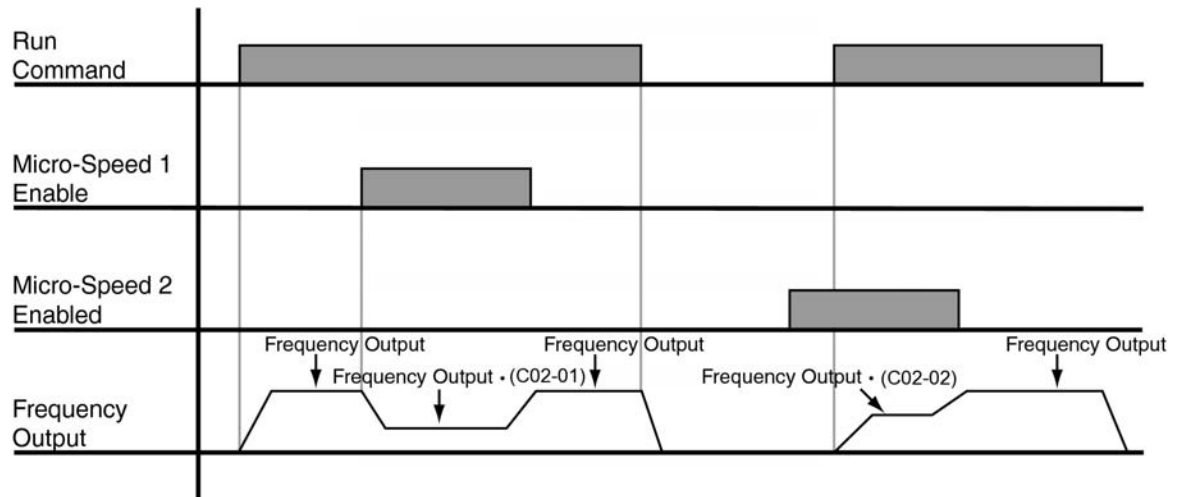


Figure 5-9: Micro-Speed Control

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

End of Travel Limits

This function can automatically slow and stop a crane or hoist when it reaches the end of travel limits. Two types of limit inputs (slowdown and stop) are available in both travel directions. Inputs can be programmed through the S4IF card.

Table 5-18: End of Travel Limits Parameter Settings

Parameter	Display	Function	Range	Default
C03-01	UL1 Speed	Speed when UL1 is detected	0.00–E01-04 Hz	6.00
C03-02	UL1 Decel Time	Decel time when UL1 is detected	0.0–25.5 sec**	1.0
C03-03	UL2 Stop Time	Decel time to STOP when UL2 is detected	0.0–25.5 sec**	1.0
C03-04	LL1 Speed	Speed when LL1 is detected	0.00–E01-04 Hz	6.00
C03-05	LL1 Decel Time	Decel time when LL1 is detected	0.0–25.5 sec**	1.0
C03-06	LL2 Stop Time	Decel time to STOP when LL2 is detected	0.0–25.5 sec**	1.0
C03-07	Lmt Stop Method	Determines the stopping method when UL2 or LL2 is detected	0-2	2*
	0 Decel to Stop			
	1 Coast to Stop			
	2 Use B3-03 Method			
C03-08	UL3 Stop Method	Weight Limit Stop Method for H01-xx = 12 or 62. Action is Alarm only when inverter is not running.	0-5	4
	0 Decel / Alarm	Decel to Stop with Alarm (no further raise allowed)		
	1 Coast / Alarm	Coast to Stop with Alarm (no further raise allowed)		
	2 Use B3-03/Alarm	Use B03-03 to Stop with Alarm (no further raise allowed)		
	3 Decel / Fault	Decel to Stop with Fault		
	4 Coast / Fault	Coast to Stop with Fault		
	5 Use B3-03/Fault	Use B03-03 to Stop with Fault		
C03-09	UL3 Decel Time	Sets the deceleration time when H01-xx = 12 or 62	0.0–25.5 sec	1.0

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Range is extended to 0.0–6000.00 when B05-16 = 1.

Phantom Stop

The Phantom Stop allows quick identification of a faulted drive while stopping other drives with Phantom Stop enabled. The Phantom Stop feature is designed to stop the drive operation using the stopping method selected in C03-10 when a Phantom Fault input (H01-01–H01-08 = 5F or 63) is active. The drive will indicate a Phantom Fault has occurred by blinking the LED on the RUN key in sequence of two short bursts. The drive will resume normal operation when a Phantom Fault is removed.

Table 5-19: Phantom Stop Parameter Settings

Parameter	Display	Function	Range	Default
C03-10	Phantom Stop Met	Stopping Method when Multi-Function Input = 5F and 63	0–2	1
	0 Decel to Stop			
	1 Coast to Stop			
	2 Use B3-03 Method			

NOTE: For settings of 0 or 2 deceleration is by B05-08.

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

The Load Share Limit function allows the drive to follow the limit switch frequency references and stopping methods when enabled.

Table 5-20: Load Share Limit Parameter Settings

Parameter	Display	Function	Range	Default	Model
C03-11	Load Share Limit	See below for detailed description	0, 1	0	VG+
	0 Disabled				
	1 Enabled				

The VG+ Series 4 Software allows one or more IMPULSE®•VG+ Series 4 driven motors to be connected in a Master/Slave fashion such that slave inverter will follow the torque reference of the master inverter. It can be configured in two ways, either as a dedicated Slave or as a Master/Slave that can be switched on or off by multi-function digital input. When it is in Load Share Mode (Slave), it is essentially a torque helper to the master motor. The Master outputs the commanded amount of torque from a ± 10 VDC analog signal into the Slave, which correlates directly to the direction and quantity of torque the Slave should apply to its own motor. This can be particularly useful when two or more motors are driving a common load (i.e. single drum, gear box, etc.) and it is important that they share the load. This will allow one inverter/motor to handle the speed reference and speed regulation while the others simply help the master. This overcomes inherent problems with having more than one inverter/motor trying to regulate speed on a common load. The Load Sharing function can be used when the master is configured for Hoist or Traverse motions (i.e. for a hoist motion, two or more motors coupled to a single gearbox; for a traverse motion, a circular crane, multiple motors driving a single end truck, cable reel, etc).

NOTE: The master drive can be an IMPULSE®•VG+ Series 1, 2, 3, or 4.

When using Multi-function digital input H01-0x = 66—“Load Share” (Torque Following mode), setting C03-11 = **Enabled** will allow the inverter to accept the Limit Switch inputs where H01-0x = 06–0D. When C03-11 = **Disabled** (Factory Default), the Slave will ignore any change in state of the Limit switch inputs. The setting of this parameter is only in effect when the Multi-function digital input H01-0x = 66 “Load Share” is **ON**. It is important to understand that when in Load Sharing mode, the Slave is only supplying torque to help the Master. The Master typically handles the logic of limit switches or

other special functions. If this is not the case, each inverter may try to move or decelerate at a different speed placing extra strain on the drive train and potentially resulting in a speed deviation fault.

NOTE:

1. The Limit Switch stopping method is not selectable in Load Sharing mode. If a Stop Limit is input, the output is turned off and the brake output will set immediately.
2. Weight Limit Input (H01-xx = 12 or 62) — Upper Limit 3 is always active regardless of the setting of parameter C03-11.

Minimum Programming Requirement for “Load Sharing” Operation

1. The **Master** and **Slave** drives must be set to Flux Vector control method, A01-02 = 3.
2. The **Master** drive requires a ±10 VDC output with H04-01 or H04-04 = 109 — “Torque Reference”.
3. The **Master** drive analog output gain (H04-02 or H04-05) should be = 50%.
4. The **Master** drive requires H02-0x = 2A — “During RUN 2”.
5. The **Slave** drive requires H01-xx = 66 — “Load Share”.
6. The **Slave** drive requires a ±10 VDC input with H03-06 or H03-10 = 13 — “Torque Reference”.
7. The **Slave** drive analog input gain (H03-07 or H03-11) should be = 200%.
8. OPTIONAL: The **Master** drive can be set to H01-xx = 68 — “LodShr Ready Run”, and then the **Slave** Drive can be set to H02-0x = 0 — “Brake Release.”

Klixon

The Klixon Multi-Function input is intended for motors that have a Motor Thermal Overload Switch. Klixon is usually embedded in the motor windings and changes state when the motor reaches a certain temperature. When a multi-function input (H01-0x = 56 or 57) is active, the drive will use the stopping method programmed in C03-12 and display the KLX Klixon alarm. The drive will resume normal operation when the motor cools down and a new RUN command is applied.

Table 5-21: Klixon Action Parameter Settings

Parameter	Display	Function	Range	Default
C03-12	Klixon Action	When MFDI = 56 (N.O.) or 57 (N.C.)	0, 1	0
	0 Use B3-03 Method			
	1 Allow Lower Only*			

* Only available in a hoist motion.

Hook Height Measurement

Hook Height Measurement provides a monitor parameter (U01-50) and analog output proportional to the hook's current position between a home position and a limit position. Hook height programming is used in conjunction with the Electronic Programmable Limit Switch parameters. Reference Figure 5-10 for Hook Height configuration. The physical limit switch must be normally open (N.O.) to prevent homing during a power-down or power loss.

Table 5-22: Hook Height Parameter Settings

Parameter	Display	Function	Range	Default	Model
C03-13	Height Measure	Number of motor revolutions from the top of travel (FWD direction) to the bottom of travel (REV direction).	0–65535 Rev	250	VG+
C03-14	Hook Height Home	Sets the MFDI to be used for setting the Hook Height Home position. Corresponding MFDI must be programmed or OPE23 will be shown.	0–4	2	VG+
	0 Home = UL2 N.O.	Motor Revolutions is set to 0 when UL2 N.O. is closed (H01-xx = 07).			
	1 Home = LL2 N.O.	Motor Revolutions is set to C03-13 when LL2 N.O. is closed (H01-xx = 09).			
	2 Home MFDI Upper	Motor Revolutions is set to 0 when Hook Height Home is closed (H01-xx = 67).			
	3 Home MFDI Lower	Motor Revolutions is set to C03-15 when Hook Height Home is closed (H01-xx = 67).			
	4 Home = UL3 N.O.	Motor Revolutions is set to 0 when UL3 N.O. is closed (H01-xx = 62).			
C03-15	Hook Height Out	Selects the output voltage for the analog Hook Height monitor.	0, 1	0	VG+
	0 0 Revs = 0%	U01-50 = 0%, MFAO = 0V			
	1 0 Revs = 100%	U01-50 = 100%, MFAO = 10V			

NOTE: Motor revolutions (U01-51) will not go negative. If 0 motor revolutions has been reached and the hoist continues in the Up (FWD) direction, the motor revolutions will remain at 0.

NOTE: An N.O. contact must be used for the Hook Height Home input.

Electronic Programmable Limit Switches (EPLS)

Using the motor revolutions (U01-51) from the Height measurement function, it is possible to program UL1, UL2, LL1, and LL2 positions without the use of rotary limit switches. When C03-16, C03-17, C03-18, or C03-19 has a value other than 0, the EPLS function will be enabled. Height measurement must be correctly setup before using EPLS.

Table 5-23: Electronic Programmable Limit Switches Parameter Settings

Parameter	Display	Range	Default	Model
C03-16	UL2 Revolutions	0–65535 Rev	0	VG+
C03-17	UL1 Revolutions	0–65535 Rev	0	VG+
C03-18	LL1 Revolutions	0–65535 Rev	0	VG+
C03-19	LL2 Revolutions	0–65535 Rev	0	VG+

NOTE: A setting of 0 disables that specific limit.

Table 5-24: Limit Switch Outputs

H02-0x or F05-0x =	Function
2B - Upper Limit 1	Output ON when keypad displays UL1
2C - Upper Limit 2	Output ON when keypad displays UL2
2D - Lower Limit 1	Output ON when keypad displays LL1
2E - Lower Limit 2	Output ON when keypad displays LL2
30 - Lower Limit	Output ON when keypad displays LL1 or LL2
31 - Up/Low Limit	Output ON when keypad displays UL1, UL2, LL1, or LL2

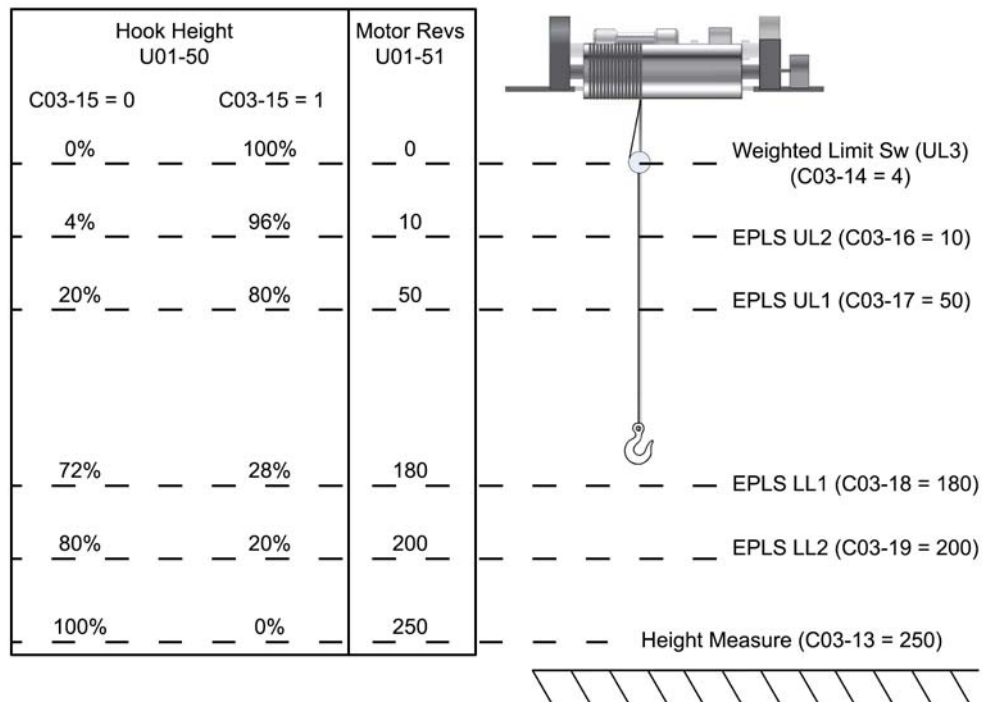


Figure 5-10: EPLS Parameter Layout

Table 5-25: Monitor Values at Hook Height Home Position

		C03-15 = 0	C03-15 = 1
C03-14	U01-51	U01-50	U01-50
0	0	0%	100%
1	C03-13	100%	0%
2	0	0%	100%
3	C03-13	100%	0%
4	0	0%	100%

Lower Limit/Upper Limit Bypass MFDI

The Limit Bypass allows for the following without the use of jumpers or re-programming of the drive parameters:

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

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

Table 5-26: Limit Bypass MFDI

Functions Bypassed	C09-0x or H01-0x settings will bypass the functions in the left most column when the input is activated	
	73	74
Upper Limit 1 N.O. (MFDI = 06)		x
Upper Limit 2 N.O. (MFDI = 07)	x	x
Lower Limit 1 N.O. (MFDI = 08)		x
Lower Limit 2 N.O. (MFDI = 09)	x	x
Upper Limit 1 N.C. (MFDI = 0A)		x
Upper Limit 2 N.C. (MFDI = 0B)	x	x
Lower Limit 1 N.C. (MFDI = 0C)		x
Lower Limit 2 N.C. (MFDI = 0D)	x	x
UL2 detected by EPLS (C03-16)	x	x
UL1 detected by EPLS (C03-17)		x
LL1 detected by EPLS (C03-18)		x
LL2 detected by EPLS (C03-19)	x	x

x = Limit Bypass

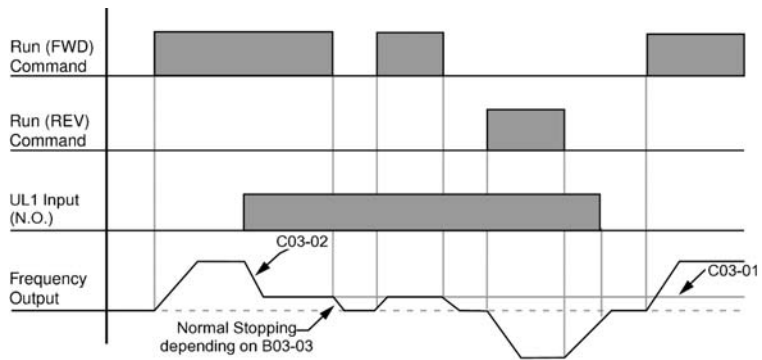


Figure 5-11: Upper Limit (UL1)

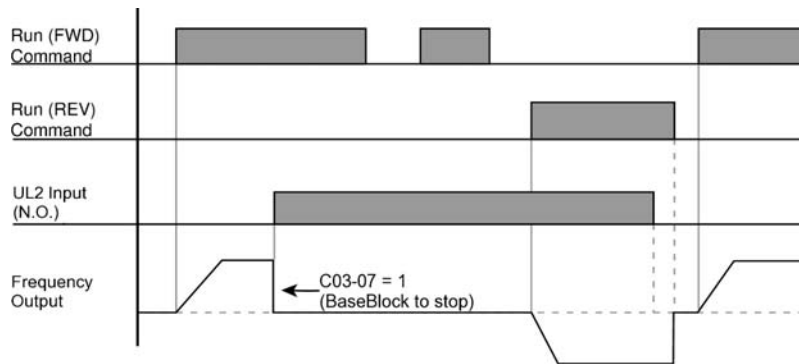


Figure 5-12: Upper Limit 2 (UL2)

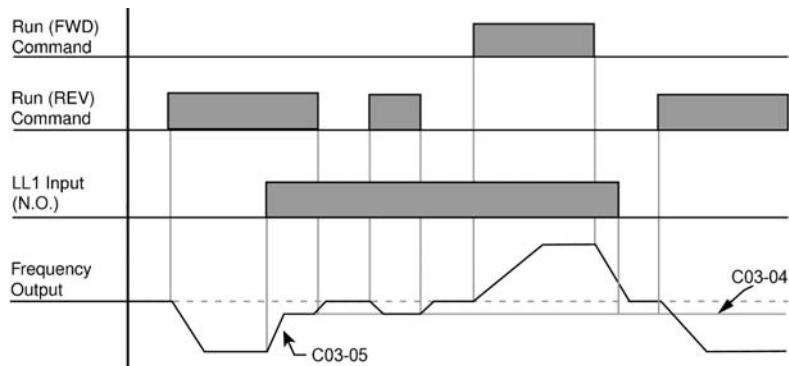


Figure 5-13: Lower Limit 1 (LL1)

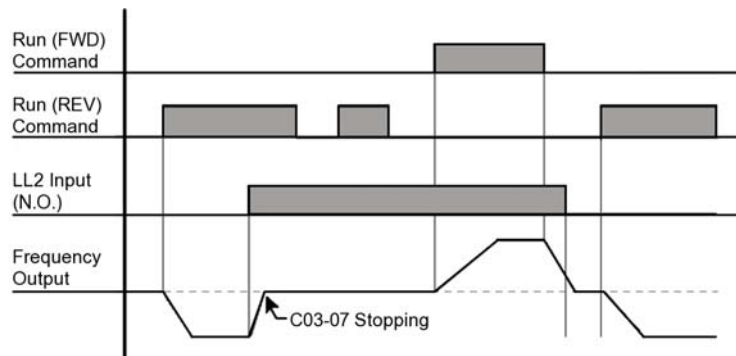


Figure 5-14: Lower Limit 2 (LL2)

Load Float

When Load Float (C08-10) is enabled, it maintains the motor shaft at a stationary position with brake open. The Load Float 2 (MFDI=35) function triggers the drive to go into Load Float for the time set in C04-01. During Load Float, the drive will open the brake and hold the motor at a zero position. A FWD or REV run command will take priority over this function. In NLB applications, the standard brake checks will be performed if starting from Base Block.

Table 5-27: Load Float Time 2 Parameter Settings

Parameter	Display	Function	Range	Default
C04-01	Load Float Time2	Maximum duration of Load Float 2 time when MFDI = 35	0–65535 sec	10
C04-02	Load Float Gain	Load Float Gain.	0–100	10*

* Dependent on kVA (≤ 30 HP: 10; > 30 HP: 20)

Load Check II™

The Load Check II function is a load-limiting feature which ensures the programmed load limit of the hoist is not exceeded. It prevents the lifting (and potential stall) of a load that is overweight. When IMPULSE®•G+ & VG+ Series 4 detects an overload condition it prevents any further lifting. The load may then be lowered at the speed that is specified by the Load Check Alarm Speed (C05-08).



DANGER

Load Check II is designed to limit loads less than or equal to the crane's rated capacity. Consult the factory and crane manufacturer before calibrating Load Check II with a load heavier than the crane capacity.

V/f Operation (A01-02 = 00)

When using Load Check II in V/f control method (during lifting) the IMPULSE®•G+ Series 4 will compare the motor current readings (U01-03) to values stored during the Load Check set up process. If they exceed the values for the active Load Check Zone, the IMPULSE®•G+ Series 4 will stop the motor based on the LC Alarm Action (C05-02) and display a Load Check alarm (LC).

NOTE: *If an application requires Load Check to be bypassed, an MFDI may be programmed to 69 (N.O.) or 6A (N.C.)*

NOTE: *It is highly recommended to use OLV or FLV control methods for Load Check II.*

OLV and FLV Operation (A01-02 = 02 and 03)

When using Load Check II in Open Loop Vector or Flux Vector control method, the IMPULSE®•G+ and VG+ Series 4 will compare the motor torque readings (U01-09) to values stored during the Load Check set up process. If they exceed the values for the active Load Check Zone, the IMPULSE®•G+ and VG+ Series 4 will stop the motor based on the LC Alarm Action (C05-02) and displays a Load Check alarm (LC).

NOTE: *If an application requires Load Check to be bypassed, an MFDI may be programmed to 69 (N.O.) or 6A (N.C.).*

NOTE: *The Load Check II function will alter the acceleration time, depending on loading. Therefore, it must be disabled when using two or more hoists to lift a single load. Use MFDO H01-0x = 69 or MFDO H01-0x = 6A to bypass Load Check.*

Load Check II Set Up (C05-01 = 09)

The Load Check II set up procedure will quickly measure and calculate the current or torque required at each of the Load Check Zones starting with the rated load suspended. These values will automatically be stored in parameters C05-09 through C05-24 during the Load Check II set up process.

The following steps are required to perform the Load Check II set up process.

1. Verify that when the Master Switch is at full deflection (the highest speed point if stepped, or 10V if Analog), the Frequency Reference shown in U01-01 is equal to Motor Base Frequency shown in E01-06 (typically 60Hz). For example, with a 3-Step speed reference, if B01-03 is set at 60Hz, then the frequency reference should be 60Hz when the Master Switch is pushed to full deflection. If the frequency reference doesn't reach Motor Base Frequency, set the following (depending on Speed Ref):
 - Multi-Step: B01-0x is 60Hz
 - Infinitely Variable: B02-01 = 100%
 - Analog: H03-03 = 100% and B02-01 = 100%
2. The motor should be properly Auto-tuned.
 - FLV and OLV operation – Rotational Auto-tune.
 - V/f operation – Stationary Auto-tune.
3. Check that B02-03 and E01-09 are at their desired values. If you change these values, re-run Load Check II setup.
4. Motor should be at normal operating temperature for the application (operate at or near rated capacity for at least 10 minutes) before performing the Load Check set up process.
5. Suspend the rated load just off of the ground (this allows for accurate measurements during calibration).
6. Set C05-01 equal to 9.
7. Press and hold the Hoist (Up) command button on the pendant or radio for full speed operation (60 Hz).

NOTE: *The Load Check set up process can be temporarily paused by lowering the load back to the ground, keeping the load suspended, then pressing and holding the Hoist (Up) command button at full speed until the Load Check set up process is complete.*

8. When the Load Check set up process finishes its calculations, the drive will decelerate the load to indicate the set up calibration is complete.
9. Press the Lower (Down) command to complete the Load Check set up process and lower the load to the ground.

NOTE: If an application requires Load Check to be bypassed, an MFDI may be programmed to 69 (N.O.) or 6A (N.C.)

NOTE: Upon completion of the Load Check set-up process, the drive will automatically set C05-01 to 1.

NOTE: If an error occurs during the Load Check set up, the load being lifted causes current or torque to exceed 250%. Increase Holding Time and Testing Time, and decrease the load weight.

Clearing a Load Check Alarm (LC)

A Load Check alarm/fault can be reset by pressing the RESET key on the keypad.

Table 5-28: Load Check II Parameter Settings

Parameter	Display	Function	Range	Default
C05-01	Load Check	Determines whether Load Check is enabled.	0–9	0
	0 <i>Disabled</i>	Disables Load Check II Function		
	1 <i>Hold & Measure</i>	Checks per Holding and Testing Time		
	3 <i>Immediate</i>	Immediately faults when I/T level is exceeded		
	9 <i>LC Set Up</i>	Set up Load Check II		
C05-02	LC Alarm Action	Action at Load Check alarm or fault	0–5	4
	0 <i>Alarm Only</i>	L.C. blinking, can continue raising		
	1 <i>Decel to Stop</i>	Allows lower only		
	2 <i>Coast to Stop</i>	Allows lower only		
	3 <i>Fault Stop</i>	Fault contacts change state - requires reset		
	4 <i>Use B3-03 Method</i>	Allows Lower only		
	5 <i>B03-03 with Reset</i>	Stopping method is B3-03. Allows Lower Only. Alarm will be reset when load is lowered.		
C05-03	Holding Time	Sets the time to hold the output frequency allowing the output current/torque to stabilize.	0.00–2.55 sec	0.15
C05-04	Testing Time	Sets the time (after the Holding Time) for comparing output current/torque to values for a particular LC Zone being tested.	0.00–2.55 sec	0.25
C05-05	I/T Margin Acc	Sets the margin for Load Check detection during acceleration. A setting of 00 is the most sensitive.	0–50%	5
C05-07	I/T Margin	Sets the margin for Load Check detection at speed agree. A setting of 00 is the most sensitive.	0–20%	5
C05-08	Alarm Speed	Sets the maximum lowering speed after an LC alarm.	0.0–30.0 Hz	6.0
C05-09	I/T Level 01	Current/Torque values detected during LC set up for Zone 01	0–250%	0
C05-10	I/T Level 02	Current/Torque values detected during LC set up for Zone 02	0–250%	0
C05-11	I/T Level 03	Current/Torque values detected during LC set up for Zone 03	0–250%	0
C05-12	I/T Level 04	Current/Torque values detected during LC set up for Zone 04	0–250%	0

Parameter	Display	Function	Range	Default
C05-13	I/T Level 05	Current/Torque values detected during LC set up for Zone 05	0–250%	0
C05-14	I/T Level 06	Current/Torque values detected during LC set up for Zone 06	0–250%	0
C05-15	I/T Level 07	Current/Torque values detected during LC set up for Zone 07	0–250%	0
C05-16	I/T Level 08	Current/Torque values detected during LC set up for Zone 08	0–250%	0
C05-17	I/T Level 09	Current/Torque values detected during LC set up for Zone 09	0–250%	0
C05-18	I/T Level 10	Current/Torque values detected during LC set up for Zone 10	0–250%	0
C05-19	I/T Level 11	Current/Torque values detected during LC set up for Zone 11	0–250%	0
C05-20	I/T Level 12	Current/Torque values detected during LC set up for Zone 12	0–250%	0
C05-21	I/T Level 13	Current/Torque values detected during LC set up for Zone 13	0–250%	0
C05-22	I/T Level 14	Current/Torque values detected during LC set up for Zone 14	0–250%	0
C05-23	I/T Level 15	Current/Torque values detected during LC set up for Zone 15	0–250%	0
C05-24	I/T Level 16	Current/Torque values detected during LC set up for Zone 16	0–250%	0
C05-25	LC Integral Time	Integral time used to smooth transitions	0.00–2.55 sec	0.05
C05-26	LC Delay Time	Load Check delay time for transitions	0.00–2.55 sec	0.25
C05-27	Min I->Fwd Tim	Minimum delay when switching from REV to FWD in LC. Used when the load brake cannot stop the load fast enough. Setting of 0.0 disables delay triggering timer	0.0–25.5 sec	0.0
C05-28	Dly Trig Freq	Minimum frequency that will trigger C05-27 timer	0.0–60.0 Hz	30.0

Swift-Lift™ & Ultra-Lift™

Swift-Lift/Ultra-Lift provides additional productivity by allowing a crane or hoist to quickly move into position. The feature enables the motor to spin faster than the base speed when the load is less than 100% of the rated capacity. Ultra-Lift determines the torque required for the load, calculates the maximum safe speed, and automatically accelerates to this speed. The maximum speed cannot exceed the lesser value of the Maximum Forward Speed (C06-02), Maximum Reverse Speed (C06-03), and Maximum Frequency (E01-04).

Swift-Lift

Swift-Lift can be enabled in the Standard Hoist motion of the G+ Series 4. In the V/f control method, the Swift-Lift function uses motor current to determine the maximum safe speed. When the OLV control method is selected, the Swift-Lift function uses motor torque in place of motor current for its safe speed calculations. Swift-Lift will not be enabled if the current or torque levels exceed C06-04 or C06-05 settings. Both C06-04 and C06-05 are a percentage of E02-01.

Ultra-Lift

Ultra-Lift can be enabled in the Non-mechanical Load Brake (NLB) Hoist motion of the VG+ Series 4 (FLV only). The Ultra-Lift function measures motor torque at base speed and then accelerates to the maximum safe speed. Ultra-Lift will not be enabled if the torque levels exceed C06-04 or C06-05 settings.

Adaptive Ultra-Lift

Adaptive Ultra-Lift can only be enabled in the (NLB) Hoist motion of the VG+ Series 4. The Adaptive Ultra-Lift function continuously monitors motor torque when running above base speed to increase or decrease motor speed based on varying load conditions.

NOTE: *Ultra-Lift is disabled when in traverse applications. Maximum Frequency (E01-04) must be \geq C06-02 and C06-03.*

Table 5-29: Swift-Lift/Ultra-Lift Parameter Settings

Parameter	Display	Function	Range	Default	Model
C06-01	Swift-Lift (V/f and OLV) Ultra-Lift (FLV) 0 Disabled 1 Enabled Auto 2 Enabled by MFDI 3 Enabled Adaptive 4 Adaptive by MFDI	Determines whether Swift-Lift/ Ultra-Lift is enabled. Flux Vector NLB only Flux Vector NLB only	0–4	0	G+/VG+
C06-02	SwiftLift FWDSpd (V/f and OLV) UltraLift FWDSpd (FLV)	Maximum Swift-Lift Forward Speed	0.1–150.0 Hz	60.0	G+/VG+
C06-03	SwiftLift REVSpd (V/f and OLV) UltraLift REVSpd (FLV)	Maximum Swift-Lift Reverse Speed	0.1–150.0 Hz	60.0	G+/VG+
C06-04	SL FWD Current (V/f) SL FWD Torque (OLV) UL FWD Torque (FLV)	Output Current/Torque < C06-04 to enable Swift-Lift Forward. Not used with Adaptive UL.	0–100%	50	G+/VG+

Parameter	Display	Function	Range	Default	Model
C06-05	SL REV Current (V/f) SL REV Torque (OLV) UL REV Torque (FLV)	Output Current/Torque < C06-05 to enable Swift-Lift Reverse. Not used with Adaptive UL.	0–100%	30	G+/VG+
C06-06	SL Enabling Spd (V/f and OLV) UL Enabling Spd (FLV)	Fout > C06-06 to Enable Swift-Lift. (Threshold Speed)	0.1–150.0 Hz	59.0	G+/VG+
C06-07	SL Delay Time (V/f and OLV) UL Delay Time (FLV)	Delay time at Enabling speed to check Output Torque	0.0–25.5 sec	2.0	G+/VG+
C06-08	SFS Acc Gain	Swift-Lift acceleration multiplier for V/f Modes. Settings greater than 1 increase the acceleration time proportionately; settings less than 1 decrease the acceleration time proportionately	0.1–9.9	1.0	G+
C06-10	Mtr Trq Quickset 0 Custom 1 Very Low Torque 2 Low Torque 3 Standard 4 High Torque 5 Very High Torque	Set available motor torque over base speed.	0–5	3	VG+
C06-11	Motor Torque 1	Sets the available torque at Speed 1 (above base speed)	1–100%	45	VG+
C06-12	Motor Speed 1	Sets the Speed 1 point	100–300%	150	VG+
C06-13	Motor Torque 2	Sets the available torque at Speed 2 (above base speed)	1–100%	25	VG+
C06-14	Motor Speed 2	Sets the Speed 2 point	100–300%	200	VG+
C06-15	AUL FWD Offset	Adaptive UL torque measurement offset in the up direction to allow for deceleration.	0–100%	10	VG+
C06-16	AUL REV Offset	Adaptive UL torque measurement offset in the down direction to allow for deceleration	0–100%	20	VG+

NOTE: C06-11 through C06-16 are hidden unless C06-10 is set to “Custom”. Otherwise, C06-11 through C06-14 are automatically modified by C06-10.

Configuring the Swift-Lift & Ultra-Lift Function

For 2, 3, 5-Speed Multi-Step (A01-04 = 0, 1, or 2):

1. Set C06-01= 1–4 to enable the **Swift-Lift & Ultra-Lift Function**, 1 = Enable Automatic, 2 = Enable by Multi-Function Digital Input (MFDI), 3 = Enable Adaptive (Ultra-Lift Only), 4 = Adaptive by MFDI (Ultra-Lift Only).
2. Set C06-02 and C06-03 to determine **Swift-Lift & Ultra-Lift** maximum FWD/REV output frequency.
3. Set C06-04 and C06-05 to determine **Swift-Lift & Ultra-Lift** maximum enable output current.
4. Set the **Swift-Lift & Ultra-Lift Enabling Speed (C06-06)** one or two hertz below the maximum normal running speed reference.

For example: If the maximum normal running speed is at 60 Hz, set C06-06 to 59 Hz or 58 Hz as the **Swift-Lift & Ultra-Lift Enabling Speed**.

5. Ensure that the **Maximum Frequency (E01-04)** is increased from 60 Hz.

For 2, 3 Step Infinitely Variable (A01-04 = 3 or 4)

1. If the system is using **2-Step** or **3-Step Infinitely Variable** as the **Speed Control Method**, the following formula is used to adjust the constant **B02-01 (Reference Upper Limit)**.

$$B02-01 = \frac{60 \text{ Hz} \times 100}{E01-04}$$

For Uni-Polar/Bi-Polar Analog (A01-04 = 5 or 6)

1. If the system is using **Bi-Polar Analog** or **Uni-Polar Analog** as the **Speed Control Method**, the following formula is used to adjust the constant **H03-03 (Gain Multiplier for Terminal A1 analog input signal)**.
H03-11 (Gain Multiplier for Terminal A2 analog input signal).

$$H03-03 = \frac{60 \text{ Hz} \times 100}{E01-04} \quad \text{or} \quad H03-11 = \frac{60 \text{ Hz} \times 100}{E01-04}$$



WARNING

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

Torque Limit

IMPULSE®G+ and VG+ Series 4 drives dynamically control the torque output of the motor while running. The Torque Limit Function limits the amount of torque the motor is capable of producing in Open and Closed loop vector control.

- Forward Motoring (I)
- Forward Regenerating (II)
- Reverse Motoring (III)
- Reverse Regenerating (IV)

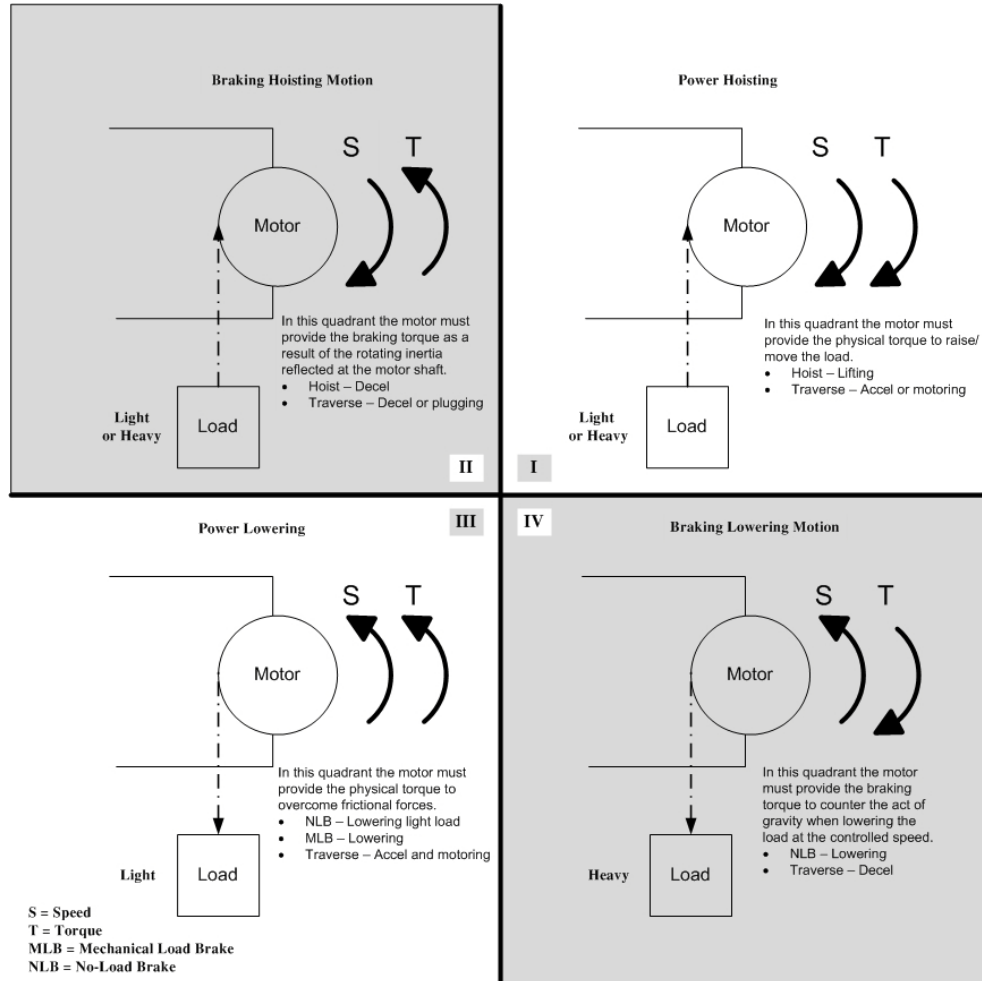


Table 5-30: Torque Limit Parameter Settings

Parameter	Display	Function	Range	Default	Model
C07-01	Trq Limit FWD	FORWARD torque limit	0–300%	150	G+/VG+
C07-02	Trq Limit REV	REVERSE torque limit	0–300%	150	G+/VG+
C07-03	Trq Lmt FWD Rgn	Regenerative torque limit at FORWARD	0–300%	180	G+/VG+
C07-04	Trq Lmt REV Rgn	Regenerative torque limit at REVERSE	0–300%	180	G+/VG+

x = Available in the specified drive/control method

Parameter	Display	Function	Range	Default	Model	
C07-05	T-Lim FWD Gain	Torque Limit gain in FWD direction when MFDI = 14 is ON. Gain is applied to C07-01. If T-Lim by Analog Input is used, gain is applied to post-scaled/biased input.	0.00–2.55	1.25	G+/VG+	
C07-06	T-Lim REV Gain	Torque Limit gain in REV direction when MFDI = 14 is ON. Gain is applied to C07-02. If T-Lim by Analog Input is used, gain is applied to post-scaled/biased input.	0.00–2.55	1.25	G+/VG+	
C07-07	T-Lim RGN Gain	Torque Limit gain in RGN mode when MFDI = 14 is ON. Gain is applied to C07-03 and C07-04. If T-Lim by Analog Input is used, gain is applied to post-scaled/biased input.	0.00–2.55	1.25	G+/VG+	
C07-08	Trq Lim I Time	Sets the integral time constant for the torque limit. (OLV only)	5–10000 ms	200	G+	
C07-09	Torque Limit Sel	Torque Limit Control Method Selection during Accel/Decel	0, 1	0	G+	
	0	<i>P-ctrl @ Acc/Dec</i>				Changes to integral control at constant speed. Use this setting when acceleration to the desired speed should take precedence over the torque limit.
	1	<i>I-ctrl @ Acc/Dec</i>				Integral control. Set L07-07 to 1 if the torque limit should take precedence. (OLV only)
C07-10	Trav Trq Limiter	ASR I time is forced to 0 when the output frequency is greater than the C07-11 speed window. When using this feature, it is suggested that the Overspeed Detect Level (F01-24) be increased to 110% to avoid overspeed faults.	0, 1	0	G+/VG+	
	0	<i>Disabled</i>				
	1	<i>Enabled</i>				
C07-11	Limiter Freq	Sets the frequency window (+/-) size for Traverse Torque Limiter (C07-10) when at speed.	0.5–10.0	2.0	G+/VG+	

x = Available in the specified drive/control method

This traverse torque limiter function (C07-10 and C07-11) is used in multi-drive, closed-loop traverse applications to reduce drive fighting due to speed discrepancies between the two sides of a bridge. This resolves the situation where one side of a bridge will be at full forward torque, while the other side is a full regen torque. When moving below the Limiter Freq, this feature is disabled and the drive behaves as normal. When accelerating past the Limiter Freq, the ASR I time is reduced to zero to limit torque imbalance. Once the motor has accelerated to within the Limiter Freq (i.e. 60 Hz) the regen torque limit also goes to zero. The drive will remain in this state until the speed reference is changed. When the speed reference is raised or lowered, regen torque is re-enabled to accel or decel the bridge as required.

Note that a heavy swinging load may pull the bridge faster than the PG Overspeed level. It is therefore highly suggested that a PG Overspeed Sel (F01-23) be set to Alarm Only.

Anti-Shock

Anti-Shock is a Hoist NLB feature on the IMPULSE®•VG+ Series 4 drive in the Flux Vector control method. The torque output of the hoist is continuously monitored, and when it increases above a threshold (C07-15 and C07-16), the hoist automatically decelerates and waits for the torque to stabilize before smoothly re-accelerating (C07-17 and C07-18). Anti-Shock is designed to maximize hoist operational efficiency while minimizing crane structure fatigue.

Initial Setup and Adjustment

1. Choosing an option to enable/disable Anti-Shock:
 - a. Setting C07-12 to 0 (Disabled) ensures Anti-Shock does not function.
 - b. Setting C07-12 to 1 (Enabled) allows Anti-Shock to run always.
 - c. Setting C07-12 to 2 (Enbl, Not In MSpd) will block Anti-Shock when Micro-Speed is enabled.
 - d. Setting H01-xx to 4B (Anti-Shock OFF) sets a digital input which, when enabled, will block Anti-Shock. This allows Anti-Shock to be enabled or disabled by an external input.
2. Run the hoist, unloaded, in the UP direction. Note the value of U01-09 and enter that approximate value into C07-23.

To make Anti-Shock less sensitive to light loads and more sensitive to heavy loads:

1. Increasing C07-15 (Torque Delta) to a higher percentage increases the torque spike magnitude that is required to trigger Anti-Shock.
2. Increasing C07-16 (Detection Time) to a higher time widens the window of time that a torque spike is looked for.

To make Anti-Shock more sensitive to light loads:

1. Decreasing C07-15 (Torque Delta) to a lower percentage lowers the torque increase magnitude that is required to trigger Anti-Shock.
2. Increasing C07-16 (Detection Time) to a higher time widens the window of time that a torque spike is looked for.

Troubleshooting

Anti-Shock is triggered when the load is already in the air:

Cause: This is caused by a torque increase due to acceleration, which falls within the parameter settings for triggering Anti-Shock.

Corrective Action:

1. Increasing C07-14 (Re-Accel Delay) to a higher time may help remedy this occurrence.
2. Increasing C07-15 (Torque Delta) and decreasing C07-16 (Detection Time) will require a higher torque spike to occur in a shorter amount of time.

When Anti-Shock is triggered, the drive faults to an OV (Overvoltage) or OC (Overcurrent):

Cause: By default, Anti-Shock is configured to decelerate very quickly when a torque increase is detected. The deceleration rate may cause a rapid increase in voltage or current, which may fault the drive.

Corrective Action:

1. Increasing C07-18 (Smoothing Decel) will increase the time it takes for the drive to decelerate directly after the torque spike is detected. Spikes in voltage and/or current will be reduced.

Table 5-31: Anti-Shock Parameter Settings

Parameter	Display	Function	Range	Default
C07-12	Anti-Shock	Enables or disables the Anti-Shock function.	0–2	0
	0 <i>Disabled</i>	Anti-Shock is disabled always.		
	1 <i>Enabled</i>	Anti-Shock is enabled always.		
	2 <i>Enbl, Not In MSpd</i>	Disables Anti-Shock if Micro-Speed is enabled.		
C07-13	Enabling Freq	Anti-Shock is disabled until the output frequency is above this setting.	0.0–60.0 Hz	6.0
C07-14	Re-Accel Delay	If the operator decelerates the hoist then re-accelerates, Anti-Shock Detection is disabled for this period of time.	0.00–2.55 sec	0.20
C07-15	Torque Delta	Torque increase required to initiate the Anti-Shock sequence.	0–180%	10
C07-16	Detection Time	Time window to detect the torque delta (C07-15).	0.01–0.50 sec	0.30
C07-17	Smoothing Freq	When the torque increase is detected, the drive will decelerate to this frequency.	0.0–15.0 Hz	3.0
C07-18	Smoothing Decel	Deceleration time once an Anti-Shock event has been detected. Increase this value in 0.1 sec increments if DEV faults are occurring.	0.00–2.55 sec	0.30
C07-20	Smoothing Time	Time window to satisfy the steadying delta condition.	0.00–0.50 sec	0.20
C07-22	AlarmDisplayTime	When Anti-Shock is triggered, an alarm will display on the keypad screen for the selected duration of time.	0–30 sec	4
C07-23	No Load Torque	Any torque values below this level are ignored. This is best described as the torque level while hoisting with an empty hook (no load).	0–100%	20
C07-24	Activation Torque	In order for Anti-Shock to be triggered, the torque increase is required to peak above this percentage.	0–180%	75
C07-25	Detection Method	Anti-Shock detection method.	0–2	1
	0 <i>Always Detect</i>	Anti-Shock can be continuously detected.		
	1 <i>Once Per Lift</i>	After Anti-Shock is detected once during a run, it will become disabled until the hoist is lowered.		
	2 <i>Fault on Detect</i>	The drive will fault when Anti-Shock is detected.		

No-Load Brake Hoist (VG+)

The No-Load Brake Hoist mode provides a start and stop sequence designed specifically for No-Load Brake Hoists. This mode is enabled automatically when the Motion is set to NLB Hoist (A01-03 = 2). This will also automatically set the Stopping Method to No-Load Brake (B03-03 = 6).

Start

The start sequence begins by building up torque in the motor to a predefined level within the C08-01 (Torque Compensation Time) timer. This level is determined by several factors which are defined below. During the C08-02 time, the drive is monitoring current to motor. The current feedback equation must be satisfied within the time set in C08-02 (IFB OK Time). If it is not, a BE2 (No-Current) fault will be displayed on the keypad and the drive will stop outputting voltage to the motor. The brake will remain closed.

Once the brake has been commanded to release, the drive output remains in Load Float for the amount of time programmed into C08-04. During C08-04, the drive waits for the brake to completely open and watches encoder feedback. If the amount of feedback is less than the setting in C08-05 (Roll Back Count), then the drive proceeds to the BE3 check. If it is not, a BE1 fault is displayed on the keypad and the sequence stops. For the BE3 check, if the brake opened mechanically, then the encoder feedback must be greater than or equal to the value programmed in C08-07 (BE3 Detect Count) within the time set in C08-06 (BE3/Alt Torq Tim). If it is not, then a BE3 fault is displayed. By the time the drive has completed the BE3 check, there should be a significant amount of motor shaft movement and the start sequence is complete.

Stop

The stop sequence begins when the run command has been removed and the output frequency has decelerated to zero. Once at zero speed, the motor maintains a Load Float position for the duration of C08-10 (Load Float Time). During the Load Float time, run commands in either direction are accepted and will begin accelerating immediately in the commanded direction, thereby skipping the start sequence entirely. The Load Float Timer is reset after each new run command. Once the Load Float Timer expires, the brake output command is removed (thereby closing the brake) and Load Float is maintained for the time set in C08-11 (Brake Set Delay) to allow the brake to fully close. Once the Brake Delay Time has expired, the BE6 check is executed. The BE6 check monitors encoder feedback while the load is being transferred from the motor to the brake and compares it to C08-13 (BE6 Max Count). The encoder feedback must not exceed the number of counts in C08-13 within the C08-12 (BE6 Detect Timer) time. If it does (meaning the load slipped through the brake), a BE6 alarm is displayed on the keypad and the drive will reset its Load Float position and maintain its new position. Run commands will still be accepted with the exception of a reduced speed in the up direction set by C08-18 (BE6 Up Speed Limit) and the NLB stop sequence will begin again once the run command had been removed.

Torque Proving

Factor 1: On the first run command after power up, or after any major fault which causes the stop sequence to be skipped, the start sequence by default uses the value programmed in C08-16, the Initial Brake Release torque.

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

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

If the stored value is less than the programmed value in C08-03 (Minimum Brake Release torque), C08-03 is used as the next brake release value. If the feature must be disabled, C08-03 will override C08-16 if it is a greater value.

Dual Brake Feature

The Dual Brake feature is designed for hoist systems with redundant holding brakes. One brake is controlled by an MFDO programmed to 00, and the second brake is controlled by an MFDO programmed to 0A. After a Load Float, during the BE6 (Brake Test) time, one brake is left Open, while the drive tests that the Closed brake is capable of holding the load. After the BE6 time expires, the second brake is closed.

This feature is only intended as a method to test each brake individually. A mechanical delay system may be required to prevent both brakes from closing simultaneously if power is lost.

NOTE: All brake faults are annunciated by both the keypad and via a programmed digital output. Since the keypad is not visible by the operator, an external warning device must be used to ensure proper safety of personnel and equipment. Annunciating a brake fault can be accomplished by using one, or both, of the following methods: 1) An indicator or strobe light that is continuously “ON”, indicating proper operation. If the light should turn “OFF”, this indicates that the light bulb has either burned out, or there is a drive or brake problem. Either scenario requires immediate corrective action. 2) The use of an indicating light wired to relay output terminals MC-MA, N.O. contact, or an audible warning device that will sound during a brake fault condition. A 120 VAC audible warning device can be wired directly to terminals MC-MA, provided that its ratings do not exceed the 1 Amp, 120 VAC, Inductive Spec.

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

If a brake fault is annunciated after the hoist has come to a complete stop, and Load Float (C08-10) has timed out, it would indicate that the drive has checked the brake and determined that the brake has insufficient torque available to hold the load. **DO NOT TURN OFF POWER.** This condition indicates that the brake has failed and the drive / motor combination is suspending the load. If, during this condition, the hoist is operated in the “Raise” direction, it will only be allowed to run at a speed equal to or less than the “BE6 Up Speed” setting in parameter C08-18 (C08-18 is 6 Hz by default.) This is an additional indication that the brake has failed to open, or the load is slipping through the brake. It is recommended that the crane be moved to a safe location and the load lowered to the ground. Corrective action should be taken to repair the brake. The keypad will be displaying one of two alarms during this condition: BE5 or BE6. Refer to “Troubleshooting the Drive” in Chapter 6 of this manual.



WARNING

DO NOT turn off power to the drive during a BE6 or BE8 alarm. This may result in loss of control of the load if the brake has failed in the open position or is unable to hold the load.

Table 5-32: No Load Brake Parameter Settings

Parameter	Display	Function	Range	Default	Model
C08-01	Torque Comp Time	Amount of time for the Torque Comp value to reach 300%.	0.00–2.55 sec	1.00	VG+
C08-02	IFB OK Time	Sets the amount of time to look for the current feedback to be OK before posting a BE2 alarm. Setting this parameter to 0.00 will disable torque proving at start & eliminate BE2 detection (consult factory before disabling torque proving).	0.00–2.55 sec	1.00	VG+
C08-03	Min Brk Rel Trq	Minimum brake release torque.	0–300%	10	VG+
C08-04	Rollback Timer	Sets the amount of time for the brake to release and for brake feedback to be received into the Brake Answer Back Multi-Function Digital Input at start before posting BE1 or BE4 alarm. It is also the time period during which the amount of rollback is checked.	0.00–2.55 sec	0.30	G+/VG+
C08-05	Rollback Count	Detection counts for excessive rollback. 4 pulses = 1 ppr of F01-01	0–15000 pulses	800	VG+
C08-06	BE3/Alt Torq Tim	Time period which C08-07 is measured. Also see C08-08.	0.00–2.55 sec	0.30	VG+
C08-07	BE3 Detect Count	Detection count for Encoder/ Seized-Brake Alarm (BE3). It is the minimum encoder pulse count, during the time period of C08-06, below which the BE3 alarm is triggered. 4 pulses = 1 ppr of F01-01	0–15000 pulses	10	VG+
C08-08	Alt Rev Trq Lim	For a LOWER command in the NLB Hoist Motion Mode only-Torque limit for time of C08-06 to prevent driving through a brake that has failed closed with a load on the hook.	0–300%	25	VG+
C08-09	Zero Speed Level	Determines speed feedback at which Load Float activates.	0.0–10.0 Hz	1.0	VG+
C08-10	Load Float Time	After stop command time period during which the load is held at the zero-position and the electric brake is not set.	0-65535 sec	10*	VG+
C08-11	Brake Set Delay	Sets the amount of time for the brake to set and for brake feedback to be removed from the Brake Answer Back Multi-Function input at stop before posting a BE5 Alarm.	0.0–25.5 sec	0.7	G+/VG+
C08-12	BE6 Detect Time	Time period during which the electric brake is set and tested for sustaining the load. NOTE: To disable BE6 detection, set C08-12 to 0.0.	0.0–25.5 sec	5.0	VG+
C08-13	BE6 Max Count	Total pulse counts must be less than C08-13, during C08-12, otherwise BE6 alarm. 4 pulses = 1 ppr of F01-01	0–15000 pulses	250	VG+

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** $1.25 \times \frac{E02-11 \times 5252}{\text{Motor RPM}}$

Parameter	Display	Function	Range	Default	Model
C08-14	Brake Hold Speed	The frequency the drive outputs to push against the brake for brake proving at start as well as the frequency the drive continues to output until Brake Set Delay Timer expires or the Brake Answerback MFDI is removed.	0.0–25.5%	0.0	VG+
C08-15	Load Float Ext T	Load Float extension time enabled by MFDI=5D.	0–65535 sec	10	VG+
C08-16	Init FWD Brk Trq	Initial Brake Release Torque. The percentage of forward/up motor torque that must be reached within C08-02 time in order for the brake to release at the start of the run command. (BE2 detection)	10–300%	100	VG+
C08-18	BE6 Up Speed Lim	Maximum up speed limit after BE6 or BE8 alarm is detected.	0.00–150.00 Hz	6.00	G+/VG+
C08-19	Brk Slip Reset	Determines if BE6 alarm is automatically reset. If enabled, drive will always perform BE6 test after Load Float time to determine if brake is operational and the fault can be cleared. If disabled the drive will remain in BE6 alarm state until drive power is cycled.	0, 1	0	VG+
		0 Disabled 1 Enabled			
C08-20	BE6 Check Torque	Torque output during a BE6 check.	0.5–20.0%	1.0	VG+
C08-21	Add Mag I Time	Sets the amount of additional time to delay during NLB start to allow the motor to develop the additional magnetizing current.	0.0–3.0 sec	0.0	VG+
C08-22	Brk Slip Detect	Enables continuous monitoring of the brake for NLB Hoists. (BE8 Detection)	0, 1	0	VG+
		0 Disabled 1 Enabled			
C08-23	Brk Slip Det Spd	Adjusts the sensitivity of Brake Slip Detection. BE8	0–10 Hz	1.0	VG+
C08-24	Brake Test Torq	Motor runs in Forward direction at C08-25 speed when MFDI 61 is active. Brake output Multi-function output is not energized, PGO and DEV detection are disabled. Monitor Brake Test Torque at U01-86.	0–6553.5 Flb	(see ** below)	VG+
C08-25	Brake Test Speed	Speed the drive will push against brake during testing.	0–10 Hz	6	VG+
C08-33	Dual Brake Test	Enabling this will alternate the brake outputs after every cycle. When enabled, MFDOs must be programmed to 00 and 0A or OPE28 will be displayed	0, 1	0	VG+
		0 Disabled 1 Enabled			
C08-34	DIR Flt Trq Lvl	Regen torque level required to trip the DIR fault. This is used to detect an NLB hoist which is set up backwards (FWD is down). A setting of 0 disables this feature.	0–100%	20	VG+

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** $1.25 \times \frac{E02-11 \times 5252}{\text{Motor RPM}}$



WARNING

During a BE5, BE6, or BE8 alarm, power should not be removed from the drive. The load should be lowered to the ground and the crane moved to a safe location for service.

E-Lift (VG+)

The E-Lift (Emergency Lift) function can be utilized to operate the drive in the event of an encoder related fault (PGO-1-S/PGO-1-H) that resulted from a defective encoder, encoder cable, or PG-X3 option card. E-Lift can be enabled with a Multi-Function Input (H01-01 ~ H01-08 = 44) under the condition that all run commands have been removed and the drive is not outputting voltage.

When E-Lift is active, the drive will switch to the control method set in E03-01. In hoist applications, it is highly recommended to leave E03-01 set to OLV, which will ensure the proper control of the load. Furthermore, all functions that depend on encoder feedback will be disabled. The Test Mode Configuration parameters (E03-xx group) are active during E-Lift operation instead of the E01-xx parameters. By default, the E-Lift function may only remain operational for 10 minutes (user-adjustable by C08-37), after which a fault will be generated.



DANGER

E-Lift is designed to allow for temporary hoisting operations of motors normally equipped with an encoder in Flux Vector control. Always follow instructions given in the E-Lift setup instructions, and utilize extreme caution when operating a hoist in E-Lift mode. Stop the hoist if any undesired motion occurs and contact Magnetek for additional assistance.



DANGER

Do NOT set E03-01 to a value of 0 (V/f Control) when using E-Lift in hoist applications. E-Lift is designed to operate using the Open Loop Vector (OLV) control method. The use of the V/f control method may cause undesired motion of the load and is only intended for troubleshooting Flux Vector Control method related problems.

E-Lift Setup Instructions

- 1. Auto-Tune the motor:**
Complete the Standard Tuning (Rotational Auto-Tuning) for the motor described in the Auto-Tuning section beginning on page 4-17.
- 2. Configure the E03 Parameter Group - Test Mode Configuration:**
When E-Lift is active, the Test Mode parameters are utilized for voltage and frequency limits instead of the E01 group. The E03 group should be configured as described Table 5-61.

3. Configure the E-Lift Parameters:

The parameters listed in Table 5-33 are used to configure the E-Lift function.

Table 5-33: E-Lift Parameters

Parameter	Display	Function	Range	Default
C08-35	Emergency Lift <i>0 Disabled</i> <i>2 Enabled by MFDI</i>	Determines whether the E-Lift MFDI function is enabled.	0, 2	2
C08-36	ELift Max Speed	Maximum frequency reference when E-Lift is active.	0–150 Hz	30
C08-37	ELift Max Time	Maximum time that E-Lift can be active.	0–6000 s	600

4. Conduct a Preliminary E-Lift Test:

After all parameters have been configured in steps 2 and 3, the E-Lift function must be tested to ensure it can raise and lower a load properly. Conduct the following steps to verify the E-Lift function:

- a. Attach a test load to the hoist (rated capacity is recommended).
- b. Raise the load approximately one foot above the floor.
- c. Turn on the MFDI associated with E-Lift enable (H01-01 ~ H01-08 = 44H).
- d. Inspect the display on the digital operator. The flashing title should alternate between “Emergency Lift” and the present menu title, which confirms that the E-Lift function is active.
- e. Perform a series of raise and lower commands and observe the test load.



DANGER

If any undesired motions occur while E-Lift is active, immediately remove any RUN commands, turn off the E-Lift MFDI, and contact Magnetek.

- f. If steps 4.a through 4.e were successful, turn off the E-Lift MFDI and return the hoist to normal operations.

Digital Input Option Set-up (DI-A3 and S4IO)

Selects the digital input controls for either the DI-A3, S4I, or S4IO option when installed.

Table 5-34: Digital Input Set-up Parameter Settings

Parameter	Display	Function	Range	Default
C09-01	Digital In Sel	Provides additional programmable MFDI	0–2, 5	0
	0 Disabled	No additional MFDI are being used.		
	1 Enabled S4IO	S4IO or S4I card is installed		
	2 Enabled DI-A3	DI-A3 card is installed		
	5 Serial	Modbus RTU using C09-02–C09-17		

Parameter	Display	Terminal Designation			Range**	Default
		DI-A3	S4I	S4IO		
C09-02*	DIO Terminal 1	0	I1	I1	00–FF	0F
C09-03*	DIO Terminal 2	1	I2	I2	00–FF	0F
C09-04*	DIO Terminal 3	2	I3	I3	00–FF	0F
C09-05*	DIO Terminal 4	3	I4	I4	00–FF	0F
C09-06*	DIO Terminal 5	4	--	--	00–FF	0F
C09-07*	DIO Terminal 6	5	--	--	00–FF	0F
C09-08*	DIO Terminal 7	6	--	--	00–FF	0F
C09-09*	DIO Terminal 8	7	--	--	00–FF	0F
C09-10*	DIO Terminal 9	8	--	--	00–FF	0F
C09-11*	DIO Terminal 10	9	--	--	00–FF	0F
C09-12*	DIO Terminal 11	A	--	--	00–FF	0F
C09-13*	DIO Terminal 12	B	--	--	00–FF	0F
C09-14*	DIO Terminal 13	C	--	--	00–FF	0F
C09-15*	DIO Terminal 14	D	--	--	00–FF	0F
C09-16*	DIO Terminal 15	E	--	--	00–FF	0F
C09-17*	DIO Terminal 16	F	--	--	00–FF	0F

* See Table 5-72 for MFDI selections. The following input functions will not operate on an input option board: 20–20F, 31, 34, 35, 47, 80, or 81.

Weight Measurement

The IMPULSE®•G+ & VG+ Series 4 includes a Weight Calculation function that can be used in hoisting applications. The weight measurement calculation is based on motor torque at a constant speed. The drive must pause the acceleration, wait for the torque to stabilize, and then perform the weight calculation based on the system tare values. The function takes a reading one time per lift (Raise Run command) when C10-01 = 1 (Automatic), or it can be configured to take a reading at any speed with a Multi-Function Input when C10-02 = 1 (Manual). The calculated weight can be displayed on the keypad of the hoist drive.

NOTE: *Weight Calculations will be more consistent when a weight measurement is calculated at the same speed every time. Example: C10-01 = 1, weight measurement is always calculated at C10-05 speed. It is important to note that after the load has been rigged, it should be suspended and the brakes should be set on the hoist. When the next raise command is given, the hoist is now ready to calculate the weight of the load. The function only works in the Raising motion (Fwd Run). If extreme accuracy is required, a load cell should be used.*

The Weight Measurement function of the hoist drive has an accuracy within 5% with VG+ drives and 10% with G+ drives of the hoist's rated capacity.

Table 5-35: Weight Measurement Parameter Settings

Parameter	Display	Function	Range	Default	Model
C10-01	Load Weight	Selects method for Load Weight measurements. Measurement is reset at Brake Closed.	0–2	0	G+/VG+
	0 Disabled				
	1 Auto - I/T	Enabled (VG+ Only)			
	2 Auto-Analog	Enabled Analog			
C10-02	LW Start	LW Measurement Start	0, 1	0	G+/VG+
	0 At C10-05				
	1 By MFDI=5C				
C10-03	LW Display Hold	Hold until next run command	0, 1	0	G+/VG+
	0 Hold Display				
	1 Hold Disp 3 Sec				
C10-04*	LW Conversion	Multiplier of torque output calculation for display. Data is n0000, so multiplier is 10000; "n" is decimal point. <i>Example: 24000 = 40.00</i>	0–39999	0	G+/VG+
C10-05	Test Freq	Frequency at which the Weight Measurement will occur.	0–E01-04 Hz	6	G+/VG+
C10-06*	Unit Displayed	Selects the units of measurement being displayed.	0–4	4	G+/VG+
	0 Tons				
	1 Pounds				
	2 Kilograms				
	3 Metric Tons				
4 Percent Load					
C10-07	Holding Time	Time for holding output frequency to measure weight.	0.0–2.55 sec	1.00	G+/VG+
C10-09	Full Load Torque	Percentage of Torque output that is considered full load.	0.0–200.0%	100.0	VG+
C10-10	No Load Torque	Percentage of Torque output that is considered no load.	0.0–200.0%	20.0	VG+

* Used for keypad display; consult factory for assistance.

System Tare and Calibration for Weight Measurement

1. Attach all of the under-hook attachments that are required during **normal** lifting (chains, slings, spreader beam, etc.). Remove the load from the bottom block. If there is a spreader beam or other lifting device that is **constantly** attached to the bottom block, it may be left in place. If the lifting device changes, it should be removed for this procedure and the known weight of the lifting device used for each lift should be manually subtracted from weight that is calculated by the hoist drive.
2. Run the **unloaded** hoist in the raise direction at the speed that the weight will be calculated at. The hoist will automatically pause at the speed programmed in parameter C10-05 (6 Hz is the default) while calculating the weight on the hook. This is the speed the hoist should be run at. An easy method would be to set the first speed point equal to C10-05 or, if using an analog speed reference, then program B02-02 (minimum speed) so that it is equal to C10-05.
3. Record the torque reading being displayed by the monitor parameter U01-09 (Torque Reference). Repeat this step several times and record the average “No Load Torque” in parameter C10-10 (No Load Torque).
4. Rig the **FULL** load that the hoist and weight measurement system will be expected to calculate. If the rigging used for the full load is different than that used in steps 2 and 3, it will need to be added to the known weight being lifted to obtain an accurate total weight at a later time.
5. Run the loaded hoist in the raise direction at the same speed as step 2.
6. Record the torque reading being displayed by the monitor parameter U01-09 (Torque Reference). Repeat this step several times and record the average “Full Load Torque” in parameter C10-09 (Full Load Torque).
7. The monitor parameter U01-29 should now be displaying a value when lifting a full load. This value is a raw number that could later be converted into a meaningful weight to be displayed on the keypad. For this procedure, it is not imperative that the number is converted to tons or pounds. Most importantly, it should read a value of zero or very close to zero when lifting no load and should be relatively consistent when lifting the same weight repeatedly.

Setting Up U01-29 to Display Actual Weight

1. Enter the weight of the FULL load into C10-04, not including chains, slings or spreader beams. Enter this number into the right-most four digits of C10-04.
2. Set the desired number of decimal places in the left most digit; see the examples below:

$$\text{Full load} = 40.0 \text{ tons} \rightarrow \begin{cases} \text{C10-04} = 10400 \\ \text{C10-06} = 0 \end{cases} \text{ (Displays as 40.0 in U01-29)}$$

$$\text{Full load} = 30,000 \text{ lbs} \rightarrow \begin{cases} \text{C10-04} = 23000 \\ \text{C10-06} = 1 \end{cases} \text{ (Displays as 30.00 in U01-29)}$$

Weight Measurement Design Considerations

1. The drive’s weight measurement monitor, U01-29, will display a fixed value after the measurement occurs. That value will continue to be displayed until the next weight measurement is taken at the next run.
2. When displaying the drive’s weight measurement feedback on an auxiliary display, such as a radio or PLC interface, the most accurate feedback can be obtained from the drive with the use of the drive’s RS-485 Memobus interface, similar to the architecture implemented with Magnetek’s RDSI systems. An analog interface can also be implemented, but it is important to understand the analog input and output resolution’s effect on feedback accuracy before implementation.

Slack Cable Detection

IMPULSE®•VG+ Series 4 offers Slack Cable Detection for hoist applications. The Slack Cable condition is detected when the torque output is drastically reduced and has dipped below a set-point (C11-03) level. When Slack Cable condition occurs, the output action is defined by the C11-02 which has six selections.

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

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

Setup Procedure:

- *Set the Slack Cable Detection torque level (C11-03), by lowering the hoist without load at a constant speed that the hoist would normally run during the operation. Monitor and record the torque reference (U01-09). Repeat the above operation several times to ensure an accurate reading.*
- *Then set C11-03 = [(U01-09)-2].*
- *Enable Slack Cable Detection by setting the C11-01 to 1.*
- *Select output action when Slack Cable is detected by defining C11-02.*

Table 5-36: Slack Cable Detection

Parameter	Display	Function	Range	Default	Model
C11-01	Slack Cable	(For Hoist Application) Determines whether Slack Cable Detection is enabled.	0–2	0	VG+
	0	<i>Disabled</i>			
	1	<i>Enabled</i>			
	2	<i>Enabled by MFDI</i>			
C11-02	Action at SLC	Multi-function output that occurs at Slack Cable Detection. For all Selections, RAISE command is permitted (MFDO = 28).	0–5	2	VG+
	0	<i>No Action</i>			
	1	<i>No Act/C3-04</i>			
	2	<i>Decel/C3-04</i>			
	3	<i>Decel/No Opr</i>			
	4	<i>Dec Stop/C3-04</i>			
	5	<i>Dec Stop/No Opr</i>			

Parameter	Display	Function	Range	Default	Model
C11-03	SLC Detect Torq	Percentage of Output Torque below which the enabled Slack Cable Detection is activated-as long as the Frequency output is between C11-04 and C11-06, and the delay time is between C11-05 and C11-07.	-50–100%	30	VG+
C11-04	SLC Detect Spd 1	The Frequency Output that is required for the enabled Slack Cable Detection to be activated. It corresponds to Slack Cable Detection Delay Time 1 (C11-05).	0–E01-04 Hz	2	VG+
C11-05	SLC Delay Time 1	The delay time before the enabled Slack Cable Detection can be activated. It corresponds to Slack Cable Detection Speed 1 (C11-04). Prevents false outputs.	0.00–2.55 sec.	0.50	VG+
C11-06	SLC Detect Spd 2	The Frequency Output below which the enabled Slack Cable Detection can be activated. It corresponds to Slack Cable Detection Delay Time 2 (C11-07).	0–E01-04 Hz	60	VG+
C11-07	SLC Delay Time 2	The delay time before the enabled Slack Cable Detection can be activated. It corresponds to Slack Cable Detection Speed 2 (C11-06). Prevents false outputs.	0.00–2.55 sec.	0.10	VG+

Snap Shaft Detection

This feature is designed to detect a broken or loose coupling by monitoring for a speed deviation between rotating shafts on a drive train. Ideally, mount one encoder on the motor, which drives the gearbox and one encoder on the last rotating part of the drive train, usually near the drum if used for a hoist motion. It is required that a second brake be mounted on the drum shaft. The encoders are wired into two separate PG-X3 encoder input cards, with channel 1 (CN5-C) being the high speed shaft input and channel 2 (CN5-B) being the low speed shaft input. The drive will use channel 1 as the flux vector feedback. The software monitors and compares the speed of both encoders. A gear ratio is entered into parameters C11-12 and C11-13. In an example, if the gearbox ratio is 46.34 : 1, then you would program C11-12 to 4634 and C11-13 to 100. If the difference in speed is greater than the value in C11-10 for a period longer than the setting of C11-11, a “Snap Shaft” is displayed on the keypad display and the drive will perform the action at snap (C11-09).

Set Up

Parameter U01-30 should be monitored during operation to obtain the exact speed difference in Hz between the two shafts. The low speed shaft speed is normalized internally by multiplying the speed of the gear ratio. The value of C11-12 should be adjusted at start up such that U01-30 approaches 0.0.

Table 5-37: Snap Shaft Parameter Settings

Parameter	Display	Function	Range	Default	Model
C11-08	Snap Shaft 0 <i>Disabled</i> 1 <i>Enabled</i>	Determines whether snap shaft detection is enabled.	0, 1	0	VG+
C11-09	Action at Snap 0 <i>Brake/Fault Out</i> 1 <i>Alarm Only</i>	Action taken at detection. A setting of 0 will set the brake and display a fault. With a setting of 1, the drive will continue to run.	0, 1	0	VG+
C11-10	Delta Speed	Difference in speeds of the two shafts normalized by the gear ratio.	0.0–E01-04 Hz	1.0	VG+
C11-11	Delay Time	Gear backlash time in milliseconds	0–2000 ms	250	VG+
C11-12	Gear Ratio Num	Gear ratio numerator	1–65535	10000	VG+
C11-13	Gear Ratio Den	Gear ratio denominator	1–65535	10000	VG+

Brake Delay Timers

This function is used in trolley or bridge applications. It can reduce the mechanical brake wear when the operator tries to position a load. This function is available only in traverse mode and the constant B03-03 must be set to 4 (Decel With Timer).

Table 5-38: Delay Timers Parameter Settings

Parameter	Display	Function	Range	Default
C12-01	Brake Jog Delay	Brake set delay time at Jog Control input.	0.0–100.0 sec	0.0 sec
C12-02	Brake Run Delay	Brake set delay time at RUN input.	0.0–100.0 sec	0.0 sec

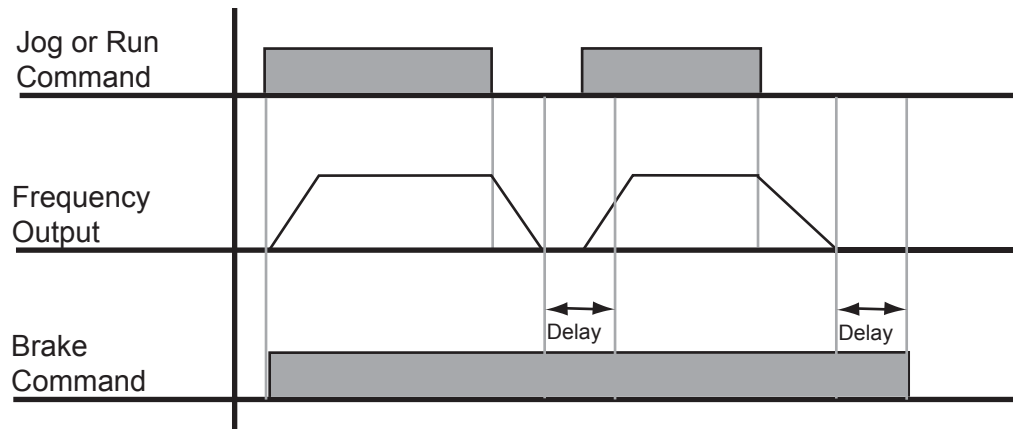


Figure 5-15: Brake Delay Timers

NOTE: The Jog control input is a multi-function input. It is enabled by programming H01-01-08 = 15 or 16.

Timer Function

- The timer function is enabled when the timer function MFDI (H01-0x = 43) and the timer function MFDO (H02-0x = 12) are set respectively.
- The input and output serve as general purpose I/O. Chattering of sensors, switches, contactors, etc., can be prevented by setting a delay time.
- When the timer function input **ON** time is longer than the value set for **C12-03** (Timer function ON-Delay Time), the timer function output turns **ON**.
- When the timer function input **OFF** time is longer than the value set for **C12-04** (Timer function OFF-Delay Time), the timer function output turns **OFF**.

Table 5-39: Timer Function Parameter Settings

Parameter	Display	Function	Range	Default
C12-03*	Delay-ON timer	Timer function output On-delay time (dead zone) for timer function input is set at a unit of seconds.	0.0–3000.0 sec	0.0
C12-04*	Delay-OFF timer	Timer function output Off-delay time (dead zone) for timer function input is set at a unit of seconds.	0.0–3000.0 sec	0.0

* This function is enabled when timer function is set to MFDI/MFDO; H01-xx=43, H02-xx=12.

Maintenance Timer

The “Maintenance Timer” is a maintenance feature that will alert an operator, for example, when the bearings need to be greased. It consists of a Multi-Function Output (H02-0x-08 = 37) that becomes active when the total running time has exceeded the amount of time (in hours) programmed in parameter C12-05 and the frequency reference will be multiplied by a programmable gain (C12-06) to slow the motion down until the bearings have been greased. An alarm will also be posted on the Keypad stating “Maintenance Required”. Once the bearings have been greased, the output and alarm message can be reset by two different methods. One method is through a Multi-Function Input programmed for Maintenance Reset (H01-01-08 = 5A) and the second method is by pressing the Mode/Service (Local/Remote) button three consecutive times with no more than 2 seconds between presses. Press enter to reset the timer. A message will then appear on the keypad stating that the timer has been reset. The Multi-Function Output will turn off at this time. When C12-01 = 0, the function is disabled.

Table 5-40: Maintenance Timer Parameter Settings

Parameter	Display	Function	Range	Default
C12-05	Maintenance Tmr	Maintenance Timer Trip Level	0–32767 Hr	0
C12-06	Maintenance Gain	Speed Reference Gain	0.00–1.00	0.50

Load Share

Please refer to page 5-20 for more information on Load Share.

Table 5-41: Load Share Parameter Settings

Parameter	Display	Function	Range	Default
C12-07	LdShare Flt Time	The amount of time to wait for Slave drives to give a Slave Ready Signal, when in Load Share, before triggering a fault.	0.0–25.5 sec	1.5

Inching Control

Inching Control Function can be enabled by programming H01-01–08 = 17, 18, and 19, respectively. The frequency reference used during inching is determined by B01-17 (Jog Reference).



Table 5-42: Inching Control Parameter Settings

Parameter	Display	Function	Range	Default	Model
C13-01	Inch Run Time	Inching Control run time.	0.00–2.55 sec	1.00	G+/VG+
C13-02	Repeat Delay Tim	Inching Control repeat delay time.	0.00–2.55 sec	1.00	G+/VG+

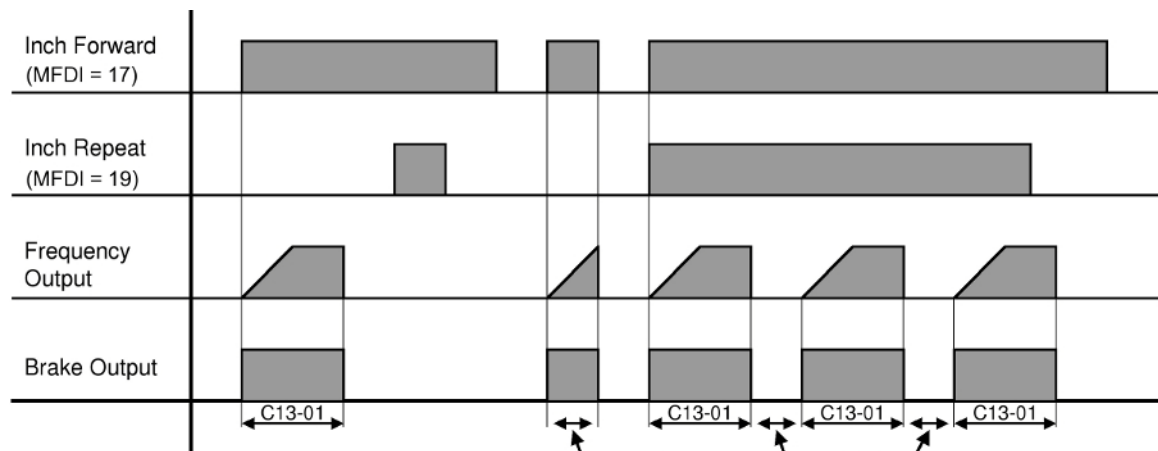


Figure 5-16: Inching Function and Inching Repeat

Index Function

Indexing allows for precise movement of the motor each time a run command is applied by the operator and the Index function is enabled by a Multi-Function Input (H01-xx = 60). This function can only be used with Traverse (A01-03 = 0) and No Load Brake (A01-03 = 2) motions in Flux Vector Control Method (A01-02 = 3) and with any Speed Reference setting for A01-04.

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

$$\text{Total distance (Pulses)} = [\text{F01-01}(\text{Pulse/Rev}) * \text{C13-04(Revs)}] + \text{C13-05(Pulses)}$$

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

When an Index move is complete, a Multi-Function Output (Index Complete H02-xx = 34) can be programmed to turn ON, and will remain ON until one of the following is true:

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

When Applied in Traverse (A01-03 = 0)

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

Open on Index Command (C13-12 = 0)

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

Open on Each Run (C13-12 = 1)

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

Latch Open on Run (C13-12 = 2)

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

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

When Applied in No-Load Brake (NLB) Hoist (A01-03 = 2)

When the motion is No-Load Brake Hoist and the Index Brake Control C13-12 = 2, the action of the brake is controlled by the No-Load Brake sequence. The Index function can be enabled at any time during operation and the action of the brake is described below in C13-12.

At Stop

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

During Run

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

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

NOTE: When either the Index Enable or Run Command is removed, the stop sequence will be initiated.

Table 5-43: Index Function Parameter Settings

Parameter	Display	Function	Range	Default	Model
C13-03	Index Run Ref	Index frequency Ref. (MFDI = 60)	0.01–60.00 Hz	0.10	VG+
C13-04	Index Revs	Index motor revolutions (F01-01 PPR = 1 Rev.)	0–65535 Rev	0**	VG+
C13-05	Index Count	Index fractional motor revolution. 4 pulses = 1 ppr of F01-01	0–65535 Pulses	100**	VG+
C13-06	Index Rpt Delay	Index Repeat Delay Time (Setting of 0.00 disables Index Repeat).	0.00–60.00 sec	0.00	VG+
C13-07	Index Complete	Index Complete Width (Quadrupled) for MFDO = 34. Upper Limit range is dependent on the following conditions: 32767 or (C13-04 *4 * PG constant PPR + C13-05 -1), whichever is smaller. 1 pulse = 1 ppr of F01-01	0–32767	10	VG+
C13-08	Index Zsv Gain	Index Zero Servo Gain.	0–100	10	VG+
C13-09	Index ASR P Gain	Index ASR P Gain.	0.00–300.00	30.00	VG+
C13-10	Index ASR I Time	Index ASR Integral Time.	0.000–10.000 sec	0.200	VG+
C13-11	Acc/Dec Gain	Index Accel/Decel Rate Gain.	0.0–5.0	1.0	VG+

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

Parameter	Display	Function	Range	Default	Model
C13-12	Index Brake Ctrl	Configures brake behavior when indexing (traverse only).	TRAV: 0–2 NLB: 0, 2	NLB: 2 else: 0	VG+
	0 <i>Open on Index</i>	Brake will open on Index Cmd and remain open until Index Cmd is OFF. Drive is in Load Float between runs.			
	1 <i>Open on each Run</i>	Brake will open on Run cmd and close when run is finished, or after Load Float in NLB.			
	2 <i>Ltch Open on Run</i>	Brake will open on Run cmd and remain open with drive in Load Float until Index is turned off.			

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

Tuning

- D1 DC Injection Braking
- D2 Motor Slip Compensation
- D3 Torque Compensation
- D4 Automatic Speed Regulator (ASR) Tuning
- D5 Torque Control
- D8 Dwell Function
- D9 S-Curve Acceleration/Deceleration
- D10 Carrier Frequency
- D11 Hunting Prevention

DC Injection

With decel to stop enabled (B03-03=0), upon removal of the run command, the IMPULSE®•G+ and VG+ Series 4 drive controls motor deceleration according to the Decel Time setting (B05-02), until output frequency reaches the DC Injection Braking Start Frequency (D01-01 setting). Then the IMPULSE®•G+ and VG+ Series 4 frequency output is turned off and DC injection current is applied to the motor. The effective DC injection time and current should be set to provide adequate stopping without excessive motor heating. The DC injection voltage is determined by the DC injection braking current and motor impedance.

Table 5-44: DC Injection Parameter Settings

Parameter	Display	Function	Range	Default
D01-01	DCInj Start Freq	DC Injection Braking Frequency Start	0.0–10.0 Hz	0.5
D01-02*	DCInj Current	Sets the DC Injection Braking current as a percentage of the drive rated current.	0–100%	50
D01-03	DCInj Time@Start	DC Injection Braking Time	0.00–10.00 sec	0.00
D01-04	DCInj Time@Stop	DC Injection Braking Time at Stop	0.00–10.00 sec	0.05

* Not available in the Flux Vector control method (A01-02 = 3).

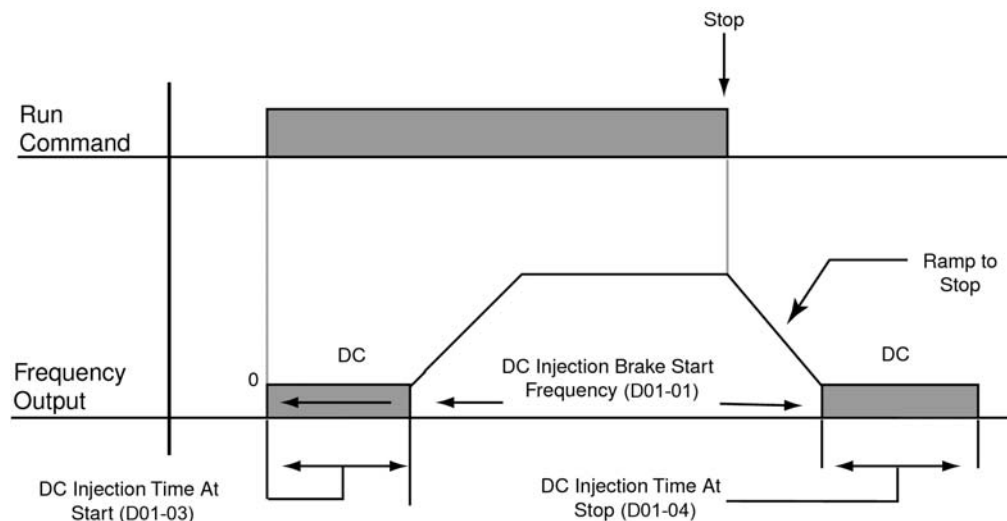


Figure 5-17: DC Braking Sequence

Motor Slip Compensation

As the load becomes larger, the motor speed is reduced and the motor slip increases. The slip compensation function keeps the motor speed constant under varying load conditions. D02-01 sets the slip compensation gain. When the gain is “1.0”, the output frequency is increased by 1% of the E01-06 setting at rated current. A setting of “0.0” results in no slip compensation.

Table 5-45: Motor Slip Compensation Parameter Settings

Parameter	Display	Function	Range	Default	Model
D02-01	Slip Comp Gain	Slip compensation multiplier.	0.0–2.5	V/f: 0.0 OLV: 1.0 FLV: 1.0	G+/VG+
D02-02	Slip Comp Time	Adjusts the slip compensation function delay time,	0–10000 ms	V/f: 2000 OLV: 200	G+
D02-03	Slip Comp Limit	Sets an upper limit for the slip compensation function as a percentage of motor rated slip (E02-02).	0–250%	200	G+
D02-04	Slip Comp Regen <i>0 Disabled</i> <i>1 Enabled >6 Hz</i> <i>2 Enabled >2 Hz</i>	Disabled slip compensation during regeneration.	0–2	0	G+
D02-05	Output V Lim Sel <i>0 Disabled</i> <i>1 Enabled</i>	Automatically reduces motor flux when the output voltage saturates.	0, 1	0	G+/VG+
D02-13*	Output V Lim Sta	Output Voltage Limit Operation Start Level	70.0–90.0%	85.0	VG+
D02-14*	Output V Lim Max	Maximum Output Voltage Limit Level	85.0–100.0%	90.0	VG+
D02-15*	Output V Lim Lev	Output Voltage Limit Level	30.0–100.0%	90.0	VG+

* Available only for 4810 and 41090 models.

Torque Compensation

The motor torque requirement changes according to load conditions. Full-range automatic torque boost adjusts the voltage of the V/f pattern according to the required torque. The IMPULSE®•G+ and VG+ Series 4 automatically adjusts the voltage during constant-speed operation as well as during acceleration.

The required torque is calculated by the inverter. This ensures trip-less operation and power savings.

Output voltage \propto Torque compensation gain x Required torque

When more torque is needed, increase the torque compensation gain in one-tenth (0.1) increments. Increase the setting when the wiring distance between the inverter and the motor is 100ft. or longer. If the motor generates excessive vibration or oscillates, decrease the torque compensation.

Increasing torque compensation gain increases motor torque, but an excessive increase may cause the following:

- Inverter fault trips due to motor overexcitation, and/or
- Motor overheat or excessive vibration.

Increase the torque compensation time constant in 10 ms increments when the motor's output current is unstable. Decrease this value when speed response is slow.

Parameter	Display	Function	Range	Default	Model
D03-01	Torq Comp Gain	Sets the gain for the automatic torque (voltage) boost function and helps to produce better starting torque.	0.00–2.50	1.0*	G+
D03-02	Torq Comp Time	Sets the torque compensation filter time.	0–60000 ms	V/f: 200 OLV: 20	G+
D03-03	F TorqCmp@Start	Sets torque compensation at forward start as a percentage of motor torque.	0.0–200.0%	0.0	G+**
D03-04	R TorqCmp@Start	Sets torque compensation at reverse start as a percentage of motor torque.	-200.0–0.0%	0.0	G+**
D03-05	TorqCmp Delay T	Sets the time constant for torque compensation at forward start and reverse start (C04-03 and C04-04).	0–200 ms	10	G+**
D03-06	Start Torq Time	Sets the torque compensation time 2.	0–10000 ms	150	G+**

*Default setting is determined by parameter A01-02, Control Method Setting.
 ** Only available in Open Loop Vector control method (A01-02 = 2).

Automatic Speed Regulator (ASR) Tuning

The ASR controls the motor speed in the FLV control method and adjusts the output torque reference to minimize the difference between frequency reference and actual motor speed.

The figure below illustrates ASR functionality:

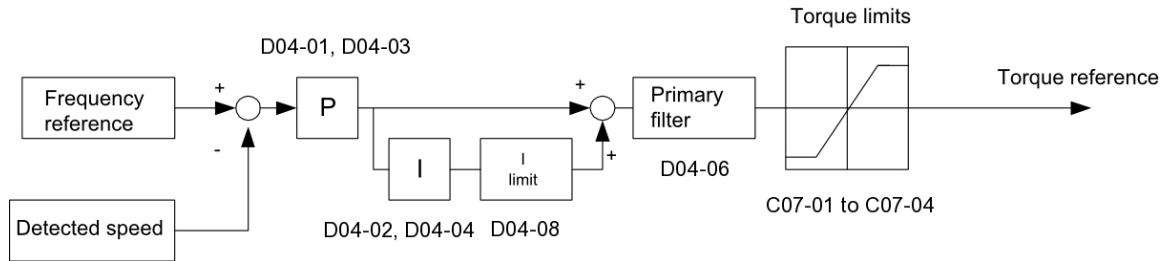


Figure 5-18: Speed Control Block Diagram for FLV

Perform Auto-Tuning and set up all motor data correctly prior to adjusting ASR parameters.

Generally when tuning the ASR, optimize the ASR gain before adjusting the integral time settings. Always make adjustments with the load connected to the motor.

Adjusting the ASR Parameters in FLV

The drive is preset to use ASR settings D04-01/02 over the entire speed range in FLV. If required by the application, a second set of ASR parameters (D04-03/04) can be automatically activated depending on the motor speed or by using a digital input. Refer to the description in D04-01/D04-02 and D04-03/D04-04 on page 5-59.

Perform the following steps for adjusting ASR parameters:

1. Run the motor at zero speed and increase the ASR gain (D04-01) as much as possible without oscillation.
2. Run the motor at zero speed and decrease the ASR integral time (D04-02) as much as possible without oscillation.
3. Run at the normal operating speed. Check for over/undershoot when changing speed and for any oscillation.
4. If problems occur in step 3, increase the integral time and reduce the gain.

Alternatively, use different ASR settings for high and low speed. Set the values from step 1 and 2 to parameters D04-03 and D04-04, then set an ASR switching frequency in parameter D04-07. Run the motor at a speed higher than D04-07 and repeat step 3 while adjusting D04-01 and D04-02.

Solving Problems During ASR Setup

Use Table 5-46 when making adjustments to ASR.

Table 5-46: ASR Setup Problems and Corrective Actions

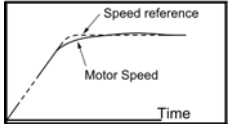
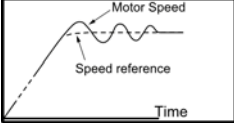
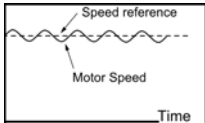
Problem	Possible Solutions
<p>Slow response to speed changes or speed deviation lasts for too long</p> 	<ul style="list-style-type: none"> • Increase the ASR gain. • Decrease the integral time.
<p>Overshoot or undershoot at the end of acceleration or deceleration</p> 	<ul style="list-style-type: none"> • Decrease the ASR gain. • Increase the integral time.
<p>Vibration and oscillation occur at constant speed</p> 	<ul style="list-style-type: none"> • Decrease the ASR gain. • Increase the integral time. • Increase the ASR delay time (D04-06).
<p>Oscillation at low speed and response is too slow at high speed (or vice versa)</p> <p style="text-align: center;">--</p>	<ul style="list-style-type: none"> • FLV: Use D04-01, D04-02, D04-03, and D04-04 to define optimal ASR settings for high and low speed. Use D04-07 to define a switching frequency.

Table 5-47: ASR Tuning Parameter Settings

Parameter	Display	Function	Range	Default	Model
D04-01	ASR P Gain 1	Sets the proportional gain of the speed control loop (ASR).	0.00–300.00	20.00	VG+
D04-02	ASR I Time 1	Sets the integral time of the speed control loop (ASR).	0.000–10.000 sec	0.500	VG+
D04-03	ASR P Gain 2	Sets the speed control gain 2 of the speed control loop (ASR).	0.00–300.00	20.00	VG+
D04-04	ASR I Time 2	Sets the integral time 2 of the speed control loop (ASR).	0.000–10.000 sec	0.500	VG+
D04-06	ASR Delay Time	ASR Output Primary Delay Time.	0.000–0.500 sec	0.004	VG+
D04-07	ASR Gain SW Freq	ASR Gain Switching Frequency.	0.0–150.0 Hz	0.0	VG+
D04-08	ASR I Limit	ASR Integral Limit.	0–400%	400	VG+
D04-36	NLB Strt ASR I	Integral Time at NLB start	0.000–30.000	0.100	VG+
D04-37	NLB Strt ASR Dly	ASR Gain Delay at NLB start	0.00–2.55	0.50	VG+

These parameter settings will function differently depending on the control method.

NOTE: *Mechanical backlash in an application can cause secondary current (I_2) reference variations in the motor's rotor. This condition can prevent the desired adjustment of ASR parameters. The output delay time constant is used to increase the stability of the system allowing a wider setting range of ASR parameters.*

Flux Vector (FLV)

Parameters D04-03 and D04-04 define the ASR proportional gain and integral time at zero speed. The settings in D04-01 and D04-02 are used at speeds above the setting in D04-07. D04-07 is set by default to 0.0 so D04-01 and D04-02 are used by default over the entire speed range. However, changing D04-07 creates two levels of ASR control settings, as shown in Figure 5-19 below.

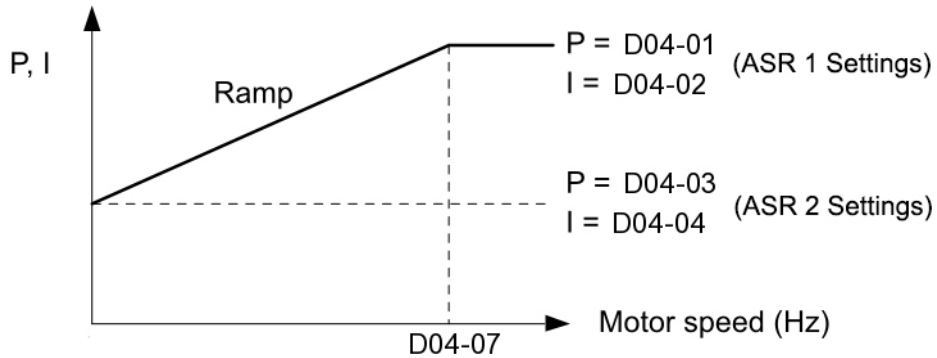


Figure 5-19: Low-speed and High-speed Gain Settings

The switching frequency (D04-07) can also be controlled with a digital input programmed to “ASR gain switch” (H01-xx = 37). When the terminal is open, the drive uses the ASR gain level set by the pattern in Figure 5-19 above. When the terminal closes, D04-03 is used. The integral time set to D04-02 is used to change linearly between these settings, as shown in Figure 5-20 below. The ASR gain switch command from a multi-function input terminal overrides the switching frequency set to D04-07.

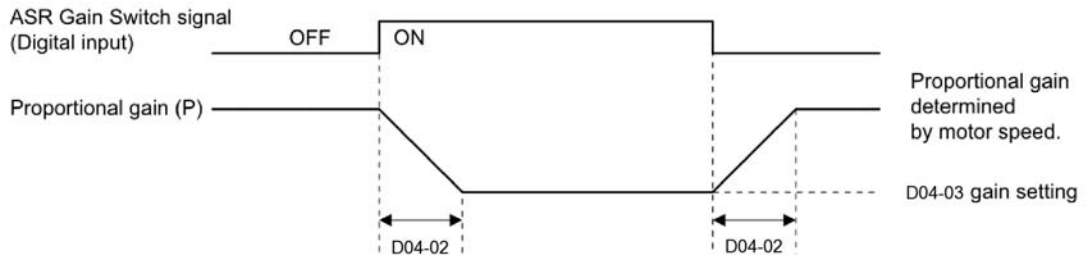


Figure 5-20: ASR Proportional Gain Switch

Torque Control

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

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

Table 5-48: Torque Control Parameter Settings

Parameter	Display	Function	Range	Default	Model
D05-01	Torq Control Sel	Determines whether Speed or Torque Control is selected.	0, 1	0	VG+
	0 <i>Speed Control</i>	Speed Control enabled with torque limit			
	1 <i>Torque Control*</i>	Torque control enabled with speed limit.			
D05-02	Torque Ref Filter	Primary delay time for Torque Reference Input.	0–1000 ms	0	VG+
D05-03	Speed Limit Sel	Speed Limit Selection (See Figure 5-21)	1, 2	2	VG+
	1 <i>Fref Limit</i>	Limit set by the frequency reference in B01-01.			
	2 <i>Speed Limit Sel</i>	Limit set by D05-04.			
D05-04	Speed Lmt Value	Speed Limit Value (% of E01-04)	-120–120%	105	VG+
D05-05	Speed Lmt Bias	Speed Limit Bias (% of E01-04)	0–120%	10	VG+
D05-06	Ref Hold Time	Speed/Torque Switching Timer	0–1000 ms	0	VG+
D05-08	Drctn SpdLmt Sel	Parameter D05-08 selects how the speed limit bias is applied.	0, 1	1	VG+
	0 <i>Disabled</i>				
	1 <i>Enabled</i>				

* Cannot set D05-01 = 1 for NLB Hoist; use Load Share MFDI (H01-xx = 66) instead.

NOTE: Speed/torque control selection can also be made by using a multi-function input select (H01-xx = 34 speed-torque control changeover).

Speed/Torque Control Switching

Speed control or torque control is used in traverse applications and can be selected “on the fly” with the VG+ drive by using the multi-function input speed/torque control selection command (H01-xx = 34).

Table 5-49: Speed/Torque Control Switch Parameters

Terminal Number	Parameter Number	Setting	Description
S1 - S8	H01-01–H01-08	34	Speed/torque control selection
A1	B03-01 D05-03	1 1	Frequency reference selection (terminals A1, A2, or A3) Speed limit selection (terminals A1, A2, or A3)
A3/A2	H03-06/H03-10	13	Torque reference/torque limit

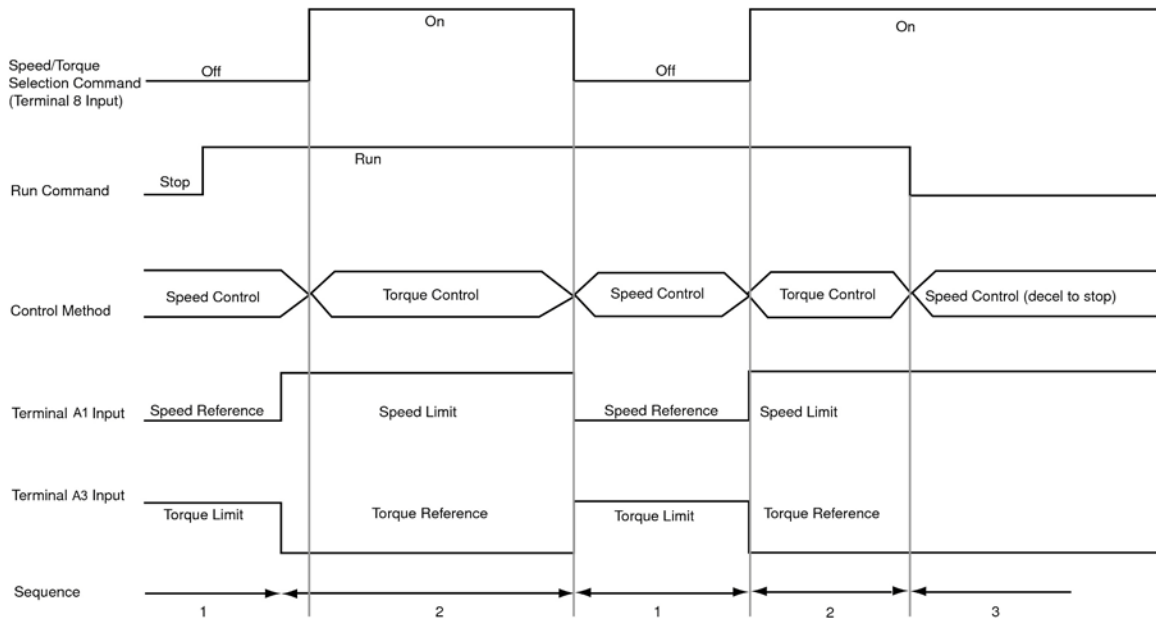


Figure 5-21: Speed/Torque Control Selection Timing Diagram

1. When the speed/torque control selection contact is OFF, speed control is activated.
 - *Speed reference during speed control depends on the frequency reference selection (B03-01) setting. To use terminal A1, A2, or A3 as the master frequency reference, set B03-01 to "1."*
 - *Torque limit during speed control is the smaller of the absolute value of terminal A2 or A3 torque limit, or the values set in the torque limit parameters (C07-01 to C07-04) is used as the torque limit.*
 - *When a stop command is given during speed control, speed control is maintained as the motor decelerates to stop and the smaller of the absolute value of the terminal A2 or A3 torque limit, or the values set in the torque limit parameters (C07-01 to C07-04) is used as the torque limit.*
2. When the speed/torque control selection is ON, torque control is activated.
 - *Speed limit during torque control is the master frequency reference at terminal A1, A2, or A3 when speed limit selection (D05-03) is set to "1", and is the speed limit value (D05-04) when D05-03 = "2", regardless of the frequency reference selection (B03-01) setting.*
 - *During torque control, the terminal A2 or A3 analog input value becomes the torque reference.*
3. By giving a stop command during torque control, operation changes to speed control automatically, and the motor decelerates to stop. The torque limit during deceleration to stop becomes the values set in the torque limit parameters (C07-01 to C07-04).

NOTE: The control method actually changes after the speed/torque control selection command changes and the reference delay timer (D05-06) elapses. The speed reference/speed limit and the torque limit/torque reference are stored in the inverter until the time set to D05-06 elapses.

Dwell Function

The Dwell Function is used to temporarily hold the output frequency at a set reference for a set time. Enable by setting H01-01 – 08 to 65.

Table 5-50: Dwell Function Parameter Settings

Parameter	Display	Function	Range	Default	Access Level
D08-01	Dwell Ref @ Start	Sets Dwell frequency reference at start.	0.0–150.0 Hz	0.0	Adv
D08-02	Dwell Time @ Start	Sets the time duration for the Dwell function at start.	0.0–10.0 sec	0.0	Adv
D08-03	Dwell Ref @ Stop	Sets Dwell frequency Reference at stop.	0.0–150.0 Hz	0.0	Adv
D08-04	Dwell Time @ Stop	Sets the time duration for the Dwell function at stop.	0.0–10.0 sec	0.0	Adv

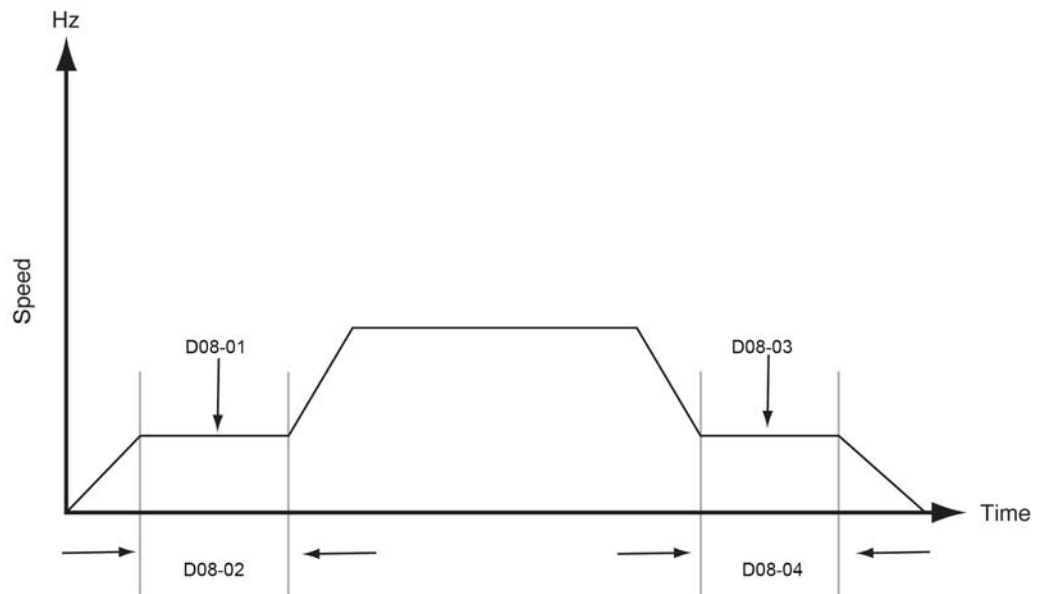


Figure 5-22: Dwell Function

S-Curve Acceleration/Deceleration

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

Table 5-51: S-Curve Acceleration/Deceleration Parameter Settings

Parameter	Display	Function	Range	Default
D09-01	SCrv Acc @ Start	Sets the S-Curve at the beginning of the Accel time.	0.00–10.00 sec	0.20*
D09-02	SCrv Acc @ End	Sets the S-Curve at the end of the Accel time.	0.00–10.00 sec	0.20*
D09-03	SCrv Dec @ Start	Sets the S-Curve at the beginning of the Decel time.	0.00–10.00 sec	0.20*
D09-04	SCrv Dec @ End	Sets the S-Curve at the end of the Decel time.	0.00–10.00 sec	0.20

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

The figure below shows FWD/REV run switching during deceleration to stop. The S-curve function will add time to the acceleration and deceleration. Time to accelerate from the minimum frequency to the maximum frequency (total acceleration) is:

$$\text{Total Acceleration} = B05-01 + \frac{D09-01 + D09-02}{2}$$

Time to decelerate from the maximum frequency to the minimum frequency (total deceleration) is:

$$\text{Total Deceleration} = B05-02 + \frac{D09-03 + D09-04}{2}$$

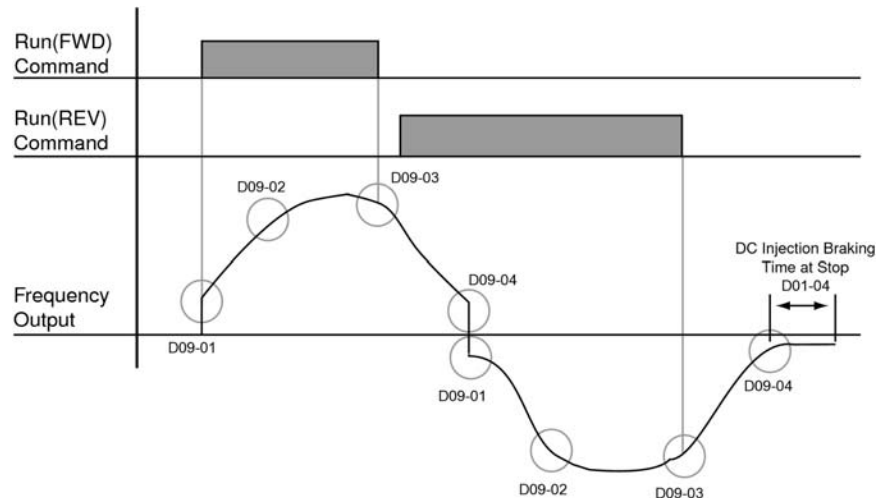


Figure 5-23: S-Curve Characteristic-FWD/REV Operation

Carrier Frequency

The Carrier Frequency group provides the ability to modify the drive's output carrier frequency and drive overload level.



CAUTION

Consult Magnetek for drive derating before modifying the D10 group parameters. Failure to do so may result in equipment damage.

Table 5-52: Carrier Frequency Parameter Settings

Parameter	Display	Function	Range	Default	Model
D10-01	Heavy/NormalDuty 0 <i>Heavy Duty</i> 1 <i>Normal Duty</i>	Constant Torque/Variable Torque Selection	0, 1	0	G+/VG+
D10-02	CarrierFreq Sel 1 <i>Fc=2.0kHz</i> 2 <i>Fc=5.0kHz</i> 3 <i>Fc=8.0kHz</i> 4 <i>Fc=10.0 Hz</i> 5 <i>Fc=12.5kHz</i> 6 <i>Fc=15.0kHz</i> 7 <i>Swing PWM1*</i> 8 <i>Swing PWM2*</i> 9 <i>Swing PWM3*</i> A <i>Swing PWM4*</i> F <i>User Defined</i>	Carrier Frequency Selection Determined by D10-03 through D10-05	1–9, A, F	1	G+/VG+
D10-03	CarrierFreq Max	Determines the carrier frequency upper limit.	1.0–15.0 kHz	2.0	G+/VG+
D10-04	CarrierFreq Min	Determines the carrier frequency lower limit (V/f Control only).	1.0–15.0 kHz	2.0	G+
D10-05	CarrierFreq Gain	Carrier Frequency Gain (V/f Control only).	0–99	0	G+

* Not available in VG+ (A01-02 = 3)

Hunting Prevention

Occasionally, in an application, resonance between the internal control system and the mechanical system causes instability. This is called hunting, and may cause a crane to vibrate at a lower speed (up to 30 Hz) and/or with a light load. The hunting prevention function monitors the motor flux and uses a special control circuit to “smooth out” any peaks in the output current wave form.

Increase the set value of D11-02 when hunting is present while driving a light load. Decrease the set value of D11-02 when the motor vibrates or stalls while driving a heavy load.

Table 5-53: Hunting Prevention Parameter Settings

Parameter	Display	Function	Range	Default	Control Method	Model
D11-01	Hunt Prev Select	Enable/Disable Hunt Prevention function	0, 1	1	V/f	G+
	<i>0 Disabled</i>					
	<i>1 Enabled</i>					
D11-02	Hunt Prev Gain	Hunting Prevention Gain	0.00–2.50	1.00	V/f	G+
D11-03	Hunt Prev Time	Hunting Prevention Time Constant	0–500ms	10	V/f	G+
D11-05	Rev Hunt Prev Gn	Reverse Hunting Prevention Gain	0.00–2.50	0.00	V/f	G+

Motor Parameters

- E1 V/f Pattern 1
- E2 Motor Set-up
- E3 Test Mode

Voltage/Frequency Pattern



WARNING

Drive input voltage (not motor voltage) must be set in E01-01 for the protective features of the drive to function properly. Failure to do so may result in equipment damage and/or death or personal injury.

Table 5-54: V/f Pattern Parameter

Parameter	Display	Function	Range	Default
E01-01	Input Voltage	Sets input voltage	230V: 155–255 VAC	230
			460V: 310–510 VAC	460
			575V: 446–733 VAC	575

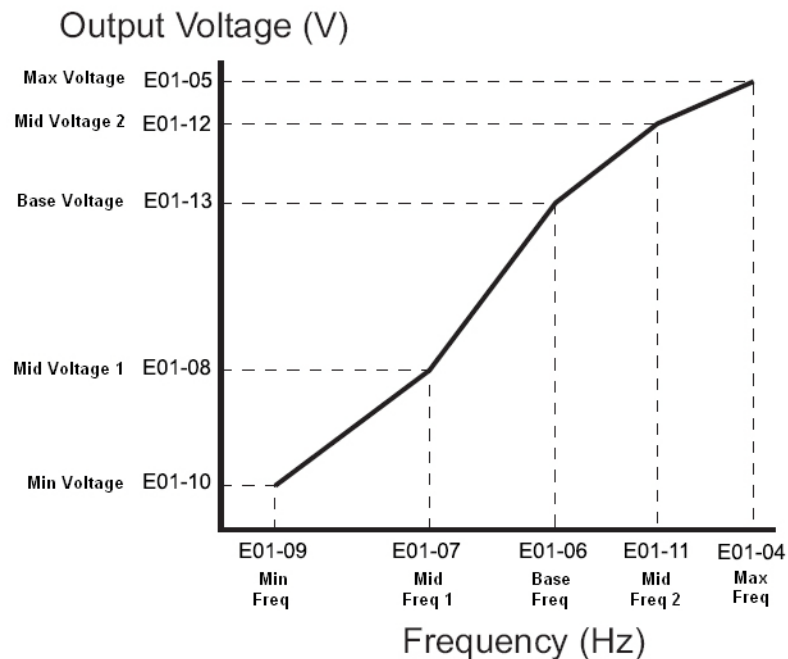


Figure 5-24: E01-01 Input Voltage

- *Factory setting is 230 (230V units) or 460 (460V units).*
- *When E01-11 = 0, then the value of E01-11 is not used.*
- *When E01-12 = 0, then the value of E01-12 is not used.*
- *When E01-13 = 0, then the value of E01-13 is not used.*

An OPE10 error will occur if the following conditions are not met:

$$E01-05 \geq E01-12 \geq E01-13 \geq E01-08 \geq E01-10$$

$$E01-04 \geq E01-11 \geq E01-06 \geq E01-07 \geq E01-09$$

NOTE: *When using the Flex Vector control method, the V/f pattern voltage values will be adjusted by the Auto-Tuning function.*

The setting E01-01 sets the maximum and base voltage used by preset V/f patterns (E01-03 = 0 to E), and adjusts the levels of drive protective features (e.g. Overvoltage, braking resistor turn-on, stall prevention, etc).

Table 5-55: DC Bus Regulation

Inverter Voltage	E01-01 Setting	Overvoltage Trip		Braking Transistor		Stall Level
		Trip	Reset	On	Off	
230	155–255	410 V	380V	380V	375V	380V
460	≥400	820 V	760V	760V	750V	760V
460	<400	740 V	680V	660V	650V	670V
575	≥500 V	1040 V	990V	990V	970V	960V
575	<500 V	990 V	940V	860V	840V	830V

Parameter E01-01 performs the above mentioned function in all three control methods.

Table 5-56:V/f Parameters

Parameter	Display	Function	Range	Default
E01-03	V/f Selection	Motor V/f selection	V/f: 0–9, A–F, FF OLV: F, FF	*
	0 60 Hz, Level 0	(Default for A01-03 = 0 (Traverse), A01-03 = 4 (Braketronic))		
	1 60 Hz, Level 1			
	2 60 Hz, Level 2			
	3 60 Hz, Level 3			
	4 60 Hz, Level 4	(Default for A01-03 = 1 (Std Hoist))		
	5 60 Hz, Level 5			
	6 60 Hz, Level 6			
	7 60 Hz, Level 7			
	8 60 Hz, Level 8			
	9 50 Hz, Level 0			
	A 50 Hz, Level 2			
	B 50 Hz, Level 4			
	C 50 Hz, Level 6			
	D 75 Hz, Level 4			
	E 90 Hz, Level 4			
	F Custom V/f	E01-04 through E01-13 settings define the V/f pattern, (Default for A01-03 = 2 (Hoist NLB)). When A01-03 = 0, 1, 3, or 4 and E01-03 is changed to 0F, the values for E01-04 through E01-13 are the same as E01-03 = 4. See V/f tables for appropriate voltage.		
	FF Custom w/o limit	Custom with no lower limits on E01-xx.		
E01-04	Max Frequency	Maximum Frequency	40.0–150.0 Hz	60.0
E01-05	Max Voltage	Maximum Voltage	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	Determined by O02-04
E01-06	Base Frequency	Motor Base Frequency	0.0–150.0 Hz	60.0
E01-07	Mid Frequency A	Motor Middle output frequency	0.0–150.0 Hz	Determined by E01-03
E01-08	Mid Voltage A	Motor Middle output frequency Voltage	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	Determined by E01-03
E01-09	Min Frequency	Minimum Frequency	0.0–150.0 Hz	Determined by E01-03
E01-10	Min Voltage	Motor Minimum output frequency Voltage	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	Determined by E01-03
E01-11	Mid Frequency B	Midpoint Output Frequency B	0.0–150.0 Hz	0.0
E01-12	Mid Voltage B	Midpoint Output Voltage B	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	0.0
E01-13	Base Voltage	Motor Base Voltage	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	0.0

* Initial value determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

Table 5-57: Voltage/Frequency (V/f) Pattern Options (230 V)

	E01-04	E01-05* ³	E01-06	E01-07	E01-08* ⁴	E01-09	E01-10* ⁴	E01-11	E01-12* ⁴	E01-13* ⁴
E01-03	Hz	VAC	Hz	Hz	VAC	Hz	VAC	Hz	VAC	VAC
0*	60.0	230.0	60.0	3.0	15.0	1.3	8.1	0.0	0.0	0.0
1	60.0	230.0	60.0	3.0	16.1	1.3	9.2	0.0	0.0	0.0
2	60.0	230.0	60.0	3.0	17.3	1.3	10.4	0.0	0.0	0.0
3	60.0	230.0	60.0	3.0	18.4	1.3	11.5	0.0	0.0	0.0
4* ¹	60.0	230.0	60.0	3.0	19.6	1.3	12.7	0.0	0.0	0.0
5	60.0	230.0	60.0	3.0	20.7	1.3	13.8	0.0	0.0	0.0
6	60.0	230.0	60.0	3.0	21.9	1.3	15.0	0.0	0.0	0.0
7	60.0	230.0	60.0	3.0	23.0	1.3	16.1	0.0	0.0	0.0
8	60.0	230.0	60.0	3.0	24.2	1.3	17.3	0.0	0.0	0.0
g* ²	50.0	200.0	50.0	25	13.0	1.1	7.0	0.0	0.0	0.0
A	50.0	200.0	50.0	25	15.0	1.1	9.0	0.0	0.0	0.0
B* ³	50.0	200.0	50.0	25	17.0	1.1	11.0	0.0	0.0	0.0
C	50.0	200.0	50.0	25	19.0	1.1	13.0	0.0	0.0	0.0
D	75.0	200.0	50.0	25	17.0	1.1	11.0	0.0	0.0	0.0
E	90.0	230.0	60.0	30	19.6	1.3	12.7	0.0	0.0	0.0
US (V/f) F & FF	60.0	230.0	60.0	3.0	19.6	1.3	12.7	0.0	0.0	0.0
Euro (V/f) F & FF	50.0	200.0	50.0	2.5	17.0	1.3	11.0	0	0	0
US (OLV) F & FF	60.0	230.0	60.0	3.0	13.8	0.5	2.9	0	0	0
Euro (OLV) F & FF	50.0	200.0	50.0	2.5	12.0	0.5	2.5	0	0	0

* Default for O02.09 = 1 and not Std Hoist

*1 Default for O02.09 = 1 and Std Hoist

*2 Default for O02.09 = 2 and not Std Hoist

*3 Default for O02.09 = 2 and Std Hoist

Table 5-58: Voltage/Frequency (V/f) Pattern Options (460 V)

	E01-04	E01-05* ³	E01-06	E01-07	E01-08* ⁴	E01-09	E01-10* ⁴	E01-11	E01-12* ⁴	E01-13* ⁴
E01-03	Hz	VAC	Hz	Hz	VAC	Hz	VAC	Hz	VAC	VAC
0*	60.0	460.0	60.0	3.0	29.9	1.3	16.2	0.0	0.0	0.0
1	60.0	460.0	60.0	3.0	32.2	1.3	18.4	0.0	0.0	0.0
2	60.0	460.0	60.0	3.0	34.6	1.3	20.8	0.0	0.0	0.0
3	60.0	460.0	60.0	3.0	36.8	1.3	23.0	0.0	0.0	0.0
4* ¹	60.0	460.0	60.0	3.0	39.1	1.3	25.4	0.0	0.0	0.0
5	60.0	460.0	60.0	3.0	41.4	1.3	27.6	0.0	0.0	0.0
6	60.0	460.0	60.0	3.0	43.8	1.3	30.0	0.0	0.0	0.0
7	60.0	460.0	60.0	3.0	46.0	1.3	32.2	0.0	0.0	0.0
8	60.0	460.0	60.0	3.0	48.4	1.3	34.6	0.0	0.0	0.0
9	50.0	400.0	50.0	2.5	26.1	1.1	14.1	0.0	0.0	0.0
A	50.0	400.0	50.0	2.5	30.1	1.1	18.1	0.0	0.0	0.0
B	50.0	400.0	50.0	2.5	34.1	1.1	22.1	0.0	0.0	0.0
C	50.0	400.0	50.0	2.5	38.1	1.1	26.1	0.0	0.0	0.0

* Default for O02.09 = 1 and not Std Hoist

*1 Default for O02.09 = 1 and Std Hoist

*2 Default for O02.09 = 2 and not Std Hoist

*3 Default for O02.09 = 2 and Std Hoist

	E01-04	E01-05* ³	E01-06	E01-07	E01-08* ⁴	E01-09	E01-10* ⁴	E01-11	E01-12* ⁴	E01-13* ⁴
E01-03	Hz	VAC	Hz	Hz	VAC	Hz	VAC	Hz	VAC	VAC
D	75.0	400.0	50.0	2.5	34.1	1.1	22.1	0.0	0.0	0.0
E	90.0	460.0	60.0	3.0	39.2	1.3	25.4	0.0	0.0	0.0
US (V/f) F & FF	60.0	460.0	60.0	3.0	39.1	1.3	25.3	0.0	0.0	0.0
Euro (V/f) F & FF	50.0	200.0	50.0	2.5	34.0	1.3	22.0	0	0	0
US (OLV) F & FF	60.0	460.0	60.0	3.0	27.6	0.5	5.8	0	0	0
Euro (OLV) F & FF	50.0	400.0	50.0	2.5	24.0	0.5	5.0	0	0	0

* Default for O02.09 = 1 and not Std Hoist

*1 Default for O02.09 = 1 and Std Hoist

*2 Default for O02.09 = 2 and not Std Hoist

*3 Default for O02.09 = 2 and Std Hoist

Table 5-59: Voltage/Frequency (V/f) Pattern Options (575 V)

	E01-04	E01-05* ³	E01-06	E01-07	E01-08* ⁴	E01-09	E01-10* ⁴	E01-11	E01-12* ⁴	E01-13* ⁴
E01-03	Hz	VAC	Hz	Hz	VAC	Hz	VAC	Hz	VAC	VAC
0*	60.0	575.0	60.0	3.0	37.5	1.3	20.3	0.0	0.0	0.0
1	60.0	575.0	60.0	3.0	40.3	1.3	23.0	0.0	0.0	0.0
2	60.0	575.0	60.0	3.0	43.3	1.3	26.0	0.0	0.0	0.0
3	60.0	575.0	60.0	3.0	46.0	1.3	28.8	0.0	0.0	0.0
4* ¹	60.0	575.0	60.0	3.0	49.0	1.3	31.8	0.0	0.0	0.0
5	60.0	575.0	60.0	3.0	51.8	1.3	34.5	0.0	0.0	0.0
6	60.0	575.0	60.0	3.0	54.8	1.3	37.5	0.0	0.0	0.0
7	60.0	575.0	60.0	3.0	57.5	1.3	40.3	0.0	0.0	0.0
8	60.0	575.0	60.0	3.0	60.5	1.3	43.3	0.0	0.0	0.0
9	50.0	500.0	50.0	2.5	32.6	1.1	17.7	0.0	0.0	0.0
A	50.0	500.0	50.0	2.5	37.7	1.1	22.6	0.0	0.0	0.0
B	50.0	500.0	50.0	2.5	42.6	1.1	27.7	0.0	0.0	0.0
C	50.0	500.0	50.0	2.5	47.7	1.1	32.6	0.0	0.0	0.0
D	75.0	500.0	50.0	2.5	42.6	1.1	27.7	0.0	0.0	0.0
E	90.0	575.0	60.0	3.0	49.0	1.3	31.8	0.0	0.0	0.0
US (V/f) F & FF	60.0	575.0	60.0	3.0	49.0	1.3	31.8	0.0	0.0	0.0
Euro (V/f) F & FF	50.0	500.0	50.0	2.5	42.5	1.3	27.5	0	0	0
US (OLV) F & FF	60.0	575.0	60.0	3.0	34.5	0.5	7.3	0	0	0
Euro (OLV) F & FF	50.0	500.0	50.0	2.5	30.0	0.5	6.3	0	0	0

* Default for O02.09 = 1 and not Std Hoist

*1 Default for O02.09 = 1 and Std Hoist

*2 Default for O02.09 = 2 and not Std Hoist

*3 Default for O02.09 = 2 and Std Hoist

Motor Set-up

E2 constants define motor parameters. Normally, the default settings for E2 constants are determined by kVA selection (O02-04). In flux vector control and open loop vector, the E2 constants will be set automatically during auto-tuning. At minimum, the motor rated current should be entered into E02-01.

If rotational auto-tuning cannot be performed, E02-02 and E02-05 can be calculated using the motor's nameplate information or by performing non-rotational auto-tuning.

Motor rated slip frequency (E02-02) can be calculated by using the following equation:

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

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

Motor terminal resistance E02-05 can be calculated by using the following equation:

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

Where...
 r_t : motor terminal resistance
 r_p : Phase-to-Phase resistance at insulation class temperature
 T_i : insulation class temperature ($^\circ C$)

Table 5-60: Motor Set-up Parameter Settings

Parameter	Display	Function	Range	Default
E02-01	Motor Rated FLA	Motor-rated current	*	*
E02-02**	Motor Rated Slip	Motor-rated slip frequency	0.00–20.00 Hz	*
E02-03**	No-Load Current	Motor no-load current	0–[(E02-01)-1]	*
E02-04	Number of Poles	Number of poles in motor	2–48	4
E02-05**	Term Resistance	Motor terminal resistance	0.000–65.000 Ω	*
E02-06**	Leak Inductance	Leakage Inductance	0.0–40.0%	*
E02-07**	Saturation Comp 1	Core-Saturation Compensation Coefficient 1	0.00–0.50	0.50
E02-08**	Saturation Comp 2	Core-Saturation Compensation Coefficient 2	E02-07–0.75	0.75
E02-09**	Mechanical Loss	Sets the motor mechanical loss as a percentage of motor rated power (HP) for the motor.	0.0–10.0%	0.0
E02-10**	Motor Iron Loss	Sets the motor iron loss in Watts for the motor.	0–65535 W	*
E02-11	Rated Power	Rated output	0.0–650.0 HP/kW	*

* Initial value is determined by O02-04 (kVA Selection) and D10-01.

** This value is automatically set during auto tuning.

Test Mode Configuration

Test Mode is a troubleshooting aid that is intended for troubleshooting Flux Vector control method problems in the field. This feature cannot be left on indefinitely, as it will generate a fault after being on for a total accumulated time of ten minutes. At this time, the fault must be reset or the power must be cycled.

To enable Test Mode, refer to parameter L05-01.

Table 5-61: Test Mode Configuration Parameter Settings

Parameter	Display	Function	Range	Default
E03-01	Control Method <i>0 V/f Control</i> <i>2 Open Loop Vector</i>	Control Method.	0, 2	2
E03-02	Stopping Method <i>0 Decel to Stop</i> <i>1 Coast to Stop</i>	Deceleration Method	0, 1	1
E03-03	Max Frequency	Maximum Frequency	40.0–150.0 Hz	60.0
E03-04	Max Voltage	Maximum Voltage	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	Determined by E02-04
E03-05	Base Frequency	Motor Base Frequency	0.0–150.0 Hz	60.0
E03-06	Mid Frequency A	Motor Middle output frequency	0.0–150.0 Hz	Determined by E01-03
E03-07	Mid Voltage A	Motor Middle output frequency voltage	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	Determined by E01-03
E03-08	Min Frequency	Minimum Frequency	0.0–150.0 Hz	Determined by E01-03
E03-09	Min Voltage	Motor Minimum output frequency voltage	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	Determined by E01-03
E03-10	Mid Frequency B	Midpoint Output Frequency B	0.0–150.0 Hz	0.0
E03-11	Mid Voltage B	Midpoint Output Voltage B	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	0.0
E03-12	Base Voltage	Motor Base Voltage	230 V: 0.0–255.0 460 V: 0.0–510.0 575 V: 0.0–733.1	0.0

Option Card Parameters

- F1 Encoder (PG-X3) Option Set-up
- F2 Analog Input (AI-A3) Option Set-up
- F4 Analog Output (AO-A3) Option Set-up
- F5 Digital Output (DO-A3 or S4IO) Option Set-up
- F6 Communication Option Card Set-up
- F7 Ethernet Option Card Set-up

Encoder (PG) Option Set-up

Table 5-62: Encoder (PG) Option Set-Up Parameter Settings

Parameter	Display	Function	Range	Default	Model
F01-01	PG1 Pulses/Rev	Sets encoder Pulses/Rev for Channel 1	0–60000 ppr	1024	VG+
F01-02	PG1 Rotation Sel	Changing this parameter has the same effect as swapping A+ and A- encoder wires. 0 Fwd = C.C.W. 1 Fwd = C.W.	0, 1	0	VG+
F01-03	PG1 Output Ratio	Sets the division ratio for the pulse monitor used of the PG option card installed to CH1 (port CN5-C). $f_{\text{Pulse Input}} = f_{\text{Pulse Output}} * \frac{(1 + n)}{m}$ <p>Example: For a ratio of 1/32 between the PG card pulse input and output, set F01-03 = 032 (where n = 0 and m = 32). If only using the A pulse for one-track input, the input ratio will be 1:1 regardless of F01-03 setting.</p>	1–132	1	VG+
F01-04	PG1 #Gear Teeth1	Sets the gear ratio between the motor shaft and the encoder (PG). A gear ratio of 1 will be used if F01-04 or F01-05 are set to 0.	0–1000	0	VG+
F01-05	PG1 #Gear Teeth2	Sets the gear ratio between the motor shaft and the encoder (PG). A gear ratio of 1 will be used if F01-04 or F01-05 are set to 0.	0–1000	0	VG+
F01-06	PGO-1-H	Delay time for PGO-1-H detection. A setting of zero disables PGO-1-H detection. Channel 1 is associated with slot CN5-C, used for motor encoder feedback.	0–100 ms	15	VG+
F01-11	PG2 Pulses/Rev	Sets the number of pulses for a PG option card connected to port CN5-B.	0–60000 ppr	1024	VG+

Parameter	Display	Function	Range	Default	Model
F01-12	PG2 Rotation Sel	Changing this parameter has the same effect as swapping A+ and A- encoder wires.	0, 1	0	VG+
	0 Fwd = C.C.W.				
	1 Fwd = C.W.				
F01-13	PG2 #Gear Teeth1	Sets the gear ratio between the motor shaft and the encoder (PG). A gear ratio of 1 will be used if F01-13 or F01-14 are set to 0.	0–1000	0	VG+
F01-14	PG2 #Gear Teeth2	Sets the gear ratio between the motor shaft and the encoder (PG). A gear ratio of 1 will be used if F01-13 or F01-14 are set to 0.	0–1000	0	VG+
F01-15	PG2 Output Ratio	Sets the division ratio for the pulse monitor used of the PG option card installed to port CN5-B.	1–132	1	VG+
F01-16	PGO-2-H	Delay time for PGO-2-H detection. A setting of zero disables PGO-2-H detection. Channel 2 is associated with slot CN5-B.	0–100 ms	15	VG+
F01-21	PG Fdbk Loss Sel	Stopping method when PGO-1-S or PGO-2-S faults are detected.	Traversal: 0–3 NLB: 1	1	VG+
	0 Decel to Stop	Decelerate to stop using the deceleration time in B05-02.			
	1 Coast to Stop				
	2 Fast Stop	Decelerate to stop using the deceleration time in B05-08.			
	3 Alarm Only				
F01-22	PGO-1-S Det Time	PGO-1-S (CH1) disconnection detection time. A setting of zero disables PGO-1-S detection.	0.0–10.0 sec	2.0	VG+
F01-23	PG Overspeed Sel	Sets the stopping method when an overspeed (OS) fault occurs.	Traversal: 0–3 NLB: 1	1	VG+
	0 Decel to Stop	Decelerate to stop using the deceleration time in B05-02.			
	1 Coast to Stop				
	2 Fast Stop	Decelerate to stop using the deceleration time in B05-08.			
	3 Alarm Only				
F01-24	PG Overspd Level	Sets the overspeed detection level as a percentage of the maximum output frequency.	0–120%	105	VG+
F01-25	PG Overspd Time	Sets the time in seconds for an overspeed situation to trigger a fault (oS).	0.0–2.0 sec	0.0	VG+

Parameter	Display	Function	Range	Default	Model
F01-26	PG Deviation Sel	Stopping method at excessive speed deviation.	Traverse: 0–7 NLB: 5	5	VG+
	0 @Spd Agree-Decel	Stops by deceleration time 1 - B05-02.			
	1 @Spd Agree-Coast	Coast to stop.			
	2 @Spd Agree-F-Stop	Decelerates by fast-stop B05-08.			
	3 @Spd Agree-Alm	DEV displayed, operation continues.			
	4 @Run-Decel	Stops by deceleration time 1 - B05-02.			
	5 @Run-Coast	Coast to stop.			
	6 @Run-Fast Stop	Decelerates by fast-stop B05-08.			
	7 @Run-Alarm Only	DEV displayed, operation continues			
F01-27	PG Deviate Level	Sets the speed deviation detection level as a percentage of the maximum output frequency.	0–50%	10	VG+
F01-28	PG Deviate Time	Sets the time in seconds for a speed deviation situation to trigger a fault DEV.	0.0–10.0 sec	0.3	VG+

Analog Input (AI-A3) Option Set-up

Sets CH1 to CH3 input functions when AI-A3 option is connected.

When the 3CH individual input is used, parameter B03-01 is automatically set to “1” (frequency reference from control circuit terminal). The option/inverter reference selection, which is selected by a multi-function digital input (H01-xx= “1F”), is disabled when using the AI-A3 option.

Table 5-63: Analog Input Option Parameters

Parameter	Display	Function	Range	Default
F02-01	AI Function Sel	Determines whether the 3-channel input selection is individual or addition. See Table 5-63.	0, 1	0
	0 3ch Individual			
	1 3ch Addition			
F02-02	AI Input Gain	Sets the gain for the input signal to the analog card.	-999.9–999.9%	100.0
F02-03	AI Input Bias	Sets the bias for the input signal to the analog card.	-999.9–999.9%	0.0

Table 5-64: Analog Input Option Configuration

Setting	Function	CH1 (V1 to AC)	CH2 (V2 to AC)	CH3 (V3 to AC)
0	3-channel individual input (factory default)	Substitute for terminals V1 & AC	Substitute for terminals V2 & AC	Substitute for terminals V3 & AC
1	3-channel addition input	Sum of CH1 to CH3 input values is used as the frequency reference value		

Analog Output (AO-A3) Option Set-up

Selects the analog output monitors for channel 1 and 2 if the AO-A3 optional card is connected.

Table 5-65: Analog Output Option Set-Up Parameter Settings

Parameter	Display	Function	Range	Default
F04-01	AO Ch1 Select	Analog output option Channel 1 selection	1–630	102
F04-02	AO Ch1 Gain	Analog output Channel 1 multiplier	-999.9–999.9%	100
F04-03	AO Ch2 Select	Analog output option Channel 2 selection (Same as F04-01)	1–630	103
F04-04	AO Ch2 Gain	Analog output Channel 2 multiplier	-999.9–999.9%	50
F04-05	AO Ch1 Bias	Channel 1 bias	-999.9–999.9%	0.0
F04-06	AO Ch2 Bias	Channel 2 bias	-999.9–999.9%	0.0
F04-07	AO Opt Level Ch1 0 0 to 10 V 1 -10 to 10 V	Channel 1 output signal	0, 1	0
F04-08	AO Opt Level Ch2 0 0 to 10 V 1 -10 to 10 V	Channel 2 output signal	0, 1	0

Table 5-66: Parameter Settings for F04-01 and F04-03

Display	Display
0 Not Used	165 PG Output Freq
101 Frequency Ref	184 NLB State*
102 Output Freq	185 NLB Rel Trq*
103 Output Current	408 Heatsink Temp
105 Motor Speed*	416 Motor OL1 Level
106 Output Voltage	417 Drive OL2 Level
107 DC Bus Voltage	601 Mot SEC Current
108 Output HP	602 Mot EXC Current*
109 Torque Reference*	603 ASR Input*
115 Term A1 Level	604 ASR Output*
116 Term A2 Level	605 Voltage Ref (Vq)*
117 Term A3 Level	606 Voltage Ref (Vd)*
120 SFS Output	607 ACR(q) Output*
121 AI Opt Ch1 Level	608 ACR(d) Output*
122 AI Opt Ch2 Level	611 Iq Reference*
123 AI Opt Ch3 Level	612 Id Reference*
129 Load Weight	618 PG1 CounterValue
130 SS Delta Speed	619 PG2 CounterValue
150 Hook Height*	622 Zero Servo Pulse*
154 Input Pulse Mon	626 FF Cont Output*
163 PG CH1 Freq	627 FF Estimate SPD*
164 PG CH2 Freq	--

* Not available in the V/f control method (A01-02 = 0)

Digital Output (DO-A3) and S4IO Option Set-up

Selects the multi-function digital output settings for channels 1 through 8 of the DO-A3 and S4IO option cards.

Table 5-67: Digital Output Set-Up Parameter Settings

Parameter	Display	Terminal Designation		Range	Default
		DO-A3	S4IO		
F05-01*	DO Ch1 Select	M1-PC	O1-O2	0–148	F
F05-02*	DO Ch2 Select	M2-PC	O3-O2	0–148	F
F05-03*	DO Ch3 Select	M3-PC	O4-O5	0–148	F
F05-04*	DO Ch4 Select	M4-PC	O6-O5	0–148	F
F05-05*	DO Ch5 Select	M5-PC	--	0–148	F
F05-06*	DO Ch6 Select	M6-PC	--	0–148	F
F05-07*	DO Ch7 Select	M1-M2	--	0–148	F
F05-08*	DO Ch8 Select	M3-M4	--	0–148	F
F05-09	DO Function Sel	Selects how the DO-A3 option card will work with the drive.		0–2	2
	0	<i>8ch Individual</i>			
	1	<i>Binary Output</i>			
	2	<i>8ch Selected</i>			

* See Table 5-76 for MFDO selections.

Selects the multi-function output selections for the DO-A3 option.

Table 5-68: DO-A3 Output Mode Selection for IMPULSE®G+ and VG+ Series 4

Parameter F05-09 setting	Output Type	Terminals	Output Contents			
0	8-Channel Individual (Fixed Data)	TD5 – TD11	OverCurrent (SC, OC, GF)			
		TD6 – TD11	OverVoltage (OV)			
		TD7 – TD11	Drive Overload (OL2, OH, OH1)			
		TD8 – TD11	Fuse Blown (PUF)			
		TD9 – TD11	OverSpeed (OS-1, OS-2)			
		TD10 – TD11	Motor Overload (OL1)			
		TD1 – TD2	Brake Release			
		TD3 – TD4	Limit Switch (UL1, UL2, UL3, LL1, or LL2)			
1	Binary Coded	TD5 – TD11 (Bit 0)	Bit 3, 2, 1, 0	Output	Bit 3, 2, 1, 0	Output
			0000	No Fault	1000	EF (ALL)
		TD6 – TD11 (Bit 1)	0001	SC, OC, GF	1001	CPF (ALL)
			0010	OV	1010	oL1
			0011	OL2	1011	BE7
			0100	OH, OH1	1100	UV (ALL)
		TD7 – TD11 (Bit 2)	0101	OS-1, OS-2	1101	DEV-1, DEV-2
			0110	PUF	1110	PGO-1-S PGO-1-H PGO-2-S PGO-2-H
		TD8 – TD11 (Bit 3)	0111	LF	1111	Not Used
			TD9 – TD11	Minor Fault (Alarm)		
		TD10 – TD11	Inverter Ready			
		TD1 – TD2	Brake Release			
		TD3 – TD4	Limit Switch (UL1, UL2, UL3, LL1, or LL2)			
		2	8-Channel Selectable	TD5 – TD11	F05-01 (See Table 5-76 for output selections)	
TD6 – TD11	F05-02 (See Table 5-76 for output selections)					
TD7 – TD11	F05-03 (See Table 5-76 for output selections)					
TD8 – TD11	F05-04 (See Table 5-76 for output selections)					
TD9 – TD11	F05-05 (See Table 5-76 for output selections)					
TD10 – TD11	F05-06 (See Table 5-76 for output selections)					
TD1 – TD2	F05-07 (See Table 5-76 for output selections)					
TD3 – TD4	F05-08 (See Table 5-76 for output selections)					

Profibus-DP Communication Option Card Set-up

Settings for the Profibus-DP communication option card SI-P3.

Table 5-69: Communication Option Card Parameter Settings

Parameter	Display	Function	Range	Default
F06-01	Comm Bus Fit Sel 0 <i>Decel to Stop</i> 1 <i>Coast to Stop</i> 2 <i>Fast-Stop</i> 3 <i>Use B3-03 Method</i> 4 <i>Alarm Only</i>	Stopping method at communication error.	0–4	1
F06-02	EF0 Detection 0 <i>Always Detected</i> 1 <i>Only During Run</i>	Option External Fault	0, 1	0
F06-03	EF0 Fault Action 0 <i>Decel to Stop</i> 1 <i>Coast to Stop</i> 2 <i>Fast-Stop</i> 3 <i>Use B3-03 Method</i> 4 <i>Alarm Only</i>	Option External Fault	0–4	1
F06-04	BUS Err Det Time	Set the maximum time the drive should wait for a communication error to occur (bUS).	0.0–5.0 sec	2.0
F06-06	Torq Ref/Lmt Sel 0 <i>Disabled</i> 1 <i>Enabled</i>	Torque Reference Limit Selection (FLV only)	0, 1	0
F06-07	Fref PrioritySel 0 <i>Net/Com REF</i> 1 <i>MultiStep Speed</i>	Selects how multi-step speed inputs are treated when the NetRef command is set. Multi-step reference disabled Multi-step reference enabled	0, 1	0
F06-08	Com Prm Init Sel 0 <i>Init Com Prms</i> 1 <i>No Init Com Prms</i>	Determines whether communication-related parameters (F06-xx and F07-xx) are reset when the drive is initialized using A01-05. Communication-related parameters (F06-xx and F07-xx) are not reset when the drive is initialized using A01-05. Reset all communication-related parameters (F06-xx and F07-xx) when the drive is initialized using A01-05.	0, 1	0
F06-30	PB Node Address	Sets the node address if the Profibus-DP option card is installed	0–125	0

Parameter	Display	Function	Range	Default
F06-31	PB Clear Select	Determines the operation when a "Clear Mode" command is received on the Profibus-DP option Card	0, 1	0
	0 <i>Reset to Zero</i>	Resets drive operation with a Clear mode command.		
	1 <i>Hold Prev Value</i>	Maintains the previous operation state when Clear mode command is given.		
F06-32	PB Map Select	Selects the data format used for Profibus-DP communications.	0, 1	0
	0 <i>PPO Type</i>			
	1 <i>Conventional</i>			
F06-35	CO Node Address	Sets the node address if a CANopen option card is installed.	0–126	0
F06-36	CO Baud Rate	Sets the baud rate for the CANopen option card	0–8	6
	0 <i>Auto Detect</i>			
	1 <i>10 kbps</i>			
	2 <i>20 kbps</i>			
	3 <i>50 kbps</i>			
	4 <i>125 kbps</i>			
	5 <i>250 kbps</i>			
	6 <i>500 kbps</i>			
	7 <i>800 kbps</i>			
8 <i>1 Mbps</i>				
F06-50	DN MAC Address	Sets the MacID address of the DeviceNet option card.	0–64	64
F06-51	DN Baud Rate	Sets the baud rate for the DeviceNet option card.	0–4	4
	0 <i>125 kbps</i>			
	1 <i>250 kbps</i>			
	2 <i>500 kbps</i>			
	3 <i>Set from Network</i>			
4 <i>Automatic</i>				
F06-52	DN PCA Selection	Sets the format of the data received from the DeviceNet master to the drive.	0–255	21
F06-53	DN PPA Selection	Sets the format of the data sent from the drive to the DeviceNet master.	0–255	71
F06-54	DN Idle Flt Det	Selects whether the drive triggers an EF0 fault when no data is received from the DeviceNet master (such as when the master is idling).	0, 1	0
	0 <i>Enabled</i>			
	1 <i>Disabled</i>	No fault detection		

Parameter	Display	Function	Range	Default
F06-55	DN BAUD RATE MEM 0 125 kbps 1 250 kbps 2 500 kbps	Displays the baud rate of the DeviceNet network. (Read Only - Monitor)	0–2	0
F06-56	DN Speed Scale	Sets the scaling factor for the speed monitor in DeviceNet.	-15–15	0
F06-57	DN Current Scale	Sets the scaling factor for the output current monitor in DeviceNet.	-15–15	0
F06-58	DN Torque Scale	Sets the scaling factor for the torque monitor in DeviceNet.	-15–15	0
F06-59	DN Power Scale	Sets the scaling factor for the power monitor in DeviceNet.	-15–15	0
F06-60	DN Voltage Scale	Sets the scaling factor for the voltage monitor in DeviceNet.	-15–15	0
F06-61	DN Time Scale	Sets the scaling factor for the time monitor in DeviceNet.	-15–15	0
F06-62	DN Heart Beat	Sets the heartbeat interval for DeviceNet communications. A setting of 0 disables the heartbeat.	0–10	0
F06-63	DN MAC ID MEM	Displays the DeviceNet MacID assigned to the drive (Read Only - Monitor).	0–63	0

Ethernet Option Card Set-up (Ethernet IP & Modbus TCP/IP)

Settings for communication option cards SI-EN3 and SI-EM3.

Table 5-70: Communication Option Card Parameter Settings

Parameter	Display	Function	Range	Default
F07-01	IP Address 1	IP Address 1	0–255	192
F07-02	IP Address 2	IP Address 2	0–255	168
F07-03	IP Address 3	IP Address 3	0–255	1
F07-04	IP Address 4	IP Address 4	0–255	20
F07-05	Subnet Mask 1	Subnet Mask 1	0–255	255
F07-06	Subnet Mask 2	Subnet Mask 2	0–255	255
F07-07	Subnet Mask 3	Subnet Mask 3	0–255	255
F07-08	Subnet Mask 4	Subnet Mask 4	0–255	0
F07-09	Gateway IP Add 1	Gateway Address 1	0–255	192
F07-10	Gateway IP Add 2	Gateway Address 2	0–255	168
F07-11	Gateway IP Add 3	Gateway Address 3	0–255	1
F07-12	Gateway IP Add 4	Gateway Address 4	0–255	1
F07-13	IP Add Mode Sel 0 User Defined 1 BOOTP 2 DHCP	Sets how the option card IP Address is set at start up	0–2	2

Parameter	Display	Function	Range	Default
F07-14	Duplex Select 0 <i>Half Duplex</i> 1 <i>Auto Negotiate</i> 2 <i>Full Duplex</i>	Sets how the communication between host/client will be determined	0–2	1
F07-15	Baud Rate 10 <i>10 Mbps</i> 100 <i>100 Mbps</i>	Sets the communication speed for the option card.	10, 100 Mbps	10
F07-16	CommLoss Tout	Sets the time-out value for communication loss detection in tenths of a second. A value of 0 disables the connection time-out. Example: an entered value of 100 represents 10.0 seconds.	0–300 deciseconds	0
F07-17	EN Speed Scale	Sets the scaling factor for the EtherNet/IP speed setting/monitor	-15–15	0
F07-18	EN Current Scale	Sets the scaling factor for the EtherNet/IP output current setting/monitor	-15–15	0
F07-19	EN Torque Scale	Sets the scaling factor for the EtherNet/IP torque setting/monitor	-15–15	0
F07-20	EN Power Scale	Sets the scaling factor for the EtherNet/IP power monitor	-15–15	0
F07-21	EN Voltage Scale	Sets the scaling factor for the EtherNet/IP voltage setting/monitor	-15–15	0
F07-22	EN Time Scale	Sets the scaling factor for the EtherNet/IP time setting/monitor	-15–15	0
F07-23 to F07-32	DOA116 (1 to 10)	Dynamic parameters that contain the MEMOBUS/Modbus addresses used for programmable registers in the output assembly 116. Data residing in bites 20 to 39 of assembly 116 will be written to the respective MEMOBUS/Modbus registers identified by the addresses contained in these parameters. No data is written to the MEMOBUS/Modbus registers if the parameter setting is 0.	Modbus Address 0x- - - -	0
F07-33 to F07-42	DOA166 (1 to 10)	Dynamic parameters that contain the MEMOBUS/Modbus addresses used for programmable registers in the input assembly 166. Data residing in the MEMOBUS/Modbus registers will be written to the respective assembly 166 bytes 20 to 39. The MEMOBUS/Modbus registers are identified by the addresses contained in these parameters. No data is written to the programmable registers if the parameter setting is 0.	Modbus Address 0x- - - -	0

Terminal Parameters

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

Digital Inputs

The IMPULSE®•G+ and VG+ Series 4 has eight multi-function digital inputs for the set-up of numerous functions. The following table lists the function selections for the multi-function digital inputs (terminals S1 to S8) and indicates the control methods during which each function can be enabled. An OPE03 error will occur if a function is programmed in more than one terminal at the same time.

Table 5-71: Digital Inputs Parameter Settings

Parameter	Display	Function	Range	Default
H01-01	Term S1 Select	Selects the multi-function inputs. Reference Table 5-72	0–81	80 (FWD)
H01-02	Term S2 Select	Reference Table 5-72	0–81	81 (REV)
H01-03	Term S3 Select	Reference Table 5-72	0–81	*
H01-04	Term S4 Select	Reference Table 5-72	0–81	*
H01-05	Term S5 Select	Reference Table 5-72	0–81	*
H01-06	Term S6 Select	Reference Table 5-72	0–81	*
H01-07	Term S7 Select	Reference Table 5-72	0–81	*
H01-08	Term S8 Select	Reference Table 5-72	0–81	*
H01-14	Alt Ref Override 0 Disabled 1 Enabled	Alternate Frequency Reference Override. When enabled, and an input of H01-xx = 1F is true, will switch between Frequency Reference Source 2 (B03-15) and the terminals (B01-xx).	0, 1	0

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

Table 5-72: Multi-Function Digital Inputs (MFDI) selectable for H01-0x and C09-0x

Display	Function
0 Multi-Step Ref 2	Multi-Step Reference 2
1 Multi-Step Ref 3	Multi-Step Reference 3
2 Multi-Step Ref 4	Multi-Step Reference 4
3 Multi-Step Ref 5	Multi-Step Reference 5
4 Speed Hold 2	Speed Hold 2 (2nd Step of Three-Step Infinitely Variable)
5 Accel Command	Accel Command (2nd Step of Two-Step Infinitely Variable or 3rd Step of Three-Step Infinitely Variable)
6 Upper Lmt 1 N.O.	Upper Limit - Slow Down; Normally Open. UL1 - blinking
7 Upper Lmt 2 N.O.	Upper Limit - Stop; Normally Open. UL2 - blinking
8 Lower Lmt 1 N.O.	Lower Limit - Slow Down; Normally Open. LL1 - blinking
9 Lower Lmt 2 N.O.	Lower Limit - Stop; Normally Open. LL2 - blinking

Display	Function
<i>A Upper Lmt 1 N.C.</i>	Upper Limit - Slow Down; Normally Closed. UL1 - blinking
<i>B Upper Lmt 2 N.C.</i>	Upper Limit - Stop; Normally Closed. UL2 - blinking
<i>C Lower Lmt 1 N.C.</i>	Lower Limit - Slow Down; Normally Closed. LL1 - blinking
<i>D Lower Lmt 2 N.C.</i>	Lower Limit - Stop; Normally Closed. LL2 - blinking
<i>E M-Speed Gain 1</i>	Micro-Speed positioning control multiplier 1. Gain is set by parameter C02-01. (Has Priority over Micro-Speed 2)
<i>F Not Used</i>	No function - Terminal is disabled.
<i>10 M-Speed Gain 2</i>	Micro-Speed positioning control multiplier 2. Gain is set by parameter C02-02.
<i>11 Load Float 1</i>	Load Float Hold - When input during run, Load Float will remain On and Fref is held at 0 Hz while MFDI is ON.
<i>12 Weight Lmt N.C.</i>	Weighted Upper Limit - UL3. Stopping Method determined by C03-08.
<i>13 SwiftLift Enable UltraLift Enable</i>	Ultra/Swift Lift Enable (C06-01 = 2). Not Available for Traverse Motion.
<i>14 Alt T-Lim Gain</i>	Alternate Torque Limit Gain - C07-05. Use when Load Testing a Hoist. (Internal T-Lim* C07-05)
<i>15 Forward Jog</i>	Forward Jog (Uses B01-17 Reference)
<i>16 Reverse Jog</i>	Reverse Jog (Uses B01-17 Reference)
<i>17 Forward Inch</i>	Forward Inch
<i>18 Reverse Inch</i>	Reverse Inch
<i>19 Inch Repeat</i>	Inch Repeat
<i>1A Acc/Dec 2</i>	Acceleration/Deceleration Time Changeover 2 using B05-03 and B05-04
<i>1B Acc/Dec 3</i>	Acceleration/Deceleration Time Changeover 3 using B05-12 and B05-13
<i>1C Acc/Dec 4</i>	Acceleration/Deceleration Time Changeover 4 using B05-14 and B05-15
<i>1D Digital Chngover</i>	Analog/Digital Reference Changeover; When B01-18 = 1 If Closed = Digital
<i>1F Run/Ref Src 1/2</i>	Run/Ref Source 2 Switch - Closed = Run / Fref Selection from B03-15 / B03-16, else B03-01/B03-02
<i>20 through 2F</i>	External Fault (Desired setting is possible.) Input mode: N.O. / N.C., Detection mode: Always / During run. See External Fault Selection (Table 5-80)
<i>30 Program Lockout</i>	Closed: Parameters enabled to write; Open: Parameters disabled to write other than freq. reference (U01-01).
<i>31 Local/Remote Sel</i>	Local/Remote Changeover. Closed = Local
<i>32 Ext BaseBlk N.O.</i>	N.O.: Baseblock by ON.
<i>33 Ext BaseBlk N.C.</i>	N.C.: Baseblock by OFF.
<i>34 Spd/Trq Chngover</i>	Speed/Torque Control Changeover (ON: Torque Control)
<i>35 Load Float 2</i>	Zero Speed initiated. Manual Load Float Timed by C04-01.
<i>36 Polarity Rev</i>	Polarity Reversing command for External Torque Control. Closed = Reverse Polarity
<i>37 ASR Gain Switch</i>	ON: Switches to ASR Gain 2 parameters - Forces D04-07.
<i>38 Acc/Dec RampHold</i>	Speed Hold 1 - Accel/decel is stopped by ON, and frequency is held.
<i>39 OH2 Alarm Signal</i>	External OH2 - Inverter overheat prediction (OH2 is shown by ON.) (Alarm Only)
<i>3A MFAI Enable</i>	When closed, the terminals specified in H03-14 are enabled. When open, the drive disregards the input signal to the analog terminals. The terminals that are not set in H03-14 to be enabled by this feature will always be enabled.
<i>3F Fault Reset</i>	Resets Drive Faults when ON.
<i>41 SnapShaft Disabl</i>	Open: Snap Shaft Detection is Enabled Closed: Snap Shaft Detection is Disabled.

Display	Function
43 <i>Timer Function</i>	Function settings by C12-03, C12-04. It is set with timer function output H02-01–H02-03 = 12.
47 <i>Ref Sample Hold</i>	Analog frequency reference Sample / Hold.
48 <i>Flt Latch Reset</i>	When a function is latched, toggle this input ON and then OFF to clear the fault.
4B <i>Anti-Shock OFF</i>	When this input is ON, Anti-Shock will be blocked from functioning.
4C <i>DCInj Activate</i>	ON: DC injection braking command, once SFS reaches Zero Speed
53 <i>Comm Test Mode</i>	Communication test mode - Loopback test of Modbus RS-422/485 interface.
55 <i>Drive Enable</i>	When Programmed, must be ON in order for Inverter Ready - Generates "Can't Run - Drive Not Ready" Alarm. "RDY" is displayed in upper right hand corner of LCD when drive is ready.
56 <i>Klixon N.O.</i>	When Closed, Reset run command, use stopping method C03-12, display KLX - Klixon Alarm on Keypad
57 <i>Klixon N.C.</i>	When Open, Reset run command, use stopping method C03-12, display KLX - Klixon Alarm on Keypad
58 <i>Brake Answerback</i>	Drive will post BE0, BE4, BE5, BE7 alarm conditions only when programmed to MFDI. (C08-04, C08-11)
59 <i>Alt F-Ref Up Lmt</i>	Use Alternate Upper Limit Frequency Reference B02-04
5A <i>MaintenanceReset</i>	Resets Maintenance Timer (C12-05–06, U01-52)
5B <i>BE6/8 Up Spd Lmt</i>	Limits Fref to setting in C08-18 (BE6 Up Speed Lmt)
5C <i>Weight Measure</i>	Weight Measurement by C10-01.
5D <i>Load Float Ext</i>	Extends C08-10 Time by adding C08-15 time.
5E <i>M-Spd Gn1 & LF-E</i>	Micro-Speed Gain 1 and Load Float Extension Time. (Combination of MFDI "E" and "5D" ON)
5F <i>Phantom Flt N.C.</i>	Phantom Fault N.C. - Stops motion based C03-09 but does not change Keypad display. RUN L.E.D. on keypad blinks.
60 <i>Index Enable</i>	Enables indexing function (Hidden when B03-03 = 1 Coast to Stop)
61 <i>Brake Test</i>	Motor pushes against brake up to programmable torque setting C08-24 at programmable frequency C08-25. Disables PG Faults during this condition.
62 <i>Weight Lmt N.O.</i>	Weighted Upper Limit - UL3 - Stopping Method determined by C03-08.
63 <i>Phantom Flt N.O.</i>	Stops motion based C03-10 but does not change Keypad display. RUN L.E.D. on Display Blinks.
64 <i>Slack Cable Enable</i>	CLOSED Slack Cable is detection is Enabled OPEN: Slack Cable detection is Disabled
65 <i>Dwell Enable</i>	Enables / Disables Dwell Function. When H01-0x = 65, OFF = Disabled.
66 <i>Load Share</i>	Load Share - Enables / Disabled Load Sharing.
67 <i>Hook Height Home</i>	Used w/ C03-14 - Height Measurement function.
68 <i>LodShr Slave Rdy</i>	Load Share slave drive ready signal. Loss of this signal on the master drive while running will result in the Phantom Fault action being taken.
69 <i>LC Bypass N.O.</i>	Disables Load Check and clears any LC Faults.
6A <i>LC Bypass N.C.</i>	Disables Load Check and clears any LC Faults.
6B <i>Brake 2 AnsrBack</i>	Brake Answerback signal for Brake 2 Output (0AH). When programmed, the drive will verify that brake is open before attempting to spin motor. Drive will post BE0-2, BE4-2, BE5-2, or BE7-2 Faults or Alarms if feedback is incorrect.
70 <i>Torque Detection</i>	When the input is closed, Overtorque / Undertorque detection is enabled.
73 <i>LL2/UL2 Bypass</i>	Bypass Upper/Lower Limit 2
74 <i>LL/UL Bypass</i>	Bypass Upper/Lower Limit
80 <i>Run FWD</i>	Forward/Up Run Command
81 <i>Run REV</i>	Reverse/Down Run Command

F1 and F2 Keys Function Selection

The F1 and F2 keys on the keypad have the ability of being programmed with specific functions to imitate digital inputs. The table below displays the various settings, which are valid for these buttons.

- To operate a function assigned to the F1 or F2 key, the respective button must be held down. Releasing the button will stop the function. Be cautious when operating these keys, and remember that the STOP key will override and stop all functions.
- To quickly view the functions assigned to both buttons, press the LO/RE key three times.

Table 5-73: F1 and F2 Function Selection Parameter Settings

Parameter	Display	Function	Range	Default
H01-09	F1 Key Selection	Function selection for F1 key	0F-74	0F
H01-10	F2 Key Selection	Function selection for F2 key	0F-74	0F

Table 5-74: F1 and F2 keys function selectable for H01-09 and H01-10

Display	Function	Instruction	Alert/Confirm Message
0F <i>Not Used</i>	No function - terminal is disabled	--	--
48 <i>Flt Latch Reset</i>	When a fault is latched, toggle this input ON and then OFF to clear the fault.	Press F1 or F2 once to pre-start Fault Latch Reset. A confirm message will appear, and the same key press will be required once more to reset a latched fault.	<i>Confirm?</i> <i>Flt Latch Reset</i>
53 <i>Comm Test Mode</i>	Communication Test Mode - loopback test of Modbus RS-422/485 interface	Hold down the F1 or F2 key for 2-3 seconds to initiate the Comm Test.	<i>Running:</i> <i>Comm Test Mode</i>
5A <i>MaintenanceReset</i>	Resets Maintenance Timer (C12-05, C12-06, U01-52)	Press F1 or F2 once to pre-start Maintenance Timer Reset. A confirm message will appear, and the same key press will be required once more to reset the Maintenance Timer.	<i>Confirm?</i> <i>MaintenanceReset</i>
61 <i>Brake Test</i>	Motor pushes against brake up to programmable torque setting C08-24 at programmable frequency C08-25. Disabled PG Faults during this condition.	Hold down the F1 or F2 key to initiate the Brake Test.	<i>Running:</i> <i>Brake Test</i>
67 <i>Hook Height Home</i>	Used with C03-14 - Height Measurement function.	Press F1 or F2 once to pre-start Hook Height Home. A confirm message will appear, and the same key press will be required once more to home the Hook Height.	<i>Confirm?</i> <i>Hook Height Home</i>
69 <i>LC Bypass N.O.</i>	Disables Load Check and clears any LC faults.	Hold down the F1 or F2 key to initiate the LC Bypass.	<i>Running:</i> <i>LC Bypass N.O.</i>
73 <i>LL2/UL2 Bypass</i>	Bypass Limit MFDI and EPLS	Hold down the F1/F2 key to initiate LL2/UL2 Bypass.	<i>Running:</i> <i>LL2/UL2 Bypass</i>
74 <i>LL/UL Bypass</i>	Bypass MFDI and EPLS	Hold down the F1/F2 key to initiate LL/UL Bypass.	<i>Running:</i> <i>LL/UL Bypass</i>

Digital Outputs

The IMPULSE®G+ and VG+ Series 4 has three built-in multi-function digital outputs for indicating various conditions. Drive digital output capabilities can be increased with the installation of an S4IO or DO-A3 option card. The following table lists the function selections for the multi-function digital outputs and indicates the control methods during which each function can be enabled.

Table 5-75: Digital Outputs Parameter Settings

Parameter	Display	Function	Range	Default
H02-01	Term M0-M1 Sel	Digital Output 1 Function (Reference Table 5-76)	0–1FF	*
H02-02	Term M2-M3 Sel	Digital Output 2 Function (Reference Table 5-76)	0–1FF	*
H02-03	Term M5-M6 Sel	Digital Output 3 Function (Reference Table 5-76)	0–1FF	*
H02-06	Wh Disp Units 0 0.1 kWh units 1 1 kWh units 2 10 kWh units 3 100 kWh units 4 1000 kWh units	Watt Hour Output Unit Selection	0–4	0

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

Table 5-76: Multi-Function Digital Outputs (MFDO) selectable for H02-0x and F05-0x

Display	Function
0 Brake Release*	ON/CLOSED: When the drive is commanding the brake to be Open OFF/OPEN: When the drive is commanding the brake to be Closed
1 Zero Speed*	ON/CLOSED: When Motor Speed < D01-01 or E01-09
2 Fref/Fout Agree1	ON/CLOSED: When the output frequency (U01-02) is within the frequency reference (U01-01) ± L04-02 OFF/OPEN: When the output frequency or motor speed is not within the frequency reference (U01-01) ± L04-02
3 Fref/Set Agree 1	ON/CLOSED: When the output frequency (U01-02) is within L04-01 ± L04-02 OFF/OPEN: When the output frequency (U01-02) is not within L04-01 ± L04-02
4 Freq Detect 1	See the “Frequency Detect” section on page 5-109.
5 Freq Detect 2	See the “Frequency Detect” section on page 5-109.
6 Inverter Ready*	ON/CLOSED: After the drive has performed initialization process and no faults or programming mode is detected
7 DC Bus Undervolt*	ON/CLOSED: When the DC Bus voltage falls below the trip level set in L02-05
8 BaseBlock	ON/CLOSED: During BaseBlock - No Voltage output OFF/OPEN: When drive is not in a BaseBlock state - Voltage Output
9 Operator Ref	ON/CLOSED: When frequency reference is from the operator OFF/OPEN: When frequency reference is not from the operator (i.e. external terminals)
A Brake 2	ON/CLOSED: When the drive is commanding the secondary brake to be Open OFF/OPEN: When the drive is commanding the secondary brake to be Closed
B Trq Det 1 N.O.	ON/CLOSED: When the output current/torque exceeds the value set in parameter L06-02 for longer than the time set in parameter L06-03. OFF/OPEN: When the output current/torque does not exceed the value set in parameter L06-02 for longer than the time set in parameter L06-03.

* This output does not have an inverse output

** Contact will open when power is disconnected

Display	Function
<i>C Anti-Shock ON</i>	ON/CLOSED: When Anti-Shock is enabled and a torque spike is detected. OFF/OPEN: When torque is stable and a spike is not detected.
<i>D DB Overheat</i>	ON/CLOSED: When the drive displays an "RH" or "RR" fault OFF/OPEN: When the drive is not in an "RH" or "RR" fault condition
<i>E Fault</i>	ON/CLOSED: When the drive is in a fault condition (excluding CPF00 and CPF01) OFF/OPEN: When the drive is not in a fault condition
<i>F Not Used*</i>	No Function
<i>10 Minor Fault</i>	ON/CLOSED: When the drive is in a minor fault condition OFF/OPEN: When the drive is not in a minor fault condition
<i>11 Reset Cmd Active</i>	ON/CLOSED: When there is a reset command present using the terminals, serial communications, or communication option card OFF/OPEN: When a reset command is not present
<i>12 Timer Output</i>	ON/CLOSED: When H01-xx = 43 is active for longer than C12-03 time OFF/OPEN: When H01-xx = 43 is not active
<i>13 Fref/Fout Agree2</i>	ON/CLOSED: When the output frequency (U01-02) is within the frequency reference (U01-01) \pm L04-04 OFF/OPEN: When the output frequency (U01-02) is not within the frequency reference (U01-01) \pm L04-04
<i>14 Fref/Set Agree 2</i>	ON/CLOSED: When the output frequency (U01-02) is within L04-03 \pm L04-04 OFF/OPEN: When the output frequency (U01-02) is not within L04-03 \pm L04-04
<i>18 Trq Det 2 N.O.</i>	ON/CLOSED: When the output current/torque exceeds the value set in parameter L06-05 for longer than the time set in parameter L06-06 OFF/OPEN: When the output current/torque does not exceed the value set in parameter L06-05 for longer than the time set in parameter L06-06
<i>1A Forward Dir</i>	ON/CLOSED: During Forward/Up operation OFF/OPEN: When running in Reverse/Down direction or baseblock
<i>1B Reverse Dir</i>	ON/CLOSED: During Reverse/Down operation OFF/OPEN: When running in Forward/Up direction or baseblock
<i>1C Swift/Ultra-Lift Mode</i>	ON/CLOSED: When the drive is operating in Swift-Lift/Ultra-Lift mode OFF/OPEN: When the drive is not operating in Swift-Lift/Ultra-Lift mode
<i>1D Brk Trans Fault</i>	ON/CLOSED: When the drive detects a brake transistor failure OFF/OPEN: Normal operation
<i>1E LC Operating</i>	ON/CLOSED: When the drive is testing the current load before posting a LC Fault OFF/OPEN: Normal operation
<i>1F Regenerating</i>	ON/CLOSED: When the drive is in a regenerative mode OFF/OPEN: Normal operation
<i>20 Auto-Rst Attempt</i>	ON/CLOSED: When Auto-reset is enabled OFF/OPEN: Normal operation
<i>21 Overload (OL1)</i>	ON/CLOSED: When the drive exceeds 90% of the motor overload detection level (oL1) OFF/OPEN: Normal operation
<i>22 OH Pre-Alarm</i>	ON/CLOSED: When the drive heatsink temperature \geq L08-02 OFF/OPEN: Normal operation
<i>23 Torque Limit</i>	ON/CLOSED: When the torque (U01-09) is \geq C07-01–C07-04. OFF/OPEN: Normal operation
<i>24 Speed Limit</i>	ON/CLOSED: When: <ul style="list-style-type: none"> 1. the frequency reference has reached the upper limit set in B02-01 (D02-01). 2. the frequency reference has fallen below B02-02 (D02-02) or B02-03 (D02-03). 3. parameter B03-05 (B01-05) = 1, 2, or 3, and the frequency reference is $<$ E01-09. OFF/OPEN: Normal operation

* This output does not have an inverse output

** Contact will open when power is disconnected

Display	Function
25 <i>During Load Flt</i>	ON/CLOSED: When drive is in Load Float OFF/OPEN: When drive is not in Load Float
26 <i>Run Cmd is Input</i>	ON/CLOSED: When either a Forward or Reverse command is active on H01-xx OFF/OPEN: When neither a Forward or Reverse command is active on H01-xx
27 <i>Load Check Det</i>	ON/CLOSED: When the drive has detected a Load Check fault OFF/OPEN: Normal operation
28 <i>Slack Cable Det</i>	ON/CLOSED: When the drive has detected a Slack Cable OFF/OPEN: Normal operation
29 <i>Upper Limit</i>	ON/CLOSED: When a UL1, UL2, or UL3 is detected OFF/OPEN: Normal operation
2A <i>During RUN 2</i>	ON/CLOSED: When a run command is active and the drive is outputting voltage.
2B <i>Upper Limit 1</i>	ON/CLOSED: When UL1 is detected OFF/OPEN: Normal operation
2C <i>Upper Limit 2</i>	ON/CLOSED: When UL2 is detected OFF/OPEN: Normal operation
2D <i>Lower Limit 1</i>	ON/CLOSED: When LL1 is detected OFF/OPEN: Normal operation
2E <i>Lower Limit 2</i>	ON/CLOSED: When LL2 is detected OFF/OPEN: Normal operation
30 <i>Lower Limit</i>	ON/CLOSED: When LL1 or LL2 is detected OFF/OPEN: Normal operation
31 <i>Up/Low Limit</i>	ON/CLOSED: UL1, UL2, UL3, LL1, or LL2 is detected OFF/OPEN: Normal operation
32 <i>Snap Shaft</i>	ON/CLOSED: When the drive has detected a Snap Shaft OFF/OPEN: Normal operation
34 <i>Index Complete</i>	ON/CLOSED: When the Index move is complete OFF/OPEN: Normal operation or Index move is not complete
35 <i>Ready for F-Ref</i>	ON/CLOSED: When C08-04 timer has expired or the Brake Answerback is detected H01-xx = 58 is true OFF/OPEN: Normal operation or drive detected a BE1, BE2, BE4 alarm or is stopped.
36 <i>Fan Alm Det</i>	ON/CLOSED: When the drive detects that the internal cooling fan has failed OFF/OPEN: Normal operation
37 <i>Maintenance</i>	ON/CLOSED: When the Maintenance Timer U01-52 \geq C12-05 OFF/OPEN: Normal operation or the Maintenance Timer U01-52 $<$ C12-05
38 <i>Spd Lim @ T Cont</i>	ON/CLOSED: When Speed Limit has been reached while using Torque Control OFF/OPEN: When the Speed Limit has not been reached when using Torque Control
39 <i>Drive Enable</i>	ON/CLOSED: When Drive is Enabled OFF/OPEN: When Drive Enable (H01-xx =65) is not active
3B <i>Watt-hour Pulse</i>	ON/CLOSED: When the Watt-hour time is reached (based on setting of H02-06), the contact will close for 200 ms OFF/OPEN: When the Watt-hour time has not been reached
3D <i>Fault or Alarm</i>	ON/CLOSED: When either a Fault or Alarm condition is detected OFF/OPEN: Normal operation
3E <i>Overspeed</i>	ON/CLOSED: When an overspeed condition is detected OFF/OPEN: Normal operation
3F <i>Klixon</i>	ON/CLOSED: When a Klixon alarm is detected (H01-xx = 56 or 57 is active) OFF/OPEN: Normal operation

* This output does not have an inverse output

** Contact will open when power is disconnected

Display	Function
<i>40 through FF</i>	ON/CLOSED: When specific fault condition are detected (see Fault Annunciation)
<i>Flt Annunciate</i>	OFF/OPEN: Normal operation
<i>102 through 1FF**</i>	Parameter Settings 2 through FF with inverse output.

** This output does not have an inverse output*

*** Contact will open when power is disconnected*

Digital Outputs—Alarm/Fault Annunciate (H02-01–03=40)







Digital Outputs—Fault Annunciate enables you to assign a set of six fault outputs to Relay Output M2/M3 and/or Output M5/M6. In addition, you can select whether each fault output is enabled.

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




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

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

To program **Digital Outputs—Fault Annunciate** (from the **Programming Menu**):

1. Press the  and the  buttons to navigate to H02-01.
2. Determine the output terminal to which you want **Fault Annunciate** assigned; Terminals M0-M1, M2-M3 or M5-M6 and press  until the value blinks.
3. Press the  or  button until H02-xx = 040 appears.
4. Press the  button.

H02-xx = 40 Flt Annunciate

 appears.
5. From the worksheet in table 5-77, select one of three fault output sets (each row is a set). Enter the one-zero combination that corresponds to the set (row) that you selected.
6. Determine which fault outputs should be enabled. To enable a fault output, enter 1 in the box above the fault output; otherwise, enter 0. Do this for each fault output in the set.
7. Using the Binary to Hexadecimal Conversion chart (table 5-79), determine the 1-digit hexadecimal number for both 4-digit binary numbers.
8. Press the  or  and  buttons until the appropriate hexadecimal number appears and press Enter.

Example: Select a fault annunciate set in which the fault you want to appear is shown. You must select only faults from one set. If you want to have the relay output to change based on only inputs LL1 and UL1, you would choose Set 2.

1. *Place a “1” below LL1 and UL1 for Set 2.*
2. *Use table 5-78 to convert the left binary value “1 0 0 0” to Hex 8.*
3. *Use table 5-78 to convert the right binary value “1 0 1 0” to Hex A.*
4. *Enter this value into H02-xx.*

Table 5-77: Fault Annunciate Example

	First digit from the left				Second digit from the left			
	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0
Set 2	1	0	OT1	OT2	LL1	LL2	UL1	UL2
Binary Number	1	0	0	0	1	0	1	0

First digit from the left = 8

Second digit from the left = A, so **H02-xx = 8A**

Table 5-78: Fault Annunciate Worksheet

	First digit from the left				Second digit from the left			
	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0
Set 1	0	1	BE8	BE6	BE5	BE3	BE2	BE1
Binary Number	0	1						

	First digit from the left				Second digit from the left			
	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0
Set 2	1	0	OT1	OT2	LL1	LL2	UL1	UL2
Binary Number	1	0						

	First digit from the left				Second digit from the left			
	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0	1 or 0
Set 3	1	1	SLC	BE4	BE3	BE2	BE1	BE0
Binary Number	1	1						

Table 5-79: Binary to Hexadecimal Conversion

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

External Fault Response Selection

It is sometimes desirable to have at least one external fault input to the drive. To properly program a multi-function input (H01-01 to H01-08) for this purpose an external fault response must be selected. The table below shows the possible selections for an external fault response.

Table 5-80: External Fault Selection

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

(1) N.O. = normally open contact; N.C. = normally closed contact
 (2) Uses B05-08 timer

Analog Inputs

The IMPULSE®•G+ and VG+ Series 4 has three built-in analog inputs for the external input of numerous references and limits. Drive analog input capabilities can be increased with the installation of an AI-A3 option card.

Table 5-81: Analog Inputs Parameter Settings

Parameter	Display	Function	Range	Default
H03-01	Term A1 Signal 0 0 to 10 V 1 -10 to 10 V	Voltage for Terminal A1 analog input signal	0, 1	*
H03-02	Terminal A1 Sel	Sets the function of terminal A1 (see tables 5-82 and 5-83 for option selections).	0–31	*
H03-03	Terminal A1 Gain	Sets the level of the input value selected in H03-02 when 10 V is input at terminal A1.	-999.9–999.9%	100.0
H03-04	Terminal A1 Bias	Sets the level of the input value selected in H03-02 when 0 V is input at terminal A1.	-999.9–999.9%	0.0
H03-05	Term A3 Signal 0 0 to 10 V 1 -10 to 10 V	Voltage for Terminal A3 analog input signal	0, 1	0
H03-06	Terminal A3 Sel	Sets the function of terminal A1 (see tables 5-82 and 5-83 for option selections).	0–31	*
H03-07	Terminal A3 Gain	Gain multiplier for Terminal A3 analog input signal	-999.9–999.9%	100.0
H03-08	Terminal A3 Bias	Bias multiplier for Terminal A3 analog input signal	-999.9–999.9%	0.0
H03-09	Term A2 Signal 0 0 to 10 V 1 -10 to 10 V 2 4 to 20 mA 3 0 to 20 mA <i>NOTE: Use DIP switch S1 to set input terminal A2 for a current or a voltage input signal.</i>	Terminal A2 Signal Level Selection	0–3	2
H03-10	Terminal A2 Sel	Sets the function of terminal A2 (see tables 5-82 and 5-83 for option selections).	0–31	1F
H03-11	Terminal A2 Gain	Gain multiplier for terminal A2 analog input signal	-999.9–999.9%	100.0
H03-12	Terminal A2 Bias	Bias multiplier for terminal A2 analog input signal	-999.9–999.9%	0.0
H03-13	Filter Avg Time	Analog input filter average time	0.00–2.00sec	0.03

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

Parameter	Display	Function	Range	Default
H03-14	A1/A2/A3 Sel	Determines which analog input terminals will be enabled when a digital input programmed for "MFAI Enable" (H01-xx = 3A) is activated.	1–7	7
	1	A1 Available		
	2	A2 Available		
	3	A1/A2 Available		
	4	A3 Available		
	5	A1/A3 Available		
	6	A2/A3 Available		
	7	All Available		
H03-15	TerminalA1Offset	Adds an offset when the analog signal to terminal A1 is 0V	-500–500	0
H03-16	TerminalA2Offset	Adds an offset when the analog signal to terminal A2 is 0V	-500–500	0
H03-17	TerminalA3Offset	Adds an offset when the analog signal to terminal A3 is 0V	-500–500	0

* Initial value is determined by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

Table 5-82: Option Selections for H03-02, H03-06, and H03-10 (Flux Vector)

Display	Function
0 Analog Freq Ref1	Analog Frequency reference 1 10V = E01-04 (Maximum output frequency)
1 Frequency Gain	The value of the analog frequency reference will be multiplied with the analog frequency reference gain value.
2 Analog Freq Ref2	Analog Frequency reference 2 10V = E01-04 (Maximum output frequency)
3 Analog Freq Ref3	Analog Frequency reference 3 10V = E01-04 (Maximum output frequency)
5 Acc/Dec T Reduct	10V = 100%
7 OT / UT Det Lvl	Motor rated torque (vector control); inverter rated current (V/f control)
9 Ref Lower Limit	Max. output frequency 10V = E01-04 (Maximum output frequency)
D Freq Ref Bias 2	The input value of an analog input set to this function will be added to the frequency reference. This function can be used with any frequency reference source.
E MotorTemperature	
10 FWD Torque Limit	Torque limit when motoring in the forward direction.
11 REV Torque Limit	Torque limit when motoring in the reverse direction.
12 Regen Torque Limit	Torque limit during regen.
13 Torque Reference	Torque reference when in Torque Control mode; Torque limit when in Speed Control mode.
14 Torque Comp	
15 Torque Limit	Torque limit when motoring.
16 Load Cell	Used for Weight Measurement and/or Load Check
1F Not Used	--

Table 5-83: Option Selections for H03-02, H03-06, and H03-10 (V/f)

Display	Function
0 <i>Analog Freq Ref1</i>	100% = Max output frequency (E01-04) Same value can be set using H03-02 and H03-10. 10V = E01-04 (Maximum output frequency)
1 <i>Frequency Gain</i>	The value of the analog frequency bias will be multiplied with the analog frequency reference gain value.
2 <i>Analog Freq Ref2</i>	Max. output frequency 10V = E01-04 (Maximum output frequency)
3 <i>Analog Freq Ref3</i>	Max. output frequency 10V = E01-04 (Maximum output frequency)
4 <i>Voltage Bias</i>	Output Voltage Bias. This bias boosts the output voltage of the V/f curve as a percentage of the maximum output voltage (E01-05). Only available in V/f mode. Motor rated voltage (E01-05) 10V = E01-05 (Motor rated Voltage)
5 <i>Acc/Dec T Reduct</i>	10V = 100%
6 <i>DC Inj Braking</i>	DC Injection Braking Current 10V = 100% Drive rated current 4 to 20 mA = 0 to 100% Drive rated current
7 <i>OT / UT Det Lvl</i>	Motor rated torque (vector control); inverter rated current (V/f control)
8 <i>Stall Prev Level</i>	
9 <i>Ref Lower Limit</i>	Max. output frequency 10V = E01-04 (Maximum output frequency)
D <i>Freq Ref Bias 2</i>	The input value of an analog input set to this function will be added to the frequency reference. This function can be used with any frequency reference source.
E <i>MotorTemperature</i>	
16 <i>Load Cell</i>	Used for Weight Measurement and/or Load Check
1F <i>Not Used</i>	--

Analog Outputs

The IMPULSE®•G+ and VG+ Series 4 has two built-in analog outputs for the external monitoring of drive conditions. Drive analog output capabilities can be increased with the installation of an AO-A3 option.

Table 5-84: Analog Outputs Parameter Settings

Parameter	Display	Function	Range	Default
H04-01	Terminal FM Sel	Assigns one of the following function analog output parameters to Terminal FM. Reference the U monitor group for output function descriptions.	000–630	102
	<i>0 Not Used</i>			
	<i>101 Frequency Ref</i>			
	<i>102 Output Freq</i>			
	<i>103 Output Current</i>			
	<i>105 Motor Speed</i>			
	<i>106 Output Voltage</i>			
	<i>107 DC Bus Voltage</i>			
	<i>108 Output HP</i>			
	<i>109 Torque Reference</i>			
	<i>115 Term A1 Level</i>			
	<i>116 Term A2 Level</i>			
	<i>117 Term A3 Level</i>			
	<i>120 SFS Output</i>			
	<i>121 AI Opt Ch1 Level</i>			
	<i>122 AI Opt Ch2 Level</i>			
	<i>123 AI Opt Ch3 Level</i>			
	<i>129 Load Weight</i>			
	<i>130 SS Delta Speed</i>			
	<i>150 Hook Height</i>			
	<i>154 Input Pulse Mon</i>			
	<i>163 PG CH1 Freq</i>			
	<i>164 PG CH2 Freq</i>			
	<i>165 PG Output Freq</i>			
	<i>408 Heatsink Temp</i>			
	<i>416 Motor OL1 Level</i>			
	<i>417 Drive OL2 Level</i>			
	<i>601 Mot SEC Current</i>			
	<i>602 Mot EXC Current</i>			
	<i>603 ASR Input</i>			
	<i>604 ASR Output</i>			
	<i>605 Voltage Ref (Vq)</i>			
	<i>606 Voltage Ref (Vd)</i>			
	<i>607 ACR(q) Output</i>			
	<i>608 ACR(d) Output</i>			
	<i>611 Iq Reference</i>			
	<i>612 Id Reference</i>			

Parameter	Display	Function	Range	Default
	618 PG1 CounterValue			
	619 PG2 CounterValue			
	622 Zero Servo Pulse			
	625 ASR Out w/o Fil			
	626 FF Cont Output			
	627 FF Estimate SPD			
H04-02	Terminal FM Gain	Gain multiplier for Terminal FM analog output signal	-999.9–999.9%	100.0
H04-03	Terminal FM Bias	Bias multiplier for Terminal FM analog output signal	-999.9–999.9%	0.0
H04-04	Terminal AM Sel	Assigns one of the above function analog output parameters to Terminal AM	000–630	103
H04-05	Terminal AM Gain	Gain multiplier for Terminal AM analog output signal	-999.9–999.9%	50.0
H04-06	Terminal AM Bias	Bias multiplier for Terminal AM analog output signal	-999.9–999.9%	0.0
H04-07	FM Level Select	Sets the voltage output level of U Monitor data for Terminal FM (Some monitors may not be assigned)	0–2	0
	0 0 to 10 V			
	1 -10 to 10 V			
	2 4 to 20 mA	(Terminal FM only)		
H04-08	AM Level Select	Sets the voltage output level of U Monitor data for Terminal AM (Some monitors may not be assigned)	0–2	0
	0 0 to 10 V			
	1 -10 to 10 V			
	2 4 to 20 mA	Only available for 24 VDC interface card		

Serial Communication Set-up

The IMPULSE®•G+ and VG+ Series 4 uses terminals R⁺/R⁻, S⁺/S⁻ to communicate the MODBUS RTU (RS-485/422) protocol. Cycle power after changing serial format parameters.

Table 5-85: Serial Communication Set-up Parameter Settings

Parameter	Display	Function	Range	Default
H05-01	Serial Comm ADR	Serial communication address	00–FF	1F
H05-02	Serial Baud Rate	Sets the baud rate	0–8	3
	0 1200 bps			
	1 2400 bps			
	2 4800 bps			
	3 9600 bps			
	4 19.2 kbps			
	5 38.4 kbps			
	6 57.6 kbps			
	7 76.8 kbps			
	8 115.2 kbps			
	Cycle power for the setting to take effect.			
H05-03	Serial Com Sel	Sets the parity type	0–2	0
	0 No Parity			
	1 Even Parity			
	2 Odd Parity			
	Cycle power for the setting to take effect.			
H05-04	Serial Fault Set	Determines stopping method when a serial fault occurs.	0–3	0
	0 Decel to Stop			
	1 Coast to Stop			
	2 Fast Stop			
	3 Alarm Only			
H05-05	Serial Flt Dtct	Determines whether Serial Fault Detection is enabled	0, 1	1
	0 Disabled			
	1 Enabled			
H05-06	Transmit WaitTIM	Send waiting time	5–65 ms	5
H05-07	RTS Control Sel	RTS Control enable/disable	0, 1	1
	0 Disabled	RTS is always on		
	1 Enabled	RTS is ON only when sending		
H05-09	CE Detect Time	Sets the time required to detect a communications error. Adjustment may be needed when networking several drives.	0.0–10.0 sec	2.0
H05-10	CommReg 25h Unit	Selects the units for the output voltage monitor value in Modbus Register 0025H.	0, 1	0
	0 0.1V			
	1 1V			

Parameter	Display	Function	Range	Default
H05-11	Enter CommandSel		0, 1	1
	0 <i>Enter Required</i>	Drive requires an Enter command before accepting any changes to parameter settings.		
	1 <i>No EnterRequired</i>	Parameter changes are activated immediately without the Enter command.		
H05-12	Run CommandSel		0, 1	0
	0 <i>FWD Run &REV Run</i>			
	1 <i>Run & FWD/REV</i>			
H05-17	Busy Enter Sel	Allows drive to substitute a RAM enter with a ROM enter when under heavy CPU load.	0, 1	0
	0 <i>No ROM Enter</i>			
	1 <i>RAM Enter</i>			
H05-18	MtrSpd Monitor T	Motor Speed Monitor Filter Time. Allows adding a filter to the Motor Speed monitor (U01-05).	0–100 ms	0

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

Pulse Train Input/Output

Pulse Input and Output provides speed control capabilities via the RP and MP terminals.

Table 5-86: Pulse Input/Output Parameter Settings

Parameter	Display	Function	Range	Default
H06-01	Pulse Input Sel	Selects the function of pulse input terminal RP.	0, 5–7	0
	0 <i>Frequency Ref</i>	Set B03-01 = 4 (pulse input) to enable this input.		
	5 <i>Simple PG</i>	OLV Control with Simple PG feedback (possible only when using motor 1 in Hoist NLB).		
	6 <i>PG Feedback</i>	PG-X3 pulse feedback into the RP terminal coming from a Slave drive.		
	7 <i>RP Feedback</i>	Pulse feedback into the RP terminal coming from a Slave drive.		
H06-02	Pulse In Scale	Number of pulses equal to the maximum output frequency	1000–32000 Hz	1440
H06-03	Pulse Input Gain	Sets the output level when input is 100%	0.0–1000.0%	100.0
H06-04	Pulse Input Bias	Sets the output level when input is zero Hz.	-100.0–100.0%	0.0
H06-05	Pulse In Filter	Sets the input filter time constant	0.00–2.00 sec	0.10
H06-06	Pulse Output Sel	Selects the function of pulse output terminal MP.	0–120	102
	000 <i>Not Used</i>			
	101 <i>Frequency Ref</i>			
	102 <i>Output Freq</i>			
	105 <i>Motor Speed</i>			
	120 <i>SFS Output</i>			
H06-07	Pulse Out Scale	Item output by pulse monitor is selected by corresponding U01-xx value.	0–32000 Hz	1440
H06-08	Pulse Min Freq	Sets the minimum frequency for the pulse train input to be detected. Enabled when H06-01 = 0.	0.1–1000.0 Hz	0.5
H06-09	Pulse Dev Detect	When the Pulse Input terminal RP (H06-01) is programmed for PG Feedback (6) or RP Feedback (7), the pulse input from terminal RP is compared to the pulse output of terminal MP. If the difference is greater than the percentage programmed into H06-09, the drive will fault and display "PULSDEV" on the keypad display.	0.0–25.5%	5.0

Protection Parameters

- L1 Motor Overload
- L2 Power Loss Ride Thru
- L3 Stall Prevention
- L4 Reference Detection
- L5 Test Mode
- L6 Torque Detection
- L8 Hardware Protection
- L9 Automatic Fault Reset
- L9 Fault Latch

Motor Overload

The IMPULSE®•G+ and VG+ Series 4 drive has an electronic overload protection function (OL1) for protecting the motor from overheating. The drive bases the protection on time, output current, and output frequency. The electronic thermal overload function is UL-recognized, so an external thermal overload relay is not required for single motor operation.

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

Setting L01-01 = 1 selects a motor with limited cooling capability below rated (base) speed when running at 100% load. The OL1 function derates the motor any time it is running below base speed.

Setting L01-01 = 2 selects a motor capable of cooling itself at any speed when running at 100% load. The OL1 function derates the motor when it is running at 1/10 of its rated speed or less.

Setting L01-01 = 3 selects a motor capable of cooling itself at any speed when running at 100% load. This includes zero speed. The OL1 function does not derate the motor at any speed.

If the drive is connected to a single motor, the motor overload protection should be enabled (L01-01 = 1, 2, 3) unless another means of preventing motor thermal overload is provided. When the electronic thermal overload function is activated, an OL1 fault occurs, shutting OFF the drive's output, thus preventing additional overheating of the motor. The motor temperature is continuously calculated as long as the drive is powered up.

When operating several motors with one drive, install a thermal relay on each motor and disable the motor overload protection (L01-01 = 0).

Table 5-87: Motor Overload Parameter Settings

Parameter	Display	Function	Range	Default
L01-01	Mtr OL Charact	Sets the type of motor overload protection.	0-3	3
	0 <i>OL1 Disabled</i>			
	1 <i>VT Motor</i>	General purpose motor (standard fan cooled)		
	2 <i>CT Motor</i>	Drive dedicated motor with a speed range of 1:10		
	3 <i>Vector Motor</i>	Speed range of 1:100		
L01-02	MOL Time Const	Time for OL1 fault when motor current is $\geq 150\%$ of the motor rated current.	0.1–5.0 min	1.0

Parameter	Display	Function	Range	Default
L01-03	Mtr OH Alarm Sel	Operation when the motor temperature analog input (H03-02, H03-06, or H03-10 = E) exceeds the OH3 alarm level. (1.17V)	0–3	3
	0 <i>Decel to Stop</i>			
	1 <i>Coast to Stop</i>			
	2 <i>Fast Stop (Alarm)</i>	Decel by B05-08		
	3 <i>Alarm Only</i>	OH3 Flashes		
L01-04	Mtr OH Fault Sel	Operation when the motor temperature analog input (H03-02, H03-06, or H03-10 = E) exceeds the OH4 fault level. (2.34V)	0–2	1
	0 <i>Decel to Stop</i>			
	1 <i>Coast to Stop</i>			
	2 <i>Fast Stop</i>	Decel by B05-08		
L01-05	Mtr Temp Filter	Motor temperature analog input filter time constant (H03-02, H03-06, or H03-10 = E)	0.00–10.00 sec	0.20
L01-13	Mtr OL Mem Sel	Determines whether or not to hold the current value of the electrothermal motor protection (L01-01) when the power supply is interrupted.	0, 1	1
	0 <i>Disabled</i>			
	1 <i>Enabled</i>			

Power Loss Ride Thru

Table 5-88: Power Loss Ride Thru Parameter Settings

Parameter	Display	Function	Range	Default
L02-01	PwrL Selection	Enables/disables the Power Loss Ride thru function	0–2	0
	0 <i>Disabled</i>	Drive trips on (Uv1) fault when power is lost for more than 15 minutes.		
	1 <i>Enable w/ Timer</i>	Recover within the time set in L02-02. Uv1 will be detected if power loss is longer than L02-02.		
	2 <i>Enable if CPU on</i>	Recover as long as CPU has power. Uv1 is not detected.		
L02-02	PwrL Ridethru t	Power Loss Ride thru time	0.0–25.5 sec	**
L02-03	PwrL Baseblock t	Output turn on delay after power resumes	0.1–5.0 sec	**
L02-04	PwrL V/F Ramp t	Voltage recovery time after speed search is complete	0.0–5.0 sec	**
L02-05	PUV Det Level	Under voltage fault detection level	230V: 150–210 VDC 460V: 300–420 VDC 575V: 431–604 VDC	Determined by E01-01

** Initial value is dependent on drive size, which is determined by O02-04 (kVA Selection).

Stall Prevention

Table 5-89: Stall Prevention Parameter Settings

Parameter	Display	Function	Range	Default	Model
L03-01	StallP Accel Sel	Sets how the Stall Prevention will function during acceleration.	0–2	1	G+
	0 <i>Disabled</i>				
	1 <i>General Purpose</i>	Acceleration is paused as long as the current is above the L03-02 setting.			
	2 <i>Intelligent</i>	Accelerate in the shortest possible time without exceeding the L03-02 level.			
L03-02	StallP Accel Lvl	Sets the output current level at which the Stall Prevention during acceleration is activated.	0–150%	*	G+
L03-03	StallPAcc LowLim	Sets Stall Prevention lower limit during acceleration when operating in the constant power range. Set as a percentage of drive rated current.	0–100%	50	G+
L03-05	StallP Run Sel	Sets the control for the stall prevention during run.	0–2	1	G+
	0 <i>Disabled</i>	Drive runs at a set frequency. A heavy load may cause speed loss.			
	1 <i>Decel Time 1</i>	Uses the deceleration time set to C01-02 while Stall Prevention is performed.			
	2 <i>Decel Time 2</i>	Uses the deceleration time set to C01-04 while Stall Prevention is performed.			
L03-06	StallP Run Level	Sets the current level to trigger Stall Prevention during run. Depending on the setting of parameter L03-23, the level is automatically reduced in the constant power range (speed beyond base speed). Enabled when L03-05 is set to 1 or 2.	30–150%	*	G+
L03-11	OV Inhibit Sel	Enables or disables the OV suppression function, which allows the drive to change the output frequency as the load changes to prevent an OV fault.	0, 1	0	G+/VG+
	0 <i>Disabled</i>				
	1 <i>Enabled</i>				
L03-17	DC Bus Reg Level	Sets the desired value for the DC bus voltage during overvoltage suppression and Stall Prevention during deceleration.	230 V: 150–400 VDC 460 V: 300–800 VDC 575 V: 431–1150 VDC	230 V: 375 V 460 V: 750 V 575 V: 930 V	G+/VG+
L03-20	DC Bus P Gain	Sets the proportional gain for KEB Ride-Thru, Stall Prevention, and overvoltage suppression.	0.00–5.00	A01-02	G+/VG+

* Default and Range changed by D10-01.

Parameter	Display	Function	Range	Default	Model
L03-21	Acc/Dec P Gain	Sets the proportional gain used to calculate the deceleration rate during KEB Ride-Thru, OV suppression function, and Stall Prevention during deceleration.	0.10–10.00 sec	A01-02	G+/VG+
L03-23	CHP Stall P Sel	This function reduces the Stall Prevention during run level in the constant power range.	0, 1	0	G+
	0 Lvl set in L3-06	Sets the Stall Prevention level that is used throughout the entire frequency range.			
	1 Autom. Reduction	Automatic Stall Prevention level reduction in the constant output range. The lower limit value is 40% of L03-06.			
L03-24	Mtr Accel Time	Sets the time needed to accelerate the uncoupled motor at rated torque from stop to the maximum frequency.	0.001–10.000 sec	O02-04 or E5-01	G+/VG+

* Default and Range changed by D10-01.

Speed Agree

The IMPULSE®•G+ and VG+ Series 4 utilizes three different functions for detecting output frequency:

Speed Agree 1

- When enabled using MFDO "H02-xx = 2", the contact closes when the output frequency (U01-02) is equal to the frequency reference (U01-01) plus or minus the speed agree detection width (L04-02).
 - $U01-02 = (U01-01 \pm L04-02)$
- When enabled using MFDO "H02-xx = 3", the contact closes when the output frequency (U01-02) is equal to the speed agree detection level (L04-01) plus or minus the speed agree detection width (L04-02).
 - $U01-02 = (L04-01 \pm L04-02)$

Speed Agree 2

- When enabled using MFDO "H02-xx = 13", the contact closes when the output frequency (U01-02) is equal to the frequency reference (U01-01) plus or minus the speed agree detection width (L04-04).
 - $U01-02 = (U01-01 \pm L04-04)$
- When enabled using MFDO "H02-xx = 14", the contact closes when output frequency (U01-02) is equal to the speed agree detection level (L04-03) plus or minus the speed agree detection width (L04-04).
 - $U01-02 = (L04-03 \pm L04-04)$

Frequency Detect

When Frequency Detect is enabled using MFDO "H02-xx = 4":

- Contact closes at start.
- Contact opens when accelerating: $U01-02 \geq (L04-01 + L04-02)$.
- Contact closes again when decelerating: $U01-02 < L04-01$.

When Frequency Detect is enabled using MFDO "H02-xx = 5":

- Contact opens at start.
- Contact closes when accelerating: $U01-02 \geq L04-01$.
- Contact opens again when decelerating: $U01-02 < (L04-01 - L04-02)$.

NOTE: *If L04-01 or L04-03 is set below 5 Hz, the DC Injection Start Frequency (D01-01) and Speed Agree Widths (L04-02/L04-04) may need to be adjusted lower in order for the drive to recognize runs properly.*

Table 5-90: Speed Agree Parameters

Parameter	Display	Function	Range	Default
L04-01	Spd Agree Level	Sets the detection level for the desired speed agree 1 and frequency detection functions. The detection level is effective during both FWD and REV operation.	0.0–150.0 Hz	0.0
L04-02	Spd Agree Width	Sets the detection width for speed agree 1 and frequency detection functions.	0.0–20.0 Hz	2.0
L04-03	Spd Agree Lvl+-	Sets the detection level for the desired speed agree 2 function. The detection level is effective during either FWD or REV operation, depending on the set detection level (positive value for FWD operation, negative value for REV operation).	-150.0–150.0 Hz	0.0
L04-04	Spd Agree Wdth+-	Sets the detection width for the speed agree 2 function.	0.0–20.0 Hz	2.0

Table 5-91: Reference Detection Parameter Settings

Parameter	Display	Function	Range	Default
L04-05	Ref Loss Sel	The drive can detect a loss of an analog frequency reference from input A1, A2, or A3. Frequency reference loss is detected when the frequency reference drops below 10% of the reference or below 5% of the maximum output frequency within 400 ms.	0, 1	0
	0 <i>Stop</i>	Drive stops when the frequency reference is lost.		
	1 <i>Run@L4-06PrevRef</i>	Drive runs at a reduced speed when the frequency reference is lost.		
L04-06	Fref at Floss	Sets the percentage of the frequency reference that the drive should run with when the frequency reference is lost.	0.0–100.0%	80
L04-07	Freq Detect Sel	Determines when frequency detection is active using parameters L04-01 through L04-04.	0, 1	0
	0 <i>No Detection @BB</i>	No detection during baseblock.		
	1 <i>Always Detected</i>	Detection always enabled.		

Test Mode

Test Mode is a troubleshooting aid that is intended for troubleshooting Flux Vector Control Method problems in the field. The feature cannot be left on indefinitely as it will generate a fault after being on for a total accumulated time of 10 minutes. At this time, the fault must be reset or power must be cycled.

When enabled, the Control Method in A01-02 is temporarily overridden to V/f. All other functions for the new control method are not restricted. Certain programming may need to be done to clear up any OPE conditions that may occur as a result of the change in control method during this mode. It is up to the user to determine if a special function may cause an unsafe condition during testing. Since this feature will be used mainly for No-Load Brake type hoists, many of the inherent safety checks will become disabled. It may be desirable to disable functions such as Ultra-Lift, but desirable to leave Limit Switch functions enabled. The user will need to determine what functions are being used. If unsure, it is best to ensure that the function is disabled (either by programming or MFDI in OFF state) before running the drive/motor in this mode.

Table 5-92: Test Mode Parameter Settings

Parameter	Display	Function	Range	Default
L05-01	Test Mode	Test Mode Enable. Starts a 10 minute timer after which the drive will not function until Test Mode is disabled. If power is cycled, Test Mode will become disabled. When test mode is enabled, Test Mode settings will be used for operation. Refer to the E3 group.	0, 1	0
		0 <i>Disabled</i>		
		1 <i>Enabled</i>		

Torque Detection

The overtorque detection circuit activates when the motor load causes the motor current to exceed the overtorque detection level (L06-02). When an overtorque condition is detected, alarm signals can be sent to a multi-function output. To output an overtorque detection signal, select torque detection 1 at either of the multi-function digital outputs (H02-0x = "B" or "18").

Table 5-93: Torque Detection Parameter Settings

Parameter	Display	Function	Range	Default
L06-01	Torque Det 1 Sel	Activates overtorque/undertorque detection and selects whether detection generates an alarm or a fault	0-8	0
	0	Disabled		
	1	OT@SpdAgree-Alm		
	2	OT At RUN - Alm		
	3	OT@SpdAgree-Flt		
	4	OT At RUN - Flt		
	5	UT@SpdAgree-Alm		
	6	UT At RUN - Alm		
	7	UT@SpdAgree-Flt		
	8	UT At RUN - Flt		

Table 5-94: Torque Detection Setting Descriptions

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

- NOTE:**
- To detect overtorque/undertorque during acceleration or deceleration, set to "2" or "4" / "6" or "8".
 - To continue operation after overtorque/undertorque detection, set to "1" or "2" / "5" or "6" During detection, the digital operator displays an "OT1/UT1" alarm (blinking).
 - To stop the inverter after an overtorque/undertorque detection fault, set to "3" or "4" / "7" or "8". During detection, the digital operator displays an "OT1/UT1" fault.

Table 5-95: Torque Detection Parameter Settings - continued

Parameter	Display	Function	Range	Default
L06-02	Torq Det 1 Lvl	Sets the overtorque detection as a percentage of inverter rated current, during V/f control, and motor rated torque during vector control.	0–300%	150
L06-03	Torq Det 1 Time	The overtorque detection delay time inserts a delay, between the time motor current (or torque) exceeds the overtorque level (L06-02) and when the overtorque detection function is enabled. The digital operator then displays “OT1”.	0.0–10.0 sec	0.1
L06-04	Torq Det 2 Sel	Activates overtorque/undertorque detection, and selects whether detection generates an alarm or a fault.	0–8	0
	0	<i>Disabled</i>		
	1	<i>OT@SpdAgree-Alm</i>		
	2	<i>OT At RUN - Alm</i>		
	3	<i>OT@SpdAgree-Flt</i>		
	4	<i>OT At RUN - Flt</i>		
	5	<i>UT@SpdAgree-Alm</i>		
	6	<i>UT At RUN - Alm</i>		
	7	<i>UT@SpdAgree-Flt</i>		
	8	<i>UT At RUN - Flt</i>		

Table 5-96: Torque Detection 2 Select Descriptions

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

Overtorque detection 2 functions the same as overtorque/undertorque detection 1 (L06-01), except that “OT2/UT2” is displayed on the digital operator instead. This function is used when two types of detection are output to the multi-function output terminals.

Table 5-97: Torque Detection Parameter Settings - continued

Parameter	Display	Function	Range	Default
L06-05	Torq Det 2 Lvl	Torque Detection 2 Level	0–300%	150
L06-06	Torq Det 2 Time	Torque Detection 2 Time	0.0–10.0 sec	0.1
L06-08	Mech Fatigue Sel	This function can detect an overtorque or undertorque in a certain speed range as a result of machine fatigue. It is triggered by a specified operation time and uses the oL1 detection settings (L06-01 and L06-03).	0–8	0
	0	Disabled		
	1	Alm Spd>L06-09		
	2	Alm [Spd]>L06-09		
	3	Flt Spd>L06-09		
	4	Flt [Spd]>L06-09		
	5	Alm Spd<L06-09		
	6	Alm [Spd]<L06-09		
	7	Flt Spd<L06-09		
	8	Flt [Spd]<L06-09		

Table 5-98: Mechanical Fatigue Selection Description

Setting	Description
0	Mechanical Weakening Detection disabled (factory default).
1	Continue running (alarm only). Detected when the speed (signed) is greater than L06-09.
2	Continue running (alarm only). Detected when the speed (not signed) is greater than L06-09.
3	Interrupt drive output (fault). Detected when the speed (signed) is greater than L06-09.
4	Interrupt drive output (fault). Detected when the speed (not signed) is greater than L06-09.
5	Continue running (alarm only). Detected when the speed (signed) is less than L06-09.
6	Continue running (alarm only). Detected when the speed (not signed) is less than L06-09.
7	Interrupt drive output (fault). Detected when the speed (signed) is less than L06-09.
8	Interrupt drive output (fault). Detected when the speed (not signed) is less than L06-09.

Table 5-99: Torque Detection Parameter Settings - continued

Parameter	Display	Function	Range	Default
L06-09	MechFat Det Spd	Sets the speed that triggers Mechanical Weakening Detection. When L06-08 is set for an unsigned value, the absolute value is used if the setting is negative.	-110.0–110.0%	110.0
L06-10	MechFat Det Time	Sets the time mechanical weakening has to be detected before an alarm or fault is triggered.	0.0–10.0 sec	0.1
L06-11	MechFat Det Hour	Sets the operation time (U01-04) required before Mechanical Weakening Detection is active.	0–65535	0

Hardware Protection

The IMPULSE®•G+ and VG+ Series 4 comes equipped with a number of built-in functions designed to protect the inverter and its components from damage.

Table 5-100: Hardware Protection Parameter Settings

Parameter	Display	Function	Range	Default
L08-02	OH Pre-Alarm Lvl	Sets the heatsink temperature level for protection against overheat (OH). <i>NOTE: The inverter measures heatsink temperature by an negative temperature coefficient thermistor.</i>	50–150°C	*
L08-03	OH Pre-Alarm Sel	Selects the stopping method when heatsink overheat is detected.	0–5	3
	0 <i>Decel to Stop</i>	Decel to stop using B05-02		
	1 <i>Coast to Stop</i>	Immediate stop		
	2 <i>Fast Stop</i>	Decel to stop using B05-08		
	3 <i>Use B3-03 Method</i>	Uses programmed B03-03 Method		
	4 <i>Alarm Only</i>	Operation continues and “OH Heatsink Overtemp” is displayed on keypad		
	5 <i>Run@L8-19 Rate</i>	Continue operation at reduced speed as set in L08-19.		
L08-05	Ph Loss In Sel	Input phase loss detection	0, 1	1
	0 <i>Disabled</i>			
	1 <i>Enabled</i>			
L08-07	Ph Loss Out Sel	Output phase loss detection	0–2	1
	0 <i>Disabled</i>			
	1 <i>1PH Loss Det</i>			
	2 <i>2/3PH Loss Det</i>			
L08-09	Ground Fault Sel	Enables/disables ground fault detection	0, 1	1
	0 <i>Disabled</i>			
	1 <i>Enabled</i>			
L08-10	Fan On/Off Sel	Cooling fan operation select	0, 1	0
	0 <i>Dur Run (OffDly)</i>			
	1 <i>Always On</i>			
L08-11	Fan Delay Time	When L08-10 = 0, fan will operate L08-11 seconds after Run Command is removed	0–300 sec	60
L08-12	Ambient Temp	Adjusts Overload (OL2) Protection for high ambients	-10–50°C	40
L08-13	UV3 Detect	Enabled Soft Charge Bypass Circuit Fault	0, 1	1
	0 <i>Disabled</i>			
	1 <i>Enabled</i>			
L08-15	OL2 Sel @ L-Spd	Enables/disables OL when output frequency \leq 6 Hz	0, 1	0**
	0 <i>Disabled</i>			
	1 <i>Enabled</i>			

* Initial value is dependent on drive size, which is determined by O02-04 (kVA selection)

** Initial value is dependent on carrier. 2kHz = 0, else 1

Parameter	Display	Function	Range	Default
L08-18	Soft CLA Sel 0 Disabled 1 Enabled	Enables/disables the software current limit function.	0, 1	0
L08-19	Fc Red dur OHAlm	Specifies the frequency reference reduction gain at overheat pre-alarm when L08-03 = 4.	0.1–0.9 Hz	0.8
L08-32	MC,FAN Fault Sel 0 Decel to Stop 1 Coast to Stop 2 Fast Stop 3 Use B3-03 Method 4 Alarm only	MC, FAN configure the operation of power if it detects a warning alarm	0–4	1
L08-35	Installation Sel 0: IP20/OpenChassis 1: Side-by-Side 2: IP20/Nema Type 1 3: Finless/Fin Ext	Drive Installation Method	0–3	2*
L08-38	Fc Reduct dur OL 0 Disabled 1 Active below 6Hz 2 Active @ any Spd	Temporarily reduces the carrier frequency when the drive exceeds a certain level. This temporarily increases the overload capability (OL2 detection) allowing the drive to run through transient load peaks without tripping. Enabled below 6 Hz Carrier Frequency is reduced when: < 6Hz when current > 100% of Drive Rated Current, returns to normal carrier frequency or when output current falls below 88% of drive rated current or frequency > 7Hz Enabled for the entire speed range < 6Hz when current > 100% of Drive Rated Current > 7Hz when current > 112% of Drive Rated Current	0–2	2
L08-40	FC Reduct Time	Sets the time that the drive continues running with reduced carrier frequency after the carrier reduction condition is gone. Setting L08-40 to 0.00 disables the carrier frequency reduction time.	0.00–2.00 sec	A01-02
L08-41	High Cur Alm Sel 0 Disabled 1 Enabled	Triggers a high current alarm (HCA) when the output current rises exceeds 150% of the drive rated current.	0, 1	0

* Initial value is dependent on drive size, which is determined by O02-04 (kVA selection)

** Initial value is dependent on carrier. 2kHz = 0, else 1

Parameter	Display	Function	Range	Default
L08-55	DB Tr protection	Internal Braking Transistor Protection (DB Tr protection)	0, 1	0*
	0 Disabled	Disable braking transistor protection when not using the internal braking transistor.		
	1 Enabled	Enable when connecting a braking resistor or a braking resistor unit to the drive's built-in braking transistor.		

* Initial value is dependent on drive size, which is determined by O02-04 (kVA selection)

** Initial value is dependent on carrier. 2kHz = 0, else 1

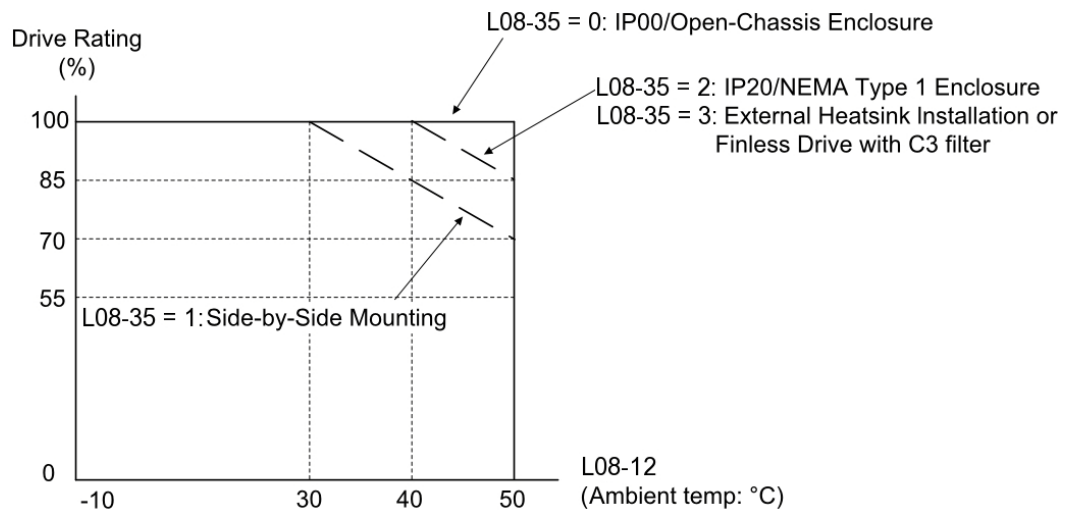


Figure 5-25: Ambient Temperature and Installation Method Derating

Automatic Fault Reset

When a fault occurs during operation, the IMPULSE®•G+ and VG+ Series 4 can be programmed for an auto reset operation to automatically reset the fault.

Table 5-101: Automatic Reset Parameter Settings

Parameter	Display	Function	Range	Default
L09-01	Reset Select 0 Disabled 1 Enabled	Activates the fault auto-reset function.	0, 1	1
L09-02	Reset Attempts	Sets the number of reset attempts. Reset attempt counter is returned to zero if no faults occur within a ten minute period.	0–10	3
L09-03	Reset Time	Sets the reset starting time.	0.5–600.0 sec	0.5
L09-04*	Reset Flt Sel 1	Reset Fault Select 1.	0–FFFF	4001
L09-05*	Reset Flt Sel 2	Reset Fault Select 2.	0–FFFF	E000
L09-06	Flt Contact Sel 0 Flt Outp Disabld 1 Flt Outp Enabled	Fault contact operation during reset attempts	0, 1	0

* To program constant L09-04 and L09-05, refer to the example on the following page and follow steps 1 through 4:

1. Assign 1 to each fault code to enable the auto reset.
2. Assign 0 to each fault code to disable the auto reset.
3. Convert all Digits (1 to 4) from binary to hex.
4. Program L09-04 and L09-05 by entering the hex number obtained from step 3.

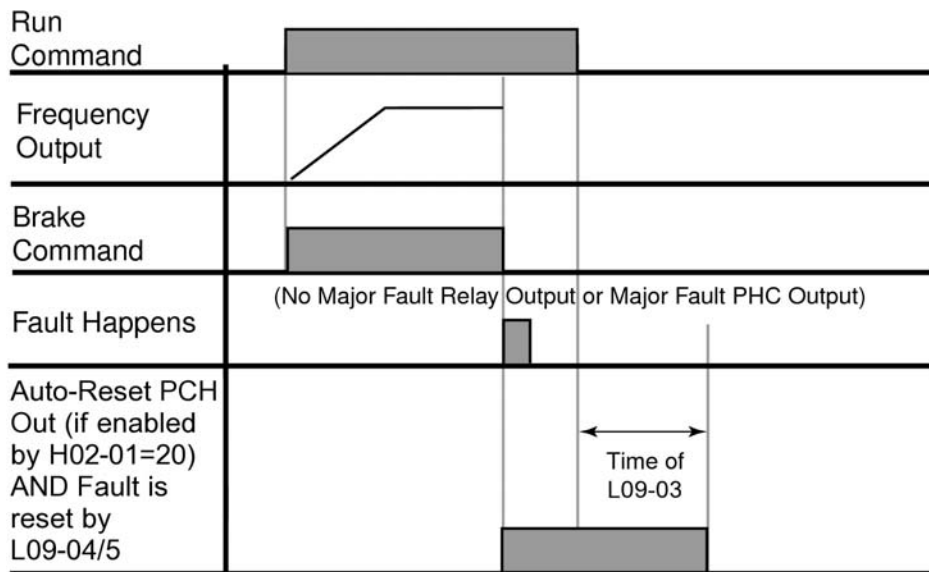


Figure 5-26: Automatic Fault Reset

Example:

Enable auto-reset for UV1 and CE faults.

Table 5-102: Auto-Reset Programming

	Digit 4	Digit 3	Digit 2	Digit 1
HEX	0	0	0	1
Binary	0 0 0 0	0 0 0 0	0 0 0 0	0 0 0 1
L09-04	E A - - F S - - O 1 - -	L P U U F F T T 1 2	O S O G H C V F 1	O U U U C V V V 3 2 1
HEX	0	0	8	0
Binary	0 0 0 0	0 0 0 0	1 0 0 0	0 0 0 0
L09-05	B B B B E E E E 1 2 3 4	O O O O L L T T 1 2 1 2	C - E E E - F F - 8 7	E E E E F F F F 6 5 4 3

Table 5-103: Auto-Reset Programming Summary

L09-04	Binary	HEX	L09-05	Binary	Hex
Digit 4	0000	0	Digit 4	0000	0
Digit 3	0000	0	Digit 3	0000	0
Digit 2	0000	0	Digit 2	1000	8
Digit 1	0001	1	Digit 1	0000	0

Table 5-104: Binary to Hexadecimal Conversion

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

Fault Latch Selection

The Fault Latch function allows for specific faults to become “latched” after the automatic fault reset attempts (L09-02) has maxed out. The Reset key on the keypad will be blocked from clearing the fault, and the fault can only be cleared by any of the methods explained below. In the case of a power loss, the fault will remain latched when power is restored.

A latched fault can be cleared in three ways:

1. The recommended method is to program an MFDI (H01-xx) to 48 (Flt Latch Reset). The digital input must be toggled (ON and then OFF) in order for the fault to clear. Since this feature is intended for safety, a key switch is the recommended form of hardware. This will prevent the recurring fault from being continuously cleared and ignored unless the key is present and toggled.
2. A second method for clearing the fault is using the Monitor tool within IMPULSE®•Link.
3. The F1 or F2 keypad key can be programmed to 48 (Flt Latch Reset). When a fault is latched, simply pressing the F1 or F2 key twice will reset the fault.

NOTE: An MFDI and F1/F2 keys are allowed to be programmed after a fault is latched.

Table 5-105: Fault Latch Selection Parameter Settings

Parameter	Display	Function	Range	Default
L09-07*	Flt Latch Sel 1	Fault Latch Select 1	0000–FFFF	0000
L09-08*	Flt Latch Sel 2	Fault Latch Select 2	0000–FFFF	0000

* To program parameters L09-07 and L09-08, refer to the example on the previous page. The same concept for the Automatic Fault Reset also applies here.

Table 5-106: Fault Latch Programming

	Digit 4				Digit 3				Digit 2				Digit 1			
HEX	0				0				0				0			
Binary	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
L09-07	-	-	-	P	P	U	D	S	B	B	B	B	B	B	B	B
	-	-	-	G	G	L	E	N	E	E	E	E	E	E	E	E
	-	-	-	O	O	3	V	A	8	7	6	5	4	3	2	1
				1				P								
				H				H								
HEX	0				0				0				0			
Binary	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0	0
L09-08	B	B	B	B	E	E	E	E	O	O	U	L	O	O	O	O
	E	E	E	E	F	F	F	F	S	V	V	C	L	L	T	T
	7	6	5	4	5	6	7	8			1		1	2	1	2
	2	2	2	2												

Operator Parameters

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

Monitor Selection

The top level in the operation mode allows the viewing of four monitor variables. They are Fref, Fout, Iout, and User-Selected monitor. This user-selected monitor can be selected from the following table. See the Monitor Parameters table on page 5-131 for available monitors by control method.

Table 5-107: Monitor Selection Parameter Settings

Parameter	Display	Function	Range	Default
O01-01	User Monitor Sel	Selects the content of the last monitor that is shown when scrolling through Drive Mode display. Enter the last three digits of the monitor parameter number to be displayed: U0X-xx. Default: 106 (Monitor: Output Voltage Reference U01-06)	104–813	106
	<i>104 Control Method</i>			
	<i>105 Motor Speed</i>			
	<i>106 Output Voltage</i>			
	<i>107 DC Bus Voltage</i>			
	<i>108 Output HP</i>			
	<i>109 Torque Reference</i>			
	<i>110 Input Term Sts</i>			
	<i>111 Output Term Sts</i>			
	<i>112 Int Ctl Sts 1</i>			
	<i>114 CPU 1 SW Number</i>			
	<i>115 Term A1 Level</i>			
	<i>116 Term A2 Level</i>			
	<i>117 Term A3 Level</i>			
	<i>120 SFS Output</i>			
	<i>121 AI Opt Ch1 Level</i>			
	<i>122 AI Opt Ch2 Level</i>			
	<i>123 AI Opt Ch3 Level</i>			
	<i>125 DI Opt Status</i>			
	<i>128 CPU 2 SW Number</i>			
	<i>134 OPE Error Code</i>			
	<i>139 Transmit Error</i>			
	<i>144 ASR Out w/o Fil</i>			
	<i>150 Hook Height</i>			
	<i>151 Motor Revolution</i>			
	<i>152 MaintenanceTimer</i>			
	<i>153 Index Count</i>			
	<i>154 Term RP Inp Freq</i>			

Parameter	Display	Function	Range	Default
	160	PG CH1 Count		
	161	PG CH2 Count		
	321	RUN Cmd Counter		
	401	Drv Elapsed Time		
	403	Fan Elapsed Time		
	404	Fan Life Mon		
	405	Cap Life Mon		
	406	ChgCirc Life Mon		
	407	IGBT Life Mon		
	408	Heatsink Temp		
	410	kWh Lower 4 dig		
	411	kWh Upper 5 dig		
	412	CPU Occup Rate		
	413	Current PeakHold		
	414	Freq@ I PeakHold		
	416	Motor OL1 Level		
	417	Drive OL2 Level		
	418	Reference Source		
	419	MEMOBUS Freq Ref		
	420	Option Freq Ref		
	421	Run Cmd Source		
	422	MEMOBUS Ref Reg		
	423	Option Ref Reg		
	601	Mot SEC Current		
	602	Mot EXC Current		
	603	ASR Input		
	604	ASR Output		
	605	Voltage Ref (Vq)		
	606	Voltage Ref (Vd)		
	607	ACR(q) Output		
	608	ACR(d) Output		
	611	Iq Reference		
	612	Id Reference		
	618	PG1 CounterValue		
	619	PG2 CounterValue		
	622	Zero Servo Pulse		
	626	FF Cont Output		

Parameter	Display	Function	Range	Default
O01-02	Power-On Monitor	Selects the monitor to be displayed on the digital operator immediately after the power supply is turned on.	1–5	3
	1 <i>Frequency Ref</i>	Frequency reference (U01-01)		
	2 <i>FWD/REV</i>	Forward/Reverse		
	3 <i>Output Freq</i>	Output frequency (U01-02)		
	4 <i>Output Current</i>	Output current (U01-03)		
	5 <i>User Monitor</i>	User-selected monitor (set by O01-01)		
O01-03	Display Scaling	Sets the units to display the frequency reference and output frequency.	0–3	0
	0 <i>0.01 Hz</i>			
	1 <i>0.01 %</i>	(100% = E01-04)		
	2 <i>RPM</i>	Calculated using the number of motor poles setting in E02-04, E4-04, or E5-04		
	3 <i>User Units</i>	User-selected units (set by O01-10 and O01-11)		
O01-04	Display Units	Setting units for E01-04, E01-06, and E01-09.	0, 1	A01-02
	0 <i>Hertz</i>			
	1 <i>RPM</i>			
O01-05	LCD Contrast	Adjusts brightness of the keypad display	0–5	3
O01-10	UserDisp Scaling	Determines the display value that is equal to the maximum output frequency. Default setting is dependent on parameter O01-03, Digital Operator Display Selection. When O01-03 = 0; O01-10=6000; O01-11 = 2 When O01-03 = 1; O01-10=10000; O01-11 = 2 When O01-03 = 2; O01-10=1800 (4 pole motor); O01-11 = 0 When O01-03 = 3; O01-10=10000; O01-11 = 2 This setting defines the displayed values when O01-03 is set to 3.	1–60000	6000
O01-11	UserDisp Dec Sel	Determines the position of the decimal position.	0–3	2
	0 <i>No Dec (XXXXX)</i>	When O01-03 = 0, O01-11 = 2		
	1 <i>1 Dec (XXXX.X)</i>	When O01-03 = 1, O01-11 = 2		
	2 <i>2 Dec (XXX.XX)</i>	When O01-03 = 2, O01-11 = 0		
	3 <i>3 Dec (XX.XXX)</i>	When O01-03 = 3, O01-11 = 2		

Keypad Key Selection

Table 5-108: Keypad Key Selection Parameter Settings

Parameter	Display	Function	Range	Default
O02-01	LO/RE Key	Pressing the LO/RE Key once displays: "Call Magnetek at 1-866-624-7378".	0, 1	0
	0 <i>Mode/Service</i>	Control Method (A01-02) Pressing the LO/RE Key a second time: Motion (A01-03) Speed Reference (A01-04) Pressing the LO/RE Key a third time: F1 and F2 Keys (H01-09 and H01-10)		
	1 <i>Local/Remote</i>	Local/remote key is enabled depressing the LO/RE key switches operation command between the digital operator and the settings of B03-01 and B03-02.		
O02-02	Oper STOP Key	Selects the action when the digital stop key is pressed.	0–2	0
	0 <i>Coast to Stop</i>	(Immediate stop)		
	1 <i>Decel to Stop</i>			
	2 <i>Use B3-03 Method</i>			
O02-03	User Default Sel		0–2	0
	0 <i>No Change</i>			
	1 <i>Set Defaults</i>	Memorizes up to 150 modified parameters. User defaults can be restored by setting A1-05= "1110".		
	2 <i>Clear All</i>	Clear user defaults.		
O02-04	Inverter Model #	Enter the drive model. Setting required only if installing a new control board.	00–FF	*
	62 2_0004	2003-G+/VG+S4		
	63 2_0006	2005-G+/VG+S4		
	64 2_0008	2007-G+/VG+S4		
	65 2_0010	2008-G+/VG+S4		
	66 2_0012	2011-G+/VG+S4		
	67 2_0018	2014-G+/VG+S4		
	68 2_0021	2017-G+/VG+S4		
	6A 2_0030	2025-G+/VG+S4		
	6B 2_0040	2033-G+/VG+S4		
	6D 2_0056	2047-G+/VG+S4		
	6E 2_0069	2060-G+/VG+S4		
	6F 2_0081	2075-G+/VG+S4		
	70 2_0110	2085-G+/VG+S4		
	72 2_0138	2115-G+/VG+S4		

Parameter	Display	Function	Range	Default
	73	2_0169	2145-G+VG+S4	
	74	2_0211	2180-G+VG+S4	
	75	2_0250	2215-G+VG+S4	
	76	2_0312	2283-G+VG+S4	
	77	2_0360	2346-G+VG+S4	
	78	2_0415	2415-G+VG+S4	
	92	4_0002	4001-G+VG+S4	
	93	4_0004	4003-G+VG+S4	
	94	4_0005	4004-G+VG+S4	
	95	4_0007	4005-G+VG+S4	
	96	4_0009	4007-G+VG+S4	
	97	4_0011	4009-G+VG+S4	
	99	4_0018	4014-G+VG+S4	
	9A	4_0023	4018-G+VG+S4	
	9C	4_0031	4024-G+VG+S4	
	9D	4_0038	4031-G+VG+S4	
	9E	4_0044	4039-G+VG+S4	
	9F	4_0058	4045-G+VG+S4	
	A1	4_0072	4060-G+VG+S4	
	A2	4_0088	4075-G+VG+S4	
	A3	4_0103	4091-G+VG+S4	
	A4	4_0139	4112-G+VG+S4	
	A5	4_0165	4150-G+VG+S4	
	A6	4_0208	4180-G+VG+S4	
	A7	4_0250	4216-G+VG+S4	
	A8	4_0296	4260-G+VG+S4	
	A9	4_0362	4304-G+VG+S4	
	AA	4_0414	4370-G+VG+S4	
	AC	4_0515	4450-G+VG+S4	
	AE	4_0675	4605-G+VG+S4	
	B0	4_0930	4810-G+VG+S4	
	B2	4_1090	41090-G+VG+S4	
	C3	5_0003	5001-G+VG+S4	
	C4	5_0004	5003-G+VG+S4	
	C5	5_0006	5004-G+VG+S4	
	C7	5_0009	5006-G+VG+S4	
	C9	5_0011	5009-G+VG+S4	
	CA	5_0017	5012-G+VG+S4	
	CC	5_0022	5017-G+VG+S4	
	CD	5_0027	5022-G+VG+S4	
	CE	5_0032	5027-G+VG+S4	
	CF	5_0041	5032-G+VG+S4	
	D1	5_0052	5041-G+VG+S4	
	D2	5_0062	5052-G+VG+S4	
	D3	5_0077	5062-G+VG+S4	
	D4	5_0099	5077-G+VG+S4	

Parameter	Display	Function	Range	Default
	D5 5_0125	5099-G+/VG+S4		
	D6 5_0145	5130-G+/VG+S4		
	D7 5_0192	5172-G+/VG+S4		
	D9 5_0242	5200-G+/VG+S4		
O02-05	Operator M.O.P.	Selects whether the ENTER key is used when the frequency reference is set by the digital operator. The digital operator can simulate a motor operated potentiometer (M.O.P.) by setting this parameter.	0, 1	0
	0 Disabled	ENTER Key Required		
	1 Enabled	ENTER Key Not Required		
		<i>NOTE: This feature cannot be used in conjunction with infinitely variable speed control.</i>		
O02-06	Oper Detection	If the digital operator is disconnected from the inverter. This parameter selects whether the inverter detects this condition. The operator is only detected when the inverter is being commanded locally.	0, 1	1
	0 Disabled			
	1 Enabled			
O02-07	FWD/REV Sel@PwrUp	Determines the direction of the motor at power up when operation is assigned to the digital operator. This parameter requires that drive operation be assigned to the digital operator.	0, 1	0
	0 Forward			
	1 Reverse			
O02-11	Test Mode Sel	Disables/enables the one-time slip measurement after a non-rotational auto-tune. Changing this parameter is normally not required.	0, 1	1
	0 Disabled			
	1 Enabled			
O02-15	Legacy RDSI	Legacy support for Hetronic RDSI.	0, 1	0
	0 Disabled			
	1 Enabled			
O02-19	ParameterSet Sel	Turns off writing to EEPROM during a UV fault.	0, 1	0
	0 Disabled			
	1 Enabled			

Maintenance History

Table 5-109: Clear History Parameter Settings

Parameter	Display	Function	Range	Default
O03-01	Elapsed Time Set	Sets the value for the cumulative operation time of the drive in units of 10 hours. Cumulative time can be viewed using monitor Cumulative Operation Time (U04-01). A setting of 30 = 300 hours	0–9999 x 10 hr	0
O03-02	Elapsed Time Run	Selects how the cumulative timer will keep track of the total operation time.	0, 1	1
	0 <i>Power-On Time</i>	Logs power-on time		
	1 <i>Running Time</i>	Logs operation time when the drive output is active (output operation time).		
O03-03	Fan ON Time Set	Sets the value of the Fan Operation Time monitor (U04-03) in units of 10 hours. A setting of 30 = 300 hours	0–9999 x 10 hr	0
O03-05	BusCap Maint Set	Sets the value of the Maintenance Monitor for the capacitors. See U04-05 to check when the capacitors may need to be replaced.	0–150%	0
O03-09	IGBT Maint Set	Sets the value of the Maintenance Monitor for the IGBTs. See U04-07 for IGBT replacement times.	0–150%	0
O03-11	Fault Data Init	Determines if Fault Trace (U02-xx) and Fault History (U03-xx) parameters will be cleared when the drive is initialized.	0, 1	0
	0 <i>No Reset</i>	Not cleared		
	1 <i>Reset</i>	Cleared (U02-xx, U03-xx, and U04-01 set to 0, and O03-01 = 0 after U2 and U3 are initialized)		
O03-12	kWh Monitor Init	Determines if the monitor data (U04-10 and U04-11) are reset when the drive is initialized.	0, 1	0
	0 <i>No Reset</i>	U04-10 and U04-11 monitor data is not reset when the drive is initialized (A01-03).		
	1 <i>Reset</i>	U04-10 and U04-11 monitor data is reset when the drive is initialized (A01-03).		
O03-14	Count Hist Clear	Determines which counter will be cleared. After counters are cleared, initial value (O03-14) is set to 0.	0–3	0
	0 <i>No Reset</i>	Number of Run commands counter is not reset when the drive is initialized (A01-03).		
	1 <i>Reset Runs</i>	Number of Run commands counter is reset (U03-21 and U03-22).		
	2 <i>OL/LC Count Clr</i>	Clears OL/LC Counters (U03-23).		
	3 <i>Both Count Clr</i>	Clears Runs and OL/LC Counters.		

Copy Function

Table 5-110: Copy Function Parameter Settings

Parameter	Display	Function	Range	Default
O04-01	Copy Function Sel	Copy parameters to/from keypad	0–3	0
	0 COPY SELECT			
	1 INV → OP READ	Drive → Keypad		
	2 OP → INV WRITE	Keypad → Drive		
	3 OP ↔ INV VERIFY	Keypad ↔ Drive		
O04-02	Read Allowable	Enables/disables copy function	0, 1	1
	0 Disabled			
	1 Enabled			
O04-07	ChrgCircMaintSet	Sets the value of the Maintenance Monitor for the soft charge bypass relay. See U04-06 to check when the bypass relay may need to be replaced.	0–150%	0

The digital operator has parameter COPY capabilities via built-in non-volatile memory. The digital operator can READ all of the parameters in the Drive and store them for later, and then WRITE back to the Drive or into a Drive with the same product code and software number. In order to read the parameter values and store them into the digital operator, select O04-02 = 1 (Enabled). If you attempt to READ the data, which overwrites any previously stored data, without first setting O04-02 = “1: Enabled,” you will get the following error:

RDER
READ DATA ERROR

After setting O04-02 = 1 (Enabled), it is possible to store parameter values in the digital operator by setting O04-01 = 1 (INV → OP READ). A successful READ of the parameter values will display:

END
READ COMPLETE

An error may occur while saving the parameter values to the digital operator's memory. If an error is displayed, press any key to cancel the error display and return to parameter O04-01. Error displays and their meanings are covered in Chapter 6: Troubleshooting of Copy function Related Faults. To COPY the parameter values into a Drive, set O04-01 = 2 (OP → INV WRITE). During the writing of the parameter values into the Drive, the digital operator will display:

COPY
OP → INV COPYING

A successful COPY of the parameter values will display:

END
COPY COMPLETE

An error may occur while writing the parameter values to the Drive. If an error is displayed, press any key to cancel the error display and return to parameter O04-01. Error displays and their meanings are covered in Chapter 6: Troubleshooting of Copy Function Related Faults.

It is possible to compare the parameter values stored in the digital operator with the parameter values currently in the Drive by using the VERIFY function. This VERIFY function should not be confused with the "-VERIFY-" that is displayed on the digital operator when viewing the "Modified Constants" menu. To VERIFY the parameter values in the Drive as compared with those stored in the digital operator, set O04-01 = 3 (OP ↔ INV VERIFY). During the comparing of the parameter values into the drive the digital operator will display:

VRFY
DATA VERIFYING

A successful VERIFY of the parameter values will display:

END
VERIFY COMPLETE

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



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

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

Model Number (e.g. 5001-G+S4)

Software Number (e.g. 14700 also known as FLASH ID)

Control Method (e.g. A01-02)

Motion (e.g. A01-03)

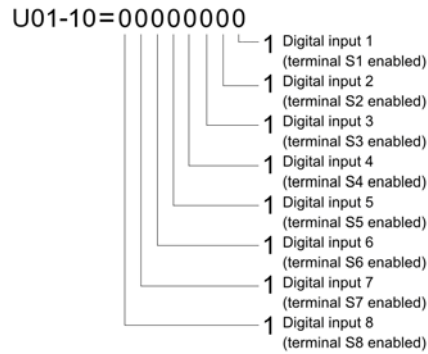
NOTE: *Reference the Copy Function Related Faults section in Chapter 6 for additional copy function troubleshooting.*

Monitor Parameters

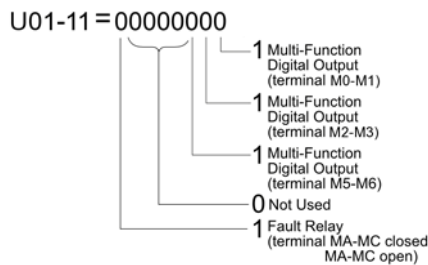
- U1 Monitor
- U2 Fault Trace
- U3 Fault History
- U4 Maintenance
- U6 Control Monitor

Table 5-111: Monitor Parameters

Parameter	Display	Function	Units
U01-01	Frequency Ref	Frequency Reference	Hz
U01-02	Output Freq	Inverter Output Frequency	Hz
U01-03	Output Current	Inverter Output Current	A
U01-04	Control Method	Displays the value of A01-02	--
U01-05	Motor Speed	Motor Speed	Hz
U01-06	Output Voltage	Inverter Output Voltage (Reference)	VAC
U01-07	DC Bus Voltage	DC Bus Voltage (Measured)	VDC
U01-08	Output HP	Inverter Output Power (Calculated)	HP
U01-09	Torque Reference	Torque Reference (Internal)	%
U01-10	Input Term Sts	Input Terminal Status	--

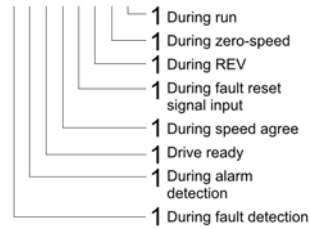


U01-11	Output Term Sts	Output Terminal Status	--
--------	-----------------	------------------------	----



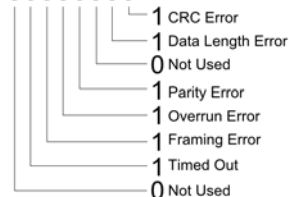
Parameter	Display	Function	Units
U01-12	Int Ctl Sts 1	Operation Status	--

U01-12 = 00000000



U01-14	CPU 1 SW Number	Flash ROM software ID number	--
U01-15	Term A1 Level	External Terminal Input level	%
U01-16	Term A2 Level	External Terminal Input level	%
U01-17	Term A3 Level	External Terminal Input level	%
U01-20	SFS Output	Primary freq. after the SFS	Hz
U01-21	AI Opt Ch1 Level	Displays the input voltage to terminal V1 on analog input card AI-A3.	%
U01-22	AI Opt Ch2 Level	Displays the input voltage to terminal V2 on analog input card AI-A3.	%
U01-23	AI Opt Ch3 Level	Displays the input voltage to terminal V3 on analog input card AI-A3.	%
U01-24	Opt Out	Displays the output from the option card S4IO - 8 bits.	--
U01-25	Opt In Low	Displays the reference value input from the DI option card (DI-A3, S4I, or S4IO) lower 8 bits.	--
U01-26	Opt In High	Displays the reference value input from the DI option card (DI-A3, S4I, or S4IO) upper 8 bits.	--
U01-28	CPU 2 SW Number	ROM ID	--
U01-29	Load Weight	Monitors load weight when C10-01 is enabled	C10-06
U01-30	SS Delta Speed	Snap Shaft Delta Speed between Ch1 and Ch2 after gear ratio	Hz
U01-34	OPE Error Code	Displays the parameter number that caused the OPExx or Err (EEPROM write error) error.	--
U01-39	Transmit Error	Displays the contents of a MEMOBUS/Modbus error	--

U01-39 = 00000000



U01-44	ASR Out w/o Filter	Output monitor from Speed Control loop (Primary Delay filter input value). 100% is displayed at motor rated secondary current.	%
U01-50	Hook Height	Percentage of Hook height is displayed. This will display 0% until the system is homed.	%
U01-51	Motor Revolution	Number of revolutions after Home with respect to Home.	Revs

Parameter	Display	Function	Units
U01-52	MaintenanceTimer	Hours since last timer reset.	Hrs
U01-53	Index Count	Number of motor revolutions the shaft has moved since the beginning of a new Index command.	Revs
U01-54	Term RP Inp Freq	Displays the frequency of pulse train input terminal RP.	Hz
U01-60	PG CH1 Count	Displays the raw PG Channel 1 pulse count 4 pulses = 1 ppr of F01-01	Pulses
U01-61	PG CH2 Count	Displays the raw PG Channel 2 pulse count 4 pulses = 1 ppr of F01-01	Pulses
U01-63	PG CH1 Freq	Displays the current input frequency on PG Channel 1	Hz
U01-64	PG CH2 Freq	Displays the current input frequency on PG Channel 2	Hz
U01-65	PG Output Freq	Displays the current output frequency on the PG Output channel	Hz
U01-66	BE6 Pulse Count	Displays the amount of shaft movement during the BE6 detection time 4 pulses = 1 ppr of F01-01	Pulses
U01-68	LC Zone	Displays the LC Zone the driver is currently running in. If an LC fault occurs, the value displayed will be which LC zone the LC fault occurred in.	--
U01-69	LC Margin	Displays how close the current/torque levels are to the target value for each of the LC zones. Values less than zero will cause an LC detection or an LC fault to occur. If the LC fault occurs, the value displayed is the amount the level was below the LC zone setting.	--
U01-84	NLB State	Displays the current NLB State Machine sequence. Analog Output Level: 0.5V/State	--
U01-85	NLB Rel Trq	Torque level for next BE2 check. Is set to 100% after BE2 is passed, and set to torque output level at end of Load Float. No signal output available	%
U01-86	Brk Test Trq	Brake breakaway torque; FLV only; MFDI needs to be programmed with "Brake Test"	Fib

Table 5-112: Fault Trace Parameters

Parameter	Display	Function	Units
U02-01	Current Fault	Display the most current fault detected before being reset.	--
U02-02	Last Fault	Displays most recent fault after being reset.	--
U02-03	Frequency Ref	Freq ref when fault was detected.	Hz
U02-04	Output Freq	Output freq when fault was detected.	Hz
U02-05	Output Current	Output current when the fault was detected.	A
U02-06	Motor Speed	Motor Speed when the fault was detected.	Hz
U02-07	Output Voltage	Output voltage when fault was detected.	VAC
U02-08	DC Bus Voltage	DC Bus voltage when fault was detected.	VDC
U02-09	Output HP	Displays the output power at the fault (U02-02).	HP
U02-10	Torque Reference	Torque reference when the fault was detected.	%
U02-11	Input Term Sts	Input terminal status when fault was detected.	--
U02-12	Output Term Sts	Output terminal status when the fault was detected.	--
U02-13	Inverter Status	Inverter status before the fault was detected.	--
U02-14	Elapsed Time	Elapsed time when the fault was detected.	Hrs

* Available only for 4810 and 41090 models.

Parameter	Display	Function	Units
U02-15	SFS Output	Displays the speed reference for the soft starter at the previous fault (U02-02).	Hz
U02-16	Motor Iq Current	Displays the q-axis current for the motor at the previous fault (U02-02).	%
U02-17	Motor Id Current	Displays the d-axis current for the motor at the previous fault (U02-02).	%
U02-20	Actual Fin Temp	Displays the temperature of the heatsink when the most recent fault occurred.	°C
U02-27*	Motor Temp (NTC)	Displays the temperature of the motor when the most recent fault occurred.	°C
U02-28*	Fault Axis	Display the module where the previous fault occurred at a decimal number.	--

* Available only for 4810 and 41090 models.

Table 5-113: Fault History Parameters

Parameter	Display	Function	Units
U03-01	Last Fault	Displays the first most recent fault.	--
U03-02	Fault Message 2	Displays the second most recent fault.	--
U03-03	Fault Message 3	Displays the third most recent faults.	--
U03-04	Fault Message 4	Displays the fourth most recent fault.	--
U03-05	Fault Message 5	Displays the fifth most recent fault.	--
U03-06	Fault Message 6	Displays the sixth most recent fault.	--
U03-07	Fault Message 7	Displays the seventh most recent fault.	--
U03-08	Fault Message 8	Displays the eighth most recent fault.	--
U03-09	Fault Message 9	Displays the ninth most recent fault.	--
U03-10	Fault Message 10	Displays the tenth most recent fault.	--
U03-11	Elapsed Time 1	Elapsed time of the first most recent fault.	Hrs
U03-12	Elapsed Time 2	Elapsed time of the second most recent fault.	Hrs
U03-13	Elapsed Time 3	Elapsed time of the third most recent fault.	Hrs
U03-14	Elapsed Time 4	Elapsed time of the fourth most recent fault.	Hrs
U03-15	Elapsed Time 5	Elapsed time of the fifth most recent fault.	Hrs
U03-16	Elapsed Time 6	Elapsed time of the sixth most recent fault.	Hrs
U03-17	Elapsed Time 7	Elapsed time of the seventh most recent fault.	Hrs
U03-18	Elapsed Time 8	Elapsed time of the eighth most recent fault.	Hrs
U03-19	Elapsed Time 9	Elapsed time of the ninth most recent fault.	Hrs
U03-20	Elapsed Time 10	Elapsed time of the tenth most recent fault.	Hrs
U03-21	RUN Cmd Counter	Counts FWD or REV run commands	Count
U03-22	U3-21 Rollovers	Increments when U03-21 passes 9999. U03-21 is set to 0. Counter cleared by O03-14.	Count
U03-23	OL/LC Count	Counts OL1, OL2, LC faults. Counter cleared by O03-14.	Count

Table 5-114: Maintenance Parameters

Parameter	Display	Function	Units
U04-01	Drv Elapsed Time	Displays the cumulative operation time of the drive. The value for the cumulative operation time counter can be reset in parameter O03-01. Use parameter O03-02 to determine if the operation time should start as soon as the power is switched on or only while the Run command is present. The maximum number displayed is 99999, after which the value is reset to 0.	Hrs
U40-03	Fan Elapsed Time	Displays the cumulative operation time of the cooling fan. The default value for the fan operation time is reset in parameter O03-03. After the count reaches 99999, the value will reset to 0 and start counting again.	Hrs
U04-04	Fan Life Mon	Displays main cooling fan usage time in as a percentage of its expected performance life. Parameter O03-03 can be used to reset this monitor.	%
U04-05	Cap Life Mon	Displays main circuit capacitor usage time in as a percentage of their expected performance life. Parameter O03-05 can be used to reset this monitor.	%
U04-06	ChgCirc Life Mon	Displays the soft charge bypass relay maintenance time as a percentage of its estimated performance life. Parameter O04-07 can be used to reset this monitor.	%
U04-07	IGBT Life Mon	Displays IGBT usage time as a percentage of the expected performance life. Parameter O03-09 can be used to reset this monitor.	%
U04-08	Heatsink Temp	Displays the heatsink temperature.	°C
U04-09	LED Oper Check	Lights all segments of the LED to verify that the display is working properly.	--
U04-10	kWh Lower 4 dig	Monitors the drive output power. The value is shown as a 9 digit number displayed across two monitor parameters, U04-10 and U04-11.	kWH
U04-11	kWh Upper 5 dig	--	MWH
U04-12	CPU Occup Rate	Displays the amount of space being used in the CPU.	%
U04-13	Current PeakHold	Displays the highest current value that occurred during run.	A
U04-14	Freq@ I PeakHold	Displays the output frequency when the current value shown in U04-13 occurred.	Hz
U04-16	Motor OL1 Level	Shows the value of the motor overload detection accumulator. 100% is equal to the OL1 detection level. Accumulator is reset when drive power is cycled.	%
U04-17	Drive OL2 Level	100% = OL2 detection level	%
U04-18	Reference Source	Displays the source for the frequency reference as XY-nn.	--
U04-19	MEMOBUS Freq Ref	Displays the frequency reference provided by MEMOBUS/Modbus (decimal).	%
U04-20	Option Freq Ref	Displays the frequency reference input by an option card (decimal).	%
U04-21	Run Cmd Source	Displays the source for the Run command as XY-nn.	--
U04-22	MEMOBUS Ref Reg	Displays the drive control data set by MEMOBUS/Modbus communications register no. 0001H as a four-digit hexadecimal number.	--
U04-23	Option Ref Reg	Displays drive control data set by an option card as a four-digit hexadecimal number.	--
U04-32*	Motor Temp (NTC)	Displays the motor temperature (NTC). U04-32 will display "20 °C" when a multi-function analog input is not set for motor thermistor input (H01-xx = 17H).	--
U04-37*	OH Alarm Axis	Displays the module where the oH alarm occurred as a binary number.	BIN

* Available only for 4810 and 41090 models.

Parameter	Display	Function	Units
U04-38*	FAN Alarm Axis	Displays the module where the FAn alarm occurred as a binary number.	BIN
U04-39*	VOF Alarm Axis	Displays the module where the voF alarm occurred as a binary number.	BIN

* Available only for 4810 and 41090 models.

Table 5-115: Control Monitor Parameters

Parameter	Display	Function	Units
U06-01	Mot SEC Current	Displays the value of the motor secondary current (Iq). Motor rated secondary current is 100%.	%
U06-02	Mot EXC Current	Displays the value calculated for the motor excitation current (Id). Motor rated secondary current is 100%.	%
U06-03	ASR Input	Displays the input value when using ASR control.	%
U06-04	ASR Output	Displays the output value when using ASR control.	%
U06-05	Voltage Ref (Vq)	Output voltage reference (Vq) for the q-axis.	VAC
U06-06	Voltage Ref (Vd)	Output voltage reference (Vd) for the d-axis.	VAC
U06-07	ACR(q) Output	Displays the output value for current control relative to motor secondary current (q-axis).	%
U06-08	ACR(d) Output	Displays the output value for current control relative to motor secondary current (d-axis).	%
U06-18	PG1 CounterValue	Monitors the number of pulses for speed detection. Analog Output Level: 10V/65535	--
U06-19	PG2 CounterValue	Monitors the number of pulses for speed detection. Analog Output Level: 10V/65535	--
U06-22	Zero Servo Pulse	Displays how far the rotor has moved from its last position in PG pulses (multiplied by 4).	--
U06-26	FF Cont Output	Output monitor for Feed Forward control.	%

Chapter 6

Troubleshooting

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Troubleshooting the Drive

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

Maintenance and Inspection

This section describes basic maintenance and inspection procedures for the IMPULSE®•G+ and VG+ Series 4.

Table 6-1: Maintenance and Inspection

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

Alarms and Faults are described as follows:

- Fault: Brake is set, operation indicator lights flash, fault is displayed on keypad and fault contact output terminal MB-MC is activated. The reset key must be pressed, a multi-function digital input set for fault reset must be enabled, or power must be cycled in order to continue operation.
- Alarm: Brake does not set, operation continues, alarm is displayed on the keypad, fault contact output is not activated.

Table 6-2: Motor Related Issues and Corrective Actions

Symptom	Corrective Action
Analog frequency reference is not stable. (drifting)	<ol style="list-style-type: none"> 1. Stabilize the analog source. 2. Increase H03-13. 3. Increase B05-01 or B05-02.
No motor rotation.	<ol style="list-style-type: none"> 1. Verify that power is on (Charge LED). 2. Verify that the keypad display is not showing a fault. 3. Verify that the run command is input to the drive (U01-10). 4. Check if motor is stalled due to excessive load.
Motor rotation is in the wrong direction.	<ol style="list-style-type: none"> 1. Verify FWD/REV or UP/DN is correct at the interface card. 2. Match wiring to the phase order of the motor leads T1, T2, T3. 3. Change motor rotation (B03-04).

Symptom	Corrective Action
Motor rotates, but at minimum speed only.	<ol style="list-style-type: none"> 1. Check wiring of speed inputs. 2. Verify speed reference setting (A01-04). 3. Verify reference and run source settings are correct (B03-01, -02). 4. Verify reference priority setting (B01-18). 5. Verify encoder direction (VG+).
Motor RPM too high or too low.	<ol style="list-style-type: none"> 1. Compare motor nameplate specifications with E2 parameters. 2. Check maximum frequency setting (E01-04). 3. Check minimum frequency setting (E01-09).

Table 6-3: Drive Faults and Alarms

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
AS1 (flashing) Anti-Shock	Anti-Shock Indicator. When the Anti-Shock function is triggered, this alarm will be displayed on the keypad for the duration of time set via C07-22.	1. No action is required.		X
BB (flashing) Base Block	External Base Block Indicator. The flashing base block signal is the result of a multi-function input in the terminal strip. The base block indicates that the drive's IGBTs have been disabled. The motor will begin coasting when the base block input is received. If a RUN command is still present when the BB signal is removed, the output voltage will be restored to the previous operating level and operation will continue at the previously commanded frequency.	<ol style="list-style-type: none"> 1. Check constants H01-01 through H01-08 for proper programming. 2. Check terminal status (U01-10). 		X
BE0 (flashing) Brake Ans Lost	Brake answer back signal is lost during run. While running, the multi-function input brake answer back (H01-0x = 58) is lost.	<ol style="list-style-type: none"> 1. Check brake answer back circuit. 2. Check terminal status. (U01-10) 	X	X
BE0-2 Brake2Ans Lost	Brake 2 answer back signal is lost during run. Brake Answer-Back 2 closes during operation.	<ol style="list-style-type: none"> 1. Check brake answer back circuit. 2. Check terminal status. (U01-10) 	X	X
BE1 Rollback detect	Torque Proving Fault. The BE1 fault indicates that the drive has released the brake, but not started to accelerate the motor when it detects excessive encoder feedback. A BE1 fault will occur if the pulses received during the BE1 detection time (C08-04) are greater than the expected number of pulses (C08-05).	<ol style="list-style-type: none"> 1. Increase the value of C08-21. 2. Please reference troubleshooting encoder related faults on page 6-16. 		X

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
BE2 No Current	Torque Proving Fault. Before the brake is released, the drives current/torque did not reach Initial Brake Release Torque level (C08-16) within the IFB OK timer (C08-02).	<ol style="list-style-type: none"> 1. Ensure the motor has been Auto-tuned successfully. 2. Confirm that the holding brake is closed. 3. If a power limit switch is used, ensure that the switch is closed. 4. Decrease the value of C08-02 to no less than 0.5 seconds. 5. Decrease the value of C04-02 to no less than 5. 6. Decrease the value of C08-16 to no less than 50. 	X	
BE3 Brake Release NG	Brake Release Fault. The BE3 fault indicates that the drive has released the brake and commanded the drive to run, but it has not detected the expected encoder feedback. A BE3 fault will occur if the pulses received during the BE3 detection time (C08-06) are less than the expected number of pulses (C08-07).	<ol style="list-style-type: none"> 1. Please reference encoder related faults on page 6-16. 	X	
BE4 (flashing) Brake Answer 1	Brake Answer-Back, Brake not Released. At Start, Brake Answer-back is not input within predetermined time (C08-04) after electric brake release command is output—Electric brake not released.	<ol style="list-style-type: none"> 1. Check brake answer back circuit. 2. Increase the value of C08-04. 3. Check terminal status (U01-10). 		X
BE4-2 Brake 2 Answer 1	Brake 2 Answer-Back Brake not Released. Brake 2 Answer-Back does not release during Brake Release state.	<ol style="list-style-type: none"> 1. Check brake answer back circuit. 2. Increase the value of C08-04. 3. Check terminal status (U01-10). 	X	X
BE5 (flashing) Brake Answer 2	Brake Answer-Back At Stop. At Stop, Brake Answer-back signal is not removed within predetermined time (C08-11) after electric brake release command is removed—Electric brake not closed. See the Fault Latch Table for on page 5-120 for Fault Latching Options.	<ol style="list-style-type: none"> 1. Check brake answer back circuitries 2. Increase the value of C08-11 time. 	X	X
BE5-2 Brake 2 Answer 2	Brake 2 Answer-Back at Stop. Brake 2 Answer-Back does not close during Brake Set time.	<ol style="list-style-type: none"> 1. Check brake answer back circuitries 2. Increase the value of C08-11 time. 	X	X
BE6 (flashing) Brake Stop	Brake Proving Alarm. The BE6 alarm indicates that the drive has commanded the brake to set but it has detected more than the expected encoder feedback. A BE6 alarm will occur if the number of pulses received during the BE6 detection time (C08-12) is greater than the expected number of pulses (C08-13). See the Fault Latch Table for on page 5-120 for Fault Latching Options.	<ol style="list-style-type: none"> 1. Check the brake. 2. Please reference troubleshooting encoder related faults on page 6-16. 	X	X
BE6-2 Brake 2 Slipping	Brake 2 Slipping. Load slipping while Brake 2 is closed.	<ol style="list-style-type: none"> 1. Check the brake. 2. Please reference troubleshooting encoder related faults on page 6-16. 	X	X
BE7 Brake Welded	Brake Answer-Back Fault. At Power Up, Brake Answer-Back is on - Electric brake not closed.	<ol style="list-style-type: none"> 1. Check if brake is closed. 2. Check brake answer back circuitry. 	X	

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
BE7-2 Brake 2 Welded	Brake 2 Answer-Back Major Fault. Brake Answer-Back is on at power-up.	1. Check if brake is closed. 2. Check brake answer back circuitry.	X	
BE8 Brake Slipping	Brake Slipping Fault. The BE8 alarm indicates that the drive has detected more than the expected encoder feedback. A BE8 alarm will occur if the encoder frequency exceeds C08-23; Load Float will be enabled, and the brake will remain closed. See the Fault Latch Table for on page 5-120 for Fault Latching Options.	1. Check the brake. 2. Check C08-23 for proper programming.	X	X
boL	Braking Transistor Overload Fault. The braking transistor reached its overload level.	1. The wrong braking resistor is installed. 2. Select the correct braking resistor. 3. Install an external braking module.	X	X
BUS Option Com Err	Option Card Communication Error. Communication to the option card was lost.	1. Check all connections.	X	X
CALL (flashing) SI-F/G Com Call	Serial Communication Transmission Error. Control data is not received correctly after power supply is turned ON for 2 sec.	1. Check serial device connections. 2. Ensure drive is properly programmed for serial communication.		X
Cant Run Drive Not Ready	User is trying to give a run command while a FWD or REV is present at Power Up.	1. Turn on Drive Enable Multi-Function Input. 2. Check H01-01 to H01-08 programming. 3. Change B03-10 to allow run at power up.		X
Can't SW Motor Running	Can't Switch - Motor Running. The user is trying to enable or disable the Digital Changeover MFDI (H01-XX = 1D), while the motor is still running.	1. Allow the motor to come to a stop before enabling or disabling the Digital Changeover MFDI.		X
CE Memobus Com Err	Communication Error. Serial communications disruption. Fault or alarm defined by H05-04.	1. Check serial connections (6 CN). 2. Check H05-01 through H05-05 for proper programming.	X	X
COF	Current Offset Fault. The drive automatically adjusts the current offset, the calculated value exceeded the allowable setting range.	1. Press reset. 2. Check brake. 3. Check brake contact.	X	
CPF00 CPF01	Control Circuit Error. There is a self-diagnostic error in the control circuit, or the connector on the operator is damaged.	1. Cycle power to the drive. 2. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board. 3. Replace the operator if it is damaged.	X	
CPF02	A/D Conversion Error. An A/D conversion error or control circuit error occurred. The control circuit is damaged.	1. Cycle power to the drive. 2. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board.	X	

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
CPF03	<p>Control Board Connection Error. Connection error between the control board and the drive. Can be caused by a connection error, or the drive failing to operate properly due to noise interference.</p>	<p>Connection Error:</p> <ol style="list-style-type: none"> 1. Turn off the power and check the connection between the control board and the drive. 2. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board. <p>Noise Interference:</p> <ol style="list-style-type: none"> 1. Check the various options available to minimize the effects of noise. 2. Counteract noise in the control circuit, main circuit, and ground wiring. 3. Use only recommended cables or other shielded line. Ground the shield on the controller side or the drive input power side. 4. Ensure that other equipment such as switches or relays do not cause noise. Use surge suppressors if required. 5. Separate all communication wiring from drive power lines. Install an EMC noise filter to the drive power supply input. 	X	
CPF06 EEPROM Error	<p>EEPROM Memory Data Error. An Error in the data saved to EEPROM. Can be caused by an error in the EEPROM control circuit, or the power supply being switched off while parameters are being saved to the drive.</p>	<p>Error in the EEPROM Circuit</p> <ol style="list-style-type: none"> 1. Turn off the power and check the connection between the control board and the drive. 2. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board. <p>Parameter Save Interruption</p> <ol style="list-style-type: none"> 1. Reinitialize the drive (A01-03 = 5432). 	X	
CPF07 CPF08	<p>Terminal Board Connection Error. There is a fault connection between the terminal board and the control board.</p>	<ol style="list-style-type: none"> 1. Turn off the power and reconnect the terminal board. 1. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board. 	X	
CPF20 or CPF21	<p>Control Circuit Error. Hardware is damaged.</p>	<ol style="list-style-type: none"> 1. Cycle power to the drive. 2. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board. 	X	
CPF22 Hybrid IC Failure	<p>Hybrid IC Failure. Hybrid IC failure on the power board.</p>	<ol style="list-style-type: none"> 1. Cycle power to the drive. 2. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board. 	X	

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
CPF23	Control Board Connection Error. Connection error between the control board and the drive. The hardware is damaged.	1. Turn off the power and check the connection between the control board and the drive. 2. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board.	X	
CPF24	Drive Unit Signal Fault. The drive capacity cannot be detected correctly (drive capacity is checked when the drive is powered up). The hardware is damaged.	1. If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board.	X	
CPF25	Terminal Board Not Connected. Terminal board is not connected correctly.	1. Reconnect the terminal board to the connector on the drive, then cycle power to the drive.	X	
CPF26– CPF34	Control Circuit Error.	1. Cycle power. 2. Ensure that the terminal board is seated properly. 3. Set A01-05 = 5550. 4. Replace control board and/or terminal board.	X	
CPF40– CPF45				
DEV Speed Deviation	Speed Deviation Fault. Occurs when the deviation of the speed reference and speed feedback exceeds the regulation level, F01-27 for the time F01-28. Alarm or fault defined by F01-26.	1. Please reference troubleshooting encoder related faults on page 6-16.	X	X
DIR Direction Fault	Direction Fault. Occurs when the drive detects that a hoist is configured so FWD direction is DOWN motion.	1. Verify FWD is shown on the keypad when moving in the UP direction. Set B03-01 if REV is shown when going UP. 2. If correct travel direction has been verified, set C08-34 to zero to disable DIR detection.	X	
EF (flashing) External Fault	Both FORWARD/UP and REVERSE/DOWN commands are input at same time for 500 msec or longer.	1. Check control input wiring. 2. Check the sequence of operation.		X
EF0 Optional External Fault	External fault input from communication option card. Alarm or fault defined by F06-03.	1. Check communication option card connection and signals.	X	X
EF1 External Fault 1	External fault occurs on Terminal S1. Alarm or fault defined by the External Fault Selection table (table 5-80 on page 5-96).	1. Check constant H01-01 for proper programming. 2. Check the conditions for input terminal S1.	X	X
EF2 External Fault 2	External fault occurs on Terminal S2. Alarm or fault defined by the External Fault Selection table (table 5-80 on page 5-96).	1. Check constant H01-02 for proper programming. 2. Check the conditions for input terminal S2.	X	X
EF3 External Fault 3	External fault occurs on Terminal S3. Alarm or fault defined by the External Fault Selection table (table 5-80 on page 5-96).	1. Check constant H01-03 for proper programming. 2. Check the condition of the input terminal S3.	X	X

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
EF4 External Fault 4	External fault occurs on Terminal S4. Alarm or fault defined by the External Fault Selection table (table 5-80 on page 5-96).	1. Check constant H01-04 for proper programming. 2. Check the condition of the input terminal S4.	X	X
EF5 External Fault 5	External fault occurs on Terminal S5. Alarm or fault defined by the External Fault Selection table (table 5-80 on page 5-96).	1. Check constant H01-05 for proper programming. 2. Check the condition of the input terminal S5.	X	X
EF6 External Fault 6	External fault occurs on Terminal S6. Alarm or fault defined by the External Fault Selection table (table 5-80 on page 5-96).	1. Check constant H01-06 for proper programming. 2. Check the condition of the input terminal S6.	X	X
EF7 External Fault 7	External fault occurs on Terminal S7. Alarm or fault defined by the External Fault Selection table (table 5-80 on page 5-96).	1. Check constant H01-07 for proper programming. 2. Check the condition of the input terminal S7.	X	X
EF8 External Fault 8	External fault occurs on Terminal S8. Alarm or fault defined by the External Fault Selection table (table 5-80 on page 5-96).	1. Check constant H01-08 for proper programming. 2. Check the condition of the input terminal S8.	X	X
ERR EEPROM R/W Err	EEPROM Read/Write Fault. EEPROM internal data did not match when initializing the parameter.	1. Cycle Power. 2. User initialize (A01-05=1110). 3. Replace Control board.		X
FAn	Internal Fan Fault. Internal cooling fan has malfunctioned. Alarm or fault defined by L08-32.	1. Cycle power to the drive. 2. Check for fan operation. 3. Verify the fan elapsed time with U04-03 and verify the fan maintenance timer with U04-04. 4. Replace fan.	X	X
GF Ground Fault	During operation, the inverter sums the currents of all three motor phases. Ideally, the sum should always equal zero. If the sum is greater than 50% of the inverter rated output current, a GF occurs.	1. Disconnect motor from drive and check it for shorts using a megger. 2. Ensure that R/C Surge Suppressors are used across all brake contactor coils to prevent disturbance by electrical transients.	X	
HBB or HBBf (flashing) Hardware Base Block	External Base Block Indicator. The flashing Hardware Base Block signal is a result of either of the Safe Disable inputs being open. The motor will begin coasting when the Hardware Base Block signal is open, and the brake relay digital output will close.	1. Check signal status at the input terminals H1 and H2. 2. Check the Sink/Source Selection for the digital inputs (see table 3- 7 on page 3-19). 3. If the Safe Disable function is not utilized, verify that H1 and H2 jumpers are installed correctly (see table 3-7 on page 3-19). 4. Replace either the control board or the entire drive.		X
KLX Klixon	Klixon Circuit Alarm. Input by MFDI H01-0x = 56 or 57.	1. Check Motor for Overtemp. 2. Check Klixon Circuit.		X
LC Load Check Err	Load Check Fault. Load is greater than specified amount. Alarm or fault defined by C05-02.	1. Reduce Load. 2. Check Load Check sequence set-up. (C05-xx).	X	X

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
LC Done Load Check Done	Load Check Done Alarm. This alarm is displayed after the LC set up process is done. The alarm will clear when the Down command is pressed and complete the LC set up process.	1. None.		X
LF Output Phase Loss	An open phase occurred at the inverter output.	1. Check for broken wires in output cable. 2. Check for open winding in the motor. 3. Check for loose terminals	X	
LF2 Output Current Imbalance	Output Current Imbalance. One or more of the phases in the output current are lost.	1. Check for faulty wiring or poor/ loose connections on the output side of the drive. 2. Correct the wiring. 3. Measure the line-to-line resistance for each motor phase. Ensure all values match. 4. Replace the motor.	X	
LL1 <i>(flashing)</i> Lower Limit 1 Err	Lower Limit 1—SLOW DOWN Indicator. Lower Limit 1—SLOW DOWN is input (switch status is changed).	1. May not require corrective action. 2. Check the Limit Switches position. 3. Check the Limit Switches condition.		X
LL2 <i>(flashing)</i> Lower Limit 2 Err	Lower Limit 2—STOP Indicator. Lower Limit 2—STOP is input (switch status is changed).	1. May not require corrective action. 2. Check the Limit Switches position. 3. Check the Limit Switches condition.		X
MNT Maintenance Req'd	Maintenance Required Alert. Running time has exceeded C12-05	1. Reset timer by H01-0x = 5A or depress Mode/Service key three times and enter within 2 seconds.		X
OC Over Current	Over Current Detected. Output current exceeds 200% of inverter rated output current.	1. Check for a phase-to-phase short in the motor or wiring using a megger. 2. Extend the acceleration/ deceleration time. 3. Check torque limit setting. 4. Please reference troubleshooting encoder related faults on page 6-16.	X	
OH <i>(flashing)</i> Heatsnk Over temp	Overheat Pre-Alarm. Heatsink is overheating. The temperature of the inverter's heatsink exceeded the setting in L08-02.	1. The inverter cooling fan has stopped. 2. Reduce the ambient temperature.	X	X
OH1 Heatsink MaxTemp	Overheat Fault. There are two situations that result in an overheat fault. The first occurs when the measured heat sink exceeded 105°C. The second is a result of a fault in the internal 24 VDC cooling fan.	1. Ensure that the heat sink cooling fans are functioning. 2. Ensure that the heat sink is free from dirt and debris. 3. Ensure that the inverter's ambient temperature is within specification.	X	
OH2 <i>(flashing)</i> Overheat 2	Overheat Alarm. Signal is input by external terminal. H01-0x=39	4. Replace the 24 VDC fan 5. Replace the heat sink thermistor(s)		X

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
OH3 Motor Overheat 1	Motor Overheating 1. Thermistor analog input detected motor overheating. See L01-03. Alarm defined by L01-03.	1. Check the motor rated current value, E02-01. 2. Increase cycle time or reduce the load.		X
OH4 Motor Overheat 2	Motor Overheating 2. Thermistor analog input detected motor overheating. See L01-04		X	
OL1 Motor Overloaded	Motor Overload Fault. Inverter output exceeded the motor overload level. Alarm or fault defined by L06-08.	1. Ensure drive is programmed with proper motor full load Amps (E02-01). 2. Reduce the load.	X	X
OL2 Drive Overloaded	Inverter Overload Fault. Inverter output exceeded the inverter overload level.	1. Reduce the load. 2. Extend the acceleration time.	X	X
OPR Oper Disconnect	Keypad Disconnected. The keypad is removed while the inverter is running, and the run command was initiated via the keypad RUN key.	1. Secure the keypad. 2. Verify O02-06 setting.	X	X
OS Over Speed	Overspeed Fault. The motor has exceeded the programmed detection level and time. This is typically caused by an overshoot condition due to an over-responsive ASR loop. If the drive is programmed to flux vector "torque control" mode, and no load is present, an overspeed fault will typically occur. Alarm or fault defined by F01-23.	1. Check the Automatic Speed Regulator settings, D04 sub group. 2. Check setting of F01-24, F01-25. 3. Verify proper encoder PPR setting, F01-01.	X	X
OT1 Overtorque Det 1	Overtorque Detection Level 1. Defined by L06-02. Alarm or fault defined by L06-01.	1. Check for proper programming for L06-02 and L06-03.	X	X
OT2 Overtorque Det 2	Overtorque Detection Level 2. Defined by L06-05. Alarm or fault defined by L06-04.	1. Check for proper programming for L06-05 and L06-06.	X	X
OV DC Bus Overvolt	Overvoltage Fault. The main circuit direct current voltage exceeded the overvoltage level.	1. Extend the deceleration time. 2. Check for proper DBU operation. 3. Check the resistor. 4. Check the line voltage.	X	
OV (flashing) DC Bus Overvolt	Overvoltage Fault. Overvoltage occurs during stop. Main circuit DC voltage rises above the detection level while the drive output is off.	1. Check the line voltage.		X
PF Input Phase Loss	Input Phase Loss Fault. Inverter input power supply has open phase.	1. Check the line voltage and fuses. 2. Remove power. 3. Re-tighten the input terminal screws.	X	
PGO-1-S PGO-1-H PG Open Ch1	Pulse Generator Channel 1 Fault. PGO-1-S, software detected fault. PGO-1-H, hardware detected fault. Alarm or fault defined by F01-21.	1. Check for proper direction of encoder feedback. 2. Please reference troubleshooting encoder related faults on page 6-16.	X	X
PGO-2-S PGO-2-H PG Open Ch2	Pulse Generator Channel 2 Fault. PGO-2-S, software detected fault. PGO-2-H, hardware detected fault. Alarm or fault defined by F01-21.	1. Check for proper direction of encoder feedback. 2. Please reference troubleshooting encoder related faults on page 6-16.	X	X

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
PULSDEV Pulse Deviation	Pulse Deviation. The pulse input into terminal RP compared to the pulse output from terminal MP is greater than the percentage programmed into H06-09.	1. During operation, verify that there is an incoming pulse signal on the RP terminal, viewable at U01-54. 2. Increase the deviation margin percentage in parameter H06-09.	X	
RF	Braking Resistor Fault. the resistance of the braking resistor is too low, or the proper braking resistor has not been installed.	1. Verify correct braking resistor.	X	
RH	Braking Resistor Overheat. Deceleration time is too short and excessive regenerative energy is flowing back into the drive.	1. Verify correct braking resistor.	X	
RR DynBrk Transistr	Braking Transistor Fault. Internal Braking transistor failed.	1. Verify that the external braking resistor is connected to the proper terminals. 2. Confirm that the proper resistor is installed. 3. Check for a short circuit across the braking resistor.	X	
SC Short Circuit	Short Circuit Fault. The inverter has detected an output short circuit condition.	1. Disconnect the motor from the inverter. 2. Check for a short circuit in the motor or wiring using a megger.	X	
SLC Slack Cable Detection	Slack Cable Fault. A hoist slack cable condition occurred.	1. May not require corrective action. 2. Check proper programming of Slack Cable Detection (C11-xx).		X
SNAP Snapped Shaft	Snapped Shaft Fault. A drive train discontinuity has been detected. Alarm or fault defined by C11-09.	1. Check for loose or broken coupling. 2. Check for loose encoder(s). 3. Check for broken shaft.	X	X
TST END Exit Test Mode	Exceeded the 10 minute time limit.	1. Ensure the test mode MFDI is OFF. 2. Reset the fault (Fault Reset MFDI, Keypad, or cycle power) 3. Ensure that test mode is not used for normal operation.		X
UBNC Unbalanced Cur	Current Unbalance. Current flow has become unbalanced. Exclusive to 4810 and 41090 models.	1. Check wiring. 2. Check for damaged transistors. 3. Check for short circuits or grounding problems on the connected motor.	X	
UL1 Upper Limit 1 Err	Upper Limit 1—SLOW DOWN Indicator. Upper Limit 1—SLOW DOWN switch status is changed.	1. May not require corrective action. 2. Check the limit switches location. 3. Check the limit switches condition.		X
UL2 Upper Limit 2 Err	Upper Limit 2—STOP Indicator. Upper Limit 2—STOP switch status is changed.	1. May not require corrective action. 2. Check the limit switches location. 3. Check the limit switches condition.		X

Code	Fault/Alarm Description	Corrective Action	Fault	Alarm
UL3 Upper Limit 3 Err	Upper Limit 3—Weighted Stop. Upper Limit weighted limit switch tripped.	1. May not require corrective action. 2. Check the position of the Limit Switch. 3. Check the condition of the Limit Switch. 4. Check the conditions of/for terminal H01-xx (U01-10)	X	X
UT1 Undertorque Det 1	Undertorque Detection 1. The current is less than L06-02 for more than L06-03. Alarm or fault defined by L06-01.	1. Check settings. 2. Check motor coupling.	X	X
UT2 Undertorque Det 2	Undertorque Detection 2. The current is less than L06-05 for more than L06-06. Alarm or fault defined by L06-04.	1. Check settings. 2. Check motor coupling.	X	X
UV DC Bus Undervolt	Undervoltage Fault. Undervoltage status occurs for more than 2 sec during STOP.	1. Check the power source wiring. 2. Replace any bad branch fuses. 3. Check collector system.		X
UV1 DC Bus Undervolt	Undervoltage 1 Fault. Undervoltage status occurs for more than 2 sec during RUN command.	1. Check power supply wiring. 2. Correct the line voltage. 3. Check collector system.	X	
UV2 CTL PS Undervolt	Undervoltage 2 Fault. The inverter detected a loss of the 24V logic power supply voltage.	1. Check power supply wiring. 2. Correct the line voltage. 3. Check collector system.	X	
UV3 MC Answerback	MC Fault. The pre-charge contactor opened during operation.	1. Check power supply wiring. 2. Correct the line voltage. 3. Check collector system. 4. Wait 30-45 seconds before restarting drive after auto shut down.	X	
UV4 GC Undervolt	Gate Drive Board Undervoltage. Voltage drop in the gate drive board circuit. Exclusive to 4810 and 41090 models.	1. Cycle power to the drive and see if the fault reoccurs. 2. If the problem continues, replace either the gate drive board or the entire drive. For instructions on replacing the gate drive board, contact Magnetek or a Magnetek representative.	X	X
voF	Output Voltage Detection Fault. Problem detected with the voltage on the output side of the drive.	1. Replace the drive.	X	X

Table 6-4: Operation Error Table

Code	Error Name/Description	Corrective Action
OPE01 kVA Selection	kVA Setting Error. Inverter kVA setting range is incorrect.	1. Check O02-04 constant for proper kVA.

Code	Error Name/Description	Corrective Action
OPE02 Limit	Setting Out of Range. Parameter setting is out of range.	<ol style="list-style-type: none"> 1. With the fault displayed on the keypad, press the ENTER key to reveal the "Out of Range" parameter via the U01-34 monitor. 2. Verify that E02-03 is < E02-01. 3. Verify E01-05 is within range. 4. Compare modified constants with defaults. 5. Cycle Power.
OPE03 Terminal	Multi-Function Input Setting Error. Set values other than "F" are duplicated.	<ol style="list-style-type: none"> 1. Check the settings for H01-01 to H01-10, verify that the same input is not used twice.
OPE04 BoardReplaceDet	Initial Parameter Settings Error. The control board or terminal board has been replaced and the parameter settings no longer match.	<ol style="list-style-type: none"> 1. Set A01-05 to 5550 to use the parameter settings saved to the terminal block memory.
OPE05 Sequence Select	Frequency Reference Source Selection Error. A frequency reference is assigned to an option card that is not connected.	<ol style="list-style-type: none"> 1. Cycle power. 2. Ensure that the option card is seated properly into the option card slot. 3. Replace option card.
OPE06 PG Opt Missing	Missing PG Card. A closed loop control method was selected, and the required PG feedback card is not installed.	<ol style="list-style-type: none"> 1. Install the required option card. 2. Remove power and reset the option card. 3. Check the A01-02, control method, program setting
OPE07 Analog Selection	Multi-Function Analog Input Setting Error. H03-02, H03-06, and/or H03-10 multi-function analog input settings are set to the same value.	<ol style="list-style-type: none"> 1. Check the function selections.
OPE08 Ctrl Func Error	Selection Parameter Error. A parameter has been changed that is not available in the present control method.	<ol style="list-style-type: none"> 1. Undo the last parameter change (if known) 2. Scroll through modified constants for obvious setting errors. 3. Perform a user initialize (A01-05=1110) CAUTION: All settings will be restored to the factory defaults.
OPE10 V/f Ptrn Setting	V/f Parameter Setting Error.	<ol style="list-style-type: none"> 1. Check Parameters E01-04 to E01-11.
OPE11 CarrFrq/ON-Delay	Carrier Frequency Parameter Error.	<ol style="list-style-type: none"> 1. Check Parameters D10-01 to D10-05.
OPE13	<p>Sync & Ultra-Lift.</p> <p>Master: Drive is programmed for Ultra-Lift and requires an MFD1 to be programmed for Sync Ultra-Lift (H01-0x or C09-0x = 7C).</p> <p>Slave: Drive is programmed for Ultra-Lift and requires an MFDO to be programmed for Sync Ultra-Lift (H02-0x or F05-0x = 3C).</p>	<p>Special programming/wiring is required to use Ultra-Lift and Hoist Synchronization.</p> <ol style="list-style-type: none"> 1. Ensure that the proper wiring scheme is in place to utilize Ultra-Lift. 2. Set H01-0x = 7C or H02-0x = 3C or both according to interlock wiring requirements.
OPE16 Weight Measure	Weight Measurement. Full load torque is less than no load torque.	<ol style="list-style-type: none"> 1. Satisfy condition C10-09 > C10-10.

Code	Error Name/Description	Corrective Action
OPE19 Stp-Mthd & Ctrl	Incompatible Setting of Stopping Method and Control Method.	1. Satisfy $B03-03 \geq 6$ and $A01-02 \leq 1$.
OPE20 EPLS Setting	Electronic Programmable Limit Switch Setting Error.	1. Check if $C03-14 = 0, 2$ or 4 : $C03-19 > C03-18 > C03-17 > C03-16$ 1. Check if $C03-14 = 1$ or 3 : $C03-19 < C03-18 < C03-17 < C03-16$
OPE21 2nd Chan Missing	Option Card PG-X3 is missing when C11-08 is Enabled.	1. Install correct option card.
OPE22 Ctrl & Motion	Incompatible Setting of Motion and Control Method.	1. Satisfy $A01-02 \leq 1$ and $A01-03 \geq 2$.
OPE23 Hook Height Home	Hook Height Home MFDI Setting Error. Hook Height Home is set to UL2 N.O., LL2 N.O., or UL3 N.O., but no MFDI is programmed for the corresponding function.	1. Check C03-14 settings. 2. Check H01-xx settings.
OPE24 Slack Cable	Slack Cable. Incorrect setup.	1. Satisfy condition $C11-04 < C11-06$ and $C11-05 < C11-07$.
OPE28 Dual Brake MFDO	Dual Brake MFDO. MFDO programmed to 0AH, but no output programmed to 00H. Must have 00H and 0AH programmed.	1. Check that one MFDO is programmed to 00H. 2. Check that one MFDO is programmed to 0AH. 3. Set C08-33 to Disabled.

Troubleshooting Encoder Related Faults

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

Fault Code: DEV– Speed Deviation Fault

Definition

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

Corrective Action

1. Do **NOT** continue to operate the hoist.
NOTE: Continued attempts to operate the hoist with speed deviation faults occurring can result in loss of control of the load under certain circumstances.
2. As a precaution the load float time, parameter C08-10 should be set to zero until the source of the speed deviation fault has been determined and corrected.
3. Verify if the load has snagged or if there is a load on the hook that exceeds capacity.
4. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive will get erratic pulse signals or no signals at all causing a speed deviation fault or PGO (Pulse Generator Open) fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.
5. If the encoder appears to have no mechanical problems, the encoder cable should be checked for damage and replaced if a problem is found.
 - 5.1 Each of the encoder wires should be checked for continuity.
 - 5.2 The wires should be checked for shorts between any two wires.
 - 5.3 The wires should be checked for shorts to the shield or ground.
 - 5.4 Visually inspect the cable for damage that may be causing intermittent problems.
6. If the encoder feedback system checks out mechanically and electrically, then the last physical check to make is for something in the mechanical system that might be resisting normal operation. One example may be the brake is not opening fully and is causing enough drag to prevent the system from operating at commanded speed.

7. If the encoder feedback system checks out and no other mechanical problems can be found, then something must have changed in the control system.
 - 7.1 Check if the acceleration or deceleration times have been changed (B05-01, B05-02, C01-02, C01-04, or C01-05).
 - 7.2 Check if a function that provides an alternate acceleration or deceleration rate has been enabled or changed (Quick Stop, Reverse Plug Simulation, Accel/Decel Time 2).

If one of these times is too short, causing torque limited acceleration or deceleration, then the times should be extended.
8. If none of the above steps has identified a valid problem(s), only then should the speed deviation detection levels be adjusted.

NOTE: The reaction time necessary to stop a load is limited to the lift of the hoist and the response time of the hoist brakes. It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.)
9. Increase Encoder Excessive Speed Deviation Level to no more than 30 (F01-27).
10. After the corrective action has been taken and the fault no longer occurs then the load float time, C08-10, can be set back to its initial value.

Fault Code: PGO-X-S/PGO-X-H–Pulse Generator Signal Fault

Definition

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

NOTE: The "X" in PGO-X-S and PGO-X-H depicts either a "1" if the PG-X3 is seated in connector CN5-C, or a "2" if the PG-X3 is seated in connector CN5-B.

Corrective Action

1. Do **NOT** continue to operate the hoist in the event of a PGO-X-H fault or repeated PGO-X-S faults.

NOTE: Continued attempts to operate the hoist with PGO faults occurring can result in loss of control of the load under certain circumstances.
2. As a precaution, the load float time, parameter C08-10, should be set to zero until the source of the PGO Fault has been determined and corrected. Disable PGO hardware detection with F01-06 or F01-08.
3. Check the alignment of the encoder pulse wheel with the sensor head, the encoder shaft coupling (depending on the type of encoder used), or check for a failed encoder sensor head. If one of these conditions exists the drive will get erratic pulse signals or no signal at all causing a speed deviation fault or PGO fault. Repairs to the encoder wheel or shaft coupling should be made immediately before attempting to operate the hoist again.
4. If the encoder appears to have no mechanical problems, the encoder cable should be checked for damage and replaced if a problem is found.
 - 4.1 Each of the encoder wires should be check for continuity.
 - 4.2 The wires should be checked for shorts between any two wires.
 - 4.3 The wires should be checked for shorts to the shield or ground.
 - 4.4 Visually inspect the cable for damage that may be causing intermittent problems.
5. If the encoder feedback system checks out, then check for physical obstruction to motor rotation such as brake failing to open.

6. After corrective action has been taken and the fault no longer occurs then the load float time, C08-10, can be set back to initial value.

Fault Code: BE1–Rollback Fault

Definition

The BE1 fault indicates that the drive has released the brake, but has not started to accelerate the motor when it detects more than the expected encoder feedback. A BE1 fault will occur if the pulses received during the BE1 detection time (C08-04) are greater than the expected number of pulses (C08-05). This is typically caused by the drive/motor having insufficient torque to suspend the load.

Correction Action

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

NOTE: It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.
4. Increase C08-05 to no more than 800 pulses.

Fault Code: BE2–Torque Proving Fault

Definition

The BE2 fault indicates that the drive was unable to develop sufficient torque before releasing the brake. A BE2 fault occurs when the torque (U01-09) is less than the Initial Forward Brake Torque (C08-16) during the current feedback timer (C08-02) at start. This typically indicates that the brake is slipping while torque is building up in the motor before releasing the brake.

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

Corrective Action

1. Check the brake for proper operation and adjustment. If the brake does not set, is improperly adjusted or is excessively worn, it may not be able to hold the load. This will allow the encoder pulses received while torque is building up in the motor.
2. Check the encoder cable for damage and proper grounding. Replace it if a problem is found.
 - 2.1 Each of the encoder signals should be checked for excessive noise.
 - 2.2 The shielded encoder cable should be properly grounded.
 - 2.3 Visually inspect the cable for damage that may be causing intermittent problems.
3. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft

coupling (depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive may get erratic pulse signals possibly causing a BE2 fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.

4. Perform a Brake Torque test to verify the braking torque compared to the brake specifications before proceeding.
5. If none of the above steps has identified a valid problem(s), the brake may need to be replaced.

NOTE: It is desirable to have the Current Feedback Timer set as low as possible without causing nuisance trips.

Fault Code: BE3–Brake Release Fault

Definition

The BE3 fault indicates that the drive has released the brake and commanded the drive to run, but has not detected the expected encoder feedback. A BE3 fault will occur if the pulses received during the BE3 detection time (C08-06) are less than the expected number of pulses (C08-07).

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

Corrective Action

1. Check the brake for proper operation. If the brake does not open the drive will not see the proper number of encoder pulses returned and will post this fault.
2. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive will get erratic pulse signals or no signals at all possibly causing a BE3 fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.
3. If the encoder appears to have no mechanical problems, the encoder cable should be checked for damage and replaced if a problem is found.
 - 3.1 Each of the encoder wires should be checked for continuity.
 - 3.2 The wires should be checked for shorts between any two wires.
 - 3.3 The wires should be checked for shorts to the shield or ground.
 - 3.4 Visually inspect the cable for damage that may be causing intermittent problems.
4. If none of the above steps has identified a valid problem(s), only then should the BE3 detection parameters be adjusted.

NOTE: It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.
5. Ensure that C08-04 is equal to the brake's mechanical delay time.
6. Increase the value of C08-06 to no more than 1 second.
7. Decrease the value of C08-07 to no less than 10 pulses.

Alarm Code: BE6–Brake Proving Alarm

Definition

The BE6 alarm indicates that the drive has commanded the brake to set but it has detected more encoder pulse feedback than expected. A BE6 alarm will occur if the number of pulses received during the BE6 detection time (C08-12) is greater than the expected number of pulses (C08-13). The drive will initiate Load Float for the duration of the BE6 alarm.

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

*NOTE: The BE6-Brake Proving Alarm is re-verified during every brake set, including brake sets that occur after the BE6 alarm is posted. **The BE6 alarm will turn off if a successful brake check occurs after an initial BE6 alarm condition is posted based on the setting of C08-19.***

Corrective Action

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

NOTE: It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.
5. Ensure that C08-11 is equal to the brake's mechanical delay time.
6. Increase the value of C08-13.

Alarm Code: BE8–Brake Slipping Alarm

Definition

The BE8 alarm indicates that the drive has detected that the brake slipping after the brake is set. A BE8 alarm will occur if the drive detects that the load is moving greater than the brake Slip Detection Speed (C08-23) when the brake is set. When this occurs, the drive will go into load float while the brake is set.

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

Corrective Action

1. Check the brake for proper operation and adjustment. If the brake does not set, is improperly adjusted or is excessively worn, it may not be able to hold the load. This will allow the encoder pulses received while the brake is set.
2. Check the encoder cable for damage and proper grounding. Replace it if a problem is found.
 - 2.1 Each of the encoder signals should be checked for excessive noise.
 - 2.2 The shielded encoder cable should be properly grounded.
 - 2.3 Visually inspect the cable for damage that may be causing intermittent problems.
3. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive may get erratic pulse signals possibly causing a BE8 fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.
4. If none of the above steps has identified a valid problem(s), the brake may need to be replaced.

NOTE: It is desirable to have as fast a fault reaction time as possible without causing nuisance trips.

Fault Code: OC–Over Current Fault

Definition

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

Corrective Action

1. Check the motor wiring and the motor itself for a short between phases.
2. Check the alignment of the encoder pulse wheel with the sensor head, or the encoder shaft coupling (depending on the type of encoder used). If the pulse wheel is misaligned or the shaft coupling is loose the drive will get erratic pulse signals or no signals at all possibly causing an OC fault. Repairs to the encoder wheel or shaft coupling should be made immediately before again attempting to operate the hoist.
3. If the encoder appears to have no mechanical problems, the encoder cable should be checked for damage and replaced if a problem is found.
 - 3.1 Each of the encoder wires should be check for continuity.
 - 3.2 The wires should be checked for shorts between any two wires.
 - 3.3 The shield should be check for proper grounding.
 - 3.4 The wires should be checked for shorts to the shield or ground.
 - 3.5 Visually inspect the cable for damage that may be causing intermittent problems.
4. If none of the above steps has identified a valid problem(s), check if any of the torque limit parameters (C07-01 to C07-04) have been changed. If these parameters have been changed to allow a higher torque value, it could cause overcurrent trips.

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

Fault Display and Corrective Actions at Auto-Tuning

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

Table 6-5: Fault Display and Corrective Actions

Fault Display	Fault or Indicator Name/Description	Corrective Action
Er-01 Fault	Motor Data Fault. Motor data input fault for auto-tuning. Relationship between motor output and motor rated current fault. Relationship between input motor rated current and set no-load current fault (at vector control method and line-to-line resistance tuning.)	<ul style="list-style-type: none"> • Check input data. • Check inverter and motor capacity • Check motor rated current and no-load current.
Er-02 Minor Fault	Alarm. The minor fault is detected during auto-tuning.	<ul style="list-style-type: none"> • Check input data. • Check wirings • Check load.
Er-03 STOP Key	STOP Key Input. The stop key is pressed during auto-tuning.	
Er-04 Resistance	Line to Line Resistance Fault. Auto-tuning is not completed within the expected time. The auto-tuning is outside the parameter setting.	<ul style="list-style-type: none"> • Check input data.
Er-05 No-Load Current	No-load Current Fault. Auto-tuning is not completed within the expected time. The auto-tuning is outside the parameter setting.	<ul style="list-style-type: none"> • Check motor wiring. • If a motor and a load are connected, disconnect the motor from machinery system.
Er-08 Rated Slip	Rated Slip Fault. Auto-tuning is not completed within the expected time. The auto-tuning is outside the parameter setting.	
Er-09 Accelerate	Acceleration Fault. The motor did not accelerate at the expected time.	<ul style="list-style-type: none"> • Increase B05-01 (acceleration time). • If C07-01 and C07-02 (torque limit value) are decreased, increase values. • If a motor and a load are connected, separate the motor from the load.
Er-10 Motor Direction	Motor Direction Error. The encoder signal lines are not properly connected to the drive; the motor direction and PG direction are opposite; or the load pulled the motor in the opposite direction of the speed reference and the torque exceeded 100%.	<ul style="list-style-type: none"> • Check and correct wiring to the PG encoder. • Check the motor speed monitor U01-05 while manually turning the motor forward. If the sign displayed is negative, change the setting of parameter F01-02. • Uncouple the motor from the load and restart Auto-Tuning.
Er-11 Motor Speed	Motor Speed Fault (Rotation type tuning only). The motor speed was over 100% at auto-tuning (flux vector control without PG only).	<ul style="list-style-type: none"> • Increase B05-01 (acceleration time). • If a motor and a load are connected, separate the motor from the load.
Er-12 I.det.Circuit	Current Detection Fault. Current exceeded the motor rated current.	<ul style="list-style-type: none"> • Release brake. • Check for open motor lead.
Er-13 Leakage Inductance	Leakage Inductance Fault. Auto-tuning did not finish within the set time.	<ul style="list-style-type: none"> • Check the T1 parameters. • Check motor wiring.

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

Fault Display	Fault or Indicator Name/Description	Corrective Action
End 1* V/f Oversetting	Excess V/f setting (Rotation type tuning only). The torque reference exceeded 100% and no load current exceeded 70%.	<ul style="list-style-type: none"> • Check the T1 parameters. • Disconnect the motor from the load.
End 2 Saturation	Motor Iron Core Saturation Coefficient Fault (Rotation type tuning only). Since the motor iron core saturation coefficient could not be auto-tuned within the set time, tentative value is set in the iron core saturation coefficient.	<ul style="list-style-type: none"> • Check the T1 parameters. • Check motor wiring. • Disconnect the motor from the load
End 3 Rated FLA Alm	Rated Current Set Alarm. Motor current during tuning was greater than the set value.	<ul style="list-style-type: none"> • Check E02-01.
End 4	Adjusted Slip Calculation Error. The slip that was calculated is outside the allowable range.	<ul style="list-style-type: none"> • Make sure the data entered for Auto-Tuning is correct. • Execute Rotational Auto-Tuning instead. If not possible, try Stationary Auto-Tuning 2.
End 5	Resistance Tuning Error. The resistance value that was calculated is outside the allowable range.	<ul style="list-style-type: none"> • Double check the data that was entered for the Auto-Tuning process. • Check the motor and motor cable connection for faults.
End 6	Leakage Inductance Alarm. The leakage inductance value that was calculated is outside the allowable range.	<ul style="list-style-type: none"> • Double check the data that was entered for the Auto-Tuning process.
End 7	No-Load Current Alarm. The entered no-load current value was outside the allowable range, or Auto-Tuning results were less than 5% of the motor current.	<ul style="list-style-type: none"> • Check and correct faulty motor wiring. • Double check the data that was entered for the Auto-Tuning process.

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

Troubleshooting Option Card Related Faults

Drive-Side Error Codes

Table 6-6 lists the various fault codes related to option cards. Check the following items first when an error code occurs on the drive:

- Communication cable connections.
- Make sure the option is properly installed to the drive.
- Did a momentary power loss interrupt communications?

NOTE: The ports are checked in alphanumeric order. Please see Figure 6-1 for port locations.

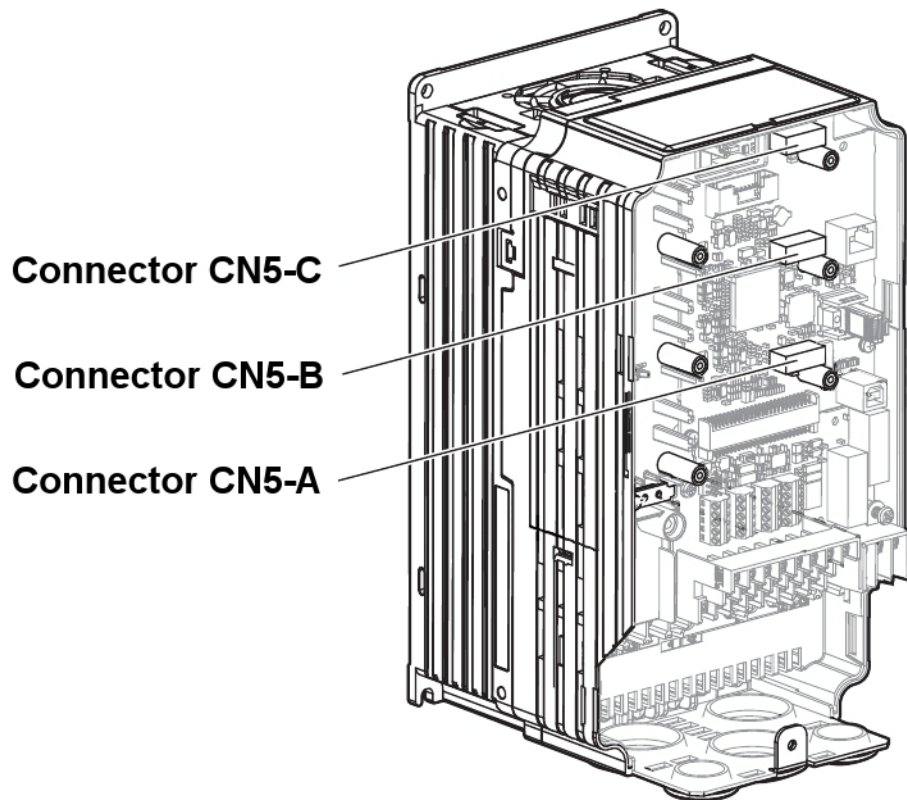


Figure 6-1: Option Card Ports

Table 6-6: Fault Codes for Option Cards

Error	Card	Fault or Indicator Name/Description	Cause	Possible Solution
oFA00	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option Card Connection Error at Option Port CN5-A.	<ul style="list-style-type: none"> The option card installed into port CN5-A is incompatible with the drive. A PG option card is connected to option port CN5-A. 	<ul style="list-style-type: none"> Check if the drive supports the option card to be installed. Contact Magnetek for assistance. PG option cards are supported by option ports CN5-B and CN5-C only. Connect the PG option card to the correct option port.
oFA01	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option Fault (CN5-A). Option is not properly connected.	<ul style="list-style-type: none"> Option at drive port CN5-A was changed during run. 	<ul style="list-style-type: none"> Turn the power off and check the connectors between the drive and the option.
oFB01	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option Fault (CN5-B). Option is not properly connected.	<ul style="list-style-type: none"> Option at drive port CN5-B was changed during run. 	<ul style="list-style-type: none"> Turn the power off and check the connectors between the drive and the option.
oFB02	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option Fault (CN5-B). Two of the same option cards are connected simultaneously.	<ul style="list-style-type: none"> AI-A3: AI-A3 option connected to CN5-B port while another input option was connected to CN5-A port. DI-A3: DI-A3 option connected to CN5-B port while another input option was connected to CN5-A port. AO-A3/DO-A3: Duplicate type of option card is connected to drive ports CN5-A, CN5-B, and CN5-C. 	<ul style="list-style-type: none"> AI-A3: Only one of the options, AI-A3, DI-A3, or SI-xx can be connected to the drive at the same time. DI-A3: Only one of the options, AI-A3, DI-A3, or SI-xx can be connected to the drive at the same time. AO-A3/DO-A3: Use only compatible options.
oFC00	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option connection error at drive port CN5-C.	<ul style="list-style-type: none"> The option card installed into port CN5-C is incompatible with the drive A communication option card has been installed in option port CN5-C 	<ul style="list-style-type: none"> Confirm that the drive supports the option card to be installed. Contact Magnetek for assistance. Communication option cards are only supported by option port CN5-A. It is not possible to install more than one communication option.

Error	Card	Fault or Indicator Name/Description	Cause	Possible Solution
oFC01	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option connection error at drive port CN5-C.	<ul style="list-style-type: none"> Option at drive port CN5-C was changed during run. 	<ul style="list-style-type: none"> Turn off the power and check the connectors between the drive and the option.
oFC02	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option Fault (CN5-C). Two of the same option cards are connected simultaneously.	<ul style="list-style-type: none"> AI-A3: AI-A3 option connected to CN5-B port while another input option was connected to CN5-A port. DI-A3: DI-A3 option connected to CN5-B port while another input option was connected to CN5-A port. AO-A3/DO-A3: Duplicate type of option card is connected to drive ports CN5-A, CN5-B, and CN5-C. 	<ul style="list-style-type: none"> AI-A3: Only one of the options, AI-A3, DI-A3, or SI-xx can be connected to the drive at the same time. DI-A3: Only one of the options, AI-A3, DI-A3, or SI-xx can be connected to the drive at the same time. AO-A3/DO-A3: Use only compatible options.
oFC03 to oFC11	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option Card Fault at Option Port CN5-C.	<ul style="list-style-type: none"> Option card or hardware is damaged. 	<ul style="list-style-type: none"> Cycle power to the drive If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board.
oFC12 to oFC17	A1-A3 AO-A3 DI-A3 DO-A3 S4I S4IO	Option Card Fault at Option Port CN5-C.	<ul style="list-style-type: none"> Option card or hardware is damaged. 	<ul style="list-style-type: none"> Cycle power to the drive If the problem continues, replace the control board or the entire drive. Contact Magnetek for instructions on replacing the control board.
oPE05	A1-A3 DI-A3 S4I S4IO	Run command/frequency reference source selection error.	<ul style="list-style-type: none"> Frequency reference is assigned to an option (B03-01 = 3), but an option is not connected. 	<ul style="list-style-type: none"> Reconnect the option to the drive.
oPE06	--	Control Method Selection Error	<ul style="list-style-type: none"> A control mode has been selected that requires a PG option card to be installed, but no PG encoder is installed (A01-02 = 1 or 3). 	<ul style="list-style-type: none"> Connect to a PG option card. Correct the value set to A01-02.

Error	Card	Fault or Indicator Name/Description	Cause	Possible Solution
oPE07	A1-A3	Multi-function Analog Input Selection Error.	<ul style="list-style-type: none"> At least two analog input terminals are set to the same function. Analog input terminal and pulse train input are set to the same function. 	<ul style="list-style-type: none"> Adjust H03-02, H03-06, and H03-10 settings so functions no longer conflict.

Copy Function Related Faults

Tasks, Errors, and Troubleshooting

The table below lists the messages and errors that may appear when using the Copy function.

When executing the tasks offered by the Copy function, the operator will indicate the task being performed. When an error occurs, a code appears on the operator to indicate the error. Note that errors related to the Copy function do not trigger a multifunction output terminal that has been set up to close when a fault or alarm occurs. To clear an error, simply press any key on the operator and the error display will disappear.

Table 6-7 lists the corrective action that can be taken when an error occurs.

NOTE:

- Whenever using the copy function, the drive should be fully stopped.
- The drive will not accept a Run command while the Copy function is being executed.
- Parameters can only be saved to a drive when the voltage class, capacity, control method, and software version match.

Table 6-7: Copy Function Task and Error Displays

Fault Display	Fault or Indicator Name/Description	Corrective Action
CPEr	Control Method Mismatch. Control method of the parameters to be loaded onto the drive and the control method set to the drive do not match.	<ul style="list-style-type: none"> Verify the control method for the parameters to be loaded onto the drive and the control method on the drive to which those parameters will be written. Set the same control method using parameter A01-02 and retry.
CPyE	Error Writing Data. Failed writing parameters.	Attempt to write parameters again.
CSEr	Copy Unit Error. Hardware fault.	Replace the operator or the USB Copy Unit.
iFEr	Communication Error. <ul style="list-style-type: none"> A communication error occurred between the drive and the operator or the USB copy unit. A non-compatible cable is being used to connect the USB Copy Unit and the drive. 	<ul style="list-style-type: none"> Check the cable connection. Use the cable originally packaged with the USB Copy Unit.

Fault Display	Fault or Indicator Name/Description	Corrective Action
ndAT	<p>Model, Voltage Class, Capacity Mismatch.</p> <ul style="list-style-type: none"> The drive from which the parameters were copied and the drive to which the parameters will be written have different electrical specifications, capacities, are set to different control methods, or are different models. The device being used to write the parameters is blank and does not have any parameters saved on it. 	<ul style="list-style-type: none"> Make sure model numbers and specifications are the same for both drives. Make sure all connections are correct, and copy the parameter settings onto the USB Copy Unit or the operator.
rdEr	<p>Error Reading Data. Failed while attempting to read parameter settings from the drive.</p>	<p>Press and hold the READ key on the USB Copy Unit for at least one second to have the unit read parameters from the drive.</p>
vAEr	<p>Voltage Class, Capacity Mismatch. The drive from which the parameters were copied and the drive on which the Verify mode is being performed have different electrical specifications or are a different capacity.</p>	<p>Make sure electrical specifications and capacities are the same for both drives.</p>
vFyE	<p>Parameter settings in the drive and those saved to the copy function are not the same. Indicates that parameter settings that have been Read and loaded onto the Copy Unit or Digital Operator are different.</p>	<p>To synchronize parameters, either write the parameters saved on the USB Copy Unit or digital operator onto the drive, or Read the parameter settings on the drive onto the USB Copy Unit.</p>

Power Section Check



WARNING

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

Power Off Checks

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

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

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

1. “+” could be any one of three (+) terminals which are labeled as Ⓣ1, Ⓣ2, and Ⓣ3.

2. If the bus fuse is blown you must install a jumper across the fuse terminals to get accurate resistance measurements.

3. If the pre-charge resistor is open, you will read infinite W between + and any output terminal unless you install a temporary jumper across the resistor.

S4IF Replacement Procedure



WARNING

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

NOTE: When handling boards always use electrostatic discharge protection. Keep the boards in the ESD bag as long as you can. Do not lay the board on any surfaces without ESD protection. When handling, always hold the board from the edges and do not touch the components. Installation should be performed only by qualified personnel who are familiar with this type of equipment and the hazards involved.

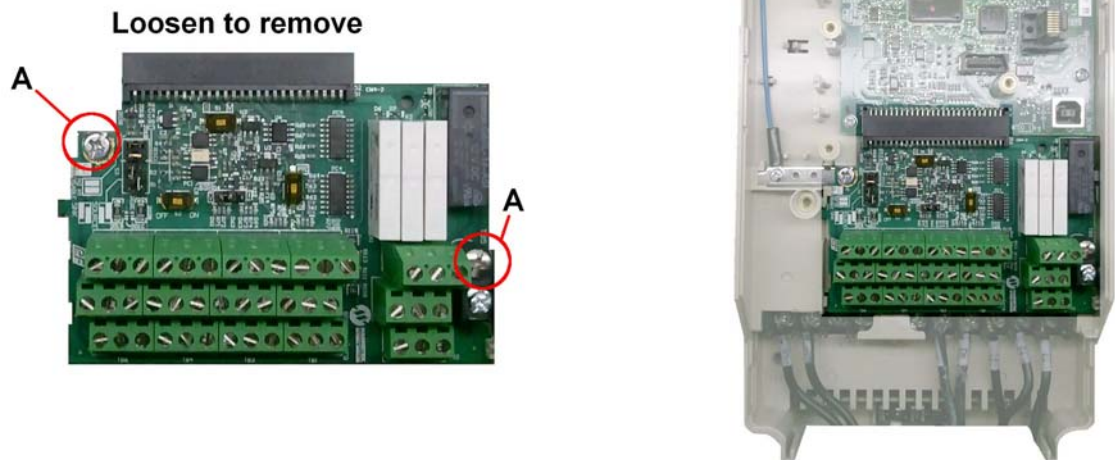


Figure 6-2: Location of Retaining Screws

1. Prior to installation, record all modified parameters.
2. Set A01-05 = 7770 (this prepares all modified and user parameters for IF card removal).
3. Disconnect all electrical power to the drive.
4. Remove the drive's front cover.
5. Verify that the "CHARGE" indicator lamp inside the drive is OFF (may take up to 5 minutes).
6. Use a voltmeter to verify the voltage at the incoming power terminals (L1, L2, and L3) has been disconnected.
7. Follow your local ESD procedures.

8. Loosen the two retaining screws (A) pictured in Figure 6-2.
 9. Remove existing interface card by grasping each corner at TB6 and TB5 and slide down until free.
 10. Return I/O board to ESD bag
 11. Complete all main circuit terminal connections as the installation of the S4IF interface card may block wiring access.
- NOTE: Wires to the S4IF interface card should be stripped 0.2" ±20% for maximum system safety. Solder dipping or ferrules are also highly recommended.*
12. Insert the S4IF interface card by sliding it onto the side guides until it mates tightly into the CN4-1 connector.
 13. Tighten the screws (A) pictured in Figure 6-2.
 14. Connect the command signals to the desired inputs of the S4IF interface card.
 15. Refer to Table 3-8 for additional information regarding the S1, S2, S3, and S4 settings.
 16. Reinstall and secure the drive's front cover.
 17. Reconnect power to the drive.
 18. Set A01-05 = 8880 (this moves all modified and user parameters to new IF card).
 19. Verify modified parameters with those recorded in Step 1.

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

**IMPULSE[®]•G+ & VG+
Series 4 Parameter Listing**

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IMPULSE®•G+ & VG+ Series 4 Parameter Listing

Parameter	Parameter Name	Default	Range	Units	Reference
A01-01	Access Level	2	0–2	--	4-9
A01-02	Control Method	3	0, 2, 3	--	4-9
A01-03	Motion	G+: 1 VG+: 2	0–2, 4	--	4-10
A01-04	Speed Reference	*	0–8	--	4-10
A01-05	Init Parameters	0	0–8880	--	4-15
A01-06	Enter Password 1	0	--	--	4-15
A02-01 to A02-32	User Parameters	--	--	--	4-16
B01-01	Reference 1	15.00*	0.00–E1-04	Hz	5-3
B01-02	Reference 2	30.00*	0.00–E1-04	Hz	5-3
B01-03	Reference 3	60.00*	0.00–E1-04	Hz	5-3
B01-04	Reference 4	0.00*	0.00–E1-04	Hz	5-3
B01-05	Reference 5	0.00*	0.00–E1-04	Hz	5-3
B01-06	Reference 6	0.00*	0.00–E1-04	Hz	5-3
B01-07	Reference 7	0.00*	0.00–E1-04	Hz	5-3
B01-08	Reference 8	0.00*	0.00–E1-04	Hz	5-3
B01-09	Reference 9	0.00*	0.00–E1-04	Hz	5-3
B01-10	Reference 10	0.00*	0.00–E1-04	Hz	5-3
B01-11	Reference 11	0.00*	0.00–E1-04	Hz	5-3
B01-12	Reference 12	0.00*	0.00–E1-04	Hz	5-3
B01-13	Reference 13	0.00*	0.00–E1-04	Hz	5-3
B01-14	Reference 14	0.00*	0.00–E1-04	Hz	5-3
B01-15	Reference 15	0.00*	0.00–E1-04	Hz	5-3
B01-16	Reference 16	0.00*	0.00–E1-04	Hz	5-3
B01-17	Jog Reference	6.00	0.00–E1-04	Hz	5-3
B01-18	Ref Priority	0*	0–2	--	5-3
B02-01	Ref Upper Limit	100.0*	0.0–110.0	%	5-5
B02-02	Ref Lower Limit	0.0	0.0–110.0	%	5-5
B02-03	Ref1 Lower Limit	2.0*	0.0–110.0	%	5-5
B02-04	Alt Upper Limit	0.0	0.0–110.0	%	5-5
B03-01	Ref Source 1	1*	0–4	--	5-6
B03-02	Run Source 1	1*	0–3	--	5-6
B03-03	Stopping Method	G+: 0* VG+: 6*	0, 1, 4, 6	--	5-7
B03-04	Change Rotation	0	0, 1	--	5-9
B03-05	Zero-Speed Oper	0	0–3	--	5-9
B03-06	Cntl Input Scans	1	0, 1	--	5-9

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
B03-07	LO/RE RUN Sel	0	0, 1	--	5-10
B03-08	RUN CMD at PRG	0	0, 1	--	5-10
B03-10	AllowRun@PowerUp	0	0, 1	--	5-10
B03-15	Ref Source 2	0	0-4	--	5-10
B03-16	Run Source 2	0	0-3	--	5-11
B03-21	PG Start Sel	0	0, 1	--	5-11
B05-01	Accel Time 1	5.0*	0.0-25.5****	sec	5-12
B05-02	Decel Time 1	3.0*	0.0-25.5****	sec	5-12
B05-03	Accel Time 2	10.0	0.0-25.5****	sec	5-12
B05-04	Decel Time 2	10.0	0.0-25.5****	sec	5-12
B05-05	Acc Time N Chg	2.0	0.0-25.5	sec	5-13
B05-06	Dec Time N Chg	2.0	0.0-25.5	sec	5-13
B05-08	Fast Stop Time	0.5	0.0-25.5	sec	5-13
B05-10	Acc/Dec SW Freq	0.0	0.0-150.0	Hz	5-13
B05-11	SW Freq. Compare	1	0, 1	--	5-13
B05-12	Accel Time 3	3.0	0.0-25.5****	sec	5-13
B05-13	Decel Time 3	3.0	0.0-25.5****	sec	5-13
B05-14	Accel Time 4	3.0	0.0-25.5****	sec	5-13
B05-15	Decel Time 4	3.0	0.0-25.5****	sec	5-13
B05-16	Acc/Dec Ext Rang	0	0, 1	--	5-13
B08-01	Jump Freq 1	0.0	0.0-150.0	Hz	5-13
B08-02	Jump Freq 2	0.0	0.0-150.0	Hz	5-13
B08-03	Jump Freq 3	0.0	0.0-150.0	Hz	5-13
B08-04	Jump Bandwidth	1.0	0.0-20.0	Hz	5-13
B09-03	Field Forcing Selection	0	0, 1	--	5-14
B09-06	Field Forcing Limit	200	100-400	%	5-14
C01-01	Quick Stop	0*	0, 1	--	5-16
C01-02	Quick Stop Time	1.0	0.0-25.5	sec	5-16
C01-03	Reverse Plug	0	0, 1	--	5-17
C01-04	Rev-Plg Dec Time	2.0	0.0-25.5	sec	5-17
C01-05	Rev-Plg Acc Time	0.0	0.0-25.5	sec	5-17
C02-01	MicroSpd Gain 1	1.00	H: 0.01-1.00 T: 0.01-2.55	--	5-18
C02-02	MicroSpd Gain 2	1.00	H: 0.01-1.00 T: 0.01-2.55	--	5-18
C03-01	UL1 Speed	6.00	0-E01-04	Hz	5-19
C03-02	UL1 Decel Time	1.0	0.0-25.5****	sec	5-19
C03-03	UL2 Stop Time	1.0	0.0-25.5****	sec	5-19
C03-04	LL1 Speed	6.00	0-E01-04	Hz	5-19
C03-05	LL1 Decel Time	1.0	0.0-25.5****	sec	5-19
C03-06	LL2 Stop Time	1.0	0.0-25.5****	sec	5-19

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

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Parameter	Parameter Name	Default	Range	Units	Reference
C03-07	Lmt Stop Method	2*	0–2	--	5-19
C03-08	UL3 Stop Method	4	0–5	--	5-19
C03-09	UL3 Decel Time	1.0	0.0–25.5	sec	5-19
C03-10	Phantom Stop Met	1	0–2	--	5-20
C03-11	Load Share Limit	0	0, 1	--	5-20
C03-12	Klixon Action	0	0, 1	--	5-21
C03-13	Height Measure	250	0–65535	Rev	5-22
C03-14	Hook Height Home	2	0–4	--	5-22
C03-15	Hook Height Out	0	0, 1	--	5-22
C03-16	UL2 Revolutions	0	0–65535	Rev	5-23
C03-17	UL1 Revolutions	0	0–65535	Rev	5-23
C03-18	LL1 Revolutions	0	0–65535	Rev	5-23
C03-19	LL2 Revolutions	0	0–65535	Rev	5-23
C04-01	Load Float Time2	10	0–65535	sec	5-26
C04-02	Load Float Gain	10**	0–100	--	5-26
C05-01	Load Check	0	0, 1, 3, 9	--	5-28
C05-02	LC Alarm Action	4	0–4	--	5-28
C05-03	Holding Time	0.15	0.00–2.55	sec	5-28
C05-04	Testing Time	0.25	0.00–2.55	sec	5-28
C05-05	I/T Margin Acc	5	0–50	%	5-28
C05-07	I/T Margin	5	0–20	%	5-28
C05-08	Alarm Speed	6.0	0.0–30.0	Hz	5-28
C05-09	I/T Level 01	0	0–250	%	5-28
C05-10	I/T Level 02	0	0–250	%	5-28
C05-11	I/T Level 03	0	0–250	%	5-28
C05-12	I/T Level 04	0	0–250	%	5-28
C05-13	I/T Level 05	0	0–250	%	5-29
C05-14	I/T Level 06	0	0–250	%	5-29
C05-15	I/T Level 07	0	0–250	%	5-29
C05-16	I/T Level 08	0	0–250	%	5-29
C05-17	I/T Level 09	0	0–250	%	5-29
C05-18	I/T Level 10	0	0–250	%	5-29
C05-19	I/T Level 11	0	0–250	%	5-29
C05-20	I/T Level 12	0	0–250	%	5-29
C05-21	I/T Level 13	0	0–250	%	5-29
C05-22	I/T Level 14	0	0–250	%	5-29
C05-23	I/T Level 15	0	0–250	%	5-29
C05-24	I/T Level 16	0	0–250	%	5-29
C05-25	LC Integral Time	0.05	0.00–2.55	sec	5-29
C05-26	LC Delay Time	0.25	0.00–2.55	sec	5-29
C05-27	Min I->Fwd Tim	0.0	0.0–25.5	sec	5-29

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

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Parameter	Parameter Name	Default	Range	Units	Reference
C05-28	Dly Trig Freq	30.0	0.0–60.0	Hz	5-29
C06-01	Swift-Lift (V/f and OLV) Ultra-Lift (FLV)	0	0–4	--	5-30
C06-02	SwiftLift FWDSpd (V/f and OLV) UltraLift FWDSpd (FLV)	60.0	0.1–150.0	Hz	5-30
C06-03	SwiftLift REVSpd (V/f and OLV) UltraLift REVSpd (FLV)	60.0	0.1–150.0	Hz	5-30
C06-04	SL FWD Current (V/f) SL FWD Torque (OLV) UL FWD Torque (FLV)	50	0–100	%	5-30
C06-05	SL REV Current (V/f) SL REV Torque (OLV) UL REV Torque (FLV)	30	0–100	%	5-31
C06-06	SL Enabling Spd (V/f and OLV) UL Enabling Spd (FLV)	59.0	0.0–150.0	Hz	5-31
C06-07	SL Delay Time (V/f and OLV) UL Delay Time (FLV)	2.0	0.0–25.5	sec	5-31
C06-08	SFS Acc Gain	1.0	0.1–9.9	--	5-31
C06-10	Mtr Trq Quickset	3	0–5	--	5-31
C06-11	Motor Torque 1	45	1–100	%	5-31
C06-12	Motor Speed 1	90.0	0.0–150.0	Hz	5-31
C06-13	Motor Torque 2	25	1–100	%	5-31
C06-14	Motor Speed 2	120.0	1.0–150.0	Hz	5-31
C06-15	AUL FWD Offset	10	0–100	%	5-31
C06-16	AUL REV Offset	20	0–100	%	5-31
C07-01	Trq Limit FWD	150	0–300	%	5-33
C07-02	Trq Limit REV	150	0–300	%	5-33
C07-03	Trq Lmt FWD Rgn	180	0–300	%	5-33
C07-04	Trq Lmt REV Rgn	180	0–300	%	5-33
C07-05	T-Lim FWD Gain	1.25	0.00–2.55	--	5-34
C07-06	T-Lim REV Gain	1.25	0.00–2.55	--	5-34
C07-07	T-Lim RGN Gain	1.25	0.00–2.55	--	5-34
C07-08	Trq Lim I Time	200	5–10000	ms	5-34
C07-09	Torque Limit Sel	0	0, 1	--	5-34
C07-10	Trav Trq Limiter	0	0, 1	--	5-34
C07-11	Limiter Freq	2.0	0.5–10.0	Hz	5-34
C07-12	Anti-Shock	0	0–2	--	5-36
C07-13	Enabling Freq	6.0	0.0–60.0	Hz	5-36
C07-14	Re-Accel Delay	0.20	0.00–2.55	sec	5-36
C07-15	Torque Delta	10	0–180	%	5-36
C07-16	Detection Time	0.30	0.01–0.50	sec	5-36
C07-17	Smoothing Freq	3.0	0.0–15.0	Hz	5-36

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

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Parameter	Parameter Name	Default	Range	Units	Reference
C07-18	Smoothing Time	1.00	0.00–2.55	sec	5-36
C07-20	Steadying Time	0.20	0.00–0.50	sec	5-36
C07-22	AlarmDisplayTime	4	0–30	sec	5-36
C07-23	No Load Torque	20	0–100	%	5-36
C07-24	Required Torque	75	0–180	%	5-36
C07-25	Detection Method	1	0–2	--	5-36
C08-01	Torque Comp Time	1.00	0.00–2.55	--	5-39
C08-02	IFB OK Time	1.00	0.00–2.55	sec	5-39
C08-03	Min Brk Rel Trq	10	0–300	%	5-39
C08-04	Rollback Timer	0.30	0.00–2.55	sec	5-39
C08-05	Rollback Count	800	0–15000	pulses	5-39
C08-06	BE3/Alt Torq Tim	0.30	0.00–2.55	sec	5-39
C08-07	BE3 Detect Count	10	0–15000	pulses	5-39
C08-08	Alt Rev Trq Lim	25	0–300	%	5-39
C08-09	Zero Speed Level	1.0	0.0–10.0	Hz	5-39
C08-10	Load Float Time	10*	0–65535	sec	5-39
C08-11	Brake Set Delay	0.7	0.0–25.5	sec	5-39
C08-12	BE6 Detect Time	5.0	0.0–25.5	sec	5-39
C08-13	BE6 Max Count	250	0–15000	pulses	5-39
C08-14	Brake Hold Speed	0.0	0.0–25.5	%	5-40
C08-15	Load Float Ext T	10	0–65535	sec	5-40
C08-16	Init FWD Brk Trq	100	10–300	%	5-40
C08-18	BE6 Up Speed Lim	6.0	0.0–150.0	Hz	5-40
C08-19	Brk Slip Reset	0	0, 1	--	5-40
C08-20	BE6 Check Torque	1.0	0.5–20.0	%	5-40
C08-21	Add Mag I Time	0.0	0.0–3.0	sec	5-40
C08-22	Brk Slip Detect	0	0, 1	--	5-40
C08-23	Brk Slip Det Spd	1.0	0–10.0	Hz	5-40
C08-24	Brake Test Torq	1.25* (E02-11*5252)/F01-01	0–65535	flb	5-40
C08-25	Brake Test Speed	6	0–10	Hz	5-40
C08-33	Dual Brake Test	0	0, 1	--	5-40
C08-34	DIR Flt Trq Lvl	20	0–100%	%	5-40
C09-01	Digital In Sel	0	0–2, 5	--	5-43
C09-02	DIO Terminal 1	0	0–FF	--	5-43
C09-03	DIO Terminal 2	0F	0–FF	--	5-43
C09-04	DIO Terminal 3	0F	0–FF	--	5-43
C09-05	DIO Terminal 4	0F	0–FF	--	5-43
C09-06	DIO Terminal 5	0F	0–FF	--	5-43
C09-07	DIO Terminal 6	0F	0–FF	--	5-43
C09-08	DIO Terminal 7	0F	0–FF	--	5-43

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

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**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
C09-09	DIO Terminal 8	0F	0–FF	--	5-43
C09-10	DIO Terminal 9	0F	0–FF	--	5-43
C09-11	DIO Terminal 10	0F	0–FF	--	5-43
C09-12	DIO Terminal 11	0F	0–FF	--	5-43
C09-13	DIO Terminal 12	0F	0–FF	--	5-43
C09-14	DIO Terminal 13	0F	0–FF	--	5-43
C09-15	DIO Terminal 14	0F	0–FF	--	5-43
C09-16	DIO Terminal 15	0F	0–FF	--	5-43
C09-17	DIO Terminal 16	0F	0–FF	--	5-43
C10-01	Load Weight	0	0–2	--	5-44
C10-02	LW Start	0	0, 1	--	5-44
C10-03	LW Display Hold	0	0, 1	--	5-44
C10-04	LW Conversion	0	0–39999	--	5-44
C10-05	Test Freq	6	0–E01-04	Hz	5-44
C10-06	Unit Displayed	4	0–4	--	5-44
C10-07	Holding Time	1.00	0.00–2.55	sec	5-44
C10-09	Full Load Torque	100.0	0.0–200.0	%	5-44
C10-10	No Load Torque	20.0	0.0–200.0	%	5-44
C11-01	Slack Cable	0	0–2	--	5-46
C11-02	Action at SLC	2	0–2	--	5-46
C11-03	SLC Detect Torq	30	-50–100	%	5-47
C11-04	SLC Detect Spd 1	2	0–E01-04	Hz	5-47
C11-05	SLC Delay Time 1	0.50	0.00–2.55	sec	5-47
C11-06	SLC Detect Spd 2	60	0–E01-04	Hz	5-47
C11-07	SLC Delay Time 2	0.10	0.00–2.55	sec	5-47
C11-08	Snap Shaft	0	0, 1	--	5-48
C11-09	Action at Snap	0	0, 1	--	5-48
C11-10	Delta Speed	1.0	0.0–E01-04	Hz	5-48
C11-11	Delay Time	250	0–2000	ms	5-48
C11-12	Gear Ratio Num	10000	1–65535	--	5-48
C11-13	Gear Ratio Den	10000	1–65535	--	5-48
C12-01	Brake Jog Delay	0.0	0.0–100.0	sec	5-49
C12-02	Brake Run Delay	0.0	0.0–100.0	sec	5-49
C12-03	Delay-ON Timer	0.0	0.0–3000.0	sec	5-49
C12-04	Delay-OFF Timer	0.0	0.0–3000.0	sec	5-49
C12-05	Maintenance Tmr	0	0–32767	hr	5-50
C12-06	Maintenance Gain	0.50	0.00–1.00	--	5-50
C12-07	LdShare Flt Time	1.50	0.00–2.55	sec	5-50
C13-01	Inch Run Time	1.00	0.00–2.55	sec	5-51
C13-02	Repeat Delay Tim	1.00	0.00–2.55	sec	5-51
C13-03	Index Run Ref	0.10	0.01–60.00	Hz	5-53

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Parameter	Parameter Name	Default	Range	Units	Reference
C13-04	Index Revs	0	0–65535	Rev	5-53
C13-05	Index Count	100	0–65535	pulses	5-53
C13-06	Index Rpt Delay	0.00	0.00–60.00	sec	5-53
C13-07	Index Complete	10	0–32767	pulses	5-53
C13-08	Index Zsv Gain	10	0–100	--	5-53
C13-09	Index ASR P Gain	30.00	0.00–300.00	--	5-53
C13-10	Index ASR I Time	0.200	0.000–10.000	sec	5-53
C13-11	Acc/Dec Gain	1.0	0.0–5.0	--	5-53
C13-12	Index Brake Ctrl	TRAV: 0–2 NLB: 0, 2	NLB: 2 else: 0	--	5-54
D01-01	DCInj Start Freq	0.5	0.0–10.0	Hz	5-55
D01-02	DCInj Current	50	0–100	%	5-55
D01-03	DCInj Time@Start	0.00	0.00–10.00	sec	5-55
D01-04	DCInj Time@Stop	0.05	0.00–10.00	sec	5-55
D02-01	Slip Comp Gain	V/f: 0.0 OLV: 1.0 FLV: 1.0	0.0–2.5	--	5-56
D02-02	Slip Comp Time	V/f: 2000 OLV: 200	0–10000	ms	5-56
D02-03	Slip Comp Limit	200	0–250	%	5-56
D02-04	Slip Comp Regen	0	0–2	--	5-56
D02-05	Output V Lim Sel	0	0, 1	--	5-56
D02-13	Output V Lim Sta	85.0	70.0–90.0	%	5-56
D02-14	Output V Lim Max	90.0	85.0–100.0	%	5-56
D02-15	Output V Lim Lev	90.0	30.0–100.0	%	5-56
D03-01	Torq Comp Gain	1.0	0.00–2.50	--	5-57
D03-02	Torq Comp Time	V/f: 200 OLV: 20	0–60000	ms	5-57
D03-03	F TorqCmp@start	0.0	0.0–200.0	%	5-57
D03-04	R TorqCmp@start	0.0	-200.0–0.0	%	5-57
D03-05	TorqCmp Delay T	10	0–200	ms	5-57
D03-06	Start Torq Time	150	0–10000	ms	5-57
D04-01	ASR P Gain 1	20.00	0.00–300.00	--	5-59
D04-02	ASR I Time 1	0.500	0.000–10.000	sec	5-59
D04-03	ASR P Gain 2	20.00	0.00–300.00	--	5-59
D04-04	ASR I Time 2	0.500	0.000–10.000	sec	5-59
D04-06	ASR Delay Time	0.004	0.000–0.500	sec	5-59
D04-07	ASR Gain SW Freq	0.0	0.0–150.0	Hz	5-59
D04-08	ASR I Limit	400	0–400	%	5-59
D04-36	NLB Strt ASR I	0.100	0.000–30.000	sec	5-59

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
D04-37	NLB Strt ASR Dly	0.50	0.00–2.55	sec	5-59
D05-01	Torq Control Sel	0	0, 1	--	5-61
D05-02	Torque Ref Filter	0	0–1000	ms	5-61
D05-03	Speed Limit Sel	2	1, 2	--	5-61
D05-04	Speed Lmt Value	105	-120–120	%	5-61
D05-05	Speed Lmt Bias	10	0–120	%	5-61
D05-06	Ref Hold Time	0	0–1000	ms	5-61
D05-08	Drctn SpdLmt Sel	1	0, 1	--	5-61
D08-01	Dwell Ref @ Start	0.0	0.0–150.0	Hz	5-64
D08-02	Dwell Time @ Start	0.0	0.0–10.0	sec	5-64
D08-03	Dwell Ref @ Stop	0.0	0.0–150.0	Hz	5-64
D08-04	Dwell Time @ Stop	0.0	0.0–10.0	sec	5-64
D09-01	SCrv Acc @ Start	0.20*	0.00–10.00	sec	5-65
D09-02	SCrv Acc @ End	0.20*	0.00–10.00	sec	5-65
D09-03	SCrv Dec @ Start	0.20*	0.00–10.00	sec	5-65
D09-04	SCrv Dec @ End	0.20*	0.00–10.00	sec	5-65
D10-01	Heavy/NormalDuty	0	0, 1	--	5-66
D10-02	CarrierFreq Sel	1	1–9, A, F	--	5-66
D10-03	CarrierFreq Max	2.0	1.0–15.0	kHz	5-66
D10-04	CarrierFreq Min	2.0	1.0–15.0	kHz	5-66
D10-05	CarrierFreq Gain	0	0–99	--	5-66
D11-01	Hunt Prev Select	1	0, 1	--	5-67
D11-02	Hunt Prev Gain	1.00	0.00–2.50	--	5-67
D11-03	Hunt Prev Time	10	0–500	ms	5-67
D11-05	REV Hunt Pref Gn	0.00	0.00–2.50	--	5-67
E01-01	Input Voltage	230V: 230 460V: 460 575V: 575	230V: 155–255 460V: 310–510 575V: 446–733	VAC	5-68
E01-03	V/f Selection	*	V/f: 0–9, A–F, FF OLV: F, FF	--	5-70
E01-04	Max Frequency	60.0	40.0–150.0	Hz	5-70
E01-05	Max Voltage	**	230V: 0.0–255.0 460V: 0.0–510.0 575V: 0.0–733.1	VAC	5-70
E01-06	Base Frequency	60.0	0.0–150.0	Hz	5-70
E01-07	Mid Frequency A	Determined by E1-03	0.0–150.0	Hz	5-70

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
E01-08	Mid Voltage A	Determined by E1-03	230V: 0.0–255.0 460V: 0.0–510.0 575V: 0.0–733.1	VAC	5-70
E01-09	Min Frequency	Determined by E1-03	0.0–150.0	Hz	5-70
E01-10	Min Voltage	Determined by E1-03	230V: 0.0–255.0 460V: 0.0–510.0 575V: 0.0–733.1	VAC	5-70
E01-11	Mid Frequency B	0.0	0.0–150.0	Hz	5-70
E01-12	Mid Voltage B	0.0	0.0–733.1	VAC	5-70
E01-13	Base Voltage	0.0	0.0–733.1	VAC	5-70
E02-01	Motor Rated FLA	**	**	A	5-73
E02-02	Motor Rated Slip	**	0.00–20.00	Hz	5-73
E02-03***	No-Load Current	**	0–[(E02-01)-1]	A	5-73
E02-04	Number of Poles	4	2–48	--	5-73
E02-05***	Term Resistance	**	0.000–65.000	Ω	5-73
E02-06***	Leak Inductance	**	0.0–40.0	%	5-73
E02-07***	Saturation Comp1	0.50	0.00–0.50	--	5-73
E02-08***	Saturation Comp2	0.75	E02-07–0.75	--	5-73
E02-09***	Mechanical Loss	0.0	0.0–10.0	%	5-73
E02-10***	Motor Iron Loss	**	0–65535	W	5-73
E02-11	Rated Horsepower	**	0.00–650.00	HP	5-73
E03-02	Stopping Method	1	0, 1	--	5-74
E03-03	Max Frequency	60.0	40.0–150.0	Hz	5-74
E03-04	Max Voltage	**	230V: 0.0–255.0 460V: 0.0–510.0 575V: 0.0–733.1	VAC	5-74
E03-05	Base Frequency	60.0	0.0–150.0	Hz	5-74
E03-06	Mid Frequency A	Determined by E01-03	0.0–150.0	Hz	5-74
E03-07	Mid Voltage A	Determined by E01-03	230V: 0.0–255.0 460V: 0.0–510.0 575V: 0.0–733.1	VAC	5-74
E03-08	Min Frequency	Determined by E01-03	0.0–150.0	Hz	5-74

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
E03-09	Min Voltage	Determined by E01-03	230V: 0.0–255.0 460V: 0.0–510.0 575V: 0.0–733.1	VAC	5-74
E03-10	Mid Frequency B	0.0	0.0–150.0	Hz	5-74
E03-11	Mid Voltage B	0.0	230V: 0.0–255.0 460V: 0.0–510.0 575V: 0.0–733.1	VAC	5-74
E03-12	Base Voltage	0.0	230V: 0.0–255.0 460V: 0.0–510.0 575V: 0.0–733.1	VAC	5-74
F01-01	PG1 Pulses/Rev	1024	0–60000	PPR	5-75
F01-02	PG1 Rotation Sel	0	0, 1	--	5-75
F01-03	PG1 Output Ratio	1	1–132	--	5-75
F01-04	PG1 #Gear Teeth1	0	0–1000	--	5-75
F01-05	PG1 #Gear Teeth2	0	0–1000	--	5-75
F01-06	PGO-1-H	15	0–100	ms	5-75
F01-11	PG2 Pulses/Rev	1024	0–60000	PPR	5-75
F01-12	PG2 Rotation Sel	0	0, 1	--	5-76
F01-13	PG2 #Gear Teeth1	0	0–1000	--	5-76
F01-14	PG2 #Gear Teeth2	0	0–1000	--	5-76
F01-15	PG2 Output Ratio	1	1–132	--	5-76
F01-16	PGO-2-H	15	0–100	ms	5-76
F01-21	PG Fdbk Loss Sel	1	0–3 NLB: 1	--	5-76
F01-22	PGO-1-S Det Time	2.0	0.0–10.0	sec	5-76
F01-23	PG Overspeed Sel	1	0–3 NLB: 1	--	5-76
F01-24	PG Overspd Level	105	0–120	%	5-76
F01-25	PG Overspd Time	0.0	0.0–2.0	sec	5-76
F01-26	PG Deviation Sel	5	Traverse: 0–7 NLB: 5	--	5-77
F01-27	PG Deviate Level	10	0–50	%	5-77
F01-28	PG Deviate Time	0.3	0.0–10.0	sec	5-77
F02-01	AI Function Sel	0	0, 1	--	5-78
F02-02	AI Input Gain	100.0	-999.9–999.9	%	5-78

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
F02-03	AI Input Bias	0.0	-999.9–999.9	%	5-78
F04-01	AO Ch1 Select	102	1–630	--	5-79
F04-02	AO Ch1 Gain	100.0	-999.9–999.9	%	5-79
F04-03	AO Ch2 Select	103	1–630	--	5-79
F04-04	AO Ch2 Gain	50.0	-999.9–999.9	%	5-79
F04-05	AO Ch1 Bias	0.0	-999.9–999.9	%	5-79
F04-06	AO Ch2 Bias	0.0	-999.9–999.9	%	5-79
F04-07	AO Opt Level Ch1	0	0, 1	--	5-79
F04-08	AO Opt Level Ch2	0	0, 1	--	5-79
F05-01	DO Ch1 Select	F	0–148	--	5-80
F05-02	DO Ch2 Select	F	0–148	--	5-80
F05-03	DO Ch3 Select	F	0–148	--	5-80
F05-04	DO Ch4 Select	F	0–148	--	5-80
F05-05	DO Ch5 Select	F	0–148	--	5-80
F05-06	DO Ch6 Select	F	0–148	--	5-80
F05-07	DO Ch7 Select	F	0–148	--	5-80
F05-08	DO Ch8 Select	F	0–148	--	5-80
F05-09	DO Function Sel	2	0–2	--	5-80
F06-01	Comm Bus Flt Sel	1	0–4	--	5-82
F06-02	EF0 Detection	0	0, 1	--	5-82
F06-03	EF0 Fault Action	1	0–4	--	5-82
F06-04	BUS Err Det Time	2.0	0.0–5.0	sec	5-82
F06-06	Torq Ref/Lmt Sel	0	0, 1	--	5-82
F06-07	Fref PrioritySel	0	0, 1	--	5-82
F06-08	Com Prm Init Sel	0	0, 1	--	5-82
F06-30	PB Node Address	0	0–125	--	5-82
F06-31	PB Clear Select	0	0, 1	--	5-83
F06-32	PB Map Select	0	0, 1	--	5-83
F06-35	CO Node Address	0	0–126	--	5-83
F06-36	CO Baud Rate	6	0–8	--	5-83
F06-50	DN MAC Address	64	0–64	--	5-83
F06-51	DN Baud Rate	4	0–4	--	5-83
F06-52	DN PCA Selection	21	0–225	--	5-83
F06-53	DN PPA Selection	71	0–225	--	5-83
F06-54	DN Idle Flt Det	0	0, 1	--	5-83
F06-55	DN BAUD RATE MEM	0	0–2	--	5-84
F06-56	DN Speed Scale	0	-15–15	--	5-84
F06-57	DN Current Scale	0	-15–15	--	5-84

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
F06-58	DN Torque Scale	0	-15–15	--	5-84
F06-59	DN Power Scale	0	-15–15	--	5-84
F06-60	DN Voltage Scale	0	-15–15	--	5-84
F06-61	DN Time Scale	0	-15–15	--	5-84
F06-62	DN Heart Beat	0	0–10	--	5-84
F06-63	DN MAC ID MEM	0	0–63	--	5-84
F07-01	IP Address 1	192	0–255	--	5-84
F07-02	IP Address 2	168	0–255	--	5-84
F07-03	IP Address 3	1	0–255	--	5-84
F07-04	IP Address 4	20	0–255	--	5-84
F07-05	Subnet Mask 1	255	0–255	--	5-84
F07-06	Subnet Mask 2	255	0–255	--	5-84
F07-07	Subnet Mask 3	255	0–255	--	5-84
F07-08	Subnet Mask 4	0	0–255	--	5-84
F07-09	Gateway IP Add 1	192	0–255	--	5-84
F07-10	Gateway IP Add 2	168	0–255	--	5-84
F07-11	Gateway IP Add 3	1	0–255	--	5-84
F07-12	Gateway IP Add 4	1	0–255	--	5-84
F07-13	IP Add Mode Sel	2	0–2	--	5-84
F07-14	Duplex Select	1	0–2	--	5-85
F07-15	Baud Rate	10	10, 100	--	5-85
F07-16	CommLoss Tout	0	0–300	deci-seconds	5-85
F07-17	EN Speed Scale	0	-15–15	--	5-85
F07-18	EN Current Scale	0	-15–15	--	5-85
F07-19	EN Torque Scale	0	-15–15	--	5-85
F07-20	EN Power Scale	0	-15–15	--	5-85
F07-21	EN Voltage Scale	0	-15–15	--	5-85
F07-22	EN Time Scale	0	-15–15	--	5-85
F07-23 to F07-32	DOA116 (1 to 10)	0	Modbus Address 0x- ---	--	5-85
F0733 to F07-42	DOA166 (1 to 10)	0	Modbus Address 0x- ---	--	5-85
H01-01	Term S1 Select	80 (FWD)	0–81	--	5-86
H01-02	Term S2 Select	81 (REV)	0–81	--	5-86
H01-03	Term S3 Select	*	0–81	--	5-86
H01-04	Term S4 Select	*	0–81	--	5-86
H01-05	Term S5 Select	*	0–81	--	5-86
H01-06	Term S6 Select	*	0–81	--	5-86
H01-07	Term S7 Select	*	0–81	--	5-86
H01-08	Term S8 Select	*	0–81	--	5-86

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
H01-09	F1 Key Selection	0F	0F-74	--	5-89
H01-10	F2 Key Selection	0F	0F-74	--	5-89
H01-14	Alt Ref Override	0	0, 1	--	5-86
H02-01	Term M0-M1 Sel	*	0-1FF	--	5-90
H02-02	Term M2-M3 Sel	*	0-1FF	--	5-90
H02-03	Term M5-M6 Sel	*	0-1FF	--	5-90
H02-06	Wh Disp Units	0	0-4	--	5-90
H03-01	Term A1 Signal	*	0, 1	--	5-97
H03-02	Terminal A1 Sel	*	0-31	--	5-97
H03-03	Terminal A1 Gain	100.0	-999.9- 999.9	%	5-97
H03-04	Terminal A1 Bias	0.0	-999.9- 999.9	%	5-97
H03-05	Term A3 Signal	0	0, 1	--	5-97
H03-06	Terminal A3 Sel	*	0-31	--	5-97
H03-07	Terminal A3 Gain	100.0	-999.9- 999.9	%	5-97
H03-08	Terminal A3 Bias	0.0	-999.9- 999.9	%	5-97
H03-09	Term A2 Signal	2	0-3	--	5-97
H03-10	Terminal A2 Sel	1F	0-31	--	5-97
H03-11	Terminal A2 Gain	100.0	-999.9- 999.9	%	5-97
H03-12	Terminal A2 Bias	0.0	-999.9- 999.9	%	5-97
H03-13	Filter Avg Time	0.03	0.00-2.00	sec	5-97
H03-14	A1/A2/A3 Sel	7	1-7	--	5-98
H03-15	TerminalA1Offset	0	-500-500	--	5-98
H03-16	TerminalA2Offset	0	-500-500	--	5-98
H03-17	TerminalA3Offset	0	-500-500	--	5-98
H04-01	Terminal FM Sel	102	000-630	--	5-100
H04-02	Terminal FM Gain	100.0	-999.9- 999.9	%	5-101
H04-03	Terminal FM Bias	0.0	-999.9- 999.9	%	5-101
H04-04	Terminal AM Sel	103	000-630	--	5-101
H04-05	Terminal AM Gain	50.0	-999.9- 999.9	%	5-101
H04-06	Terminal AM Bias	0.0	-999.9- 999.9	%	5-101
H04-07	FM Level Select	0	0-2	--	5-101
H04-08	AM Level Select	0	0-2	--	5-101
H05-01	Serial Comm ADR	1F	00-FF	--	5-102
H05-02	Serial Baud Rate	3	0-8	--	5-102
H05-03	Serial Com Sel	0	0-2	--	5-102

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0-25.5 seconds is extended to 0.0-6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
H05-04	Serial Fault Sel	0	0–3	--	5-102
H05-05	Serial Flt Dtct	1	0, 1	--	5-102
H05-06	Transmit WaitTIM	5	5–65	ms	5-102
H05-07	RTS Control Sel	1	0, 1	--	5-102
H05-09	CE Detect Time	2.0	0.0–10.0	sec	5-102
H05-10	CommReg 25h Unit	0	0, 1	--	5-102
H05-11	Enter CommandSel	1	0, 1	--	5-103
H05-12	Run CommandSel	0	0, 1	--	5-103
H05-17	Busy Enter Sel	0	0, 1	--	5-103
H05-18	MtrSpd Monitor T	0	0–100	ms	5-103
H06-01	Pulse Input Sel	0	0, 5–7	--	5-104
H06-02	Pulse In Scale	1440	1000–32000	Hz	5-104
H06-03	Pulse Input Gain	100.0	0.0–1000.0	%	5-104
H06-04	Pulse Input Bias	0.0	-100.0– 100.0	%	5-104
H06-05	Pulse In Filter	0.10	0.00–2.00	sec	5-104
H06-06	Pulse Output Sel	102	0–120	--	5-104
H06-07	Pulse Out Scale	1440	0–32000	Hz	5-104
H06-08	Pulse Min Freq	0.5	0.1–1000.0	Hz	5-104
H06-09	Pulse Dev Detect	5.0	0.0–25.5	%	5-104
L01-01	Mtr OL Charact	3	0–3	--	5-105
L01-02	MOL Time Const	1.0	0.1–5.0	min	5-105
L01-03	Mtr OH Alarm Sel	3	0–3	--	5-106
L01-04	Mtr OH Fault Sel	1	0–2	--	5-106
L01-05	Mtr Temp Filter	0.20	0.00–10.00	sec	5-106
L01-13	Mtr OL Mem Sel	1	0, 1	--	5-106
L02-01	PwrL Selection	0	0–2	--	5-106
L02-02	PwrL Ridethru t	**	0.0–25.5	sec	5-106
L02-03	PwrL Baseblock t	**	0.1–5.0	sec	5-106
L02-04	PwrL V/F Ramp t	**	0.0–5.0	sec	5-106
L02-05	PUV Det Level	Determined by E1-01	230V: 150– 210 460V: 300– 420 575V: 431– 604	VDC	5-106
L03-01	StallP Accel Sel	1	0–2	--	5-107
L03-02	StallP Accel Lvl	Determined by D10-01	0–150	%	5-107
L03-03	StallPAcc LowLim	50	0–100	%	5-107
L03-05	StallP Run Sel	1	0–2	--	5-107
L03-06	StallP Run Level	Determined by D10-01	30–150	%	5-107
L03-11	OV Inhibit Sel	0	0, 1	--	5-107

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.

Parameter	Parameter Name	Default	Range	Units	Reference
L03-17	DC Bus Reg Level	230 V: 375 460 V: 750 575 V: 930	230 V: 150–400 460 V: 300–800 575 V: 431–1150	VDC	5-107
L03-20	DC Bus P Gain	A01-02	0.00–5.00	--	5-107
L03-21	Acc/Dec P Gain	A01-02	0.10–10.00	sec	5-108
L03-23	CHP Stall P Sel	0	0, 1	--	5-108
L03-24	Mtr Accel Time	O02-04 or E5-01	0.001–10.000	sec	5-108
L04-01	Spd Agree Level	0.0	0.0–150.0	Hz	5-110
L04-02	Spd Agree Width	2.0	0.0–20.0	Hz	5-110
L04-03	Spd Agree Lvl+-	0.0	-150.0–150.0	Hz	5-110
L04-04	Spd Agree Wdth+-	2.0	0.0–20.0	Hz	5-110
L04-05	Ref Loss Sel	0	0, 1	--	5-110
L04-06	Fref at Floss	80.0	0.0–100.0	%	5-110
L04-07	Freq Detect Sel	0	0, 1	--	5-110
L05-01	Test Mode	0	0, 1	--	5-111
L06-01	Torq Det 1 Sel	0	0–8	--	5-112
L06-02	Torq Det 1 Lvl	150	0–300	%	5-113
L06-03	Torq Det 1 Time	0.1	0.0–10.0	sec	5-113
L06-04	Torq Det 2 Sel	0	0–8	--	5-113
L06-05	Torq Det 2 Lvl	150	0–300	%	5-114
L06-06	Torq Det 2 Time	0.1	0.0–10.0	sec	5-114
L06-08	Mech Fatigue Sel	0	0–8	--	5-114
L06-09	MechFat Det Spd	110.0	-110.0–110.0	%	5-114
L06-10	MechFat Det Time	0.1	0.0–10.0	sec	5-114
L06-11	MechFat Det Hour	0	0–65535	--	5-114
L08-02	OH Pre-Alarm Lvl	**	50–150	°C	5-115
L08-03	OH Pre-Alarm Sel	3	0–5	--	5-115
L08-05	Ph Loss In Sel	1	0, 1	--	5-115
L08-07	Ph Loss Out Sel	1	0–2	--	5-115
L08-09	Ground Fault Sel	1	0, 1	--	5-115
L08-10	Fan On/Off Sel	1	0, 1	--	5-115
L08-11	Fan Delay Time	60	0–300	sec	5-115
L08-12	Ambient Temp	40	-10–50	°C	5-115
L08-13	UV3 Detect	1	0, 1	--	5-115
L08-15	OL2 Sel @ L-Spd	0	0, 1	--	5-115
L08-18	Soft CLA Sel	0	0, 1	--	5-116
L08-19	Fc Red dur OHAlm	0.8	0.1–0.9	Hz	5-116
L08-32	MC,FAN Fault Sel	1	0–4	--	5-116

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Parameter	Parameter Name	Default	Range	Units	Reference
L08-35	Installation Sel	**	0-3	--	5-116
L08-38	Fc Reduct dur OL	2**	0-2	--	5-116
L08-40	FC Reduct Time	A01-02	0.00-2.00	sec	5-116
L08-41	High Cur Alm Sel	0	0, 1	--	5-116
L08-55	DB Tr protection	1	0, 1	--	5-117
L09-01	Reset Select	1	0, 1	--	5-118
L09-02	Reset Attempts	3	0-10	--	5-118
L09-03	Reset Time	0.5	0.5-600.0	sec	5-118
L09-04	Reset Latch Sel 1	0001	0000-FFFF	--	5-118
L09-05	Reset Latch Sel 2	E000	0000-FFFF	--	5-118
L09-06	Fit Contact Sel	0	0, 1	--	5-118
L09-07	Fit Latch Sel 1	0000	0000-FFFF	--	5-120
L09-08	Fit Latch Sel 2	0000	0000-FFFF	--	5-120
O01-01	User Monitor Sel	106	104-626	--	5-121
O01-02	Power-On Monitor	3	1-5	--	5-123
O01-03	Display Scaling	A01-02	0-3	--	5-123
O01-04	Display Units	A01-02	0, 1	--	5-123
O01-05	LCD Contrast	3	0-5	--	5-123
O01-10	UserDisp Scaling	6000	1-60000	--	5-123
O01-11	UserDisp Dec Sel	2	0-3	--	5-123
O02-01	LO/RE Key	0	0, 1	--	5-124
O02-02	Oper STOP Key	0	0-2	--	5-124
O02-03	User Default Sel	0	0-2	--	5-124
O02-04	Inverter Model #	**	00-FF	--	5-124
O02-05	Operator M.O.P.	0	0, 1	--	5-126
O02-06	Oper Detection	1	0, 1	--	5-126
O02-07	FWD/REV Sel@PwrUp	0	0, 1	--	5-126
O02-11	Test Mode Sel	0	0, 1	--	5-126
O02-15	Legacy RDSI	0	0, 1	--	5-126
O02-19	ParameterSet Sel	0	0, 1	--	5-126
O03-01	Elapsed Time Set	0	0-9999 x10	hr	5-127
O03-02	Elapsed Time Run	1	0, 1	--	5-127
O03-03	Fan ON Time Set	0	0-9999 x10	hr	5-127
O03-05	BusCap Maint Set	0	0-150	%	5-127
O03-09	IGBT Maint Set	0	0-150	%	5-127
O03-11	Fault Data Init	0	0, 1	--	5-127
O03-12	kWh Monitor Init	0	0, 1	--	5-127
O03-14	Count Hist Clear	0	0-3	--	5-127
O04-01	Copy Function Sel	0	0-3	--	5-128
O04-02	Read Allowable	1	0, 1	--	5-128
O04-07	ChrgCircMaintSet	0	0-150	%	5-128

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Parameter	Parameter Name	Default	Range	Units	Reference
T01-01	Tuning Mode Sel	0	0–2	--	4-17
T01-02	Rated Horsepower	**	--	HP	4-17
T01-03	Rated Voltage	**	--	VAC	4-17
T01-04	Rated Current	**	--	A	4-17
T01-05	Rated Frequency	60.0	--	Hz	4-17
T01-06	Number of Poles	4	--	Poles	4-17
T01-07	Rated Speed	1750	--	RPM	4-17
T01-08	PG Pulses/Rev	1024	--	PPR	4-17
T01-09	No-Load Current	--	--	--	4-18
T01-10	Motor Rated Slip	--	--	--	4-18
U01-01	Frequency Ref	--	--	Hz	5-131
U01-02	Output Freq	--	--	Hz	5-131
U01-03	Output Current	--	--	A	5-131
U01-04	Control Method	--	--	--	5-131
U01-05	Motor Speed	--	--	Hz	5-131
U01-06	Output Voltage	--	--	VAC	5-131
U01-07	DC Bus Voltage	--	--	VDC	5-131
U01-08	Output HP	--	--	HP	5-131
U01-09	Torque Reference	--	--	%	5-131
U01-10	Input Term Sts	--	--	--	5-131
U01-11	Output Term Sts	--	--	--	5-131
U01-12	Int Ctl Sts 1	--	--	--	5-132
U01-14	CPU 1 SW Number	--	--	--	5-132
U01-15	Term A1 Level	--	--	%	5-132
U01-16	Term A2 Level	--	--	%	5-132
U01-17	Term A3 Level	--	--	%	5-132
U01-20	SFS Output	--	--	Hz	5-132
U01-21	AI Opt Ch1 Level	--	--	%	5-132
U01-22	AI Opt Ch2 Level	--	--	%	5-132
U01-23	AI Opt Ch3 Level	--	--	%	5-132
U01-24	Opt Out	--	--	--	5-132
U01-25	Opt In Low	--	--	--	5-132
U01-26	Opt In High	--	--	--	5-132
U01-28	CPU 2 SW Number	--	--	--	5-132
U01-29	Load Weight	--	--	--	5-132
U01-30	SS Delta Speed	--	--	Hz	5-132
U01-34	OPE Error Code	--	--	--	5-132
U01-39	Transmit Error	--	--	--	5-132
U01-44	ASR Out w/o Fil	--	--	%	5-132
U01-50	Hook Height	--	--	%	5-132
U01-51	Motor Revolution	--	--	Revs	5-132

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Parameter	Parameter Name	Default	Range	Units	Reference
U01-52	MaintenanceTimer	--	--	hr	5-133
U01-53	Index Count	--	--	Revs	5-133
U01-54	Term RP Inp Freq	--	--	Hz	5-133
U01-60	PG CH1 Count	--	--	Pulse	5-133
U01-61	PG CH2 Count	--	--	Pulse	5-133
U01-63	PG CH1 Freq	--	--	Hz	5-133
U01-64	PG CH2 Freq	--	--	Hz	5-133
U01-65	PG Output Freq	--	--	Hz	5-133
U01-66	BE6 Pulse Count	--	--	Pulse	5-133
U01-68	LC Zone	--	--	--	5-133
U01-69	LC Margin	--	--	%	5-133
U01-84	NLB State	--	--	--	5-133
U01-85	NLB Rel Trq	--	--	%	5-133
U01-86	Brk Test Trq	--	--	Flb	5-133
U02-01	Current Fault	--	--	--	5-133
U02-02	Last Fault	--	--	--	5-133
U02-03	Frequency Ref	--	--	Hz	5-133
U02-04	Output Freq	--	--	Hz	5-133
U02-05	Output Current	--	--	A	5-133
U02-06	Motor Speed	--	--	Hz	5-133
U02-07	Output Voltage	--	--	VAC	5-133
U02-08	DC Bus Voltage	--	--	VDC	5-133
U02-09	Output HP	--	--	HP	5-133
U02-10	Torque Reference	--	--	%	5-133
U02-11	Input Term Sts	--	--	--	5-133
U02-12	Output Term Sts	--	--	--	5-133
U02-13	Inverter Status	--	--	--	5-133
U02-14	Elapsed Time	--	--	hr	5-133
U02-15	SFS Output	--	--	Hz	5-134
U02-16	Motor Iq Current	--	--	%	5-134
U02-17	Motor Id Current	--	--	%	5-134
U02-20	Actual Fin Temp	--	--	°C	5-134
U02-27	Motor Temp (NTC)	--	--	°C	5-134
U02-28	Fault Axis	--	--	--	5-134
U03-01	Last Fault	--	--	--	5-134
U03-02	Fault Message 2	--	--	--	5-134
U03-03	Fault Message 3	--	--	--	5-134
U03-04	Fault Message 4	--	--	--	5-134
U03-05	Fault Message 5	--	--	--	5-134
U03-06	Fault Message 6	--	--	--	5-134
U03-07	Fault Message 7	--	--	--	5-134

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Parameter	Parameter Name	Default	Range	Units	Reference
U03-08	Fault Message 8	--	--	--	5-134
U03-09	Fault Message 9	--	--	--	5-134
U03-10	Fault Message 10	--	--	--	5-134
U03-11	Elapsed Time 1	--	--	hr	5-134
U03-12	Elapsed Time 2	--	--	hr	5-134
U03-13	Elapsed Time 3	--	--	hr	5-134
U03-14	Elapsed Time 4	--	--	hr	5-134
U03-15	Elapsed Time 5	--	--	hr	5-134
U03-16	Elapsed Time 6	--	--	hr	5-134
U03-17	Elapsed Time 7	--	--	hr	5-134
U03-18	Elapsed Time 8	--	--	hr	5-134
U03-19	Elapsed Time 9	--	--	hr	5-134
U03-20	Elapsed Time 10	--	--	hr	5-134
U03-21	RUN Cmd Counter	--	--	count	5-134
U03-22	U3-21 Rollovers	--	--	count	5-134
U03-23	OL/LC Count	--	--	count	5-134
U04-01	Drv Elapsed Time	--	--	hr	5-135
U04-03	Fan Elapsed Time	--	--	hr	5-135
U04-04	Fan Life Mon	--	--	%	5-135
U04-05	Cap Life Mon	--	--	%	5-135
U04-06	ChgCirc Life Mon	--	--	%	5-135
U04-07	IGBT Life Mon	--	--	%	5-135
U04-08	Heatsink Temp	--	--	°C	5-135
U04-09	LED Oper Check	--	--	--	5-135
U04-10	kWh Lower 4 dig	--	--	kWh	5-135
U04-11	kWh Upper 5 dig	--	--	MWh	5-135
U04-12	CPU Occup Rate	--	--	%	5-135
U04-13	Current PeakHold	--	--	A	5-135
U04-14	Freq@ I PeakHold	--	--	Hz	5-135
U04-16	Motor OL1 Level	--	--	%	5-135
U04-17	Drive OL2 Level	--	--	%	5-135
U04-18	Reference Source	--	--	--	5-135
U04-19	MEMOBUS Freq Ref	--	--	%	5-135
U04-20	Option Freq Ref	--	--	%	5-135
U04-21	Run Cmd Source	--	--	--	5-135
U04-22	MEMOBUS Ref Reg	--	--	--	5-135
U04-23	Option Ref Reg	--	--	--	5-135
U04-32	Motor Temp (NTC)	--	--	--	5-135
U04-37	OH Alarm Axis	--	--	BIN	5-135
U04-38	FAN Alarm Axis	--	--	BIN	5-136
U04-39	VOF Alarm Axis	--	--	BIN	5-136

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Parameter	Parameter Name	Default	Range	Units	Reference
U06-01	Mot SEC Current	--	--	%	5-136
U06-02	Mot EXC Current	--	--	%	5-136
U06-03	ASR Input	--	--	%	5-136
U06-04	ASR Output	--	--	%	5-136
U06-05	Voltage Ref (Vq)	--	--	VAC	5-136
U06-06	Voltage Ref (Vd)	--	--	VAC	5-136
U06-07	ACR(q) Output	--	--	%	5-136
U06-08	ACR(d) Output	--	--	%	5-136
U06-18	PG1 CounterValue	--	--	--	5-136
U06-19	PG2 CounterValue	--	--	--	5-136
U06-22	Zero Servo Pulse	--	--	--	5-136
U06-26	FF Cont Output	--	--	--	5-136

* Initial value set by X-Press Programming (Table 4-6, 4-7, or 4-8 on pages 4-12, 4-13, and 4-14).

** Initial value dependent on drive size, which is determined by O02-04 (kVA Selection).

*** Value is automatically set during auto tuning.

**** 0.0–25.5 seconds is extended to 0.0–6000.0 seconds when B05-16 = 1.