Oriental motor

HM-60372-2

αSTEP AZ Series/ Motorized Actuator equipped with AZ Series

EtherNet/IP™ Compatible Driver

USER MANUAL

- **AC power input type**

- **DC power input type**

Thank you for purchasing an Oriental Motor product.
This Manual describes product handling procedures and safety precautions.
- Please read it thoroughly to ensure safe operation.
- Always keep the manual where it is readily available.

1 Introduction

2 AC power input type

3 DC power input type

4 Implicit communication

5 Parameter ID lists

6 Troubleshooting

7 Reference materials

1 Introduction

This part explains the product overview and safety precautions in addition to the types and descriptions about operating manuals.

◆Table of contents

1 Before using the product

Only qualified personnel of electrical and mechanical engineering should work with the product.
Use the product correctly after thoroughly reading the section "4 Safety precautions" on p.12. In addition, be sure to observe the contents described in warning, caution, and note in this manual.
The product described in this manual has been designed and manufactured to be incorporated in general industrial equipment. Do not use for any other purpose. Oriental Motor Co., Ltd. is not responsible for any compensation for damage caused through failure to observe this warning.

2 Operating manuals

2-1 Related operating manuals

For operating manuals not included with the product, contact your nearest Oriental Motor sales office or download from Oriental Motor Website Download Page.

Operating manual name	Included or not included with product
AZ Series OPERATING MANUAL Motor	Included
AZ Series/ /Motorized Actuator equipped with **AZ** Series EtherNet/IP™ Compatible Driver OPERATING MANUAL Driver	Included
AZ Series/ /Motorized Actuator equipped with **AZ** Series EtherNet/IP™ Compatible Driver USER MANUAL (this document)	Not included
AZ Series/Motorized Actuator equipped with **AZ** Series OPERATING MANUAL Function Edition	Not included
APPENDIX UL Standards for **AZ** Series	*

* It is included with motors that conform to the UL Standards.

When using a motorized actuator, also read the following operating manuals.

Operating manual name	Included or not included with product
OPERATING MANUAL Actuator	Included
Motorized Actuator Function Setting Edition	Not included

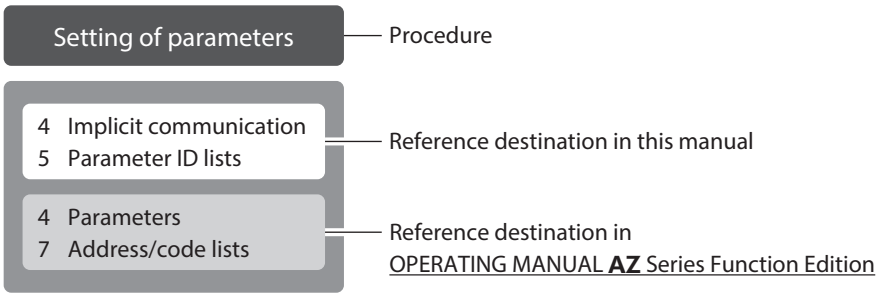
2-2 How to use operating manuals

To use the product, read this manual together with the OPERATING MANUAL **AZ** Series Function Edition.
This manual describes contents specific to the EtherNet/IP compatible driver, and the OPERATING MANUAL **AZ** Series Function Edition describes contents common to the **AZ** Series products. Refer to the OPERATING MANUAL **AZ** Series Function Edition for the contents not included in this manual.
For each control method, reference destinations are indicated according to the flow of use.

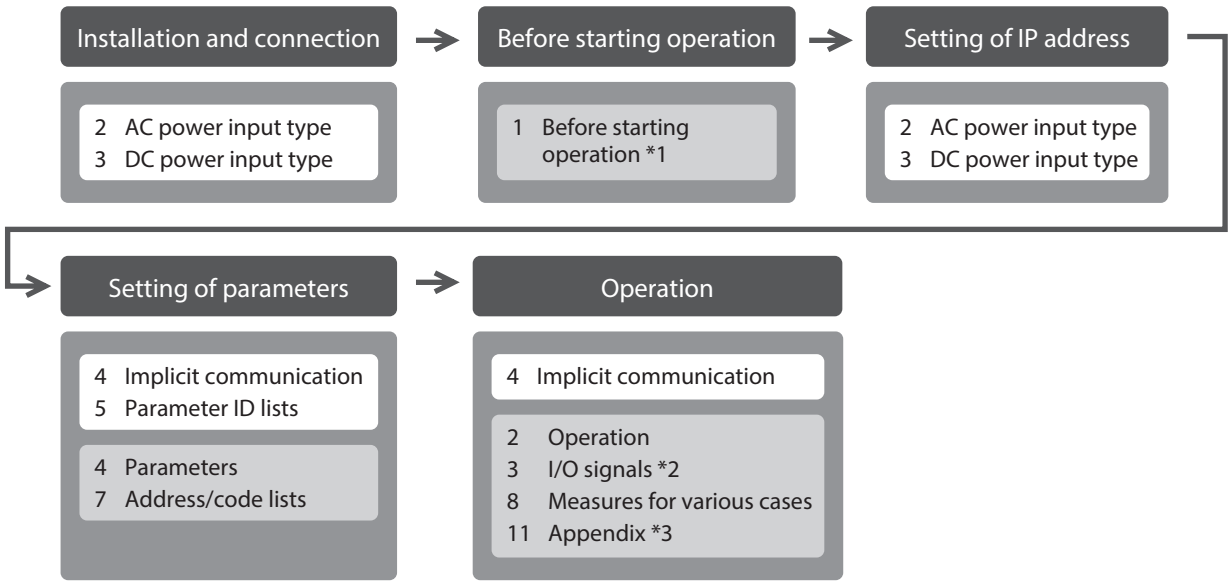
■ How to read reference destinations

The title name of the operating manual is described in the reference destination.

memo The title number described in the reference destination may be changed. Use the title name when checking the reference destination.



■ When controlling via EtherNet/IP

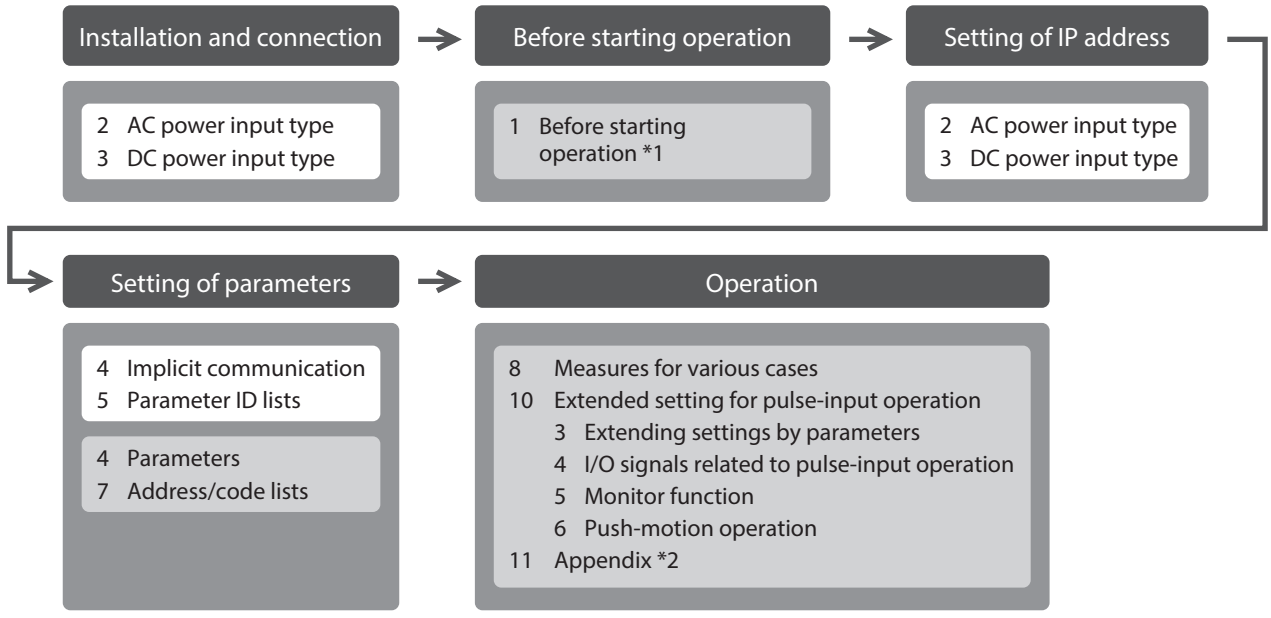


*1 When a motorized actuator is used, the following contents cannot be operated via EtherNet/IP. Use the support software **MEXE02**.
- Copying the fixed value (parameter) of the ABZO sensor to a driver
- Creation of recovery data file and method of recovery

*2 Refer to this manual for "power removable function."
- When the AC power input driver is used: p.40
- When the DC power input driver is used: p.71

*3 Refer to this manual for "LEDs of the driver."
- When the AC power input driver is used: p.22
- When the DC power input driver is used: p.54

■ When controlling by inputting pulse signals



*1 When a motorized actuator is used, the following contents cannot be operated via EtherNet/IP. Use the support software **MEXE02**.
- Copying the fixed value (parameter) of the ABZO sensor to a driver
- Creation of recovery data file and method of recovery

*2 Refer to this manual for "LEDs of the driver."
- When the AC power input driver is used: p.22
- When the DC power input driver is used: p.54

3 Overview of the product

The **AZ** Series EtherNet/IP compatible driver is the dedicated driver for the **AZ** Series products.

■ Lineup

Two types of the **AZ** Series EtherNet/IP compatible drivers are available: AC power input type and DC power input type.

■ Two types of control methods

- **Operation by Implicit communication (periodic communication) of EtherNet/IP**
- **Operation by inputting pulses**

■ Setting methods of operation data and parameters

Operation data and parameters can be set via EtherNet/IP or using the **MEXE02**.
This manual describes how to set operation data and parameters via EtherNet/IP.

■ Equipped with direct data operation function

The direct data operation is a function to start operation at the same time as rewriting of the data. It can be used when the setting of the operation data is changed frequently, such as changing the speed or travel amount according to a load.

■ Equipped with power removable function (ETO function: External torque off)

The power removable function is a function that stops supplying the power to the motor forcibly and puts the motor into a non-excitation state. This function can shut off the power supplying to the motor directly on the circuit.
It can be used for the purpose to protect a worker from malfunction of the moving part when a load is set to the jig of equipment or maintenance of the equipment is performed.

■ Providing the EDS file

The EDS file (Electronic Data Sheets file) is a file that describes the specific information of the EtherNet/IP compatible products. By importing the EDS file to the setting tool of the scanner, settings of EtherNet/IP can be performed before you receive the driver.
For details, contact your nearest Oriental Motor sales office.

4 Safety precautions

The precautions described below are intended to ensure the safe and correct use of the product, and to prevent the user and other personnel from exposure to the risk of injury. Use the product only after carefully reading and fully understanding these instructions.

⚠WARNING	Handling the product without observing the instructions that accompany a "WARNING" symbol may result in serious injury or death.
⚠CAUTION	Handling the product without observing the instructions that accompany a "CAUTION" symbol may result in injury or property damage.
Note	The items under this heading contain important handling instructions that the user should observe to ensure the safe use of the product.
memo	The items under this heading contain related information and contents to gain a further understanding of the text in this manual.

⚠WARNING

■ Common to AC power input driver and DC power input driver

General

- Do not use the product in explosive or corrosive environments, in the presence of flammable gases, locations subjected to splashing water, or near combustibles. Doing so may result in fire, electric shock or injury.
- Assign qualified personnel to the task of installing, wiring, operating/controlling, inspecting, and troubleshooting the product. Failure to do so may result in fire, electric shock, injury, or damage to equipment.
- Do not transport, install, connect or inspect the driver while the power is supplied. Doing so may result in electric shock.
- Do not touch the driver while the power is on. Doing so may result in fire or electric shock.
- Take measures to keep the moving part in position if the product is used in vertical operations such as elevating equipment. Failure to do so may result in injury or damage to equipment.
- When an alarm is generated in the driver (any of the driver's protective functions is triggered), remove the cause before clearing the alarm (protective function). Continuing the operation without removing the cause of the problem may cause malfunction of the motor and the driver, leading to injury or damage to equipment.

Installation

- Install the driver inside an enclosure. Failure to do so may result in electric shock or injury.
- The driver is Class I equipment. When installing the driver, install it inside an enclosure so that it is out of the direct reach of users. Be sure to ground if users can touch it. Failure to do so may result in electric shock.

Connection

- Always keep the power supply voltage of the driver within the specified range. Failure to do so may result in fire or electric shock.
- Connect the product securely according to the wiring diagram. Failure to do so may result in fire or electric shock.
- Do not forcibly bend, pull, or pinch the cable. Doing so may result in fire or electric shock.

Operation

- Turn off the main power supply and the control power supply in the event of a power failure. Failure to do so may result in injury or damage to equipment.
- Do not remove the motor excitation during operation. Doing so may result in the motor to stop and lose the holding force, resulting in injury or damage to equipment.

Repair, disassembly, and modification

- Do not disassemble or modify the driver. Doing so may result in injury or damage to equipment.

■ AC power input driver

General

- Do not touch the terminals indicated ⚠1 ⚠2 signs on the driver's front panel while the power is supplied because high voltage is applied. Doing so may result in fire or electric shock.

Inspection and maintenance

- Do not touch the connection terminals of the driver immediately after turning off the main power supply and the control power supply. Before performing connection or inspection, turn off the main power supply and the control power supply, and check the CHARGE LED has been turned off. Residual voltage may cause electric shock.

⚠CAUTION

■ Common to AC power input driver and DC power input driver

General

- Do not use the driver beyond its specifications. Doing so may result in electric shock, injury, or damage to equipment.
- Keep your fingers and objects out of the openings in the driver. Doing so may result in fire, electrical shock, or injury.
- Do not touch the driver during operation or immediately after stopping. Doing so may result in a skin burn(s).
- Do not forcibly bend or pull the cable that is connected to the driver. Doing so may result in damage.

Installation

- Keep the area around the driver free of combustible materials. Failure to do so may result in fire or a skin burn(s).
- Do not leave anything around the driver that would obstruct ventilation. Doing so may result in damage to equipment.

Operation

- Use a motor and a driver only in the specified combination. An incorrect combination may cause a fire.
- Provide an emergency stop device or emergency stop circuit externally so that the entire equipment will operate safely in the event of a system failure or malfunction. Failure to do so may result in injury.
- Before turning on the main power supply and the control power supply, turn all input signals to the driver to OFF. Failure to do so may result in injury or damage to equipment.
- Before rotating the motor output shaft manually (manual positioning etc.), check the FREE input of the driver is being ON. Failure to do so may result in injury.
- When an abnormal condition has occurred, immediately stop operation to turn off the main power supply and the control power supply. Failure to do so may result in fire, electrical shock or injury.
- Take measures against static electricity when operating the switches of the driver. Failure to do so may result in the driver malfunction or damage to equipment.

■ AC power input driver

Operation

- For the control power supply, use a DC power supply with reinforced insulation on its primary and secondary sides. Failure to do so may result in electric shock.

Inspection and maintenance

- Do not touch the terminals while conducting the insulation resistance measurement or dielectric strength test. Doing so may result in electric shock.

■ DC power input driver

Operation

- For the main power supply and the control power supply, use a DC power supply with reinforced insulation on its primary and secondary sides. Failure to do so may result in electric shock.

Inspection and maintenance

- Do not touch the terminals while conducting the insulation resistance measurement. Doing so may result in electric shock.

4-1 Graphical symbols on the driver's front panel

	⚠WARNING	This is the Protective Earth Terminal. Be sure to ground because improper grounding may result in electric shock.
	⚠WARNING	A high voltage is applied to the motor connector (CN3) and the main power supply input terminals (CN4). Do not touch them while the power is supplied. Doing so may result in fire or electric shock. (AC power input driver)

4-2 Warning indication (AC power input driver)

A warning about handling precautions is described on the driver. Be sure to observe the description contents when handling the product.

Electrical hazard warning label

Material: PET

5 Precautions for use

This chapter covers restrictions and requirements the user should consider when using the product.

■ Common to AC power input driver and DC power input driver

- **Be sure to use our cable to connect the motor and the driver.**

  Check the cable models on p.45 (AC power input driver) or p.76 (DC power input driver).

- **Note on connecting a power supply whose positive terminal is grounded**

  The USB communication connector, CN5, CN6, and CN7 connectors on the driver are not electrically insulated. When grounding the positive terminal of the power supply, do not connect any equipment (PC, etc.) whose negative terminal is grounded. Doing so may cause the driver and this equipment to short, damaging both. When connecting, do not ground equipment.

- **Saving data to the non-volatile memory**

  Do not turn off the control power supply while writing the data to the non-volatile memory, and also do not turn off for 5 seconds after the completion of writing the data. Doing so may abort writing the data and cause an alarm of EEPROM error to generate. The non-volatile memory can be rewritten approximately 100,000 times.

- **Noise elimination measures**

  Refer to p.35 (AC power input driver) or p.66 (DC power input driver) for the noise elimination measures.

■ AC power input driver

- **When conducting the insulation resistance measurement or the dielectric strength test, be sure to separate the connection between the motor and the driver.**

  Conducting the insulation resistance measurement or dielectric strength test with the motor and the driver connected may result in damage to the product.

- **Preventing leakage current**

  Stray capacitance exists between the driver's current-carrying line and other current-carrying lines, the earth and the motor, respectively. A high-frequency current may leak out through such capacitance, having a detrimental effect on the surrounding equipment. The actual leakage current depends on the driver's switching frequency, the length of wiring between the driver and the motor, and so on. When installing an earth leakage breaker, use a product offering resistance against high frequency current such as the one specified below.
  Mitsubishi Electric Corporation: NV series

- **If vertical drive (gravitational operation) such as elevator applications is performed or if sudden start-stop operation of a large inertial load is repeated frequently, connect our regeneration resistor RGB100.**

  An alarm of overvoltage may be detected depending on the operating condition of the motor. When the alarm of overvoltage has been detected, reconsider the operating condition or use our regeneration resistor **RGB100**. Refer to p.28 for the connection method.

■ DC power input driver

- **When conducting the insulation resistance measurement, be sure to separate the connection between the motor and the driver.**

  Conducting the insulation resistance measurement with the motor and the driver connected may result in damage to the product.

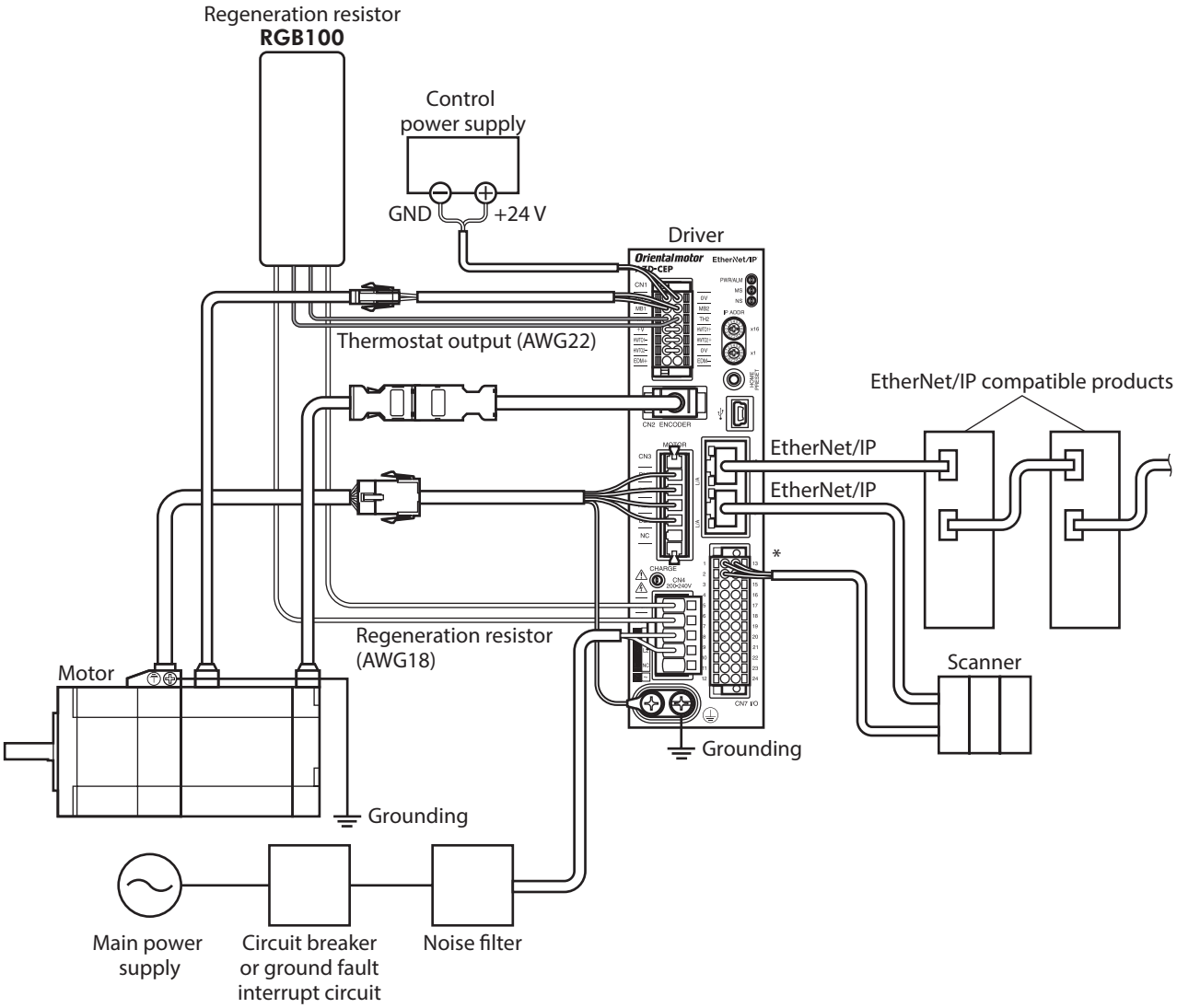
2 AC power input type

This part explains contents specific to the AC power input type driver.

◆Table of contents

1 System configuration

The figure shows models for the electromagnetic brake type with single-phase 200 to 240 VAC input.



* Connect when using direct I/O or sensors.

2 Preparation

This chapter explains the items you should check, as well as names and functions of each part.

2-1 Checking the product

Verify that the items listed below are included. Report any missing or damaged items to the Oriental Motor sales office from which you purchased the product.

- Driver .....1 unit
- CN1 connector (14 pins) .....1 pc.
- CN4 connector (5 pins).....1 pc.
- CN7 connector (24 pins) .....1 pc.
- Connector lever.....1 pc. (for CN4 connector)
- OPERATING MANUAL Driver.....1 copy

Included connector model

Type	Part number	Manufacturer
CN1 connector	DFMC1,5/7-ST-3,5-LR	PHOENIX CONTACT GmbH & Co. KG
CN4 connector	05JFAT-SAXGDK-H5.0	J.S.T. Mfg. Co., Ltd.
CN7 connector	DFMC1,5/12-ST-3,5	PHOENIX CONTACT GmbH & Co. KG

2-2 How to identify the product model

Check the model number of the driver against the number shown on the nameplate. Refer to p.20 for how to identify the nameplate.

AZD - C EP
1 2 3

1	Series	**AZD**: **AZ** Series driver
2	Power supply input	**A**: Single-phase 100-120 VAC **C**: Single-phase/Three-phase 200-240 VAC
3	Network type	**EP**: EtherNet/IP

2-3 Products possible to combine

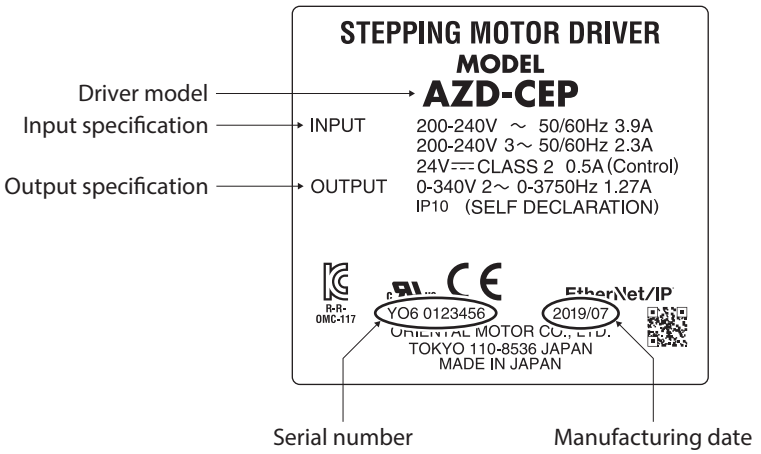
Products with which the driver can be combined are listed below. Check the model name of the product with the nameplate.

Power supply type	Product type	Applicable series	Model name representing series name *1	Example of model name
AC input	Stepping motor	**AZ** Series	**AZM**	**AZM46AC** **AZM66AC-TS10**
	Motorized actuator	**EAS** Series *2	**EASM**	**EASM4NXD005AZAC**
		EAC Series *2	**EACM**	**EACM4RWE15AZMC**
		EZS Series *2	**EZSM**	**EZSM6D005AZAC**
		EZSH Series *2	**EZSHM**	**EZSHM6H020AZAC**
		DGII Series	**DGM** **DGB**	**DGM85R-AZAC** **DGB85R12-AZACR**
		L Series	**LM**	**LM4F500AZMC-10**

*1 The driver described in this manual can be combined with products that begin with these model names.
*2 For these motorized actuators, the equipped motors have been evaluated to affix the CE Marking. Check the model name of the equipped motor with the nameplate.

2-4 Information about nameplate

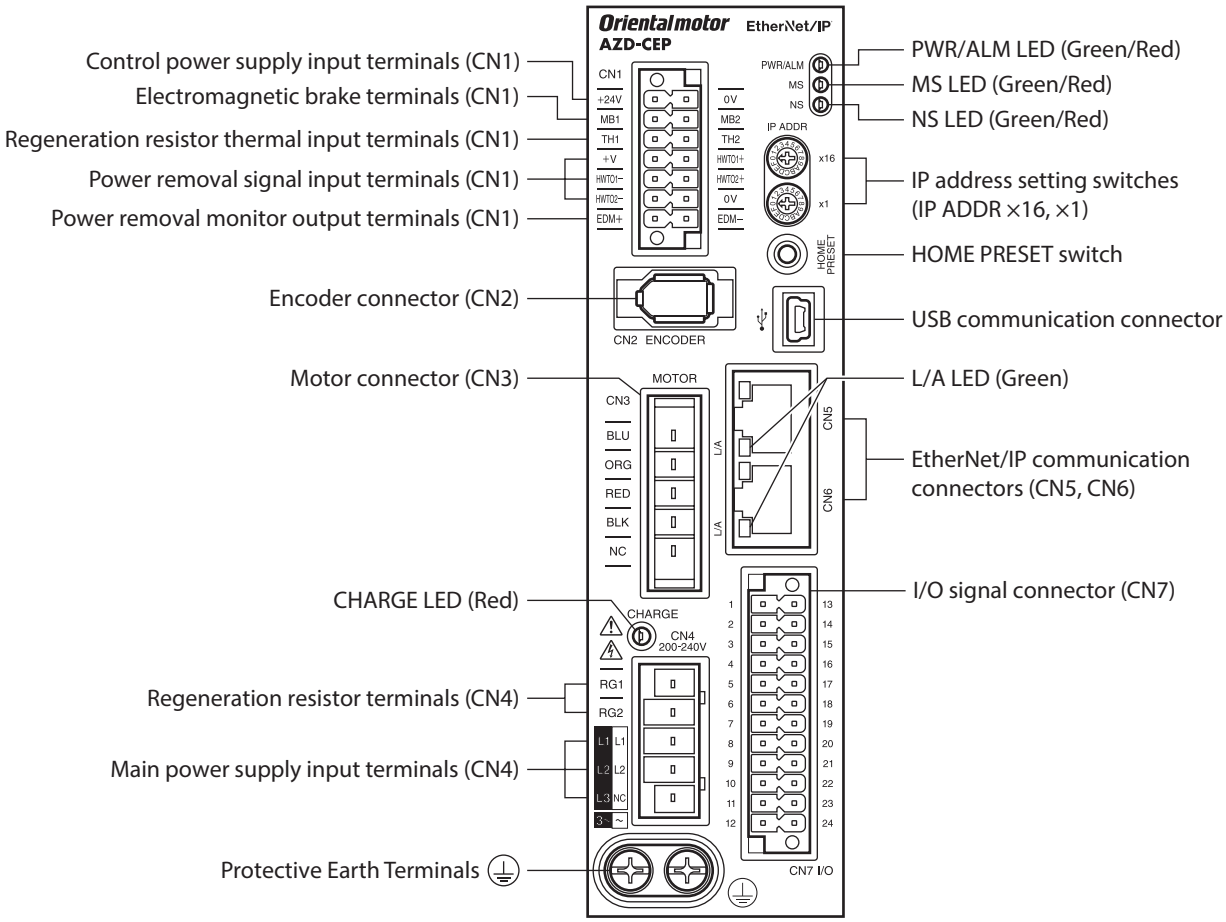
The figure shows an example.



memo The position describing the information may vary depending on the product.

2-5 Names and functions of parts

The figure shows the **AZD-CEP**.



Type	Name	Sign	Description
LED	CHARGE LED (Red)	CHARGE	This LED is lit while the main power supply is turned on. After the main power has been turned off, the LED will turn off once the residual voltage in the driver drops to a safe level.
	PWR/ALM LED (Green/Red)	PWR/ALM	• This LED is lit in green while the control power supply is turned on. • If an alarm (protective function) is generated, the LED will blink in red. • If the power removable function (p.40) is triggered, the LED will blink in green. • If information is generated, the LED will simultaneously blink in red and green twice. (Green and red colors may overlap and it may be visible to orange.)
	MS LED (Green/Red)	MS	This LED indicates the status of the driver.
	NS LED (Green/Red)	NS	This LED indicates the communication status of EtherNet/IP.
	L/A LED (Green)	L/A	This LED indicates the LINK/ACT status of EtherNet/IP.
Switch	IP address setting switches	IP ADDR ×16 IP ADDR ×1	These switches are used to set an IP address. Factory setting: 00 (×16: 0, ×1: 0)
	HOME PRESET switch	HOME PRESET	This switch is used to set the starting position (home position) when positioning operation is performed.
Connector	Encoder connector (CN2)	ENCODER	Connects the encoder.
	Motor connector (CN3)	MOTOR	Connects the motor.
	USB communication connector		Connects a PC in which the **MEXE02** has been installed. (USB2.0 mini-B port)
	EtherNet/IP communication connectors (CN5, CN6)	–	Connects the EtherNet/IP communication cable.
	I/O signal connector (CN7)	I/O	Connects when using direct I/O or sensors.
Terminal	Control power supply input terminals (CN1)	+24V, 0V	Connects the control power supply.
	Electromagnetic brake terminals (CN1)	MB1, MB2	Connects the lead wires from the electromagnetic brake.
	Regeneration resistor thermal terminals (CN1)	TH1, TH2	Connects our regeneration resistor **RGB100**. If the regeneration resistor **RGB100** is not connected, short the TH1 and TH2 terminals.
	Power removal signal input terminals (CN1)	HWTO1+, HWTO1– HWTO2+, HWTO2–	Connects switches or the scanner.
	Power removal monitor output terminals (CN1)	EDM+, EDM–	Connects the scanner.
	Regeneration resistor terminals (CN4)	RG1, RG2	Connects our regeneration resistor **RGB100**.
	Main power supply input terminals (CN4)	L, N, NC L1, L2, NC L1, L2, L3	Connects the main power supply.
	Protective Earth Terminals		Ground using a grounding wire of AWG16 to 14 (1.25 to 2.0 mm^2).

2-6 Indication of LEDs

■ PWR/ALM LED

This LED indicates the status of the driver.

LED status		Description
Green	Red	
Unlit	Unlit	The control power supply is not turned on.
Lit	Unlit	The control power supply is turned on.
Unlit	Blinking	An alarm is being generated. Details about the generated alarm can be checked by counting the number of times the LED blinks. The LED is lit in green when the alarm is reset.
Blinking	Unlit	The power removable function has been activated. The LED is lit in green when the power removable function is released.
Blinking twice at the same time *		• Information is being generated. The LED is lit in green when the information is cleared. • Teaching, remote operation is being executed with the **MEXE02**. The LED is lit in green when teaching, remote operation is complete.
Blinking at the same time *		The interlock was released by holding down the HOME PRESET switch. The LED is lit in green when the time set in the "Extended input (EXT-IN) interlock releasing time" parameter is elapsed.
Lit at the same time *		The input signal assigned to the HOME PRESET switch is being executed. The LED is lit in green when it is complete.
Repeating "Green → Red → Simultaneously lit → Unlit"		This is the driver simulation mode.

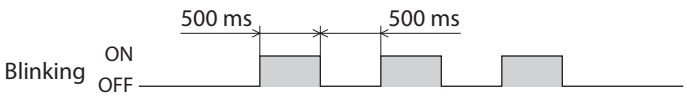
* Green and red colors may overlap and it may be visible to orange.

■ MS LED

This LED indicates the status of the driver.

LED status		Description
Green	Red	
Unlit	Unlit	The control power supply of the driver is not turned on.
Blinking	Unlit	The communication setting of EtherNet/IP is invalid.
Lit	Unlit	The driver operates properly.
Unlit	Blinking	• An alarm that can be reset with EtherNet/IP or the **MEXE02** was generated. • The setting of an IP address is duplicated in the same system.
Unlit	Lit	An alarm that cannot be reset with EtherNet/IP or the **MEXE02** was generated.
Blinking alternately		Self-diagnosis when turning on the power is executing.

The timing to blink the LED is as follows.

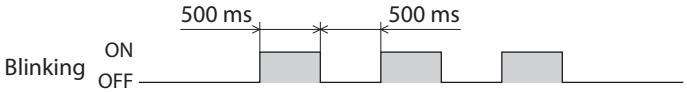


■ NS LED

This LED indicates the communication status of EtherNet/IP.

LED status		Description
Green	Red	
Unlit	Unlit	• In an offline state. • The control power supply of the driver is not turned on.
Blinking	Unlit	In an online state. Connection with the scanner is not established.
Lit	Unlit	In an online state. Connection with the scanner is being established.
Unlit	Blinking	Connection with the scanner became time-out.
Unlit	Lit	The setting of an IP address is duplicated in the same system.
Blinking alternately		Self-diagnosis when turning on the power is executing.

The timing to blink the LED is as follows.



■ L/A LED

This LED indicates the LINK/ACT status of EtherNet/IP.

LED status	Description
Unlit	• In an offline state. • The frame of EtherNet/IP is not sent and received.
Blinking	• In an online state. • The frame of EtherNet/IP is sent and received.
Lit	• In an online state. • The frame of EtherNet/IP is not sent and received.

3 Installation

This chapter explains the installation location and installation method of the driver.

3-1 Installation location

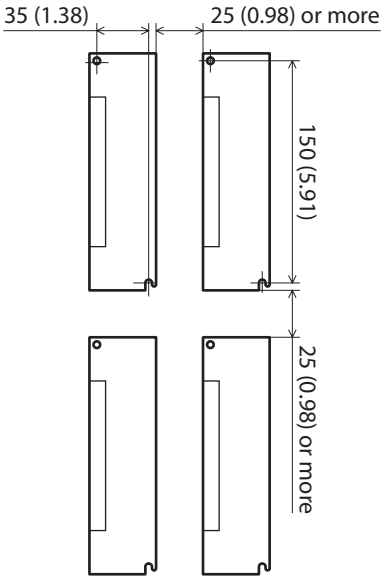
The driver is designed and manufactured to be incorporated in an equipment. Install it in a well-ventilated location that provides easy access for inspection. The location must also satisfy the following conditions:

- Inside an enclosure that is installed indoors (provide vent holes)
- Operating ambient temperature: 0 to +55°C (+32 to +131 °F) (non-freezing)
- Operating ambient humidity: 85 % or less (non-condensing)
- Area that is free of explosive atmosphere or toxic gas (such as sulfuric gas) or liquid
- Area not exposed to direct sun
- Area free of excessive amount of dust, iron particles or the like
- Area not subject to splashing water (rain, water droplets), oil (oil droplets) or other liquids
- Area free of excessive salt
- Area not subject to continuous vibrations or excessive shocks
- Area free of excessive electromagnetic noise (from welders, power machinery, etc.)
- Area free of radioactive materials, magnetic fields or vacuum
- Up to 1,000 m (3,300 ft.) above sea level

3-2 Installation method

The driver is designed so that heat is dissipated via air convection and conduction through the enclosure. Install the driver to a flat metal plate (*) offering high heat conductivity. When installing drivers, provide clearances of at least 25 mm (0.98 in.) in the horizontal and vertical directions between the driver and enclosure or other equipment within the enclosure.
When installing the driver, use two screws (M4, not included) to secure the driver through the mounting holes.

* Material: Aluminum, 200×200×2 mm (7.87×7.87×0.08 in.) or equivalent



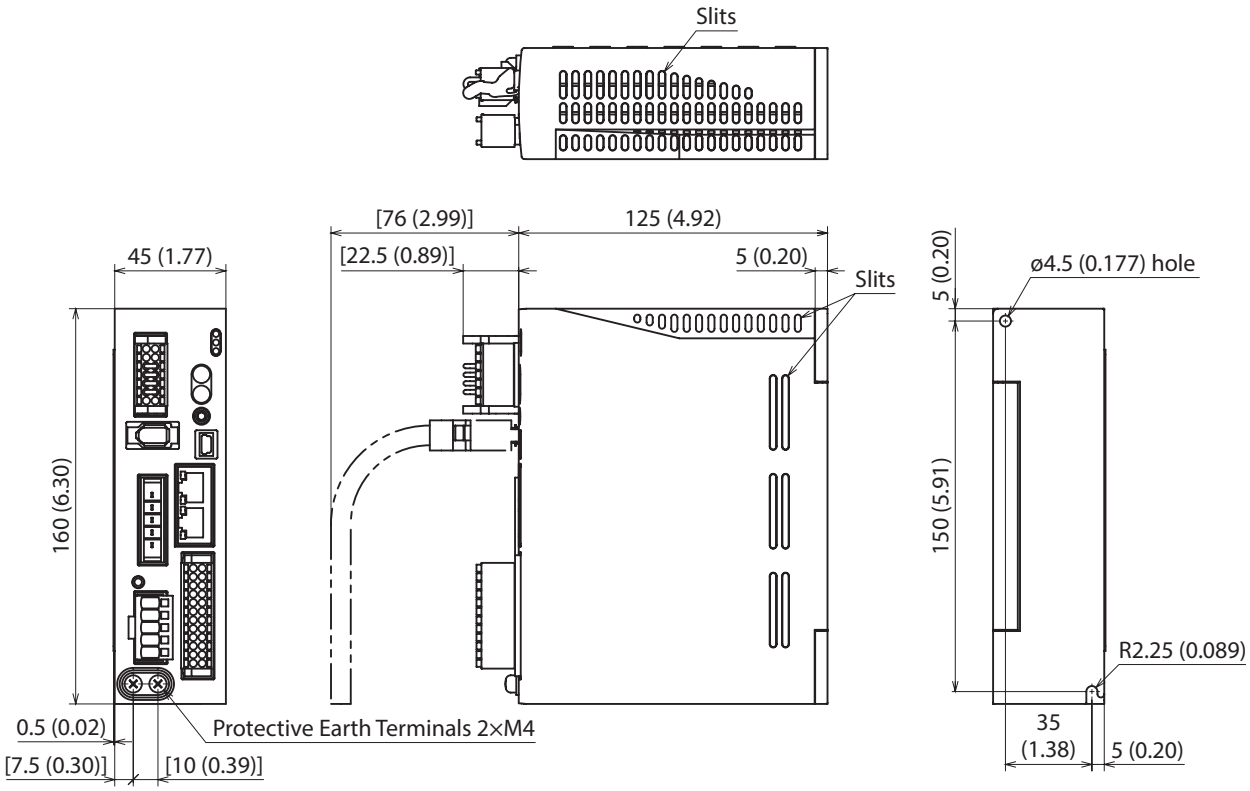
Unit: mm (in.)

Note

- Install the driver inside an enclosure whose pollution degree is 2 or better environment, or whose degree of protection is IP54 minimum.
- Do not install any equipment that generates a large amount of heat or noise near the driver.
- Do not install the driver underneath the scanner or other equipment vulnerable to heat.
- If the ambient temperature of the driver exceeds 55 °C (131 °F), improve the ventilation condition such as providing forced cooling by using fans or creating spaces between the drivers.
- Be sure to install the driver vertically (in vertical position).

■ Dimensions

- Unit: mm (in.)
- Mass: 0.68 kg (1.5 lb.)



4 Connection

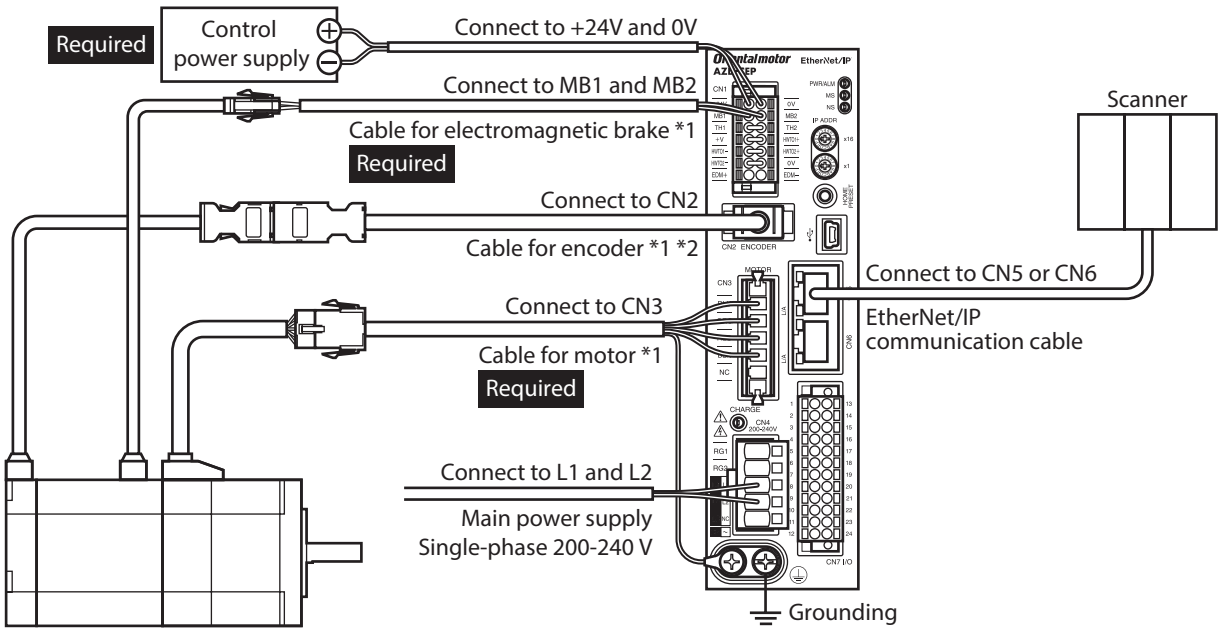
This chapter explains a connection example of a driver and a motor, connection methods of power supplies and the regeneration resistor **RGB100**, the grounding method, and others.
The installation and wiring methods in compliance with the EMC Directive as well as protection against noise are also explained.

⚠WARNING

- For protection against electric shock, do not turn on the power supply until the wiring is completed.
- A high voltage is applied to the motor connector (CN3) and the main power supply input terminals (CN4). Do not touch them while the power is on. Doing so may result in fire or electric shock.

4-1 Connection example

The figure shows models for the electromagnetic brake type with single-phase 200 to 240 VAC input.



*1 Purchase it separately.
*2 Use the cable for encoder when the length of the encoder cable of motor is not enough.

Note

- Connect the connectors securely. Insecure connections may cause malfunction or damage to the motor or driver.
- Before connecting or disconnecting a connector, turn off the main power supply and the control power supply, and check the CHARGE LED has been turned off. Residual voltage may cause electric shock.
- The lead wires of the "cable for electromagnetic brake" have polarities, so connect them in the correct polarities. If the lead wires are connected with their polarities reversed, the electromagnetic brake will not operate properly.
- Do not wire the power supply cable of the driver in the same cable duct with other power lines or motor cable. Doing so may cause malfunction due to noise.
- Keep 20 m (65.6 ft.) or less for the wiring distance between the motor and the driver. To extend more than 20 m (65.6 ft.) may result in the driver heat generation or increase of the electrical noise emitted from the product.

memo

- A control power supply is required with or without an electromagnetic brake. Be sure to connect it.
- When pulling off the motor cable, do so while pressing the latches on the connector with fingers.
- When installing the motor on a moving part, use a flexible cable offering excellent flexibility. Refer to p.45 for the model name.

■ Electrical wire size

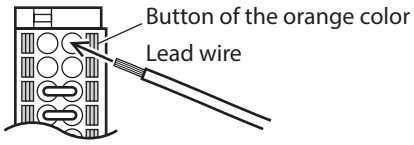
Connector	Terminal symbol	Recommended wire size
CN1	+24V, 0V, MB1, MB2, TH1, TH2, HWTO1+, HWTO1–, HWTO2+, HWTO2–, EDM+, EDM–	Stranded wire or solid wire AWG24 to 16 (0.2 to 1.25 mm^2)
CN4	RG1, RG2, L, N, L1, L2, L3	Stranded wire or solid wire AWG18 to 14 (0.75 to 2.0 mm^2)
CN7	–	Stranded wire or solid wire AWG24 to 16 (0.2 to 1.25 mm^2)

4-2 Connecting the control power supply

■ Wiring method of CN1 connector

- Applicable lead wire: AWG24 to 16 (0.2 to 1.25 mm^2)
- Stripping length of wire insulation: 10 mm (0.39 in.)

1. Strip the insulation of the lead wire.
2. Insert the lead wire while pushing the button of the orange color with a slotted screwdriver.
3. After having inserted, release the button to secure the lead wire.



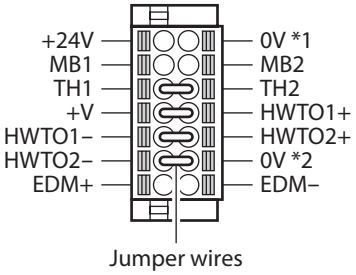
■ Power supply current capacity

Input power supply voltage	Power supply current capacity	
	Without electromagnetic brake	With electromagnetic brake
24 VDC±5 % *1	0.25 A	0.5 A *2

*1 When an electromagnetic brake motor is used, if the wiring distance between the motor and the driver is extended to 20 m (65.6 ft.) using our cable, the input voltage is 24 VDC±4 %.
*2 The **AZM46** type is 0.33 A.

■ Pin assignment

There are two terminals for 0 V: One for control power supply and the other is for internal connection. Check each position in the figure and table shown.



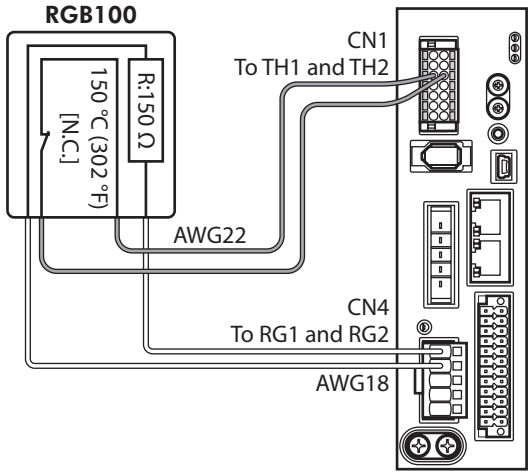
Sign	Description
+24V, 0V *1	Connects the control power supply.
MB1, MB2	Connects the lead wires from the electromagnetic brake. MB1: Electromagnetic brake– (Black) MB2: Electromagnetic brake+ (White)
TH1, TH2	Connects the signal lines of our regeneration resistor **RGB100**. If the regeneration resistor is not used, connect a jumper wire (included) between the terminals as shown in the figure.
HWTO1+, HWTO1– HWTO2+, HWTO2–	Connects switches or the scanner. If the power removal function is not used, connect a jumper wire (included) between the terminals as shown in the figure.
EDM+, EDM–	Connects the scanner.
+V, 0V *2	These are for internal connection. Do not connect anything. If the power removal function is not used, connect a jumper wire (included) between the terminals as shown in the figure.

4-3 Connecting the regeneration resistor

If vertical drive (gravitational operation) such as elevating applications is performed or if sudden start-stop operation of a large inertial is repeated frequently, connect our regeneration resistor **RGB100**.

- The two thin lead wires (AWG22: 0.3 mm^2) of the regeneration resistor are the thermostat outputs. Connect them to the TH1 and TH2 using the CN1 connector.
- Regenerative current flows through the two thick lead wires (AWG18: 0.75 mm^2) of the regeneration resistor. Connect them to the RG1 and RG2 using the CN4 connector.

Regeneration resistor



memo

- When connecting the regeneration resistor, be sure to remove the jumper wire from the CN1 connector.
- If the allowable power consumption of the regeneration resistor exceeds the allowable level, the thermostat will be triggered to generate an alarm of regeneration resistor overheat. When an alarm of regeneration resistor overheat is generated, turn off the main power supply and check the error content.

● Regeneration resistor specifications

Model	**RGB100**
Allowable power consumption	Continuous regenerative power: 50 W * Instantaneous regenerative power: 600 W
Resistance value	150 Ω
Thermostat operating temperature	Operation: Opens at 150±7 °C (302±12.6 °F) Reset: Closes at 145±12 °C (293±21.6 °F) [normally closed]
Thermostat electrical rating	120 VAC 4 A or 30 VDC 4A (minimum current 5 mA)

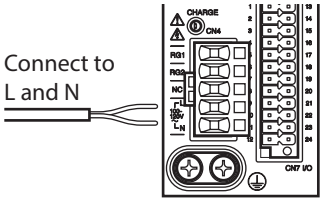
* Install the regeneration resistor in a location where heat dissipation capacity equivalent to a level achieved with a aluminum plate [350×350×3 mm (13.78×13.78×0.12 in.)] is ensured.

4-4 Connecting the main power supply

The connecting method varies depending on the power supply specification.

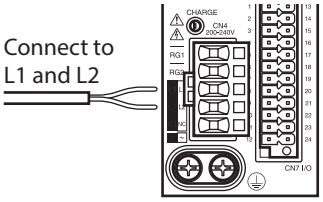
Single-phase 100-120 V –15 % to +6 % 50/60 Hz

Connect to L and N



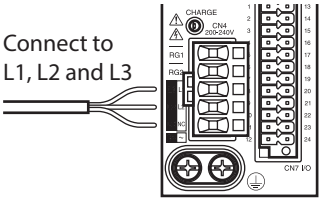
Single-phase 200-240 V –15 % to +6 % 50/60 Hz

Connect to L1 and L2



Three-phase 200-240 V –15 % to +6 % 50/60 Hz

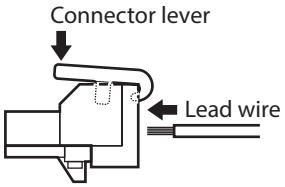
Connect to L1, L2 and L3



■ Wiring method of CN4 connector

- Applicable lead wire: AWG18 to 14 (0.75 to 2.0 mm^2)
- Stripping length of wire insulation: 9 mm (0.35 in.)

1. Strip the insulation of the lead wire.
2. Insert the connector lever.
3. Insert the lead wire while pushing down the connector lever.



■ Power supply current capacity

The current capacity for the power supply varies depending on the product combined.
Check the current capacity in reference to the equipped motor model name when using the **EAS** Series, **EAC** Series, **EZS** Series, or **EZSH** Series.

● **Single-phase 100-120 VAC**

Model	Power supply current capacity
AZM46	2.7 A or more
AZM48	2.7 A or more
AZM66	3.8 A or more
AZM69	5.4 A or more
AZM98	5.5 A or more
AZM911	6.4 A or more
DGB85	2.7 A or more
DGB130	3.8 A or more
DGM85	2.7 A or more
DGM130	3.8 A or more
DGM200	6.4 A or more
LM2	3.8 A or more
LM4	3.8 A or more

● **Single-phase 200-240 VAC**

Model	Power supply current capacity
AZM46	1.7 A or more
AZM48	1.6 A or more
AZM66	2.3 A or more
AZM69	3.3 A or more
AZM98	3.3 A or more
AZM911	3.9 A or more
DGB85	1.7 A or more
DGB130	2.3 A or more
DGM85	1.7 A or more
DGM130	2.3 A or more
DGM200	3.9 A or more
LM2	2.3 A or more
LM4	2.3 A or more

● **Three-phase 200-240 VAC**

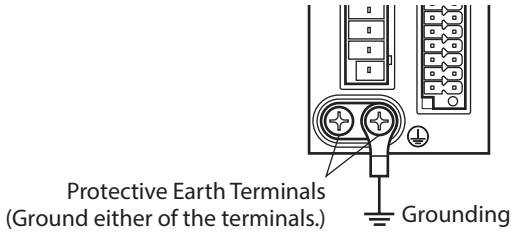
Model	Power supply current capacity
AZM46	1.0 A or more
AZM48	1.0 A or more
AZM66	1.4 A or more
AZM69	2.0 A or more
AZM98	2.0 A or more
AZM911	2.3 A or more
DGB85	1.0 A or more
DGB130	1.4 A or more
DGM85	1.0 A or more
DGM130	1.4 A or more
DGM200	2.3 A or more
LM2	1.4 A or more
LM4	1.4 A or more

4-5 Grounding the driver

Two Protective Earth Terminals (screw size: M4) are provided on the driver. Be sure to ground one of the Protective Earth Terminals. Either of the two Protective Earth Terminals can be used for grounding the driver.

- Grounding wire: AWG16 to 14 (1.25 to 2.0 mm^2)
- Tightening torque: 1.2 N·m (170 oz-in)

Connect the grounding wire of the "cable for motor" to the other terminal to ground the motor.
Do not share the grounding wire with a welder or any other power equipment.
When grounding the Protective Earth Terminal, use a round terminal and secure the grounding point near the driver.

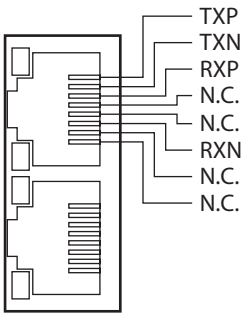


4-6 Connecting the EtherNet/IP communication cable

Connect the EtherNet/IP communication cable to the EtherNet/IP communication connector (CN5, CN6).

■ Pin assignment

Signal name	Description
TXP	Transmitted data+
TXN	Transmitted data–
RXP	Received data+
N.C.	–
N.C.	–
RXN	Received data–
N.C.	–
N.C.	–



4-7 Connecting the USB cable

Using a USB cable of the following specification, connect a PC in which the **MEXE02** has been installed to the USB communication connector.

Specification	USB2.0 (full speed)
Cable	Length: 3 m (9.8 ft.) or less Shape: A to mini B

memo

- Connect the driver and PC directly using the USB cable.
- In large electrically noisy environments, use the USB cable with a ferrite core or install a ferrite core to the USB cable.

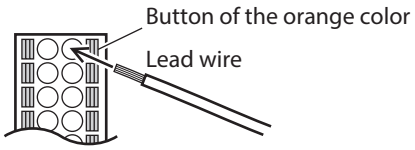
4-8 Connecting the I/O signals

Connect when using direct I/O or sensors.

■ Wiring method of CN7 connector

- Applicable lead wire: AWG24 to 16 (0.2 to 1.25 mm^2)
- Stripping length of wire insulation: 10 mm (0.39 in.)

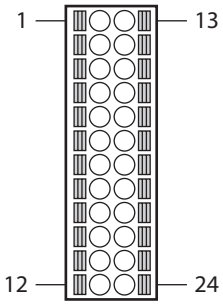
1. Strip the insulation of the lead wire.
2. Insert the lead wire while pushing the button of the orange color with a slotted screwdriver.
3. After having inserted, release the button to secure the lead wire.



memo Be certain the I/O signal cable is as short as possible. The maximum input frequency will decrease as the cable length increases.

■ Pin assignment

Pin No.	Signal name *	Description *
1	CW+ [PLS+]	CW pulse input + [Pulse input +]
2	CCW+ [DIR+]	CCW pulse input + [Rotation direction switching input +]
3	IN0	Control input 0 (ZHOME)
4	IN2	Control input 2 (STOP)
5	IN-COM 0-3	IN0 to IN3 inputs common
6	IN4	Control input 4 (FW-JOG)
7	OUT0	Control output 0 (HOME-END)
8	OUT2	Control output 2 (PLS-RDY)
9	OUT4	Control output 4 (MOVE)
10	OUT-COM	Output common
11	ASG+	Phase A pulse output +
12	BSG+	Phase B pulse output +



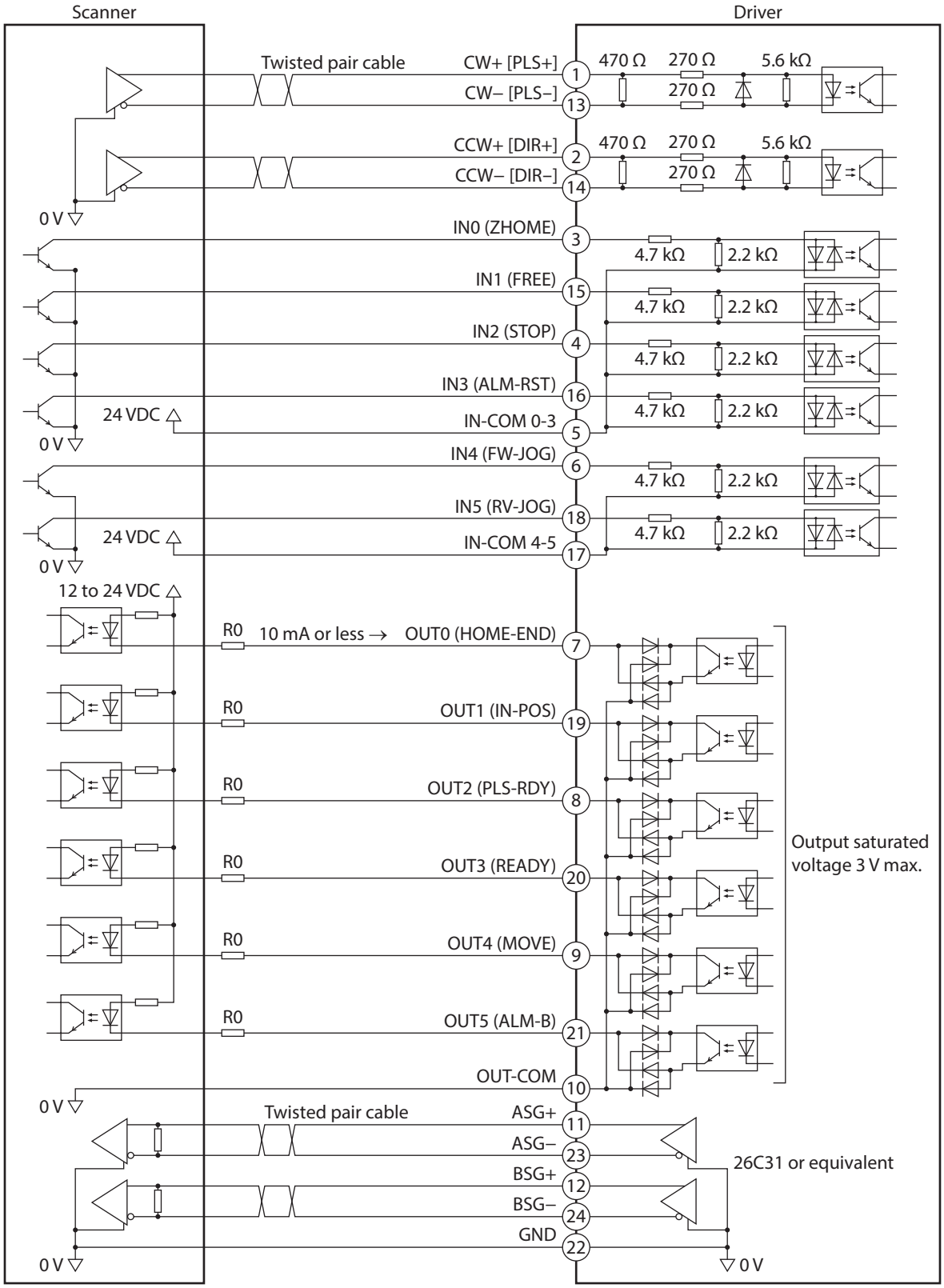
Pin No.	Signal name *	Description *
13	CW– [PLS–]	CW pulse input – [Pulse input –]
14	CCW– [DIR–]	CCW pulse input – [Rotation direction switching input –]
15	IN1	Control input 1 (FREE)
16	IN3	Control input 3 (ALM-RST)
17	IN-COM 4-5	IN4, IN5 inputs common
18	IN5	Control input 5 (RV-JOG)
19	OUT1	Control output 1 (IN-POS)
20	OUT3	Control output 3 (READY)
21	OUT5	Control output 5 (ALM-B)
22	GND	GND
23	ASG–	Phase A pulse output –
24	BSG–	Phase B pulse output –

* Values in brackets [ ] are signals when the 1-pulse input mode is set.
Values in parentheses ( ) are initial values.

■ Connection example with a current sink output circuit

● **When the pulse input circuit of the driver is of line driver type**

The pin No.1, No.2, No.13, and No.14 are only available to the pulse input. Other functions cannot be assigned.



* Values in brackets [ ] are signals when the 1-pulse input mode is set.
Values in parentheses ( ) are initial values.

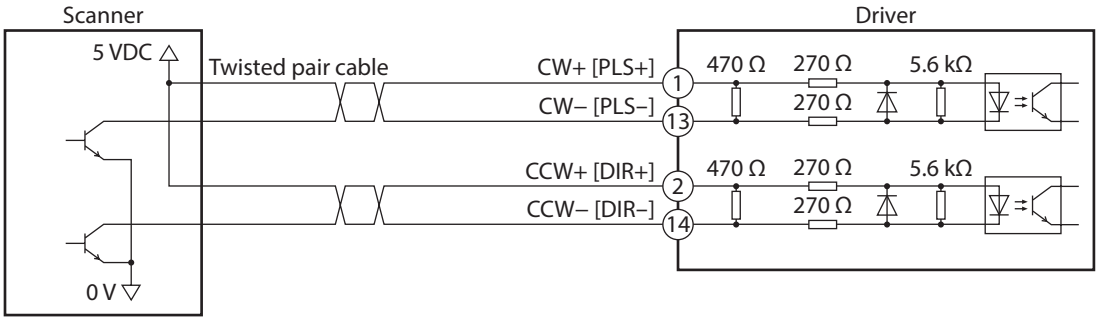
memo
- Use input signals at 24 VDC.
- Use output signals at 12 to 24 VDC, 10 mA or less. If the current exceeds 10 mA, connect an external resistor R0 so that the current becomes 10 mA or less.
- The saturated voltage of the output signal is 3 V maximum.

● **When the pulse input circuit of the driver is of open collector type**

The pin No.1, No.2, No.13, and No.14 are only available to the pulse input. Other functions cannot be assigned.

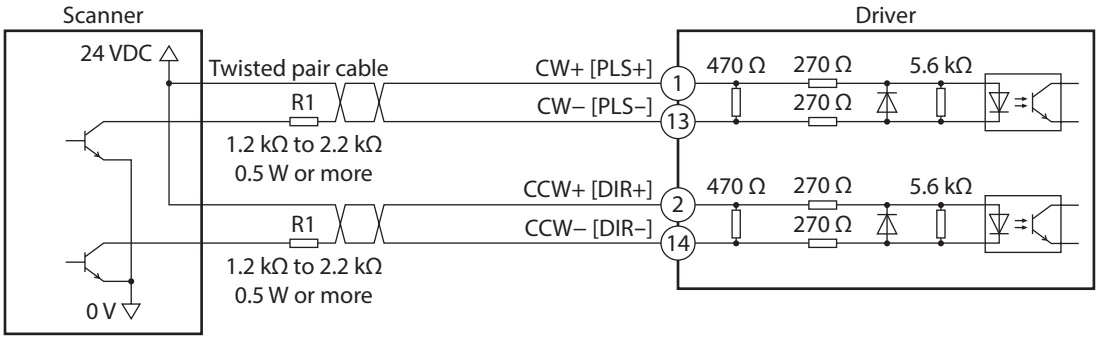
memo Use the CW [PLS] input and CCW [DIR] input at 5 to 24 VDC. When using signals at 24 VDC, connect an external resistor R1 (1.2 kΩ to 2.2 kΩ, 0.5 W or more). When using signals at 5 VDC, apply the voltage directly.

When the voltage of pulse input signals is 5 VDC



* Values in brackets [ ] are signals when the 1-pulse input mode is set.

When the voltage of pulse input signals is 24 VDC

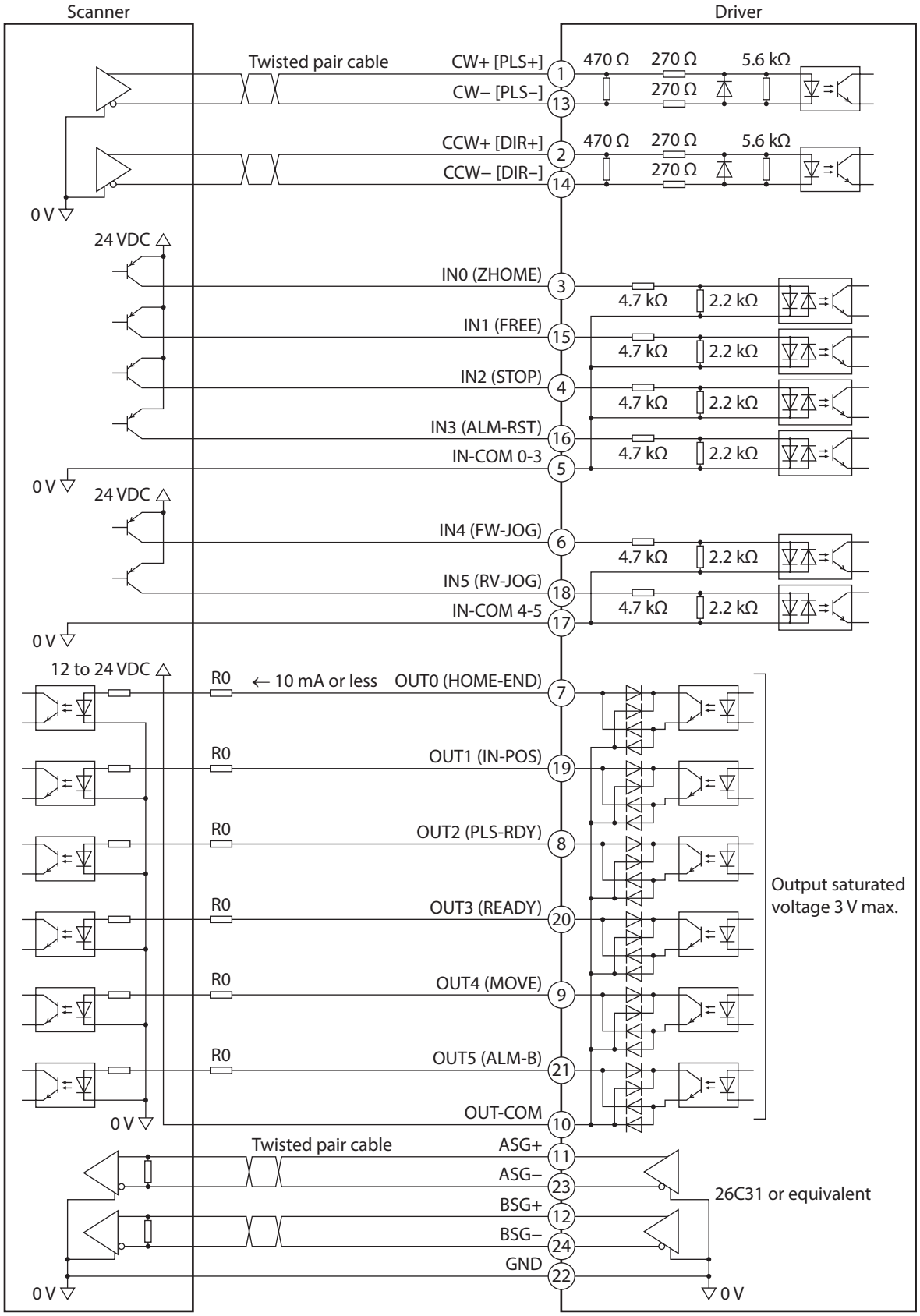


* Values in brackets [ ] are signals when the 1-pulse input mode is set.

■ Connection example with a current source output circuit

● **When the pulse input circuit of the driver is of line driver type**

The pin No.1, No.2, No.13, and No.14 are only available to the pulse input. Other functions cannot be assigned.



* Values in brackets [ ] are signals when the 1-pulse input mode is set.
Values in parentheses ( ) are initial values.

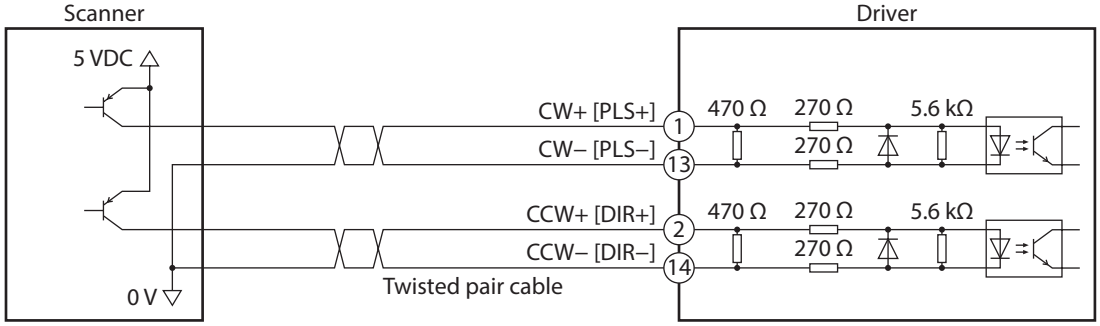
memo
- Use input signals at 24 VDC.
- Use output signals at 12 to 24 VDC, 10 mA or less. If the current exceeds 10 mA, connect an external resistor R0 so that the current becomes 10 mA or less.
- The saturated voltage of the output signal is 3 V maximum.

● **When the pulse input circuit of the driver is of open collector type**

The pin No.1, No.2, No.13, and No.14 are only available to the pulse input. Other functions cannot be assigned.

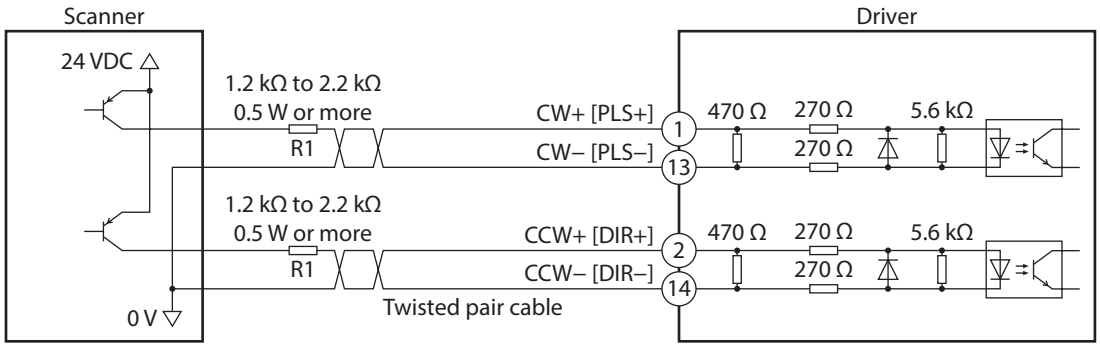
memo Use the CW [PLS] input and CCW [DIR] input at 5 to 24 VDC. When using signals at 24 VDC, connect an external resistor R1 (1.2 kΩ to 2.2 kΩ, 0.5 W or more). When using signals at 5 VDC, apply the voltage directly.

When the voltage of pulse input signals is 5 VDC



* Values in brackets [ ] are signals when the 1-pulse input mode is set.

When the voltage of pulse input signals is 24 VDC



* Values in brackets [ ] are signals when the 1-pulse input mode is set.

4-9 Noise elimination measures

There are two types of electrical noises: One is a noise to invade into the driver from the outside and cause the driver malfunction, and the other is a noise to emit from the driver and cause peripheral equipments malfunction.
For the noise that is invaded from the outside, take measures to prevent the driver malfunction. It is needed to take adequate measures because signal lines are very likely to be affected by the noise.
For the noise that is emitted from the driver, take measures to suppress it.

■ Measures against electrical noise

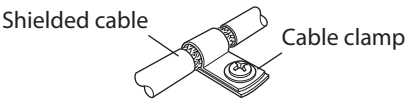
There are the following three methods mainly to take measures against the electrical noise.

● **Noise suppression**

- When relays or electromagnetic switches are used, use noise filters or CR circuits to suppress surge generated by them.
- Use our connection cable when extending the wiring distance between the motor and the driver. Refer to p.45 for the model name. This is effective in suppressing the electrical noise emitted from the motor.
- Cover the driver by a metal plate such as aluminum. This is effective in shielding the electrical noise emitted from the driver.

● Prevention of noise propagation

- Connect a noise filter to the power supply cable of the driver.
- Place the power lines, such as the motor and the power supply cables, keeping a distance of 200 mm (7.87 in.) or more from the signal lines, and also do not bundle them or wire them in parallel. If a power cable and a signal cable have to cross, cross them at a right angle.
- Use shielded twisted pair cables for power lines and signal lines.
- Keep cables as short as possible without coiling and bundling extra lengths.
- Grounding multiple points will increase effect to block electrical noise because impedance on the grounding points is decreased. However, ground them so that a potential difference does not occur among the grounding points. I/O signal cable that includes a ground wire are provided in our product line. Refer to p.47 for the model name.
- To ground a shielded cable, use a metal cable clamp that can maintain contact with the entire circumference of the shielded cable, and ground as near the product as possible.



● Suppression of effect by noise propagation

- Loop the noise propagated cable around a ferrite core. Doing so will prevent the propagated noise invades into the driver or emits from the driver. The frequency band in which an effect by the ferrite core can be seen is generally 1 MHz or more. Check the frequency characteristics of the ferrite core used. When increasing the effect of noise attenuation by the ferrite core, loop the cable a lot.
- Change the transmission method of the pulse signal to the line driver type in order to prevent noise effects. If the pulse signal of the scanner is of the open collector type, use our pulse signal converter for noise immunity. Refer to p.48 for the model name.

■ Noise suppression parts

● Noise filter

- Connect the following noise filter (or equivalent) to the power line. Doing so will prevent the propagated noise through the power line. Install the noise filter as close to the driver as possible.

Manufacturer	Single-phase 100-120 VAC Single-phase 200-240 VAC	Three-phase 200-240 VAC
SOSHIN ELECTRIC CO., LTD.	HF2010A-UPF	HF3010C-SZA
Schaffner EMC	FN2070-10-06	FN3025HP-10-71

- Use the AWG18 (0.75 mm^2) or thicker wire for the input and output cables of the noise filter, and secure firmly using a cable clamp or others so that the cable does not come off the enclosure.
- Place the input cable as far apart as possible from the output cable, and do not wire the cables in parallel. If the input and output cables are placed at a close distance or if they are wired in parallel, the noise in the enclosure affects the power cable through stray capacitance, and the noise suppressing effect will reduce.
- Connect the ground terminal of the noise filter to the grounding point, using as thick and short a wire as possible.
- When connecting a noise filter inside an enclosure, wire the input cable of the noise filter as short as possible. Wiring in long distance may reduce the noise suppressing effect.

■ Our noise suppression products

Check the model names on p.47 and p.48.

● I/O signal cable

This is a shielded cable for good noise immunity to connect the driver and scanner. The ground wire useful to grounding is extracted from both ends of the cable. The EMC measures are conducted using our I/O signal cable.

● Pulse signal converter for noise immunity

This product converts a pulse signal, which is output from the open collector output, to a pulse signal for good noise immunity by outputting the pulse signal again from the differential output.

● Surge suppressor

This product is effective to suppress the surge which occurs in a relay contact part. Connect it when using a relay or electromagnetic switch. CR circuit for surge suppression and CR circuit module are provided.

4-10 Conformity to the EMC Directive

Effective measures must be taken against the EMI that the motor and the driver may give to adjacent control-system equipment, as well as the EMS of the motor and the driver itself, in order to prevent a serious functional impediment in the machinery. The use of the following installation and wiring methods will enable the motor and the driver to be compliant with the EMC Directive. Refer to p.169 for the applicable standards.
Oriental Motor conducts EMC measurements on its motors and drivers in accordance with "Example of installation and wiring."
The user is responsible for ensuring the machine's compliance with the EMC Directive, based on the installation and wiring explained next.

● Connecting the noise filter

In large electrically noisy environments, connect a noise filter. Refer to "Noise filter" on p.36 for details.

● Connecting the control power supply

Use a power supply compliant with the EMC Directive for the control power supply.
Wire and ground the power supply over the shortest possible distance using a shielded cable.
Refer to "Prevention of noise propagation" on p.36 for how to ground the shielded cable.

● Connecting the motor cable

Use our connection cable when extending the wiring distance between the motor and the driver. Refer to p.45 for the model name.

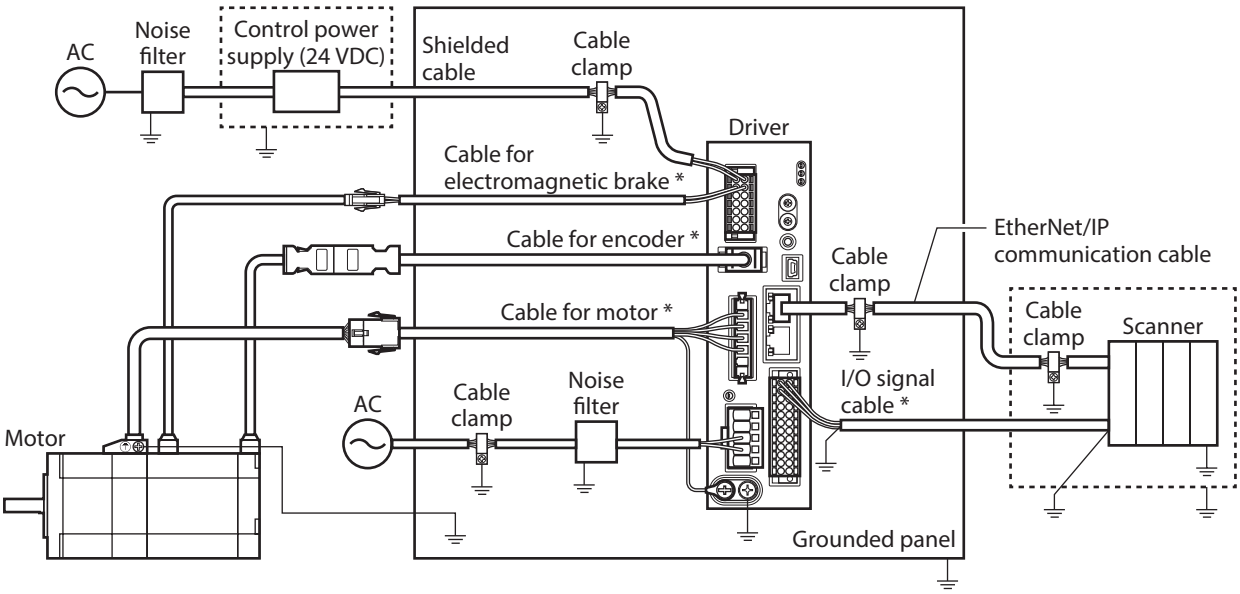
● Connecting the signal cable

Refer to "Prevention of noise propagation" on p.36.

● Grounding method

- The cable used to ground the motor, the driver, and the noise filter must be as thick and short as possible so that no potential difference is generated.
- Choose a large, thick and uniformly conductive surface for the grounding point.
- When installing the motor and the driver, ground their Protective Earth Terminals. Refer to the p.30 for the grounding method.

● Example of installation and wiring



⏚ symbol indicate the grounding.
⋯ is a shielded box.
* It is the cable in our products.

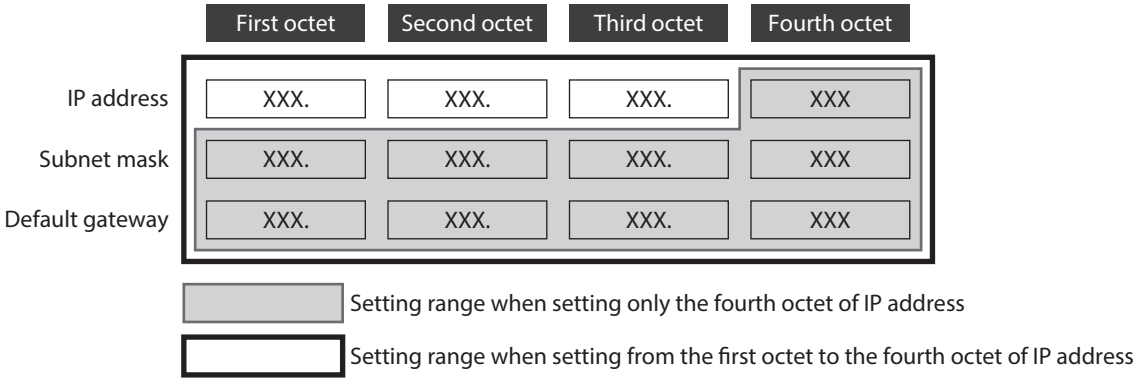
Note The driver uses parts that are sensitive to electrostatic charge. Take measures against static electricity since static electricity may cause the driver to malfunction or suffer damage.

5 Setting of IP address

This chapter explains how to set the IP address.
Set the "subnet mask" and the "default gateway" together with the IP address.

5-1 Setting method

The setting method varies depending on the setting range of the IP address.



■ When setting only the fourth octet of the IP address

Set an IP address with the IP address setting switches of the driver, and the subnet mask and the default gateway with the parameters.

- **Setting of IP address**

Set the fourth octet of the IP address using two IP address setting switches (IP ADDR ×16, ×1).
The IP address setting switches are hexadecimal number. Convert the IP address from decimal to hexadecimal to set.

Factory setting: ×16: 0, ×1: 0 (Setting of parameter or DHCP server is enabled)

Setting example

Setting of switches		Value of IP address	Note
×16	×1		
0	0	The setting of the parameter or DHCP server is enabled.	Whether either of the parameter or the DHCP server is enabled can be checked with the "Configuration control" parameter.
0	1	XXX.XXX.XXX.1	The fourth octet is set to "1."
F	E	XXX.XXX.XXX.254	The fourth octet is set to "254."
F	F	192.168.1.1	This value is applied regardless of the setting of the parameter and DHCP server.

Note

- When the switches were set, turn on the control power supply again. The new setting will be enabled when the control power supply is turned on again.
- When connecting two or more EtherNet/IP compatible products, set so that an IP address is not duplicated. If an IP address is duplicated, a communication error of the "IP address conflict" is detected.

● **Setting of subnet mask and default gateway**

Set the subnet mask and the default gateway with the parameters.

Related parameters

Parameter name	Description	Setting range	Initial value
Network mask 1	Sets the first octet of the subnet mask.	0 to 255	255
Network mask 2	Sets the second octet of the subnet mask.		255
Network mask 3	Sets the third octet of the subnet mask.		255
Network mask 4	Sets the fourth octet of the subnet mask.		0
Gateway address 1	Sets the first octet of the default gateway.	0 to 255	0
Gateway address 2	Sets the second octet of the default gateway.		0
Gateway address 3	Sets the third octet of the default gateway.		0
Gateway address 4	Sets the fourth octet of the default gateway.		0

■ When setting from the first octet to the fourth octet of IP address

Set an IP address, subnet mask, and default gateway with the parameters or DHCP server.
The parameters and the DHCP server cannot be used in combination.

● **When setting with parameters**

Set the IP address setting switches of the driver to 0 (00h) and the "Configuration control" parameter to "0: Parameter."

Related parameters

Parameter name	Description	Setting range	Initial value
Configuration control	Sets how to obtain the IP address.	0: Parameter 2: DHCP server	2
IP address 1	Sets the first octet of the IP address.	0 to 255	192
IP address 2	Sets the second octet of the IP address.		168
IP address 3	Sets the third octet of the IP address.		1
IP address 4	Sets the fourth octet of the IP address.		1
Network mask 1	Sets the first octet of the subnet mask.	0 to 255	255
Network mask 2	Sets the second octet of the subnet mask.		255
Network mask 3	Sets the third octet of the subnet mask.		255
Network mask 4	Sets the fourth octet of the subnet mask.		0
Gateway address 1	Sets the first octet of the default gateway.	0 to 255	0
Gateway address 2	Sets the second octet of the default gateway.		0
Gateway address 3	Sets the third octet of the default gateway.		0
Gateway address 4	Sets the fourth octet of the default gateway.		0

Note When connecting two or more EtherNet/IP compatible products, set so that an IP address is not duplicated. If an IP address is duplicated, a communication error of the "IP address conflict" is detected.

● **When obtaining from DHCP server**

The IP address, subnet mask and default gateway are automatically assigned from the DHCP server.
Set the IP address setting switches of the driver to 0 (00h) and the "Configuration control" parameter to "2: DHCP server."

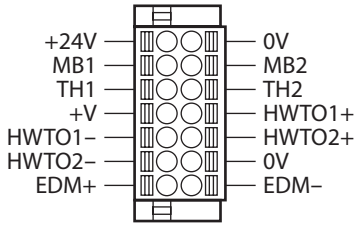
Note If the control power supply is shut off, the IP address obtained from the DHCP server is cleared.

Related parameters

Parameter name	Description	Setting range	Initial value
Configuration control	Sets how to obtain the IP address.	0: Parameter 2: DHCP server	2

6 Power removable function (ETO function: External torque off function)

The power removable function (ETO function: External torque off function) is a function that stops supplying the power to the motor forcibly to put the motor into a non-excitation state if the HWTO input of the CN1 is shut off. This function, which is different from the FREE input, shuts off the power supply to the motor directly on the circuit.
It can be used for the purpose of preventing dangerous movements of the moving part when maintenance of the equipment is performed.



Overview of the ETO function

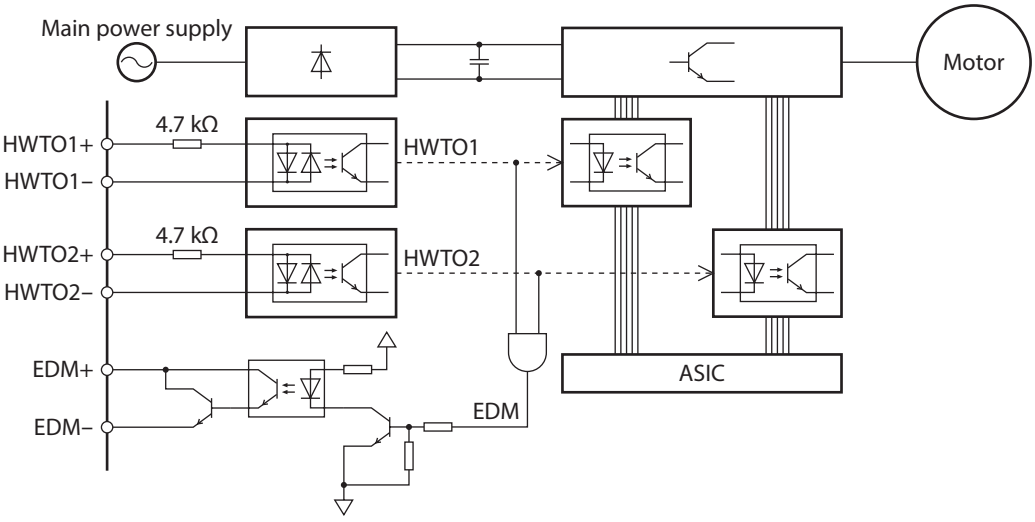
When either of the HWTO1 input or HWTO2 input is turned OFF, the hardware cuts off power supply to the motor and stops the motor. In this time, the PWR/ALM LED will blink in green.
The electromagnetic brake holds the position when the electromagnetic brake motor is used.

Note

- Be sure to check the motor is in a standstill state before executing the ETO function. If the ETO function is executed while the motor is operated, it may cause damage to the motor, driver, or equipment.
- If the ETO function is executed while the motor is operated, an excessive regenerative voltage may cause damage to the driver. Connect our regeneration resistor **RGB100** to prevent damage due to regenerative voltage.

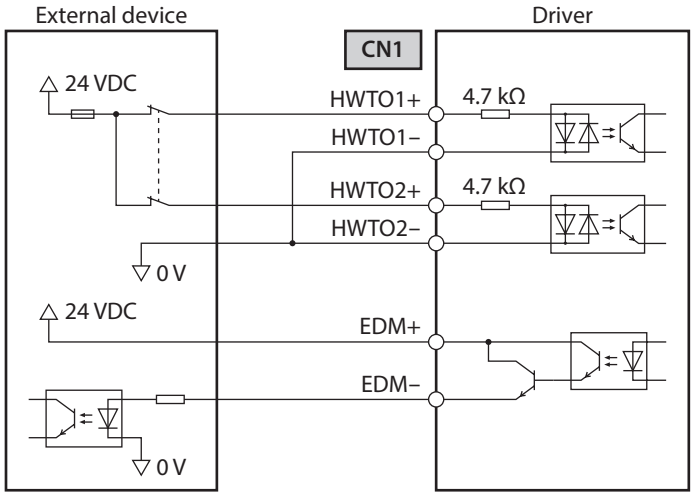
6-1 Block diagram

At the time of shipment, both the HWTO1 input and HWTO2 input are connected with a jumper wires and are being ON.



Signal name	Specification
HWTO1+ input, HWTO1– input HWTO2+ input, HWTO2– input	24 VDC±10 %
EDM+ output, EDM– output	30 VDC or less, 50 mA or less Output saturated voltage 1.1 V

6-2 Wiring example



- Separately provide contacts to operate the HWTO1 input and the HWTO2 input.
- Turning both the HWTO1 input and the HWTO2 input OFF will execute the ETO function.
- Use the EDM output to monitor an error of the ETO function.

6-3 Detection for error of the ETO function

When the ETO function is properly operated, the combination of the HWTO1 input, the HWTO2 input, and the EDM output is any of the following.

HWTO1 input	HWTO2 input	EDM output	Driver status	Motor excitation
ON	**ON**	OFF	Normal	Excitation
ON	OFF	OFF	An alarm of emergency stop circuit error is generated. *	Non-excitation
OFF	**ON**	OFF		
OFF	OFF	**ON**	The driver operates according to the setting of the "HWTO mode selection" parameter. (ETO-mode or alarm-shutdown)	Non-excitation

* It is output when a value in the "HWTO delay time of checking dual system" parameter is set to "11 to 100 ms."

Combinations other than the above represent that an error occurs in the ETO function. Check with the table next.

HWTO1 input	HWTO2 input	EDM output	Driver status
ON	**ON**	**ON**	Error in ETO function
ON	OFF	**ON**	
OFF	**ON**	**ON**	
OFF	OFF	OFF	

If an error occurs in the ETO function, a failure of the driver or external devices, or a wiring error may have caused. Check the cause and take a measure immediately.

6-4 Reset of ETO-mode

■ When the “HWTO mode selection” parameter is set to “0: ETO-mode”

Reset the ETO-mode using a signal that has set the parameter of the ETO reset action.
When the signal that has set the parameter is turned from OFF to ON, the ETO-mode is reset.
Be sure to turn the HWTO1 input and the HWTO2 input ON before turning the signal that has set the parameter ON.

Note

- If either of the HWTO1 input or the HWTO2 input is OFF, the ETO-mode cannot be reset.
- When an alarm is generated, reset the alarm before resetting the ETO-mode.

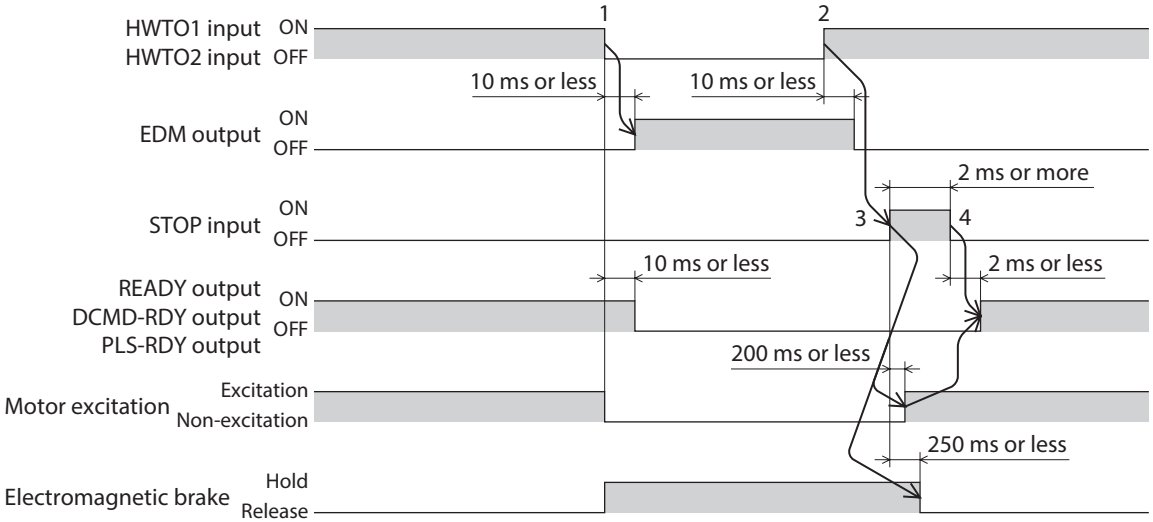
■ When the "HWTO mode selection" parameter is "1: Alarm-shutdown"

To reset the ETO-mode, turn the ALM-RST input ON. (It is enabled at the ON edge.)

6-5 Timing chart

Note Be sure to check the motor is in a standstill state before executing the ETO function. If the ETO function is executed while the motor is operated, it may cause damage to the motor, driver, or equipment.

1. When both the HWTO1 input and HWTO2 input are turned OFF, the EDM output is turned ON. The power supplying to the motor is cut off.
2. Turn the HWTO1 input and the HWTO2 input ON.
3. Turn the STOP input ON.
   The power is supplied to the motor, and excitation of the motor is restarted.
4. Turn the STOP input OFF.
   The READY output, the DCMD-RDY output, and the PLS-RDY output is turned ON.
5. Resume the operation after checking the output signals in the step 4 have been turned ON.



6-6 To use this product safely

- **When the ETO function is used, be sure to conduct a risk assessment of equipment in advance to satisfy the safety requirements of the entire system.**
- **The ETO function is designed based on the assumption that the motor is in a standstill state. Do not execute the ETO function while the motor is rotating.**
- **If the ETO function is executed while the motor is operated, an excessive regenerative voltage may cause damage to the driver. Connect our regeneration resistor RGB100 to prevent damage due to regenerative voltage.**
- **Even if the ETO function is activated, the following potential risks can be estimated. Be sure to confirm the safety by conducting a risk assessment.**
  - The motor output shaft may be rotated by an external force. If the motor output shaft is kept in place, install an external brake mechanism or equivalent. The brake mechanism of the electromagnetic brake motor is used for the purpose to hold the position. Do not use the brake mechanism of the electromagnetic brake motor for braking the motor rotation.
  - If the ETO function is activated, the driver stops supplying the power to the motor. However, the input power to the main power supply and control power supply is not shut off, and the driver is not electrically isolated. Before performing maintenance or inspection, always turn off the main power supply and control power supply, and check the PWR/ALM LED and the CHARGE LED are turned off. Residual voltage may cause electric shock.
- **The EDM output is not an output signal to ensure the safety. Do not use the EDM output for any other purpose except for monitoring a failure.**

7 Inspection and maintenance

7-1 Inspection

It is recommended that periodic inspections are conducted for the items listed below after each operation of the motor. If any failure is found, discontinue any use and contact your nearest Oriental Motor sales office.

■ Inspection item

- Check if the openings in the driver are clogged.
- Check if any of the screws having installed the driver or connection parts of the driver is loose.
- Check if dust is deposited on the driver.
- Check if the driver has unusual smells or appearance defects.

Note The driver uses semiconductor components. Static electricity may damage the semiconductor components of the driver, so be extremely careful when handling them.

7-2 Warranty

Check on the Oriental Motor Website or General Catalog for the product warranty.

7-3 Disposal

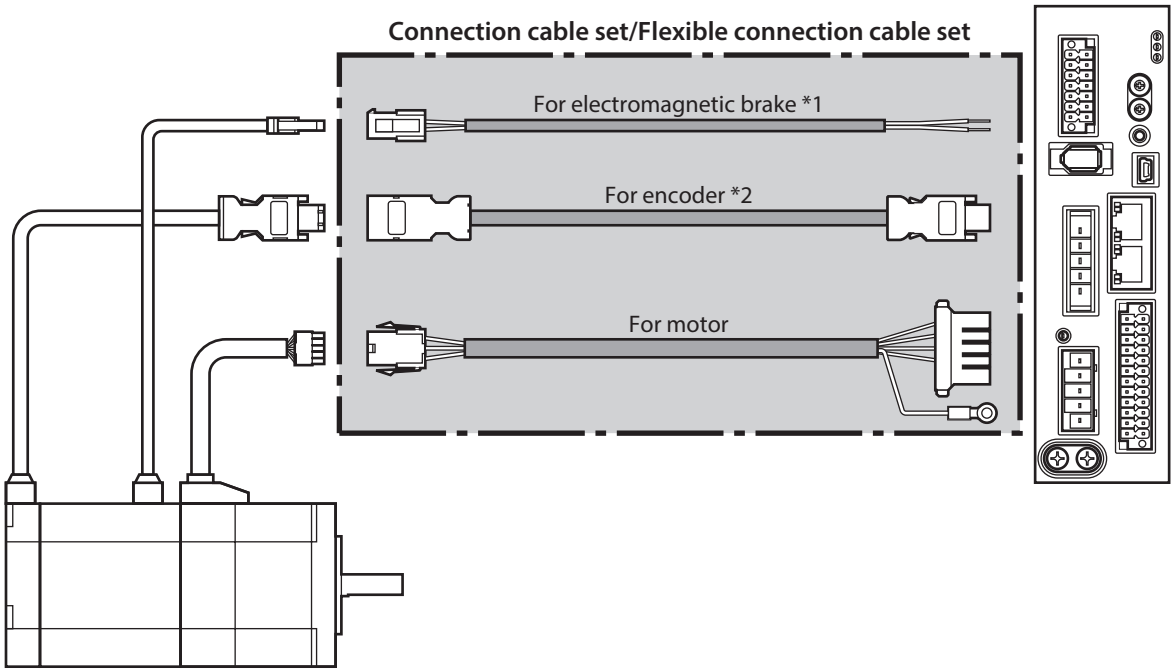
Dispose the product correctly in accordance with laws and regulations, or instructions of local governments.

8 Cables

8-1 Connection cable

■ Connection cable set/Flexible connection cable set

These cables are used when connecting a motor and a driver. It is a set of two cables for the motor and the encoder. For the cable set of electromagnetic brake motors, a set of three cables for the motor, the encoder, and the electromagnetic brake is provided.



*1 Only when the motor is the electromagnetic brake type.
*2 Use the cable for encoder when the length of the encoder cable of motor is not enough.

memo When installing the motor on a moving part, use a flexible cable offering excellent flexibility.

● **Connection cable set**

For motor/encoder

Model	Length [m (ft.)]
CC005VZF	0.5 (1.6)
CC010VZF	1 (3.3)
CC015VZF	1.5 (4.9)
CC020VZF	2 (6.6)
CC025VZF	2.5 (8.2)
CC030VZF	3 (9.8)
CC040VZF	4 (13.1)
CC050VZF	5 (16.4)
CC070VZF	7 (23.0)
CC100VZF	10 (32.8)
CC150VZF	15 (49.2)
CC200VZF	20 (65.6)

For motor/encoder/ electromagnetic brake

Model	Length [m (ft.)]
CC005VZFB	0.5 (1.6)
CC010VZFB	1 (3.3)
CC015VZFB	1.5 (4.9)
CC020VZFB	2 (6.6)
CC025VZFB	2.5 (8.2)
CC030VZFB	3 (9.8)
CC040VZFB	4 (13.1)
CC050VZFB	5 (16.4)
CC070VZFB	7 (23.0)
CC100VZFB	10 (32.8)
CC150VZFB	15 (49.2)
CC200VZFB	20 (65.6)

- **Flexible connection cable set**

For motor/encoder

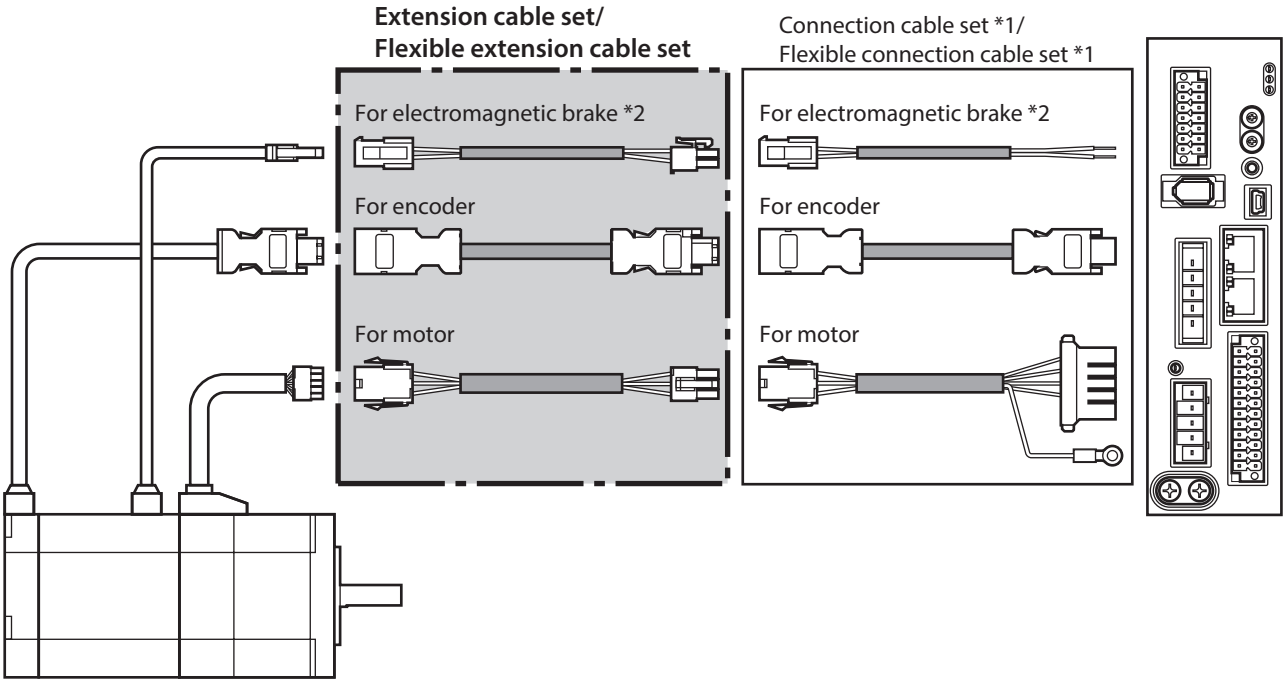
Model	Length [m (ft.)]
CC005VZR	0.5 (1.6)
CC010VZR	1 (3.3)
CC015VZR	1.5 (4.9)
CC020VZR	2 (6.6)
CC025VZR	2.5 (8.2)
CC030VZR	3 (9.8)
CC040VZR	4 (13.1)
CC050VZR	5 (16.4)
CC070VZR	7 (23.0)
CC100VZR	10 (32.8)
CC150VZR	15 (49.2)
CC200VZR	20 (65.6)

For motor/encoder/ electromagnetic brake

Model	Length [m (ft.)]
CC005VZRB	0.5 (1.6)
CC010VZRB	1 (3.3)
CC015VZRB	1.5 (4.9)
CC020VZRB	2 (6.6)
CC025VZRB	2.5 (8.2)
CC030VZRB	3 (9.8)
CC040VZRB	4 (13.1)
CC050VZRB	5 (16.4)
CC070VZRB	7 (23.0)
CC100VZRB	10 (32.8)
CC150VZRB	15 (49.2)
CC200VZRB	20 (65.6)

■ Extension cable set/Flexible extension cable set

These cables are used when extending the connection cable.
Use if the length of the connection cable used is not enough when extending the distance between a motor and a driver.
It is a set of two cables for the motor and the encoder. For the cable set of electromagnetic brake motors, a set of three cables for the motor, the encoder, and the electromagnetic brake is provided.



*1 Use the connection cable used.
*2 Only when the motor is of electromagnetic brake type.

memo
- When installing the motor on a moving part, use a flexible cable offering excellent flexibility.
- When extending the wiring length by connecting an extension cable to the connection cable, keep the total cable length to 20 m (65.6 ft.) or less.

- **Extension cable set**

For motor/encoder

Model	Length [m (ft.)]
CC010VZFT	1 (3.3)
CC020VZFT	2 (6.6)
CC030VZFT	3 (9.8)
CC050VZFT	5 (16.4)
CC070VZFT	7 (23.0)
CC100VZFT	10 (32.8)
CC150VZFT	15 (49.2)

For motor/encoder/ electromagnetic brake

Model	Length [m (ft.)]
CC010VZFBT	1 (3.3)
CC020VZFBT	2 (6.6)
CC030VZFBT	3 (9.8)
CC050VZFBT	5 (16.4)
CC070VZFBT	7 (23.0)
CC100VZFBT	10 (32.8)
CC150VZFBT	15 (49.2)

- **Flexible extension cable set**

For motor/encoder

Model	Length [m (ft.)]
CC010VZRT	1 (3.3)
CC020VZRT	2 (6.6)
CC030VZRT	3 (9.8)
CC050VZRT	5 (16.4)
CC070VZRT	7 (23.0)
CC100VZRT	10 (32.8)
CC150VZRT	15 (49.2)

For motor/encoder/ electromagnetic brake

Model	Length [m (ft.)]
CC010VZRBT	1 (3.3)
CC020VZRBT	2 (6.6)
CC030VZRBT	3 (9.8)
CC050VZRBT	5 (16.4)
CC070VZRBT	7 (23.0)
CC100VZRBT	10 (32.8)
CC150VZRBT	15 (49.2)

8-2 I/O signal cable

This is a shielded cable for good noise immunity to connect the I/O signals of the scanner to the driver. The ground wire useful to grounding is extracted from both ends of the cable. A connector is assembled at the driver side.

Model	Cable length [m (ft.)]	Number of lead wire cores
CC24D005C-1	0.5 (1.6)	24 pcs.
CC24D010C-1	1 (3.3)	
CC24D020C-1	2 (6.6)	

9 Accessories

9-1 Pulse signal converter for noise immunity

This product converts a pulse signal, which is output from the open collector output, to a pulse signal for good noise immunity by outputting the pulse signal again from the differential output.

Model: **VCS06**

9-2 Relay contact protection parts/circuits

- **CR circuit for surge suppression**

  This product is effective to suppress the surge which occurs in a relay contact part. Use it to protect the contacts of the relay or switch.

  Model: **EPCR1201-2**

- **CR circuit module**

  This product is effective to suppress the surge which occurs in a relay contact part. Use it to protect the contacts of the relay or switch.
  Four pieces of CR circuit for surge suppression are mounted on the compact circuit, and this product can be installed to the DIN rail. This product can make the wiring easily and securely since it also supports terminal block connection.

  Model: **VCS02**

9-3 Regeneration resistor

If vertical drive (gravitational operation) such as elevator applications is performed or if sudden start-stop operation of a large inertial load is repeated frequently, connect the regeneration resistor.
Be sure to connect if an alarm or warning of "overvoltage" was generated.

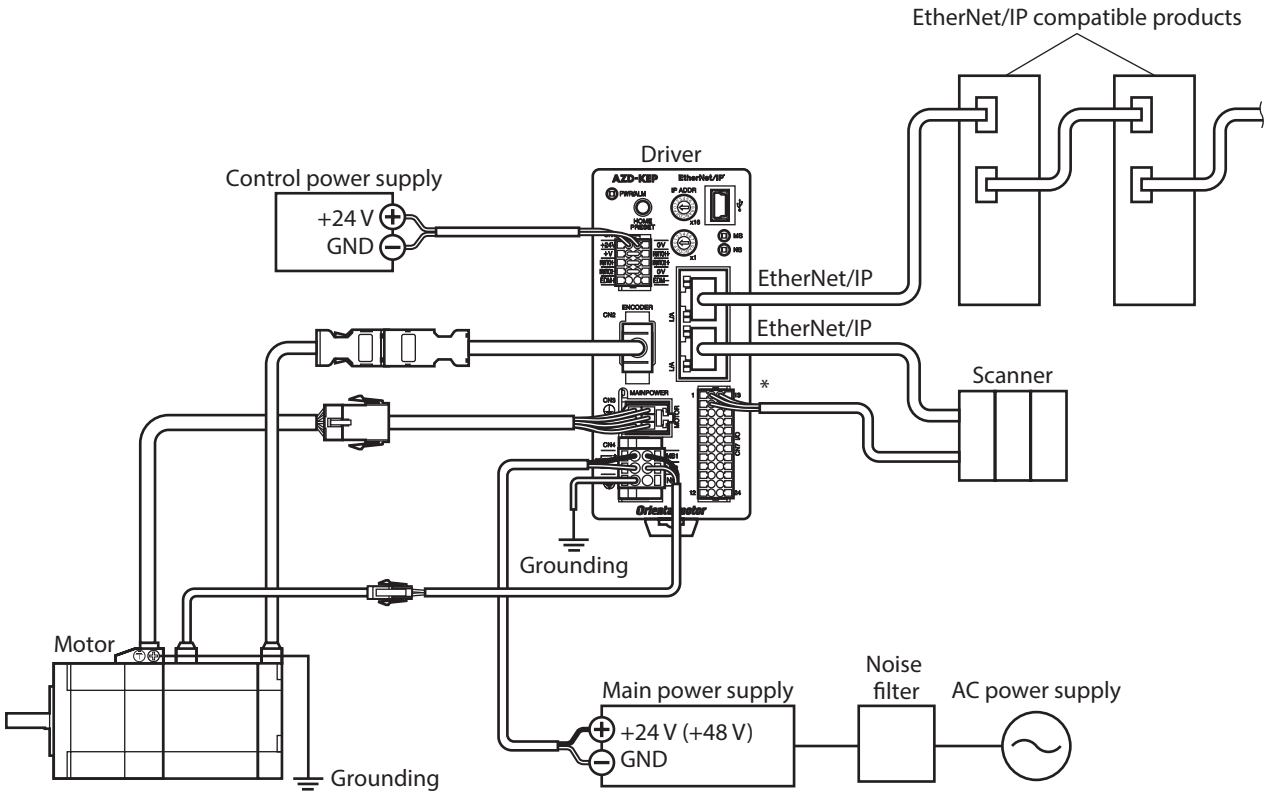
Model: **RGB100**

3 DC power input type

This part explains contents specific to the DC power input type driver.

◆Table of contents

1 System configuration



* Connect when using direct I/O or sensors.

2 Preparation

This chapter explains the items you should check, as well as names and functions of each part.

2-1 Checking the product

Verify that the items listed below are included. Report any missing or damaged items to the Oriental Motor sales office from which you purchased the product.

- Driver .....1 unit
- CN1 connector (10 pins) .....1 pc.
- CN4 connector (6 pins).....1 pc.
- CN7 connector (24 pins) .....1 pc.
- OPERATING MANUAL Driver.....1 copy

Included connector model

Type	Part number	Manufacturer
CN1 connector	DFMC0,5/5-ST-2,54	PHOENIX CONTACT GmbH & Co. KG
CN4 connector	DFMC1,5/3-ST-3,5-LR	PHOENIX CONTACT GmbH & Co. KG
CN7 connector	DFMC0,5/12-ST-2,54	PHOENIX CONTACT GmbH & Co. KG

2-2 How to identify the product model

Check the model number of the driver against the number shown on the nameplate. Refer to p.52 for how to identify the nameplate.

AZD - K EP
1 2 3

1	Series	**AZD**: **AZ** Series driver
2	Power supply input	**K**: 24/48 VDC
3	Network type	**EP**: EtherNet/IP

2-3 Products possible to combine

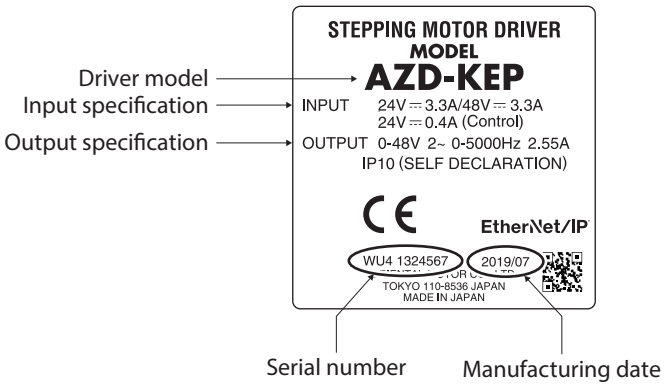
Products with which the driver can be combined are listed below. Check the model name of the product with the nameplate.

Power supply type	Product type	Applicable series	Model name representing series name *1	Example of model name
DC power input	Stepping motor	**AZ** Series	**AZM**	**AZM46AK** **AZM66AK-TS10**
	Motorized actuator	**EAS** Series *2	**EASM**	**EASM4NXD005AZAK**
		EAC Series *2	**EACM**	**EACM2E05AZAK**
		EZS Series *2	**EZSM**	**EZSM6D005AZAK**
		DR Series	**DR**	**DR28G2.5B03-AZAKU** **DR28T1B03-AZAKD-F**
		DRS2 Series	**DRSM**	**DRSM60-05A4AZAK**
		DGII Series	**DGM** **DGB**	**DGM85R-AZAK** **DGB85R12-AZAKR**
		EH Series	**EH**	**EH4-AZAKH**

*1 The driver described in this manual can be combined with products that begin with these model names.
*2 For these motorized actuators, the equipped motors have been evaluated to affix the CE Marking. Check the model name of the equipped motor with the nameplate.

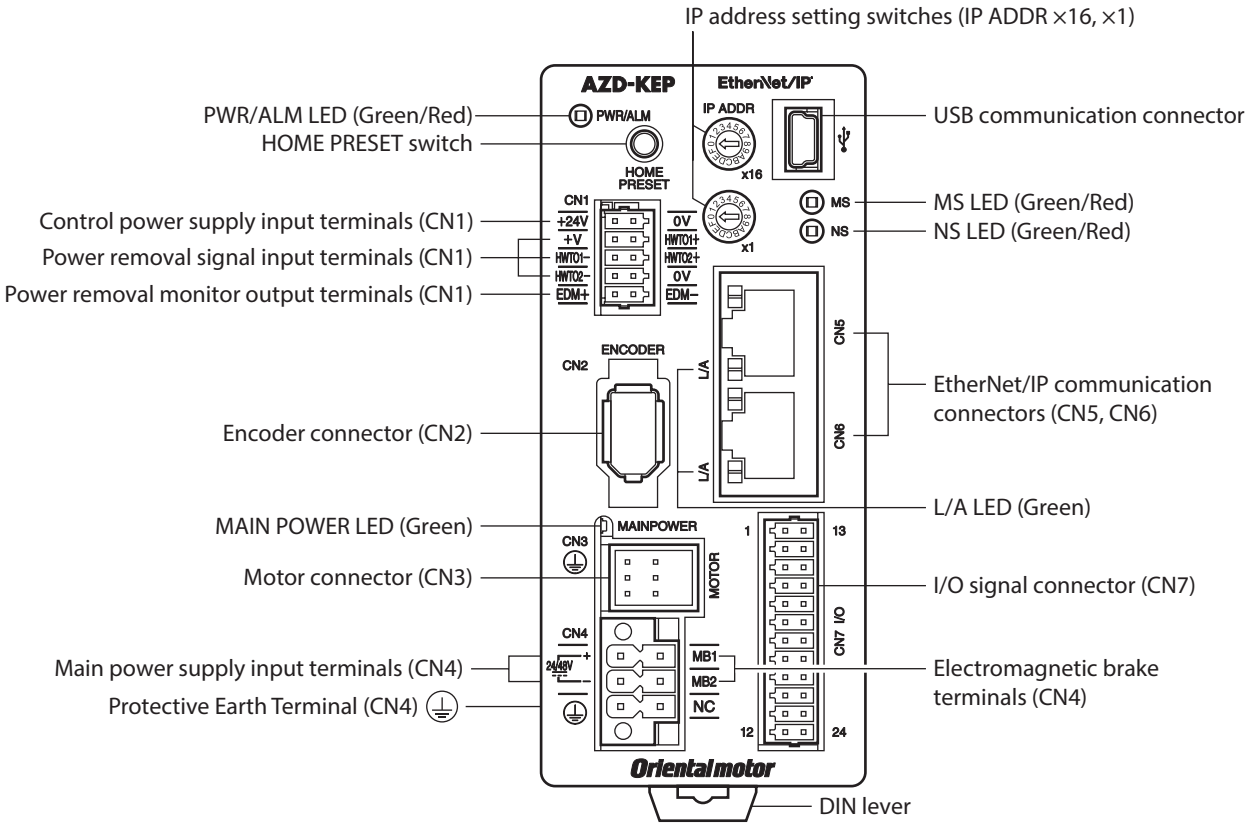
2-4 Information about nameplate

The figure shows an example.



memo The position describing the information may vary depending on the product.

2-5 Names and functions of parts



Type	Name	Sign	Description
LED	PWR/ALM LED (Green/Red)	PWR/ALM	• This LED is lit in green while the control power supply is turned on. • If an alarm (protective function) is generated, the LED will blink in red. • If the power removable function (p.71) is triggered, the LED will blink in green. • If information is generated, the LED will simultaneously blink in red and green twice. (Green and red colors may overlap and it may be visible to orange.)
	MAIN POWER LED (Green)	MAIN POWER	This LED is lit while the main power supply is turned on.
	MS LED (Green/Red)	MS	This LED indicates the status of the driver.
	NS LED (Green/Red)	NS	This LED indicates the communication status of EtherNet/IP.
	L/A LED (Green)	L/A	This LED indicates the LINK/ACT status of EtherNet/IP.
Switch	IP address setting switches	IP ADDR ×16 IP ADDR ×1	These switches are used to set an IP address. Factory setting: 00 (×16: 0, ×1: 0)
	HOME PRESET switch	HOME PRESET	This switch is used to set the starting position (home position) when positioning operation is performed.
Connector	Encoder connector (CN2)	ENCODER	Connects the encoder.
	Motor connector (CN3)	MOTOR	Connects the motor.
	USB communication connector		Connects a PC in which the **MEXE02** has been installed. (USB2.0 mini-B port)
	EtherNet/IP communication connectors (CN5, CN6)	–	Connects the EtherNet/IP communication cable.
	I/O signal connector (CN7)	I/O	Connects when using direct I/O or sensors.
Terminal	Control power supply input terminals (CN1)	+24V, 0V	Connects the control power supply.
	Power removal signal input terminals (CN1)	HWTO1+, HWTO1– HWTO2+, HWTO2–	Connects switches or the scanner.
	Power removal monitor output terminals (CN1)	EDM+, EDM–	Connects the scanner.
	Main power supply input terminals (CN4)	+, –	Connects the main power supply.
	Electromagnetic brake terminals (CN4)	MB1, MB2	Connects the lead wires from the electromagnetic brake.
	Protective Earth Terminal (CN4)		Ground using a grounding wire of AWG18 to 16 (0.75 to 1.25 mm^2).
Other	DIN lever	–	This is used to install the driver to a DIN rail.

2-6 Indication of LEDs

■ PWR/ALM LED

This LED indicates the status of the driver.

LED status		Description
Green	Red	
Unlit	Unlit	The control power supply is not turned on.
Lit	Unlit	The control power supply is turned on.
Unlit	Blinking	An alarm is being generated. Details about the generated alarm can be checked by counting the number of times the LED blinks. The LED is lit in green when the alarm is reset.
Blinking	Unlit	The power removable function has been activated. The LED is lit in green when the power removable function is released.
Blinking twice at the same time *		• Information is being generated. The LED is lit in green when the information is cleared. • Teaching, remote operation is being executed with the **MEXE02**. The LED is lit in green when teaching, remote operation is complete.
Blinking at the same time *		The interlock was released by holding down the HOME PRESET switch. The LED is lit in green when the time set in the "Extended input (EXT-IN) interlock releasing time" parameter is elapsed.
Lit at the same time *		The input signal assigned to the HOME PRESET switch is being executed. The LED is lit in green when it is complete.
Repeating "Green → Red → Simultaneously lit → Unlit"		This is the driver simulation mode.

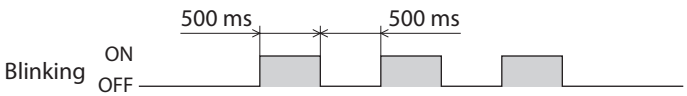
* Green and red colors may overlap and it may be visible to orange.

■ MS LED

This LED indicates the status of the driver.

LED status		Description
Green	Red	
Unlit	Unlit	The control power supply of the driver is not turned on.
Blinking	Unlit	The communication setting of EtherNet/IP is invalid.
Lit	Unlit	The driver operates properly.
Unlit	Blinking	• An alarm that can be reset with EtherNet/IP or the **MEXE02** was generated. • The setting of an IP address is duplicated in the same system.
Unlit	Lit	An alarm that cannot be reset with EtherNet/IP or the **MEXE02** was generated.
Blinking alternately		Self-diagnosis when turning on the power is executing.

The timing to blink the LED is as follows.

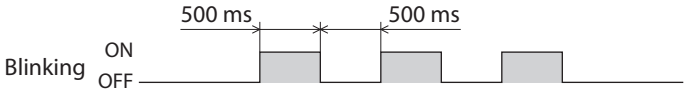


■ NS LED

This LED indicates the communication status of EtherNet/IP.

LED status		Description
Green	Red	
Unlit	Unlit	• In an offline state. • The control power supply of the driver is not turned on.
Blinking	Unlit	In an online state. Connection with the scanner is not established.
Lit	Unlit	In an online state. Connection with the scanner is being established.
Unlit	Blinking	Connection with the scanner became time-out.
Unlit	Lit	The setting of an IP address is duplicated in the same system.
Blinking alternately		Self-diagnosis when turning on the power is executing.

The timing to blink the LED is as follows.



■ L/A LED

This LED indicates the LINK/ACT status of EtherNet/IP.

LED status	Description
Unlit	• In an offline state. • The frame of EtherNet/IP is not sent and received.
Blinking	• In an online state. • The frame of EtherNet/IP is sent and received.
Lit	• In an online state. • The frame of EtherNet/IP is not sent and received.

3 Installation

This chapter explains the installation location and installation method of the driver.

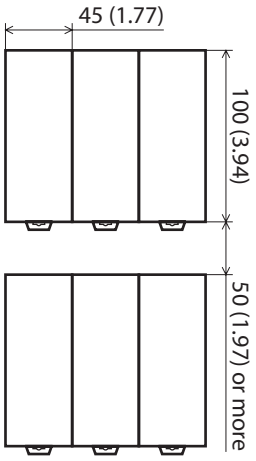
3-1 Installation location

The driver is designed and manufactured to be incorporated in an equipment. Install it in a well-ventilated location that provides easy access for inspection. The location must also satisfy the following conditions:

- Inside an enclosure that is installed indoors (provide vent holes)
- Operating ambient temperature: 0 to +50°C (+32 to +122 °F) (non-freezing)
- Operating ambient humidity: 85 % or less (non-condensing)
- Area that is free of explosive atmosphere or toxic gas (such as sulfuric gas) or liquid
- Area not exposed to direct sun
- Area free of excessive amount of dust, iron particles or the like
- Area not subject to splashing water (rain, water droplets), oil (oil droplets) or other liquids
- Area free of excessive salt
- Area not subject to continuous vibrations or excessive shocks
- Area free of excessive electromagnetic noise (from welders, power machinery, etc.)
- Area free of radioactive materials, magnetic fields or vacuum
- Up to 1,000 m (3,300 ft.) above sea level

3-2 Installation method

Mount the driver to a 35 mm (1.38 in.) width DIN rail.
When installing two or more drivers in parallel, it is possible to install them closely in the horizontal direction.
Provide a minimum clearance of 50 mm (1.97 in.) in the vertical direction.
When installing three or more drivers closely, the heat generation of the inside drivers become high. Install the less frequently used drivers toward the inside. Also, use the drivers in conditions that an ambient temperature is 0 to +40 °C (+32 to +104 °F) and the stop current is 50 % or less.



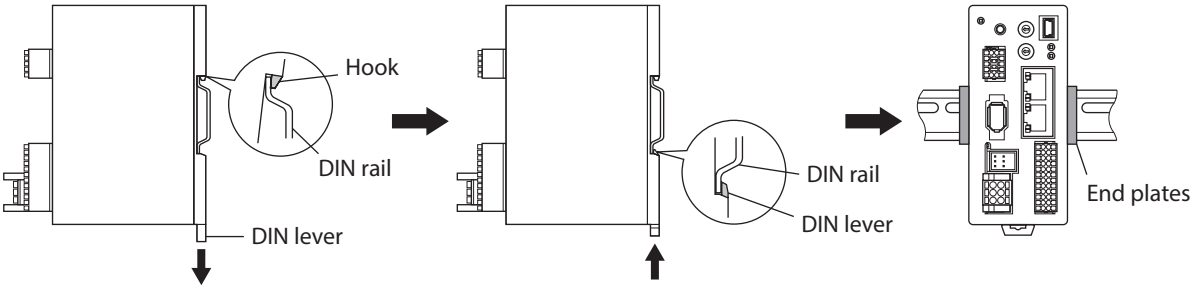
Unit: mm (in.)

Note

- Install the driver inside an enclosure whose pollution degree is 2 or better environment, or whose degree of protection is IP54 minimum.
- Do not install any equipment that generates a large amount of heat or noise near the driver.
- Do not install the driver underneath the scanner or other equipment vulnerable to heat.
- If the ambient temperature of the driver exceeds 50 °C (122 °F), improve the ventilation condition such as providing forced cooling by using fans or creating spaces between the drivers.
- Be sure to install the driver vertically (in vertical position).

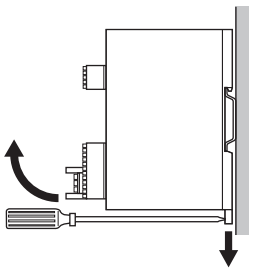
■ Mounting to DIN rail

1. Pull down the DIN lever of the driver and lock it. Hang the hook at the rear to the DIN rail.
2. Hold the driver to the DIN rail, and push up the DIN lever to secure.
3. Secure both sides using end plates.



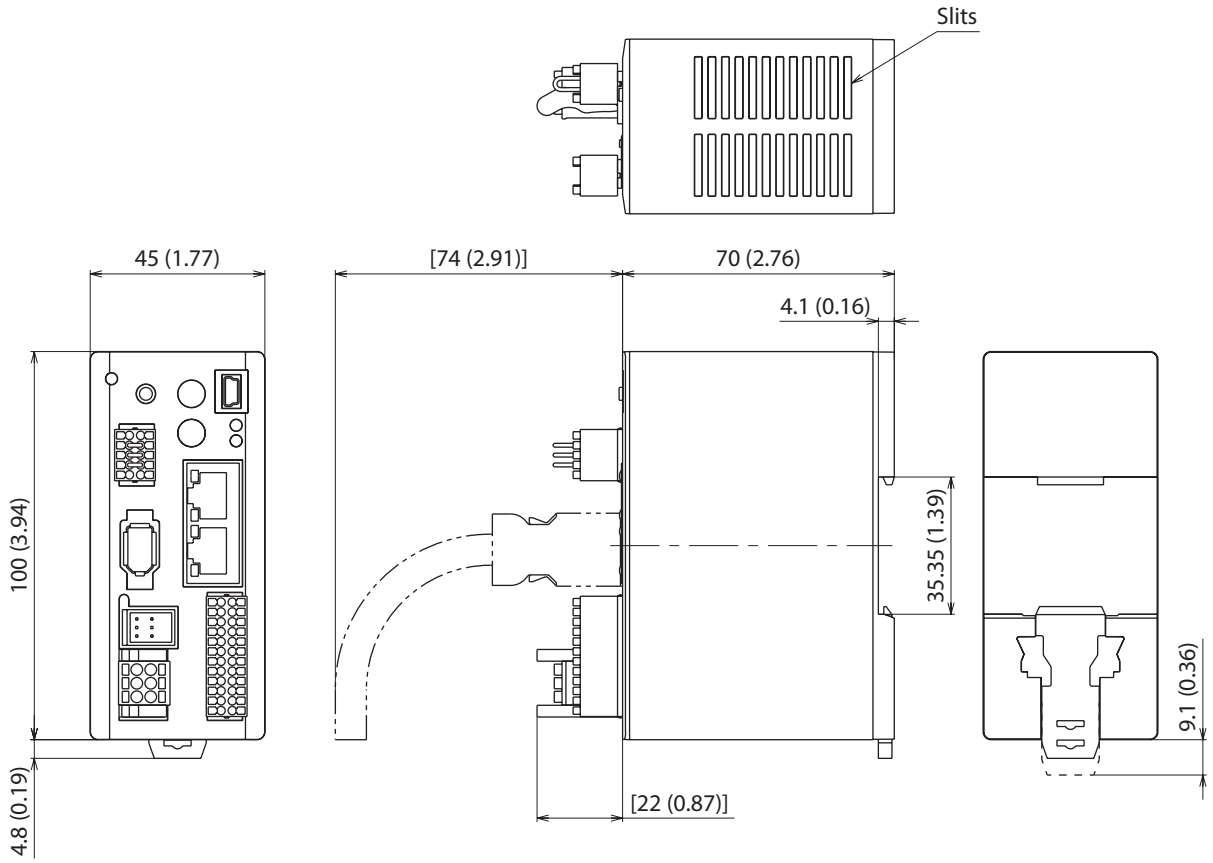
Removing from DIN rail

Pull the DIN lever down until it locks using a slotted screwdriver, and lift the bottom of the driver to remove it from the rail. Use force of about 10 to 20 N (2.2 to 4.5 lb.) to pull the DIN lever to lock it. Excessive force may damage the DIN lever.



■ Dimensions

- Unit: mm (in.)
- Mass: 0.18 kg (0.4 lb.)



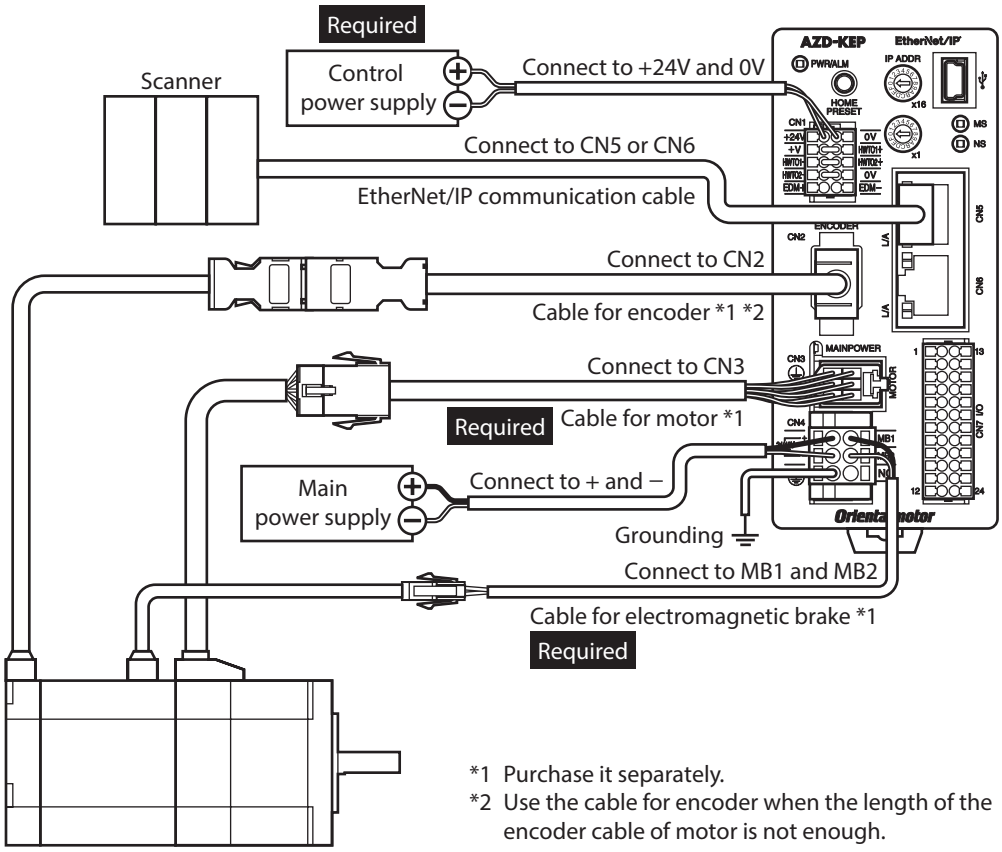
4 Connection

This chapter explains a connection example of a driver and a motor, connection methods of power supplies, the grounding method, and others.
The installation and wiring methods in compliance with the EMC Directive as well as protection against noise are also explained.

⚠WARNING For protection against electric shock, do not turn on the power supply until the wiring is completed.

4-1 Connection example

The figure shows models for the electromagnetic brake type.



*1 Purchase it separately.
*2 Use the cable for encoder when the length of the encoder cable of motor is not enough.

Note

- Connect the connectors securely. Insecure connections may cause malfunction or damage to the motor or driver.
- The lead wires of the "cable for electromagnetic brake" have polarities, so connect them in the correct polarities. If the lead wires are connected with their polarities reversed, the electromagnetic brake will not operate properly.
- Do not wire the power supply cable of the driver in the same cable duct with other power lines or motor cable. Doing so may cause malfunction due to noise.
- Keep 20 m (65.6 ft.) or less for the wiring distance between the motor and the driver. To extend more than 20 m (65.6 ft.) may result in the driver heat generation or increase of the electrical noise emitted from the product.

memo

- Before connecting or disconnecting a connector, turn off the main power supply and control power supply, and check the PWR/ALM LED and the MAIN POWER LED have been turned off.
- When pulling off the motor cable, do so while pressing the latches on the connector with fingers.
- When installing the motor on a moving part, use a flexible cable offering excellent flexibility. Refer to p.76 for the model name.

■ Electrical wire size

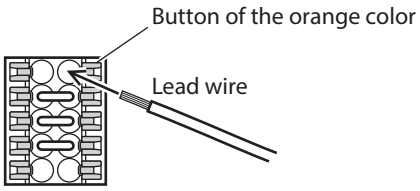
Connector	Terminal symbol	Recommended wire size
CN1	+24V, 0V, HWTO1+, HWTO1–, HWTO2+, HWTO2–, EDM+, EDM–	Stranded wire or solid wire AWG26 to 20 (0.14 to 0.5 mm^2)
CN4	+, –, MB1, MB2	Stranded wire or solid wire AWG24 to 16 (0.2 to 1.25 mm^2)
	⏚	Stranded wire or solid wire AWG18 to 16 (0.75 to 1.25 mm^2)
CN7	–	Stranded wire or solid wire AWG26 to 20 (0.14 to 0.5 mm^2)

4-2 Connecting the control power supply

■ Wiring method of CN1 connector

- Applicable lead wire: AWG26 to 20 (0.14 to 0.5 mm^2)
- Stripping length of wire insulation: 7 mm (0.28 in.)

1. Strip the insulation of the lead wire.
2. Insert the lead wire while pushing the button of the orange color with a slotted screwdriver.
3. After having inserted, release the button to secure the lead wire.



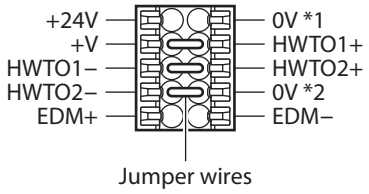
■ Power supply current capacity

Input power supply voltage	Power supply current capacity	
	Without electromagnetic brake	With electromagnetic brake
24 VDC±5 % *1	0.15 A	0.4 A *2

*1 When an electromagnetic brake motor is used, if the wiring distance between the motor and the driver is extended to 20 m (65.6 ft.) using our cable, the input voltage is 24 VDC±4 %.
*2 The **AZM46** type is 0.23 A.

■ Pin assignment

There are two terminals for 0 V: One for control power supply and the other is for internal connection. Check each position in the figure and table shown.



Sign	Description
+24V, 0V *1	Connects the control power supply.
HWTO1+, HWTO1– HWTO2+, HWTO2–	Connects switches or the scanner. If the power removal function is not used, connect a jumper wire (included) between the terminals as shown in the figure.
EDM+, EDM–	Connects the scanner.
+V, 0V *2	These are for internal connection. Do not connect anything. If the power removal function is not used, connect a jumper wire (included) between the terminals as shown in the figure.

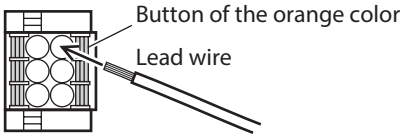
4-3 Connecting the main power supply and grounding

The CN4 connector has the power supply terminal and Protective Earth Terminal. The applicable wire size varies between lead wires for a power supply and Protective Earth. Be sure to use proper lead wires.

■ Wiring method of CN4 connector

- Applicable lead wire For power supply: AWG24 to 16 (0.2 to 1.25 mm^2)
  For grounding: AWG18 to 16 (0.75 to 1.25 mm^2)
- Stripping length of wire insulation: 10 mm (0.39 in.)

1. Strip the insulation of the lead wire.
2. Insert the lead wire while pushing the button of the orange color with a slotted screwdriver.
3. After having inserted, release the button to secure the lead wire.



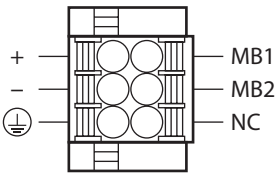
■ Power supply current capacity

The current capacity for the power supply varies depending on the product combined.
Check the current capacity in reference to the equipped motor model name when using the **EAS** Series, **EAC** Series, or **EZS** Series.

Model	Input power supply voltage	Power supply current capacity
AZM14	24 VDC±5 %	0.4 A or more
AZM15		0.5 A or more
AZM24		1.6 A or more
AZM26		1.5 A or more
DGM60		1.6 A or more
DR28		1.3 A or more
EH4		1.6 A or more
AZM46	24 VDC±5 % 48 VDC±5 %	1.5 A or more
AZM48		2.1 A or more
AZM66		3.3 A or more
AZM69		3.1 A or more
DGB85		1.5 A or more
DGB130		3.3 A or more
DGM85		1.5 A or more
DGM130		3.3 A or more
DRSM42		1.5 A or more
DRSM60		2.2 A or more

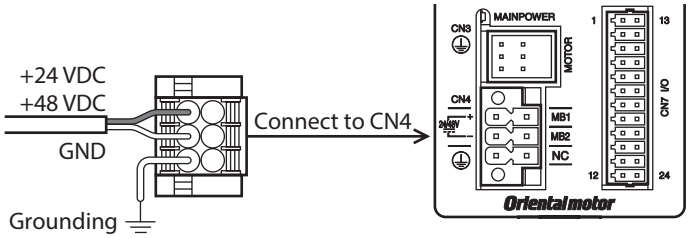
■ Pin assignment

Sign	Description
+	Main power supply input (24 VDC/48 VDC)
–	Main power supply GND
⏚	Protective Earth
MB1	Electromagnetic brake – (black)
MB2	Electromagnetic brake + (white)
NC	Not connected



■ Grounding the driver

Be sure to ground the driver.
Do not share the grounding wire with a welder or any other power equipment.
Note that the applicable wire size varies between lead wires for a power supply and Protective Earth.

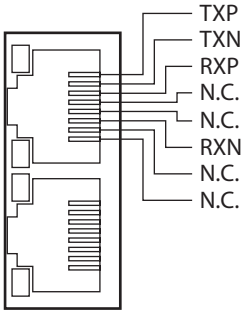


4-4 Connecting the EtherNet/IP communication cable

Connect the EtherNet/IP communication cable to the EtherNet/IP communication connector (CN5, CN6).

■ Pin assignment

Signal name	Description
TXP	Transmitted data +
TXN	Transmitted data –
RXP	Received data +
N.C.	–
N.C.	–
RXN	Received data –
N.C.	–
N.C.	–



4-5 Connecting the USB cable

Using a USB cable of the following specification, connect a PC in which the **MEXE02** has been installed to the USB communication connector.

Specification	USB2.0 (full speed)
Cable	Length: 3 m (9.8 ft.) or less Shape: A to mini B

memo

- Connect the driver and PC directly using the USB cable.
- In large electrically noisy environments, use the USB cable with a ferrite core or install a ferrite core to the USB cable.

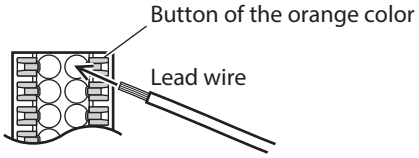
4-6 Connecting the I/O signals

Connect when using direct I/O or sensors.

■ Wiring method of CN7 connector

- Applicable lead wire: AWG26 to 20 (0.14 to 0.5 mm^2)
- Stripping length of wire insulation: 7 mm (0.28 in.)

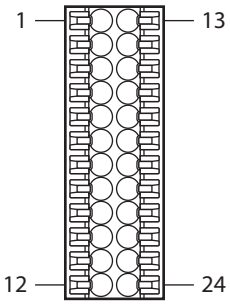
1. Strip the insulation of the lead wire.
2. Insert the lead wire while pushing the button of the orange color with a slotted screwdriver.
3. After having inserted, release the button to secure the lead wire.



memo Be certain the I/O signal cable is as short as possible. The maximum input frequency will decrease as the cable length increases.

■ Pin assignment

Pin No.	Signal name *	Description *
1	CW+ [PLS+]	CW pulse input + [Pulse input +]
2	CCW+ [DIR+]	CCW pulse input + [Rotation direction switching input +]
3	IN0	Control input 0 (ZHOME)
4	IN2	Control input 2 (STOP)
5	IN-COM 0-3	IN0 to IN3 inputs common
6	IN4	Control input 4 (FW-JOG)
7	OUT0	Control output 0 (HOME-END)
8	OUT2	Control output 2 (PLS-RDY)
9	OUT4	Control output 4 (MOVE)
10	OUT-COM	Output common
11	ASG+	Phase A pulse output +
12	BSG+	Phase B pulse output +



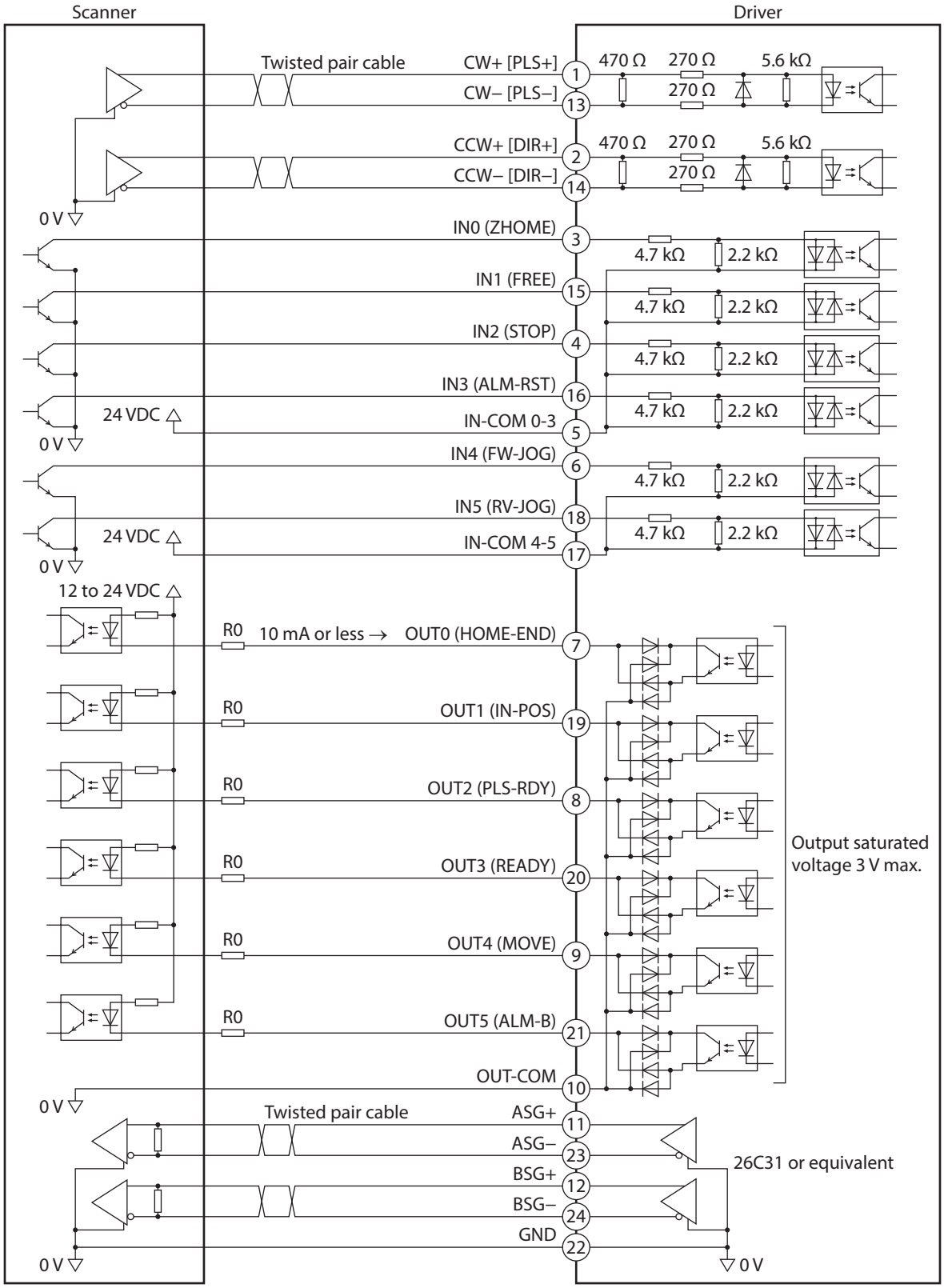
Pin No.	Signal name *	Description *
13	CW– [PLS–]	CW pulse input – [Pulse input –]
14	CCW– [DIR–]	CCW pulse input – [Rotation direction switching input –]
15	IN1	Control input 1 (FREE)
16	IN3	Control input 3 (ALM-RST)
17	IN-COM 4-5	IN4, IN5 inputs common
18	IN5	Control input 5 (RV-JOG)
19	OUT1	Control output 1 (IN-POS)
20	OUT3	Control output 3 (READY)
21	OUT5	Control output 5 (ALM-B)
22	GND	GND
23	ASG–	Phase A pulse output –
24	BSG–	Phase B pulse output –

* Values in brackets [ ] are signals when the 1-pulse input mode is set.
Values in parentheses ( ) are initial values.

■ Connection example with a current sink output circuit

● When the pulse input circuit of the driver is of line driver type

The pin No.1, No.2, No.13, and No.14 are only available to the pulse input. Other functions cannot be assigned.



* Values in brackets [ ] are signals when the 1-pulse input mode is set.
Values in parentheses ( ) are initial values.

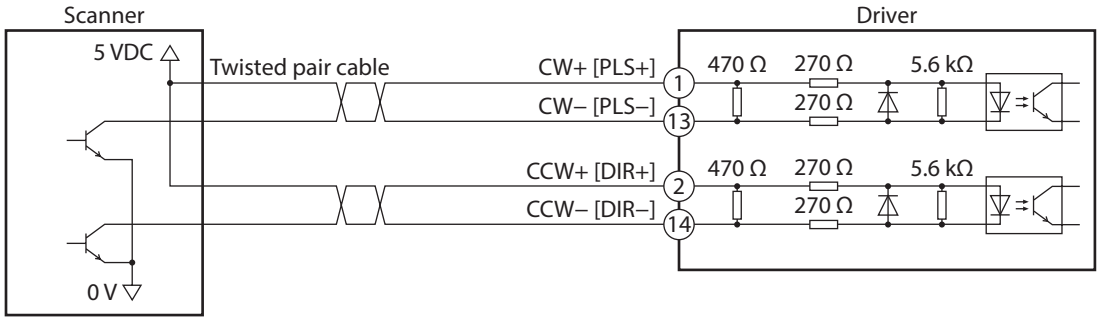
memo
- Use input signals at 24 VDC.
- Use output signals at 12 to 24 VDC, 10 mA or less. If the current exceeds 10 mA, connect an external resistor R0 so that the current becomes 10 mA or less.
- The saturated voltage of the output signal is 3 V maximum.

● **When the pulse input circuit of the driver is of open collector type**

The pin No.1, No.2, No.13, and No.14 are only available to the pulse input. Other functions cannot be assigned.

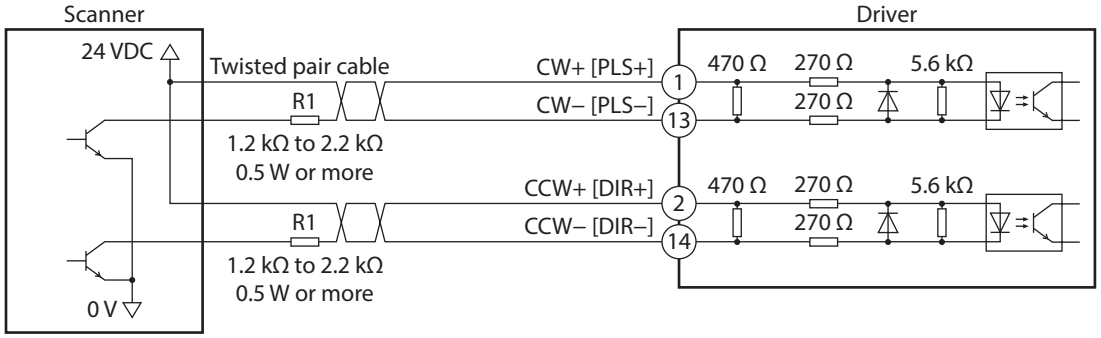
memo Use the CW [PLS] input and CCW [DIR] input at 5 to 24 VDC. When using signals at 24 VDC, connect an external resistor R1 (1.2 kΩ to 2.2 kΩ, 0.5 W or more). When using signals at 5 VDC, apply the voltage directly.

When the voltage of pulse input signals is 5 VDC



* Values in brackets [ ] are signals when the 1-pulse input mode is set.

When the voltage of pulse input signals is 24 VDC

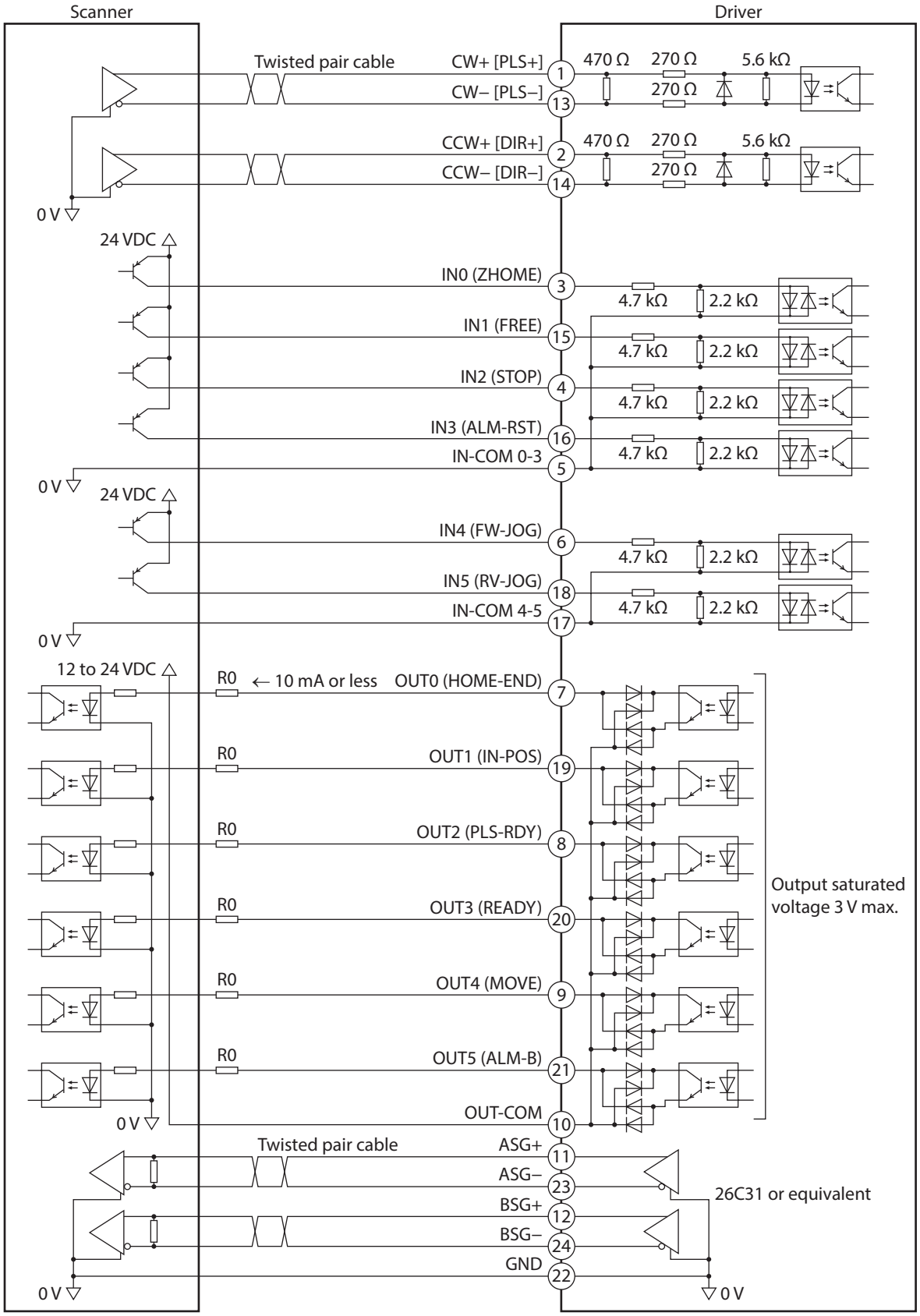


* Values in brackets [ ] are signals when the 1-pulse input mode is set.

■ Connection example with a current source output circuit

● When the pulse input circuit of the driver is of line driver type

The pin No.1, No.2, No.13, and No.14 are only available to the pulse input. Other functions cannot be assigned.



* Values in brackets [ ] are signals when the 1-pulse input mode is set.
Values in parentheses ( ) are initial values.

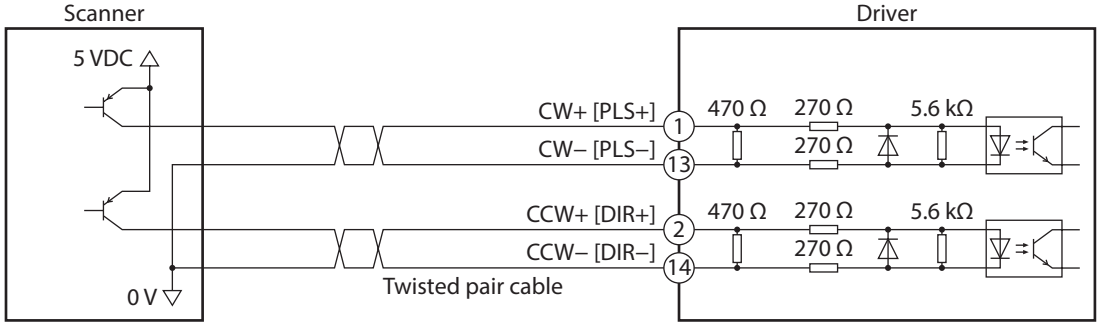
memo
- Use input signals at 24 VDC.
- Use output signals at 12 to 24 VDC, 10 mA or less. If the current exceeds 10 mA, connect an external resistor R0 so that the current becomes 10 mA or less.
- The saturated voltage of the output signal is 3 V maximum.

● **When the pulse input circuit of the driver is of open collector type**

The pin No.1, No.2, No.13, and No.14 are only available to the pulse input. Other functions cannot be assigned.

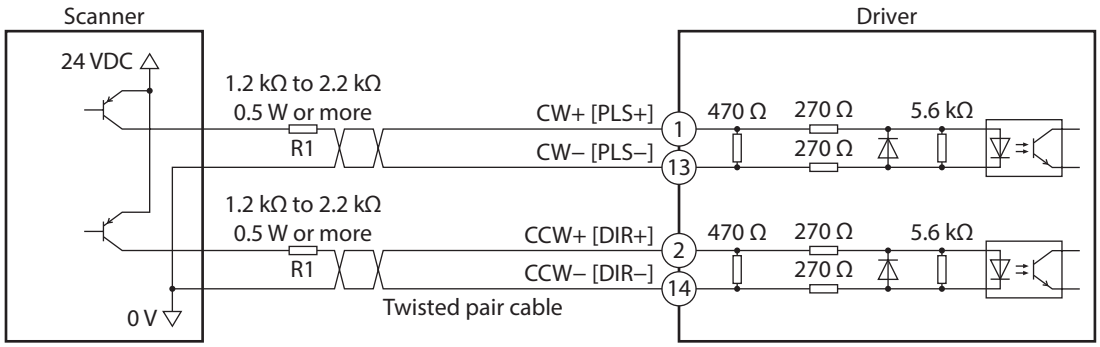
memo Use the CW [PLS] input and CCW [DIR] input at 5 to 24 VDC. When using signals at 24 VDC, connect an external resistor R1 (1.2 kΩ to 2.2 kΩ, 0.5 W or more). When using signals at 5 VDC, apply the voltage directly.

When the voltage of pulse input signals is 5 VDC



* Values in brackets [ ] are signals when the 1-pulse input mode is set.

When the voltage of pulse input signals is 24 VDC



* Values in brackets [ ] are signals when the 1-pulse input mode is set.

4-7 Noise elimination measures

There are two types of electrical noises: One is a noise to invade into the driver from the outside and cause the driver malfunction, and the other is a noise to emit from the driver and cause peripheral equipments malfunction.
For the noise that is invaded from the outside, take measures to prevent the driver malfunction. It is needed to take adequate measures because signal lines are very likely to be affected by the noise.
For the noise that is emitted from the driver, take measures to suppress it.

■ Measures against electrical noise

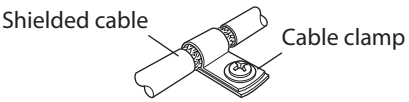
There are the following three methods mainly to take measures against the electrical noise.

● **Noise suppression**

- When relays or electromagnetic switches are used, use noise filters or CR circuits to suppress surge generated by them.
- Use our connection cable when extending the wiring distance between the motor and the driver. Refer to p.76 for the model name. This is effective in suppressing the electrical noise emitted from the motor.
- Cover the driver by a metal plate such as aluminum. This is effective in shielding the electrical noise emitted from the driver.

● Prevention of noise propagation

- Connect a noise filter on the AC input side of the DC power supply.
- Place the power lines, such as the motor and the power supply cables, keeping a distance of 200 mm (7.87 in.) or more from the signal lines, and also do not bundle them or wire them in parallel. If a power cable and a signal cable have to cross, cross them at a right angle.
- Use shielded twisted pair cables for power lines and signal lines.
- Keep cables as short as possible without coiling and bundling extra lengths.
- Grounding multiple points will increase effect to block electrical noise because impedance on the grounding points is decreased. However, ground them so that a potential difference does not occur among the grounding points. I/O signal cable that includes a ground wire are provided in our product line. Refer to p.80 for the model name.
- To ground a shielded cable, use a metal cable clamp that can maintain contact with the entire circumference of the shielded cable, and ground as near the product as possible.



● Suppression of effect by noise propagation

- Loop the noise propagated cable around a ferrite core. Doing so will prevent the propagated noise invades into the driver or emits from the driver. The frequency band in which an effect by the ferrite core can be seen is generally 1 MHz or more. Check the frequency characteristics of the ferrite core used. When increasing the effect of noise attenuation by the ferrite core, loop the cable a lot.
- Change the transmission method of the pulse signal to the line driver type in order to prevent noise effects. If the pulse signal of the scanner is of the open collector type, use our pulse signal converter for noise immunity. Refer to p.81 for the model name.

■ Noise suppression parts

● Noise filter

- Connect a noise filter (or equivalent) in the table on the AC input side of the DC power supply. When a power supply transformer is used, be sure to connect a noise filter on the AC input side of the power supply transformer. Doing so will prevent the propagated noise through the power line. Install the noise filter as close to the input terminals of DC power supply as possible.

Manufacturer	Part number
SOSHIN ELECTRIC CO., LTD.	HF2010A-UPF
Schaffner EMC	FN2070-10-06

- Use the AWG18 (0.75 mm^2) or thicker wire for the input and output cables of the noise filter, and secure firmly using a cable clamp or others so that the cable does not come off the enclosure.
- Place the input cable as far apart as possible from the output cable, and do not wire the cables in parallel. If the input and output cables are placed at a close distance or if they are wired in parallel, the noise in the enclosure affects the power cable through stray capacitance, and the noise suppressing effect will reduce.
- Connect the ground terminal of the noise filter to the grounding point, using as thick and short a wire as possible.
- When connecting a noise filter inside an enclosure, wire the input cable of the noise filter as short as possible. Wiring in long distance may reduce the noise suppressing effect.

■ Our noise suppression products

Check the model names on p.80 and p.81.

● I/O signal cable

This is a shielded cable for good noise immunity to connect the driver and scanner. The ground wire useful to grounding is extracted from both ends of the cable. The EMC measures are conducted using our I/O signal cable.

● Pulse signal converter for noise immunity

This product converts a pulse signal, which is output from the open collector output, to a pulse signal for good noise immunity by outputting the pulse signal again from the differential output.

● Surge suppressor

This product is effective to suppress the surge which occurs in a relay contact part. Connect it when using a relay or electromagnetic switch. CR circuit for surge suppression and CR circuit module are provided.

4-8 Conformity to the EMC Directive

Effective measures must be taken against the EMI that the motor and the driver may give to adjacent control-system equipment, as well as the EMS of the motor and the driver itself, in order to prevent a serious functional impediment in the machinery. The use of the following installation and wiring methods will enable the motor and the driver to be compliant with the EMC Directive. Refer to p.170 for the applicable standards.
Oriental Motor conducts EMC measurements on its motors and drivers in accordance with "Example of installation and wiring."
The user is responsible for ensuring the machine's compliance with the EMC Directive, based on the installation and wiring explained next.

- **Connecting the noise filter**

  In large electrically noisy environments, connect a noise filter. Refer to "Noise filter" on p.67 for details.

- **Connecting the power supply**

  Use a DC power supply compliant with the EMC Directive.
  Wire and ground the power supply over the shortest possible distance using a shielded cable. Refer to "Prevention of noise propagation" on p.67 for how to ground the shielded cable.

- **Connecting the motor cable**

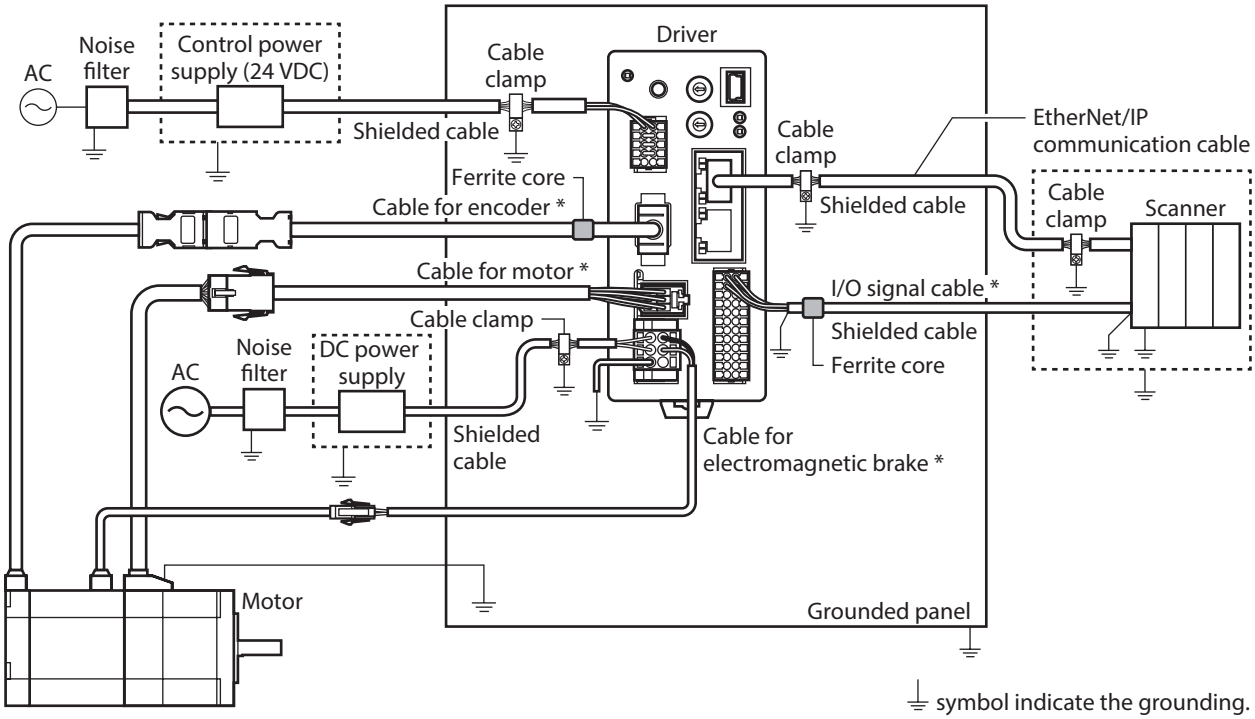
  Use our connection cable when extending the wiring distance between the motor and the driver. Refer to p.76 for the model name.

- **Connecting the signal cable**

  Refer to "Prevention of noise propagation" on p.67.

- **Grounding method**
  - The cable used to ground the motor, the driver, and the noise filter must be as thick and short as possible so that no potential difference is generated.
  - Choose a large, thick and uniformly conductive surface for the grounding point.
  - When installing the motor and the driver, ground their Protective Earth Terminals. Refer to the p.61 for how to ground the driver.

- **Example of installation and wiring**



⏚ symbol indicate the grounding.
--- is a shielded box.
* It is the cable in our products.

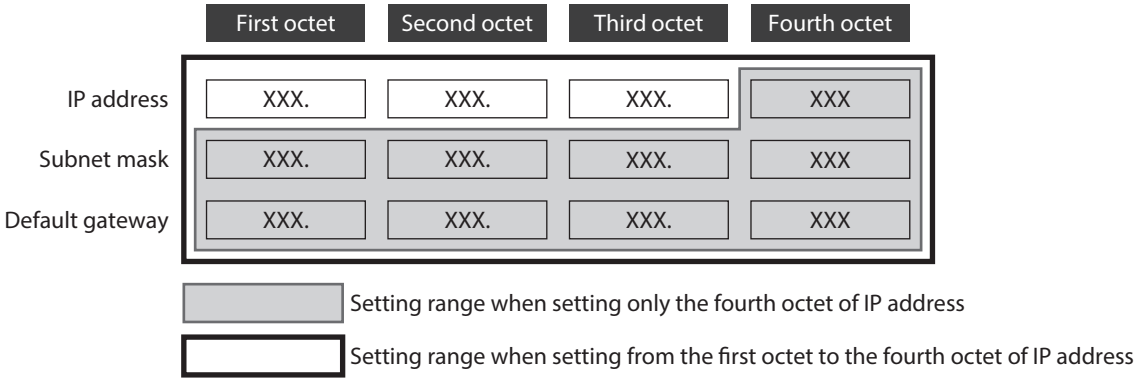
Note The driver uses parts that are sensitive to electrostatic charge. Take measures against static electricity since static electricity may cause the driver to malfunction or suffer damage.

5 Setting of IP address

This chapter explains how to set the IP address.
Set the "subnet mask" and the "default gateway" together with the IP address.

5-1 Setting method

The setting method varies depending on the setting range of the IP address.



■ When setting only the fourth octet of the IP address

Set an IP address with the IP address setting switches of the driver, and the subnet mask and the default gateway with the parameters.

- **Setting of IP address**

Set the fourth octet of the IP address using two IP address setting switches (IP ADDR ×16, ×1).
The IP address setting switches are hexadecimal number. Convert the IP address from decimal to hexadecimal to set.

Factory setting: ×16: 0, ×1: 0 (Setting of parameter or DHCP server is enabled)

Setting example

Setting of switches		Value of IP address	Note
×16	×1		
0	0	The setting of the parameter or DHCP server is enabled.	Whether either of the parameter or the DHCP server is enabled can be checked with the "Configuration control" parameter.
0	1	XXX.XXX.XXX.1	The fourth octet is set to "1."
F	E	XXX.XXX.XXX.254	The fourth octet is set to "254."
F	F	192.168.1.1	This value is applied regardless of the setting of the parameter and DHCP server.

Note

- When the switches were set, turn on the control power supply again. The new setting will be enabled when the control power supply is turned on again.
- When connecting two or more EtherNet/IP compatible products, set so that an IP address is not duplicated. If an IP address is duplicated, a communication error of the "IP address conflict" is detected.

- **Setting of subnet mask and default gateway**

  Set the subnet mask and the default gateway with the parameters.

  Related parameters

Parameter name	Description	Setting range	Initial value
Network mask 1	Sets the first octet of the subnet mask.	0 to 255	255
Network mask 2	Sets the second octet of the subnet mask.		255
Network mask 3	Sets the third octet of the subnet mask.		255
Network mask 4	Sets the fourth octet of the subnet mask.		0
Gateway address 1	Sets the first octet of the default gateway.	0 to 255	0
Gateway address 2	Sets the second octet of the default gateway.		0
Gateway address 3	Sets the third octet of the default gateway.		0
Gateway address 4	Sets the fourth octet of the default gateway.		0

■ When setting from the first octet to the fourth octet of IP address

Set an IP address, subnet mask, and default gateway with the parameters or DHCP server.
The parameters and the DHCP server cannot be used in combination.

- **When setting with parameters**

  Set the IP address setting switches of the driver to 0 (00h) and the "Configuration control" parameter to "0: Parameter."

  Related parameters

Parameter name	Description	Setting range	Initial value
Configuration control	Sets how to obtain the IP address.	0: Parameter 2: DHCP server	2
IP address 1	Sets the first octet of the IP address.	0 to 255	192
IP address 2	Sets the second octet of the IP address.		168
IP address 3	Sets the third octet of the IP address.		1
IP address 4	Sets the fourth octet of the IP address.		1
Network mask 1	Sets the first octet of the subnet mask.	0 to 255	255
Network mask 2	Sets the second octet of the subnet mask.		255
Network mask 3	Sets the third octet of the subnet mask.		255
Network mask 4	Sets the fourth octet of the subnet mask.		0
Gateway address 1	Sets the first octet of the default gateway.	0 to 255	0
Gateway address 2	Sets the second octet of the default gateway.		0
Gateway address 3	Sets the third octet of the default gateway.		0
Gateway address 4	Sets the fourth octet of the default gateway.		0

Note When connecting two or more EtherNet/IP compatible products, set so that an IP address is not duplicated. If an IP address is duplicated, a communication error of the "IP address conflict" is detected.

- **When obtaining from DHCP server**

  The IP address, subnet mask and default gateway are automatically assigned from the DHCP server.
  Set the IP address setting switches of the driver to 0 (00h) and the "Configuration control" parameter to "2: DHCP server."

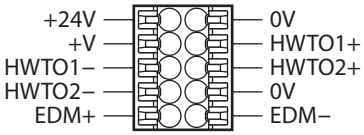
Note If the control power supply is shut off, the IP address obtained from the DHCP server is cleared.

Related parameters

Parameter name	Description	Setting range	Initial value
Configuration control	Sets how to obtain the IP address.	0: Parameter 2: DHCP server	2

6 Power removable function (ETO function: External torque off function)

The power removable function (ETO function: External torque off function) is a function that stops supplying the power to the motor forcibly to put the motor into a non-excitation state if the HWTO input of the CN1 is shut off. This function, which is different from the FREE input, shuts off the power supply to the motor directly on the circuit.
It can be used for the purpose of preventing dangerous movements of the moving part when maintenance of the equipment is performed.



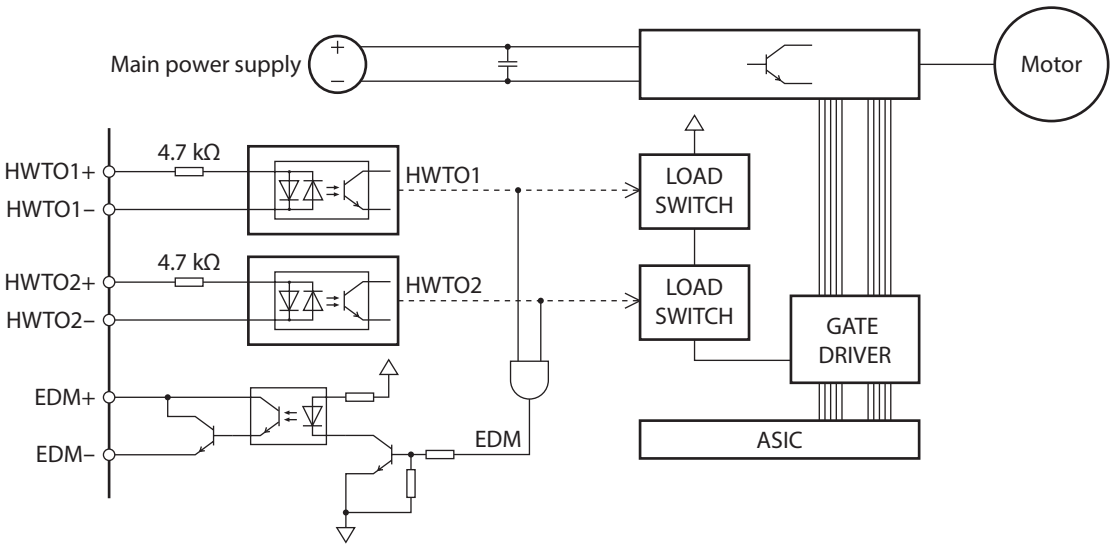
Overview of the ETO function

When either of the HWTO1 input or HWTO2 input is turned OFF, the hardware cuts off power supply to the motor and stops the motor. In this time, the PWR/ALM LED will blink in green.
The electromagnetic brake holds the position when the electromagnetic brake motor is used.

Note Be sure to check the motor is in a standstill state before executing the ETO function. If the ETO function is executed while the motor is operated, it may cause damage to the motor, driver, or equipment.

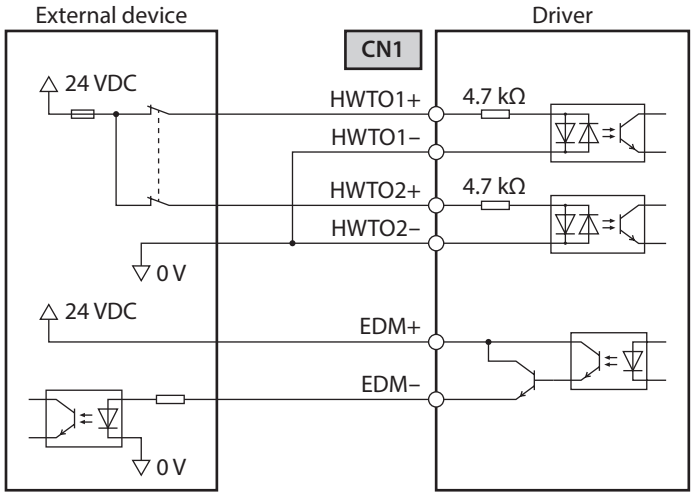
6-1 Block diagram

At the time of shipment, both the HWTO1 input and HWTO2 input are connected with a jumper wires and are being ON.



Signal name	Specification
HWTO1+ input, HWTO1– input HWTO2+ input, HWTO2– input	24 VDC±10 %
EDM+ output, EDM– output	30 VDC or less, 50 mA or less Output saturated voltage 1.1 V

6-2 Wiring example



- Separately provide contacts to operate the HWTO1 input and the HWTO2 input.
- Turning both the HWTO1 input and the HWTO2 input OFF will execute the ETO function.
- Use the EDM output to monitor an error of the ETO function.

6-3 Detection for error of the ETO function

When the ETO function is properly operated, the combination of the HWTO1 input, the HWTO2 input, and the EDM output is any of the following.

HWTO1 input	HWTO2 input	EDM output	Driver status	Motor excitation
ON	**ON**	OFF	Normal	Excitation
ON	OFF	OFF	An alarm of emergency stop circuit error is generated. *	Non-excitation
OFF	**ON**	OFF		
OFF	OFF	**ON**	The driver operates according to the setting of the "HWTO mode selection" parameter. (ETO-mode or alarm-shutdown)	Non-excitation

* It is output when a value in the "HWTO delay time of checking dual system" parameter is set to "11 to 100 ms."

Combinations other than the above represent that an error occurs in the ETO function. Check with the table next.

HWTO1 input	HWTO2 input	EDM output	Driver status
ON	**ON**	**ON**	Error in ETO function
ON	OFF	**ON**	
OFF	**ON**	**ON**	
OFF	OFF	OFF	

If an error occurs in the ETO function, a failure of the driver or external devices, or a wiring error may have caused. Check the cause and take a measure immediately.

6-4 Reset of ETO-mode

■ When the “HWTO mode selection” parameter is set to “0: ETO-mode”

Reset the ETO-mode using a signal that has set the parameter of the ETO reset action.
When the signal that has set the parameter is turned from OFF to ON, the ETO-mode is reset.
Be sure to turn the HWTO1 input and the HWTO2 input ON before turning the signal that has set the parameter ON.

Note

- If either of the HWTO1 input or the HWTO2 input is OFF, the ETO-mode cannot be reset.
- When an alarm is generated, reset the alarm before resetting the ETO-mode.

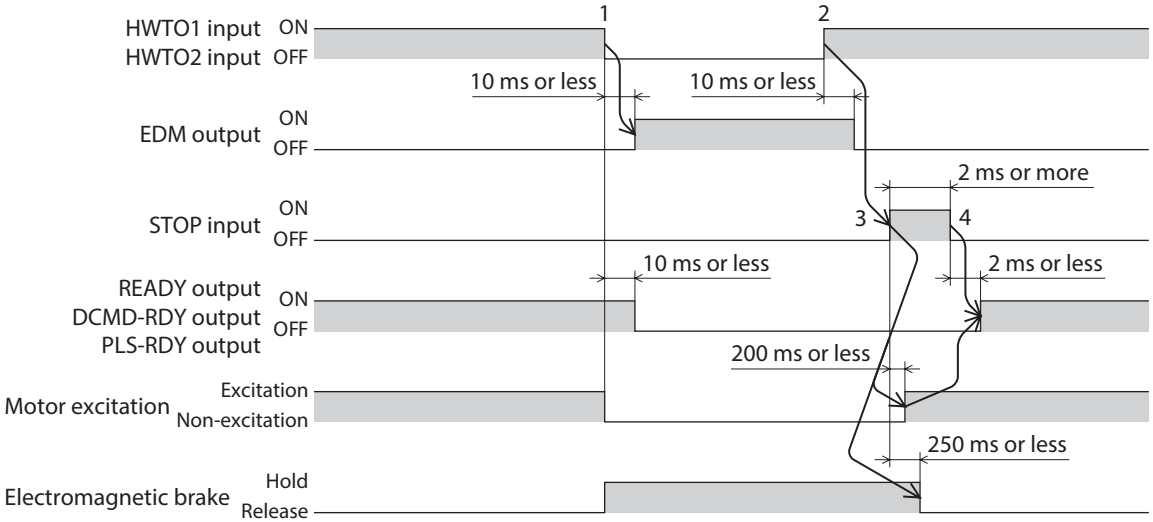
■ When the "HWTO mode selection" parameter is "1: Alarm-shutdown"

To reset the ETO-mode, turn the ALM-RST input ON. (It is enabled at the ON edge.)

6-5 Timing chart

Note Be sure to check the motor is in a standstill state before executing the ETO function. If the ETO function is executed while the motor is operated, it may cause damage to the motor, driver, or equipment.

1. When both the HWTO1 input and HWTO2 input are turned OFF, the EDM output is turned ON. The power supplying to the motor is cut off.
2. Turn the HWTO1 input and the HWTO2 input ON.
3. Turn the STOP input ON.
   The power is supplied to the motor, and excitation of the motor is restarted.
4. Turn the STOP input OFF.
   The READY output, the DCMD-RDY output, and the PLS-RDY output is turned ON.
5. Resume the operation after checking the output signals in the step 4 have been turned ON.



6-6 To use this product safely

- **When the ETO function is used, be sure to conduct a risk assessment of equipment in advance to satisfy the safety requirements of the entire system.**
- **The ETO function is designed based on the assumption that the motor is in a standstill state. Do not execute the ETO function while the motor is rotating.**
- **Even if the ETO function is activated, the following potential risks can be estimated. Be sure to confirm the safety by conducting a risk assessment.**
  - The motor output shaft may be rotated by an external force. If the motor output shaft is kept in place, install an external brake mechanism or equivalent. The brake mechanism of the electromagnetic brake motor is used for the purpose to hold the position. Do not use the brake mechanism of the electromagnetic brake motor for braking the motor rotation.
  - If the ETO function is activated, the driver stops supplying the power to the motor. However, the input power to the main power supply and control power supply is not shut off, and the driver is not electrically isolated. Before performing maintenance or inspection, always turn off the main power supply and control power supply, and check the PWR/ALM LED and the MAIN POWER LED are turned off. Residual voltage may cause electric shock.
- **The EDM output is not an output signal to ensure the safety. Do not use the EDM output for any other purpose except for monitoring a failure.**

7 Inspection and maintenance

7-1 Inspection

It is recommended that periodic inspections are conducted for the items listed below after each operation of the motor. If any failure is found, discontinue any use and contact your nearest Oriental Motor sales office.

■ Inspection item

- Check if the openings in the driver are clogged.
- Check if the mounting place of the driver is loose.
- Check if any of the connection parts of the driver is loose.
- Check if dust is deposited on the driver.
- Check if the driver has unusual smells or appearance defects.

Note The driver uses semiconductor components. Static electricity may damage the semiconductor components of the driver, so be extremely careful when handling them.

7-2 Warranty

Check on the Oriental Motor Website or General Catalog for the product warranty.

7-3 Disposal

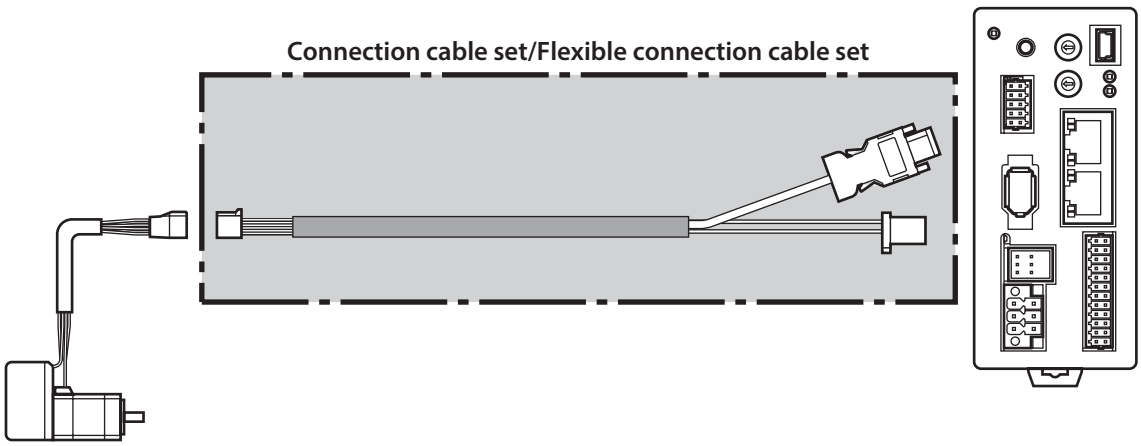
Dispose the product correctly in accordance with laws and regulations, or instructions of local governments.

8 Cables

8-1 Connection cable

■ Connection cable set/Flexible connection cable set (For AZM14, AZM15, AZM24, AZM26)

These cables are used when connecting a motor and a driver.



memo When installing the motor on a moving part, use a flexible cable offering excellent flexibility.

● **Connection cable set**

For motor/encoder

Model	Length [m (ft.)]
CC005VZ2F2	0.5 (1.6)
CC010VZ2F2	1 (3.3)
CC015VZ2F2	1.5 (4.9)
CC020VZ2F2	2 (6.6)
CC025VZ2F2	2.5 (8.2)
CC030VZ2F2	3 (9.8)
CC040VZ2F2	4 (13.1)
CC050VZ2F2	5 (16.4)
CC070VZ2F2	7 (23.0)
CC100VZ2F2	10 (32.8)
CC150VZ2F2	15 (49.2)
CC200VZ2F2	20 (65.6)

● **Flexible connection cable set**

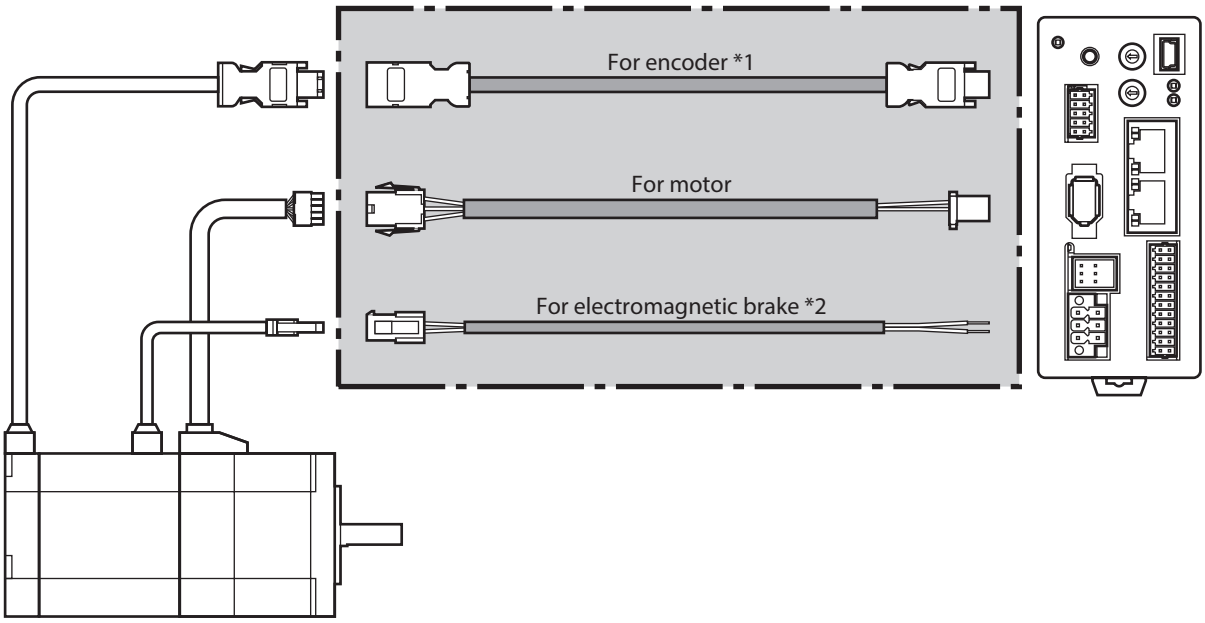
For motor/encoder

Model	Length [m (ft.)]
CC005VZ2R2	0.5 (1.6)
CC010VZ2R2	1 (3.3)
CC015VZ2R2	1.5 (4.9)
CC020VZ2R2	2 (6.6)
CC025VZ2R2	2.5 (8.2)
CC030VZ2R2	3 (9.8)
CC040VZ2R2	4 (13.1)
CC050VZ2R2	5 (16.4)
CC070VZ2R2	7 (23.0)
CC100VZ2R2	10 (32.8)
CC150VZ2R2	15 (49.2)
CC200VZ2R2	20 (65.6)

■ Connection cable set/Flexible connection cable set (For AZM46, AZM48, AZM66, AZM69)

These cables are used when connecting a motor and a driver. It is a set of two cables for the motor and the encoder. For the cable set of electromagnetic brake motors, a set of three cables for the motor, the encoder, and the electromagnetic brake is provided.

Connection cable set/Flexible connection cable set



*1 Use the cable for encoder when the length of the encoder cable of motor is not enough.
*2 Only when the motor is the electromagnetic brake type.

memo When installing the motor on a moving part, use a flexible cable offering excellent flexibility.

● **Connection cable set**

For motor/encoder

Model	Length [m (ft.)]
CC005VZF2	0.5 (1.6)
CC010VZF2	1 (3.3)
CC015VZF2	1.5 (4.9)
CC020VZF2	2 (6.6)
CC025VZF2	2.5 (8.2)
CC030VZF2	3 (9.8)
CC040VZF2	4 (13.1)
CC050VZF2	5 (16.4)
CC070VZF2	7 (23.0)
CC100VZF2	10 (32.8)
CC150VZF2	15 (49.2)
CC200VZF2	20 (65.6)

For motor/encoder/ electromagnetic brake

Model	Length [m (ft.)]
CC005VZFB2	0.5 (1.6)
CC010VZFB2	1 (3.3)
CC015VZFB2	1.5 (4.9)
CC020VZFB2	2 (6.6)
CC025VZFB2	2.5 (8.2)
CC030VZFB2	3 (9.8)
CC040VZFB2	4 (13.1)
CC050VZFB2	5 (16.4)
CC070VZFB2	7 (23.0)
CC100VZFB2	10 (32.8)
CC150VZFB2	15 (49.2)
CC200VZFB2	20 (65.6)

- **Flexible connection cable set**

For motor/encoder

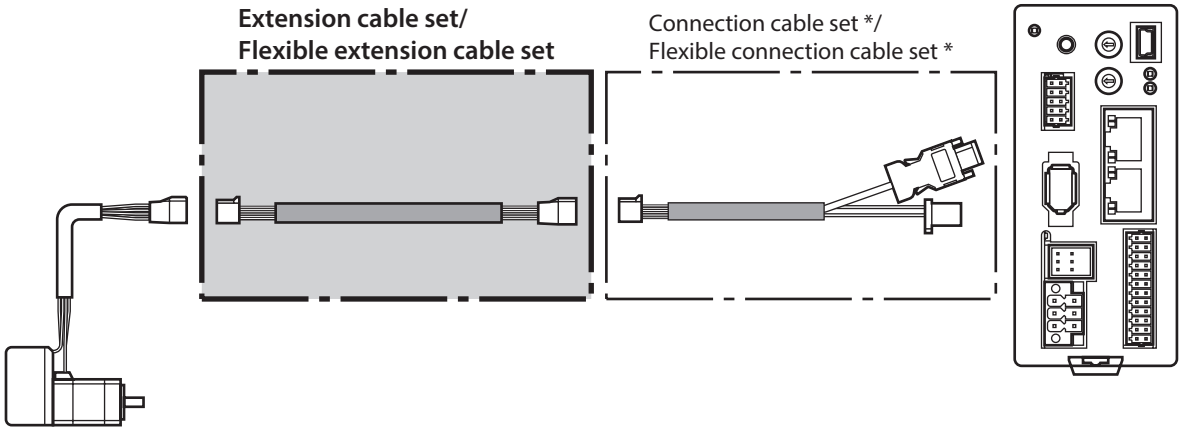
Model	Length [m (ft.)]
CC005VZR2	0.5 (1.6)
CC010VZR2	1 (3.3)
CC015VZR2	1.5 (4.9)
CC020VZR2	2 (6.6)
CC025VZR2	2.5 (8.2)
CC030VZR2	3 (9.8)
CC040VZR2	4 (13.1)
CC050VZR2	5 (16.4)
CC070VZR2	7 (23.0)
CC100VZR2	10 (32.8)
CC150VZR2	15 (49.2)
CC200VZR2	20 (65.6)

For motor/encoder/ electromagnetic brake

Model	Length [m (ft.)]
CC005VZRB2	0.5 (1.6)
CC010VZRB2	1 (3.3)
CC015VZRB2	1.5 (4.9)
CC020VZRB2	2 (6.6)
CC025VZRB2	2.5 (8.2)
CC030VZRB2	3 (9.8)
CC040VZRB2	4 (13.1)
CC050VZRB2	5 (16.4)
CC070VZRB2	7 (23.0)
CC100VZRB2	10 (32.8)
CC150VZRB2	15 (49.2)
CC200VZRB2	20 (65.6)

■ Extension cable set/Flexible extension cable set (For AZM14, AZM15, AZM24, AZM26)

These cables are used when extending the connection cable.
Use if the length of the connection cable used is not enough when extending the distance between a motor and a driver.



* Use the connection cable used.

memo
- When installing the motor on a moving part, use a flexible cable offering excellent flexibility.
- When extending the wiring length by connecting an extension cable to the connection cable, keep the total cable length to 20 m (65.6 ft.) or less.

- **Extension cable set**

For motor/encoder

Model	Length [m (ft.)]
CC010VZ2FT	1 (3.3)
CC020VZ2FT	2 (6.6)
CC030VZ2FT	3 (9.8)
CC050VZ2FT	5 (16.4)
CC070VZ2FT	7 (23.0)
CC100VZ2FT	10 (32.8)
CC150VZ2FT	15 (49.2)

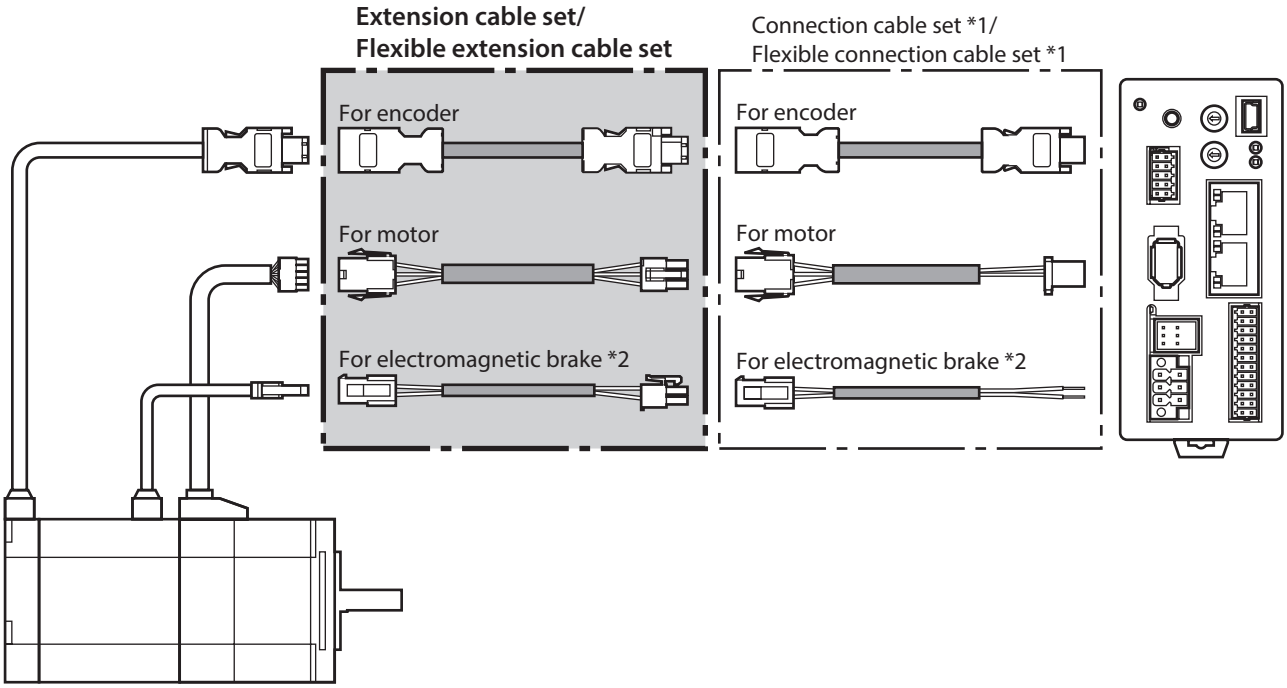
- **Flexible extension cable set**

For motor/encoder

Model	Length [m (ft.)]
CC010VZ2RT	1 (3.3)
CC020VZ2RT	2 (6.6)
CC030VZ2RT	3 (9.8)
CC050VZ2RT	5 (16.4)
CC070VZ2RT	7 (23.0)
CC100VZ2RT	10 (32.8)
CC150VZ2RT	15 (49.2)

■ Extension cable set/Flexible extension cable set (For AZM46, AZM48, AZM66, AZM69)

These cables are used when extending the connection cable.
Use if the length of the connection cable used is not enough when extending the distance between a motor and a driver.
It is a set of two cables for the motor and the encoder. For the cable set of electromagnetic brake motors, a set of three cables for the motor, the encoder, and the electromagnetic brake is provided.



*1 Use the connection cable used.
*2 Only when the motor is the electromagnetic brake type.

memo
- When installing the motor on a moving part, use a flexible cable offering excellent flexibility.
- When extending the wiring length by connecting an extension cable to the connection cable, keep the total cable length to 20 m (65.6 ft.) or less.

● **Extension cable set**

For motor/encoder

Model	Length [m (ft.)]
CC010VZFT	1 (3.3)
CC020VZFT	2 (6.6)
CC030VZFT	3 (9.8)
CC050VZFT	5 (16.4)
CC070VZFT	7 (23.0)
CC100VZFT	10 (32.8)
CC150VZFT	15 (49.2)

For motor/encoder/ electromagnetic brake

Model	Length [m (ft.)]
CC010VZFBT	1 (3.3)
CC020VZFBT	2 (6.6)
CC030VZFBT	3 (9.8)
CC050VZFBT	5 (16.4)
CC070VZFBT	7 (23.0)
CC100VZFBT	10 (32.8)
CC150VZFBT	15 (49.2)

- **Flexible extension cable set**

For motor/encoder

Model	Length [m (ft.)]
CC010VZRT	1 (3.3)
CC020VZRT	2 (6.6)
CC030VZRT	3 (9.8)
CC050VZRT	5 (16.4)
CC070VZRT	7 (23.0)
CC100VZRT	10 (32.8)
CC150VZRT	15 (49.2)

For motor/encoder/ electromagnetic brake

Model	Length [m (ft.)]
CC010VZRBT	1 (3.3)
CC020VZRBT	2 (6.6)
CC030VZRBT	3 (9.8)
CC050VZRBT	5 (16.4)
CC070VZRBT	7 (23.0)
CC100VZRBT	10 (32.8)
CC150VZRBT	15 (49.2)

8-2 I/O signal cable

This cable is a shielded cable for the driver control I/O that has good noise immunity. The ground wire useful to grounding is extracted from both ends of the cable.
Select the cable suitable for the number of I/O signals connected.

Model list

Cable length [m (ft.)]	Number of lead wires			
	6 pcs.	10 pcs.	12 pcs.	16 pcs.
0.5 (1.6)	**CC06D005B-1**	**CC10D005B-1**	**CC12D005B-1**	**CC16D005B-1**
1 (3.3)	**CC06D010B-1**	**CC10D010B-1**	**CC12D010B-1**	**CC16D010B-1**
1.5 (4.9)	**CC06D015B-1**	**CC10D015B-1**	**CC12D015B-1**	**CC16D015B-1**
2 (6.6)	**CC06D020B-1**	**CC10D020B-1**	**CC12D020B-1**	**CC16D020B-1**

9 Accessories

9-1 Pulse signal converter for noise immunity

This product converts a pulse signal, which is output from the open collector output, to a pulse signal for good noise immunity by outputting the pulse signal again from the differential output.

Model: **VCS06**

9-2 Relay contact protection parts/circuits

- **CR circuit for surge suppression**

  This product is effective to suppress the surge which occurs in a relay contact part. Use it to protect the contacts of the relay or switch.

  Model: **EPCR1201-2**

- **CR circuit module**

  This product is effective to suppress the surge which occurs in a relay contact part. Use it to protect the contacts of the relay or switch.
  Four pieces of CR circuit for surge suppression are mounted on the compact circuit, and this product can be installed to the DIN rail. This product can make the wiring easily and securely since it also supports terminal block connection.

  Model: **VCS02**

4 Implicit communication

This part explains how to control via Implicit communication.

◆**Table of contents**

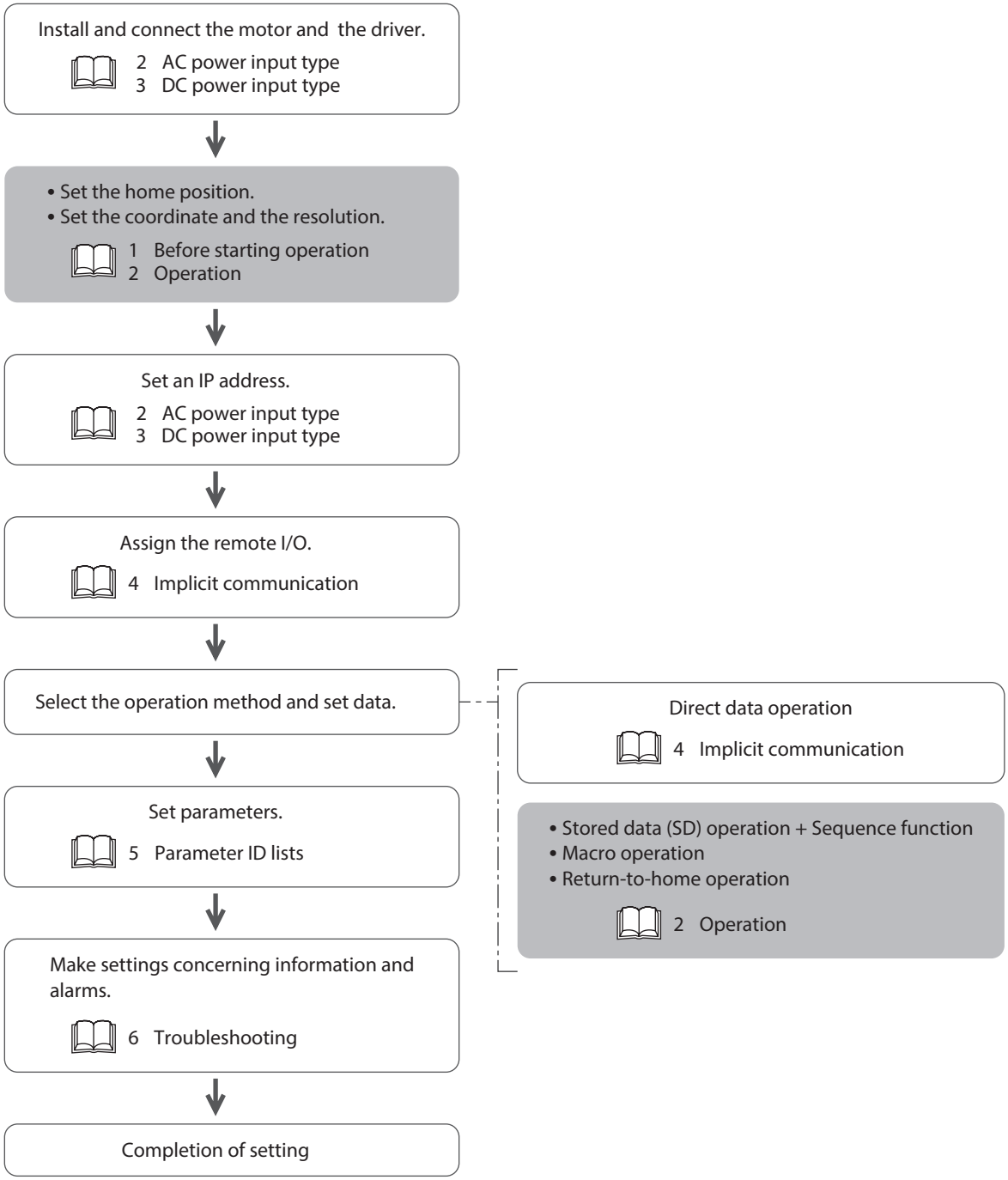
1 Flow of setting of Implicit communication

The contents of [ ] are explained in this manual.

Refer to the OPERATING MANUAL **AZ** Series Function Edition for the contents of .

is the title name described in the reference destination.

memo The title number described in the reference destination may be changed. Use the title name when checking the reference destination.



2 Guidance

If you are new to this product, read this chapter to understand the operating methods along with the operation flow. This is an example how to set the operation data and start the motor using the scanner.

STEP1	Installation and connection
↓	
STEP2	Before starting operation
↓	
STEP3	Setting of IP address
↓	
STEP4	Starting of motor

- **Operating conditions**

This operation is performed under the following conditions.

- Number of drivers connected: one unit
- IP address: 192.168.1.2

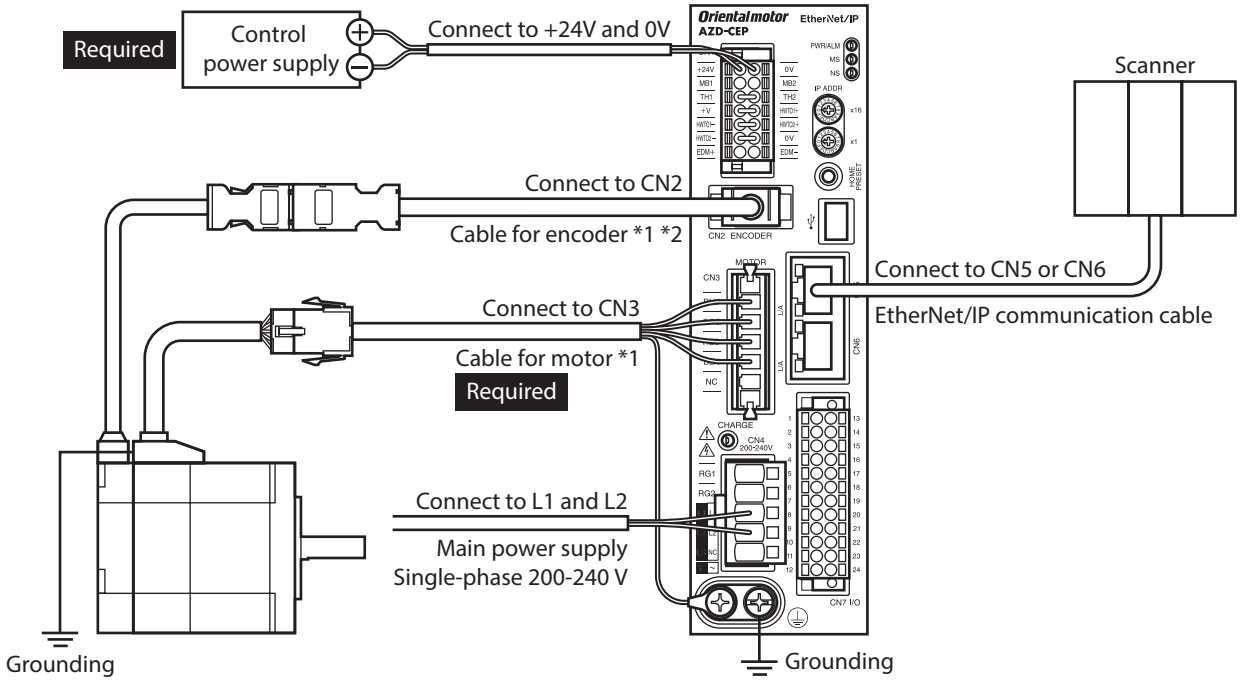
Note

- Before operating the motor, check the condition of the surrounding area to ensure safety.
- Before starting based on the guidance, import the EDS file to the setting tool of the scanner and register the system configuration in advance. For details, contact your nearest Oriental Motor sales office.

STEP 1	Check the installation and connection.

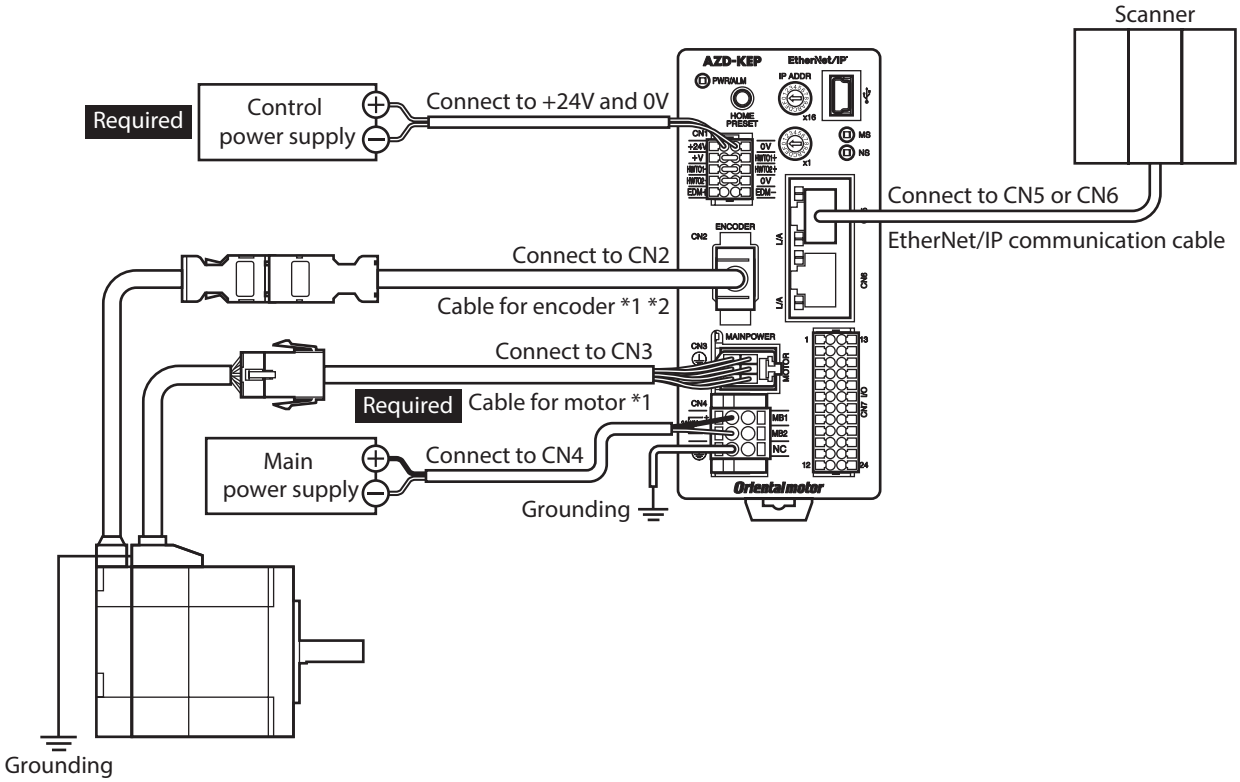
■ AC power input driver

The figure shows models for single-phase 200 to 240 VAC input.



*1 Purchase it separately.
*2 Use the cable for encoder when the length of the encoder cable of motor is not enough.

■ DC power input driver



*1 Purchase it separately.
*2 Use the cable for encoder when the length of the encoder cable of motor is not enough.

STEP 2 Make preparations for operation.

Refer to "Before starting operation" in the OPERATING MANUAL **AZ** Series Function Edition.

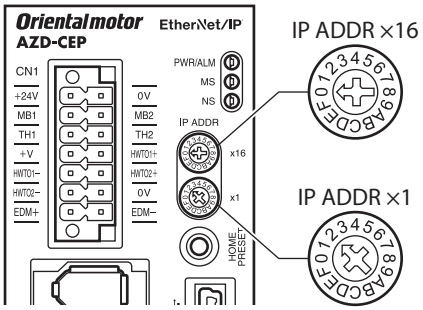
STEP 3 Set an IP address.

Set an IP address using the IP address setting switches (IP ADDR ×16, ×1) of the driver.

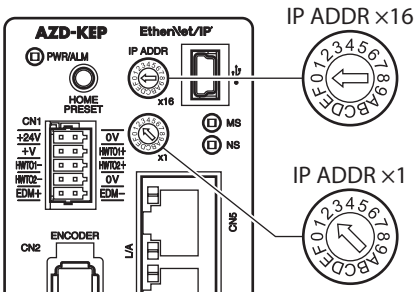
1. Set the IP address setting switches as shown below.

   Settings: ×16: 0, ×1: 2 (192.168.1.2)

■ AC power input driver



■ DC power input driver



2. Turn on the control power supply again.

Note After setting the switches, turn off the control power supply and turn on again. The setting is enabled when the control power supply is turned on again.

STEP 4 The scanner starts the motor.

As an example, this section explains how to perform the following positioning operation.

- **Setting example**
  - Operation data number: 1
  - Position: 5,000 steps
  - Other settings: Initial values
- **Operation processing flow**

Descriptions are given using the scanner as the subject.

1. Set the following operation data to turn the WR-REQ ON.
   The operation data is set in the driver. When the setting is complete, the WR-END is turned ON.

Byte	Description	Setting value	Note
34, 35	Write parameter ID	3104	Parameter ID of "Operation type" of operation data No.1
36 to 39	Write data	1	Operation type: Absolute positioning

2. Turn the WR-REQ OFF.
   The WR-END is returned to OFF.
3. Set the following operation data to turn the WR-REQ ON.
   The operation data is set in the driver. When the setting is complete, the WR-END is turned ON.

Byte	Description	Setting value	Note
34, 35	Write parameter ID	3105	Parameter ID of "Position" of operation data No.1
36 to 39	Write data	5,000	Position: 5,000 steps

4. Turn the WR-REQ OFF.
   The WR-END is returned to OFF.
5. Check the READY has been turned ON.

6. Select the operation data No.1 to turn the START ON.
   Absolute positioning operation is started.
7. Check the READY has been turned OFF, and turn the START OFF.

STEP 5 Were you able to operate?

How did it go? Were you able to operate the motor properly? If the motor does not operate, check the following points.

- Is the PWR/ALM LED blinking in red?
  An alarm is being generated. Refer to p.147 for details.
- Are the power supply, the motor and the EtherNet/IP communication cable connected securely?
- Is the IP address set correctly?
- Is the NS LED lit in red or blinking in red?
  A communication error is being detected. Refer to p.146 for details.

3 Communications specifications

Communications standards		EtherNet/IP (conforms to CT16)
Vendor ID		187: Oriental Motor Company
Device type		43: Generic Device
Transmission rate		10/100 Mbps (autonegotiation)
Communication mode		Full duplex/Half duplex (autonegotiation)
Cable specifications		Shielded twisted pair (STP) cable straight-through/crossover cable, category 5e or higher
Number of occupied bytes	Output (scanner → driver)	40 bytes
	Input (driver → scanner)	56 bytes
Implicit communication	Number of connections	2
	Connection type	Exclusive Owner, Input Only
	Communication cycle (RPI)	1 to 3,200 ms
	Connection type (scanner → driver)	Point–to–Point
	Connection type (driver → scanner)	Point–to–Point, Multicast
	Data trigger	Cyclic
Explicit communication	Number of connections	6
	Connection type	UCMM, Connection
IP address setting method		IP address setting switches, parameters, DHCP
Network topology		Star, Linear, Ring (Device Level Ring)

4 Implicit message

4-1 Implicit message format

This section shows transfer contents of Implicit message. The order of data is in little-endian format.
Contents of Implicit message is fixed and cannot be changed.

Byte	Input (driver → scanner)	Output (scanner → driver)
0, 1	Remote I/O (R-OUT)	Remote I/O (R-IN)
2, 3	Operation data number selection_R	Operation data number selection
4, 5	Fixed I/O (OUT)	Fixed I/O (IN)
6, 7	Present alarm	Direct data operation operation type
8, 9	Feedback position (lower)	Direct data operation position (lower)
10, 11	Feedback position (upper)	Direct data operation position (upper)
12, 13	Feedback speed [Hz] (lower)	Direct data operation operating speed (lower)
14, 15	Feedback speed [Hz] (upper)	Direct data operation operating speed (upper)
16, 17	Command position (lower)	Direct data operation starting/changing rate (lower)
18, 19	Command position (upper)	Direct data operation starting/changing rate (upper)
20, 21	Torque monitor	Direct data operation stopping deceleration (lower)
22, 23	CST operating current	Direct data operation stopping deceleration (upper)
24, 25	Information (lower)	Direct data operation operating current
26, 27	Information (upper)	Direct data operation forwarding destination
28, 29	Reserved	Reserved
30, 31	Read parameter ID_R	Read parameter ID
32, 33	Read/write status	Write request
34, 35	Write parameter ID_R	Write parameter ID
36, 37	Read data (lower)	Write data (lower)
38, 39	Read data (upper)	Write data (upper)
40, 41	Assignable monitor 0 (lower)	–
42, 43	Assignable monitor 0 (upper)	–
44, 45	Assignable monitor 1 (lower)	–
46, 47	Assignable monitor 1 (upper)	–
48, 49	Assignable monitor 2 (lower)	–
50, 51	Assignable monitor 2 (upper)	–
52, 53	Assignable monitor 3 (lower)	–
54, 55	Assignable monitor 3 (upper)	–

4-2 Input data

Data transferred from the driver to the scanner is called Input data.

■ Input data format

Contents of the Input data is as follows. The order of data is in little-endian format.

Assembly Instance	Attribute	Byte	Size (byte)	Description
100	3	0, 1	2	Remote I/O (R-OUT)
		2, 3	2	Operation data number selection_R
		4, 5	2	Fixed I/O (OUT)
		6, 7	2	Present alarm
		8 to 11	4	Feedback position
		12 to 15	4	Feedback speed (Hz)
		16 to 19	4	Command position
		20, 21	2	Torque monitor
		22, 23	2	CST operating current
		24 to 27	4	Information
		28, 29	2	Reserved
		30, 31	2	Read parameter ID_R
		32, 33	2	Read/write status
		34, 35	2	Write parameter ID_R
		36 to 39	4	Read data
		40 to 43	4	Assignable monitor 0
		44 to 47	4	Assignable monitor 1
		48 to 51	4	Assignable monitor 2
		52 to 55	4	Assignable monitor 3

■ Details of Input data

● Remote I/O (R-OUT)

This is the I/O accessed via EtherNet/IP.
The assignments of signals can be changed with the "R-OUT output function" parameter.

Bit	Name	Description	Initial assignment
0	R-OUT0	A response to a signal assigned with the "R-OUT output function" parameter is output.	64: M0_R
1	R-OUT1		65: M1_R
2	R-OUT2		66: M2_R
3	R-OUT3		32: START_R
4	R-OUT4		144: HOME-END
5	R-OUT5		132: READY
6	R-OUT6		135: INFO
7	R-OUT7		129: ALM-A
8	R-OUT8		136: SYS-BSY
9	R-OUT9		160: AREA0
10	R-OUT10		161: AREA1
11	R-OUT11		162: AREA2
12	R-OUT12		157: TIM
13	R-OUT13		134: MOVE
14	R-OUT14		138: IN-POS
15	R-OUT15		140: TLC

- **Operation data number selection_R**

Bit	Name	Description
0	M0_R	A response to a input signal is output.
1	M1_R	
2	M2_R	
3	M3_R	
4	M4_R	
5	M5_R	
6	M6_R	
7	M7_R	
8 to 15	Reserved	0 is returned.

- **Fixed I/O (OUT)**

This is the I/O accessed via EtherNet/IP.
Assignments of signals cannot be changed.

Bit	Name	Description
0	SEQ-BSY	This is output when stored data operation is being performed.
1	MOVE	This is output when the motor operates.
2	IN-POS	This is output when positioning operation is complete.
3	START_R	A response to a input signal is output.
4	HOME-END	This is output when high-speed return-to-home operation or return-to-home operation is complete, or position preset is executed.
5	READY	This is output when the driver is ready to operate.
6	DCMD-RDY	This is output when the driver is ready to start direct data operation.
7	ALM-A	The alarm status of the driver is output. (Normally open)
8	TRIG_R	A response to a input signal is output.
9	TRIG-MODE_R	
10	SET-ERR	This is output when an error occurs in any of the settings of operation type, position, operating speed, starting/changing speed rate, stopping deceleration, operating current, and forwarding destination for direct data operation.
11	EXE-ERR	This is output when direct data operation is failed to execute.
12	DCMD-FULL	This is output when data is being written to the buffer area of direct data operation.
13	STOP_R	A response to a input signal is output.
14	ETO-MON	This is output when the driver is in the ETO-mode.
15	TLC	This is output when the output torque reaches the upper limit value.

- **Present alarm**

Bit	Name	Description
0 to 15	Present alarm	Indicates the alarm code presently being generated.

- **Feedback position**

Bit	Name	Description
0 to 31	Feedback position	Indicates the present feedback position. When the wrap function is enabled, the value on the wrap coordinates is indicated.

- **Feedback speed (Hz)**

Bit	Name	Description
0 to 31	Feedback speed (Hz)	Indicates the present feedback speed.

- **Command position**

Bit	Name	Description
0 to 31	Command position	Indicates the present command position. When the wrap function is enabled, the value on the wrap coordinates is indicated.

- **Torque monitor**

Bit	Name	Description
0 to 15	Torque monitor	Indicates the torque presently generated as a percentage of the maximum holding torque.

- **CST operating current**

Bit	Name	Description
0 to 15	CST operating current	Indicates the operating current of the α control (CST) mode. (1=0.1 %)

- **Information**

Bit	Name	Description
0 to 31	Information	Indicates the information code presently being generated.

- **Read parameter ID_R**

Bit	Name	Description
0 to 15	Read parameter ID_R	Indicates the response of the read parameter ID.

- **Read/write status**

Bit	Name	Description
0 to 6	Reserved	0 is returned.
7	RD-ERR	This is output when an error occurred in reading. If reading is performed properly, the RD-REQ is turned OFF.
8	WR-END	The response to the WR-REQ is output. The WR-END is also turned ON while the WR-REQ is ON. OFF: Write request waiting ON: Write completed
9	SYS-BSY	This is output when the driver is in internal processing state.
10	Reserved	0 is returned.
11	WR-SET-ERR	This is output when the write parameter ID or write data is out of the setting range.
12	WR-IF-ERR	This is output when writing cannot be performed due to user I/F communication in progress.
13	WR-NV-ERR	This is output when writing cannot be performed due to non-volatile memory processing in progress.
14	WR-EXE-ERR	This is output when a command cannot be executed.
15	WR-ERR	This is output when an error occurred in writing. If the WR-REQ is turned OFF or writing is performed properly, the WR-ERR is turned OFF.

- **Write parameter ID_R**

Bit	Name	Description
0 to 15	Write parameter ID_R	Indicates the response of the write parameter ID.

- **Read data**

Bit	Name	Description
0 to 31	Read data	Indicates the value of the parameter shown in the parameter ID_R.

- **Assignable monitor**

Bit	Name	Description
0 to 31	Assignable monitor n*	Indicates the value of the parameter set in the "Assignable monitor address n" parameter.

* n: 0 to 3

4-3 Output data

The Output data is data to transfer from the scanner to the driver.

■ Output data format

Descriptions of the Output data are as follows. The order of data is in little-endian format.

Assembly Instance	Attribute	Byte	Size (byte)	Description
101	3	0, 1	2	Remote I/O (R-IN)
		2, 3	2	Operation data number selection
		4, 5	2	Fixed I/O (IN)
		6, 7	2	Direct data operation operation type
		8 to 11	4	Direct data operation position
		12 to 15	4	Direct data operation operating speed
		16 to 19	4	Direct data operation starting/changing rate
		20 to 23	4	Direct data operation stopping deceleration
		24, 25	2	Direct data operation operating current
		26, 27	2	Direct data operation forwarding destination
		28, 29	2	Reserved
		30, 31	2	Read parameter ID
		32, 33	2	Write request
		34, 35	2	Write parameter ID
		36 to 39	4	Write data

■ Details of Output data

● Remote I/O (R-IN)

This is the I/O accessed via EtherNet/IP.
The assignments of signals can be changed using the "R-IN input function" parameters.

Bit	Name	Description	Initial assignment
0	R-IN0	These are used to execute a signal assigned with the "R-IN input function" parameter.	0: Not used
1	R-IN1		
2	R-IN2		
3	R-IN3		
4	R-IN4		
5	R-IN5		
6	R-IN6		
7	R-IN7		
8	R-IN8		
9	R-IN9		
10	R-IN10		
11	R-IN11		
12	R-IN12		
13	R-IN13		
14	R-IN14		
15	R-IN15		

● Operation data number selection

Bit	Name	Description	Initial value
0	M0	The operation data number is selected using these eight bits.	0
1	M1		
2	M2		
3	M3		
4	M4		
5	M5		
6	M6		
7	M7		
8 to 15	Reserved	A value is disregarded.	0

- **Fixed I/O (IN)**

This is the I/O accessed via EtherNet/IP.
Assignments of signals cannot be changed.

Bit	Name	Description	Initial value
0	FW-JOG	This is used to execute JOG operation in the forward direction.	0
1	RV-JOG	This is used to execute JOG operation in the reverse direction.	
2	Reserved	A value is disregarded.	
3	START	This is used to execute stored data operation.	
4	ZHOME	This is used to execute high-speed return-to-home operation.	
5	STOP	This is used to stop the motor.	
6	FREE	This is used to shut off the motor current to remove the motor excitation. In the case of an electromagnetic brake motor, the electromagnetic brake is released.	
7	ALM-RST	This is used to reset the alarm being generated presently.	
8	TRIG	This is used to execute direct data operation.	
9	TRIG-MODE	This is used to set the judgment level for the TRIG. 0: Start at ON edge 1: Start at ON level	
10	ETO-CLR	This is used to release the ETO-mode.	
11	Reserved	A value is disregarded.	
12	FW-JOG-P	This is used to execute inching operation in the forward direction.	
13	RV-JOG-P	This is used to execute inching operation in the reverse direction.	
14	FW-POS	This is used to execute continuous operation in the forward direction.	
15	RV-POS	This is used to execute continuous operation in the reverse direction.	

- **Direct data operation operation type**

Bit	Name	Description	Initial value
0 to 15	Direct data operation operation type	This is used to set the operation type for direct data operation. **Setting range** 0: No setting 1: Absolute positioning 2: Incremental positioning (based on command position) 3: Incremental positioning (based on feedback position) 7: Continuous operation (position control) 8: Wrap absolute positioning 9: Wrap proximity positioning 10: Wrap forward direction absolute positioning 11: Wrap reverse direction absolute positioning 12: Wrap absolute push-motion 13: Wrap proximity push-motion 14: Wrap forward direction push-motion 15: Wrap reverse direction push-motion 16: Continuous operation (speed control) 17: Continuous operation (push-motion) 18: Continuous operation (torque control) 20: Absolute positioning push-motion 21: Incremental positioning push-motion (based on command position) 22: Incremental positioning push-motion (based on feedback position)	2

- **Direct data operation position**

Bit	Name	Description	Initial value
0 to 31	Direct data operation position	This is used to set the target position for direct data operation. **Setting range** −2,147,483,648 to 2,147,483,647 steps	0

- **Direct data operation operating speed**

Bit	Name	Description	Initial value
0 to 31	Direct data operation operating speed	This is used to set the operating speed for direct data operation. **Setting range** −4,000,000 to 4,000,000 Hz	1,000

- **Direct data operation starting/changing rate**

Bit	Name	Description	Initial value
0 to 31	Direct data operation starting/changing rate	This is used to set the acceleration/deceleration rate or the acceleration/deceleration time for direct data operation. **Setting range** 1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001s, or 1=0.001 ms/kHz)	1,000,000

- **Direct data operation stopping deceleration**

Bit	Name	Description	Initial value
0 to 31	Direct data operation stopping deceleration	This is used to set the deceleration rate or the deceleration time for direct data operation. **Setting range** 1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001s, or 1=0.001ms/kHz)	1,000,000

- **Direct data operation operating current**

Bit	Name	Description	Initial value
0 to 15	Direct data operation operating current	This is used to set the operating current for direct data operation. **Setting range** 0 to 1,000 (1=0.1 %)	1,000

- **Direct data operation forwarding destination**

Bit	Name	Description	Initial value
0 to 15	Direct data operation forwarding destination	This is used to select the stored area when the next direct data is transferred during direct data operation. **Setting range** 0: Execution memory 1: Buffer memory	0

- **Read parameter ID**

Bit	Name	Description	Initial value
0 to 15	Read parameter ID	This is used to set the parameter ID to be read from.	0

- **Write request**

Bit	Name	Description	Initial value
0	WR-REQ	This is used to set the write request. **Setting range** 0: Disable 1: Write request (ON edge)	0
1 to 15	Reserved	A value is disregarded.	0

- **Write parameter ID**

Bit	Name	Description	Initial value
0 to 15	Write parameter ID	This is used to set the parameter ID to be written to.	0

- **Write data**

Bit	Name	Description	Initial value
0 to 31	Write data	This is used to set a value to be written to the parameter specified by the write parameter ID.	0

4-4 Processing order of Implicit communication

The processing order of Implicit communication is shown.

Data writing

↓

Setting of operation command

↓

Data reading

memo

- If multiple operation commands are set in the Implicit message format, the operation command of direct data operation is prioritized.
- If the operation commands for remote I/O (R-IN) and fixed I/O (IN) are set at the same time, operations are as follows.
  · If the same operation command is set: The motor will start.
  · If different operation commands are set: The motor will not start, and information of operation start error will be generated.

4-5 Data writing

This section explains the flow that data is written from the scanner to the driver via Implicit communication.

■ Area of Implicit message format used

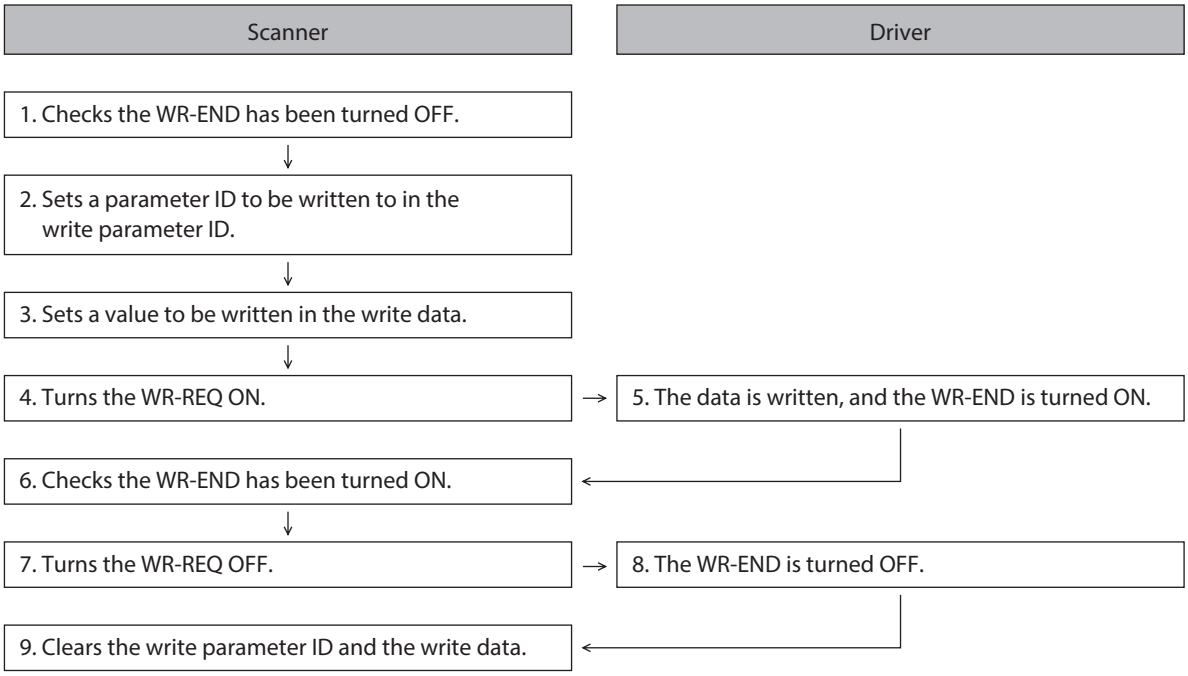
Input (transfer from driver to scanner)

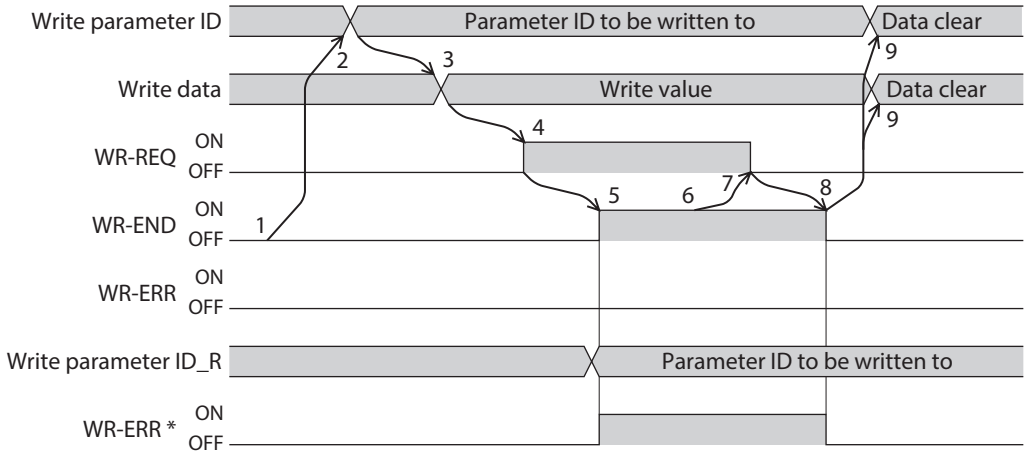
Byte	Description
32, 33	Read/write status
34, 35	Write parameter ID_R

Output (transfer from scanner to driver)

Byte	Description
32, 33	Write request
34, 35	Write parameter ID
36 to 39	Write data

■ Flow that data is written to





* If an error occurs while data is being written, the WR-END and WR-ERR are simultaneously turned ON.

4-6 Data reading

This section explains the flow that data is read from the driver to the scanner via Implicit communication.
There are the following two methods to read data.

- Use an area of "read data"
- Use an area of "assignable monitor"

■ When an area of read data is used

● Area of Implicit message format used

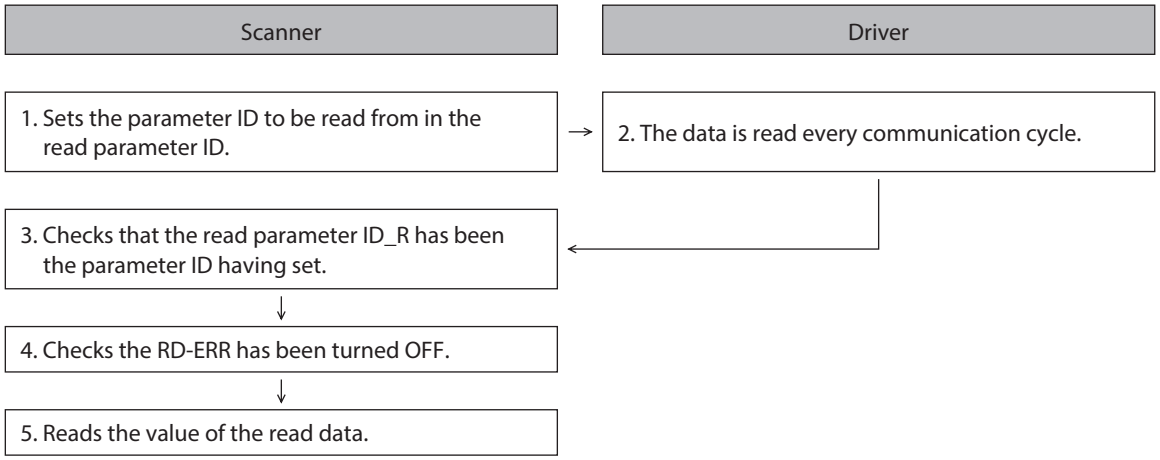
Input (transfer from driver to scanner)

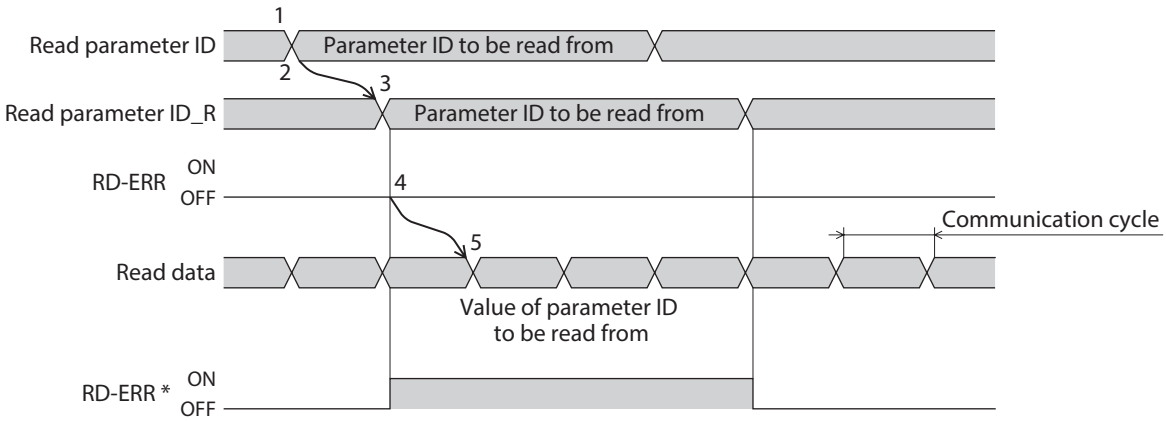
Byte	Description
30, 31	Read parameter ID_R
32, 33	Read/write status
36 to 39	Read data

Output (transfer from scanner to driver)

Byte	Description
30, 31	Read parameter ID

● Flow that data is read from





* If the parameter ID out of setting range is set to the read parameter ID, the RD-ERR is turned ON at the same time that the read parameter ID_R is updated.

■ When an area of assignable monitor is used

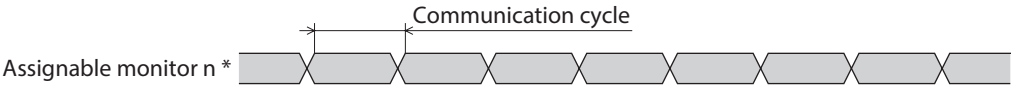
- **Area of Implicit message format used**

Input (transfer from driver to scanner)

Byte	Description
40 to 55	Assignable monitor 0 to assignable monitor 3

- **Flow that data is read from**

Scanner		Driver
Sets the "Assignable monitor address" parameter.	→	The value of the parameter set in the "Assignable monitor address" parameter is read every communication cycle.



* n: 0 to 3

- **Related parameters**

Parameter ID		Name	Description	Setting range	Initial value
Dec	Hex				
25600	6400h	Assignable monitor address 0	Sets the parameter ID to show on the assignable monitor.	Set from items of "5 Parameter ID lists"	124: Driver temperature
25601	6401h	Assignable monitor address 1			125: Motor temperature
25602	6402h	Assignable monitor address 2			109: Cumulative load monitor
25603	6403h	Assignable monitor address 3			127: Tripmeter

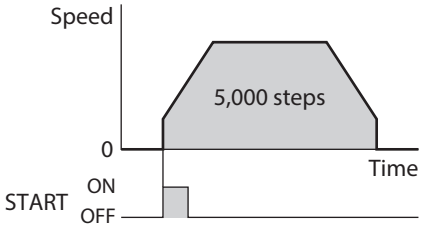
5 Example of execution for operation

This chapter describes operations that operation data is set using the write data area.
The method to execute operation is common to fixed I/O and remote I/O.

5-1 Absolute positioning operation

As an example, this section explains how to perform the following positioning operation.

- **Setting example**
  - Operation data number: 1
  - Position: 5,000 steps
  - Other settings: Initial values



- **Operation processing flow**

Descriptions are given using the scanner as the subject.

1. Set the following operation data to turn the WR-REQ ON.
   The operation data is set in the driver. When the setting is complete, the WR-END is turned ON.

   • Output (scanner → driver)

Byte	Description	Setting value	Note
34, 35	Write parameter ID	3104	Parameter ID of "Operation type" of operation data No.1
36 to 39	Write data	1	Operation type: Absolute positioning

   • Input (driver → scanner)

Byte	Description	Response	Note
34, 35	Write parameter ID_R	3104	Parameter ID of "Operation type" of operation data No.1

2. Turn the WR-REQ OFF.
   The WR-END is returned to OFF.
3. Set the following operation data to turn the WR-REQ ON.
   The operation data is set in the driver. When the setting is complete, the WR-END is turned ON.

   • Output (scanner → driver)

Byte	Description	Setting value	Note
34, 35	Write parameter ID	3105	Parameter ID of "Position" of operation data No.1
36 to 39	Write data	5,000	Position: 5,000 steps

   • Input (driver → scanner)

Byte	Description	Response	Note
34, 35	Write parameter ID_R	3105	Parameter ID of "Position" of operation data No.1

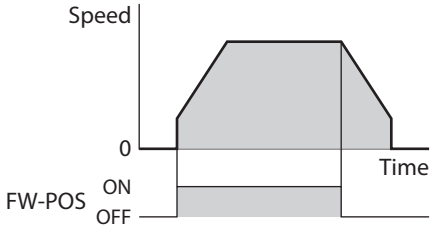
4. Turn the WR-REQ OFF.
   The WR-END is returned to OFF.
5. Check the READY has been turned ON.
6. Select the operation data No.1 to turn the START ON.
   Absolute positioning operation is started.
7. Check the READY has been turned OFF, and turn the START OFF.

5-2 Continuous operation

As an example, this section explains how to perform the following continuous operation.

● Setting example

- Operation data number: 0
- Rotation direction: Forward direction
- Other settings: Initial values



● Operation processing flow

Descriptions are given using the scanner as the subject.

1. Check the READY has been turned ON.
2. Set the following operation data to turn the FW-POS ON.
   Continuous operation is started.

   • Output (scanner → driver)

Byte	Description	Setting value	Note
2, 3	Operation data number selection	0	Selects the operation data No.0.

3. To stop continuous operation, turn the FW-POS OFF.
   The motor decelerates to a stop.

6 Direct data operation

6-1 Overview of direct data operation

Direct data operation is a mode that allows rewriting of data and start of operation to be executed at the same time. It is suitable to frequently change operation data such as the position (travel amount) and operating speed or to fine-tune the position.
There are the following seven types of triggers to start operation at the same time as rewriting of data.

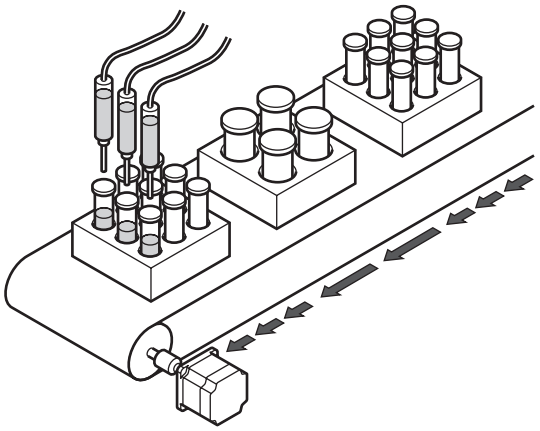
- One of the following items: Operation type, position, operating speed, starting/changing speed rate, stopping deceleration, and operating current
- The above six items are collectively rewritten

The direct data operation is executed with the TRIG of fixed I/O (IN).
A condition to execute direct data operation can be selected from the following two types using the TRIG-MODE of fixed I/O (IN).

- Start at ON edge of TRIG: The motor will start according to the operation data being set when the TRIG is turned ON.
- Start at ON level of TRIG: The motor will start at the same time when the data of the trigger set in the "Direct data operation trigger setting" parameter is changed.

■ Application example 1 of direct data operation

The position (travel amount) or the operating speed should be adjusted each time a load is changed because the feed rate is different in each load.



● Setting example

- Position (travel amount): Change as desired
- Operating speed: Change as desired
- TRIG-MODE: Start at ON edge of TRIG

● Operation processing flow

Descriptions are given using the scanner as the subject.

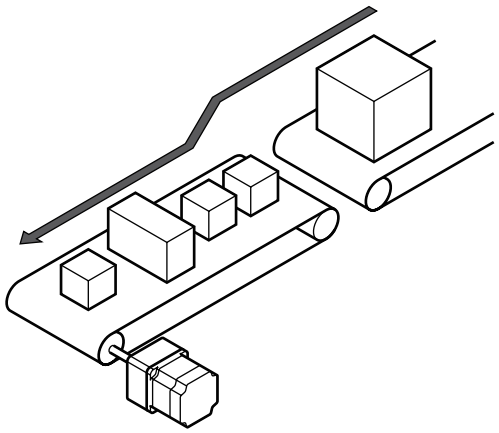
1. Write the position and the operating speed.
2. Turn the TRIG ON.

● Result

When the TRIG is turned ON, the changed value is updated immediately, and operation is performed with the new position and operating speed.

■ Application example 2 of direct data operation

The operating speed should be changed immediately with the touch screen because a large load is inspected at a lower speed.



- **Setting example**
  - Operating speed: Change as desired
  - Trigger: Operating speed (setting value of trigger: −4)
  - TRIG-MODE: Start at ON level of TRIG
- **Operation processing flow**

  Descriptions are given using the scanner as the subject.

  1. Write "−4" to the "Direct data operation trigger setting" parameter.
  2. Write the data of the operating speed.
  3. Turn the TRIG ON.
  4. Change the operating speed.
- **Result**

  When the TRIG is turned ON, operation is started. If the operating speed is changed, the changed value is updated immediately, and the operation is performed at the new operating speed.

6-2 OUTPUT data and parameters required for direct data operation

Related OUTPUT data

Byte	Name	Description	Initial value
6, 7	Direct data operation operation type	This is used to set the operation type for direct data operation. **Setting range** 0: No setting 1: Absolute positioning 2: Incremental positioning (based on command position) 3: Incremental positioning (based on feedback position) 7: Continuous operation (position control) 8: Wrap absolute positioning 9: Wrap proximity positioning 10: Wrap forward direction absolute positioning 11: Wrap reverse direction absolute positioning 12: Wrap absolute push-motion 13: Wrap proximity push-motion 14: Wrap forward direction push-motion 15: Wrap reverse direction push-motion 16: Continuous operation (speed control) 17: Continuous operation (push-motion) 18: Continuous operation (torque control) 20: Absolute positioning push-motion 21: Incremental positioning push-motion (based on command position) 22: Incremental positioning push-motion (based on feedback position)	2
8 to 11	Direct data operation position	This is used to set the target position for direct data operation. **Setting range** −2,147,483,648 to 2,147,483,647 steps	0
12 to 15	Direct data operation operating speed	This is used to set the operating speed for direct data operation. **Setting range** −4,000,000 to 4,000,000 Hz	1,000

Byte	Name	Description	Initial value
16 to 19	Direct data operation starting/changing rate	This is used to set the acceleration/deceleration rate or the acceleration/deceleration time for direct data operation. **Setting range** 1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000
20 to 23	Direct data operation stopping deceleration	This is used to set the deceleration rate or the deceleration time for direct data operation. **Setting range** 1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000
24, 25	Direct data operation operating current	This is used to set the operating current for direct data operation. **Setting range** 0 to 1,000 (1=0.1 %)	1,000
26, 27	Direct data operation forwarding destination	This is used to select the stored area when the next direct data is transferred during direct data operation. **Setting range** 0: Execution memory 1: Buffer memory	0

Related parameter

Parameter ID		Name	Description	Initial value
Dec	Hex			
24852	6114h	Direct data operation trigger setting	This is used to set the trigger to execute direct data operation. The trigger setting is enabled only when the TRIG-MODE is set to "1: Start at ON level." **Setting range** −6: Operation type −5: Position −4: Speed −3: Starting/changing rate −2: Stopping deceleration −1: Operating current 0: Disable 1: Apply all data	1

■ Trigger setting

This is a trigger to start operation at the same time as rewriting of data in direct data operation.
The trigger setting is enabled only when the TRIG-MODE is set to "1: Start at ON level."

- **When the trigger setting is "0"**

  Direct data operation is disabled.

- **When the trigger setting is "1"**

  When the TRIG is turned from OFF to ON, direct data operation is started. After that, if any of data is changed, the motor will be started. The motor will be started only when data is changed.

- **When the trigger setting is "−1 to −6"**

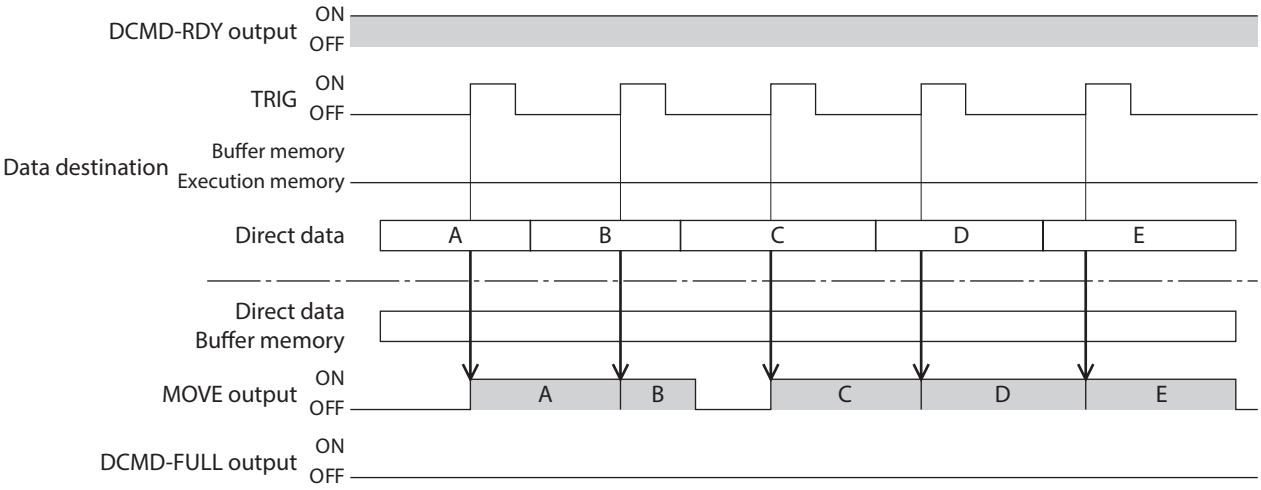
  When the TRIG is turned from OFF to ON, direct data operation is started. After that, only when the data corresponding to the trigger is changed, the motor will be started. Even if data other than the trigger is changed, the motor will not be started.

■ Data forwarding destination

During direct data operation, the stored area when the next direct data is transferred can be selected.

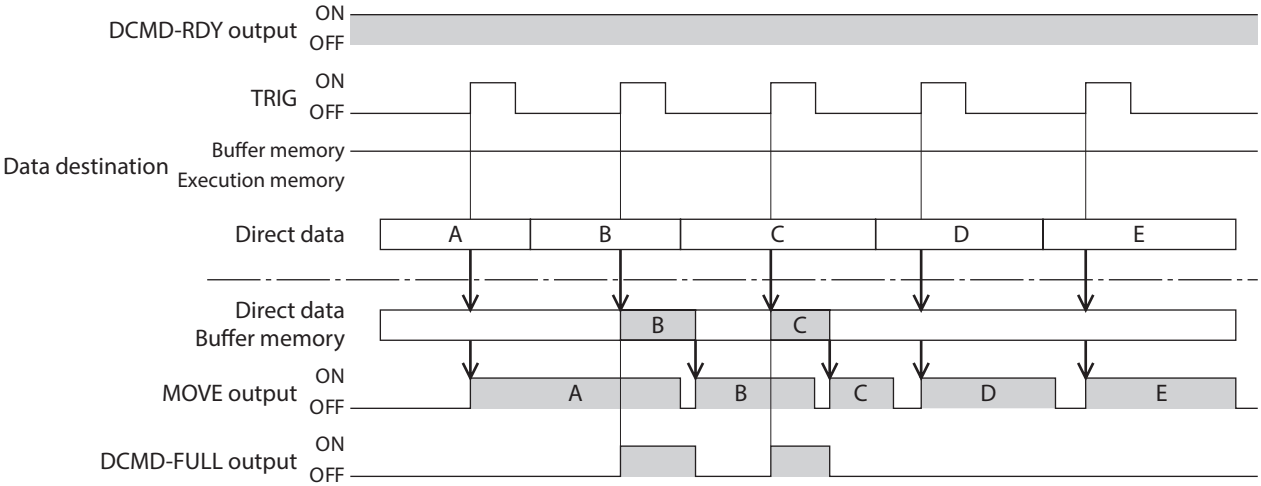
- **When the forwarding destination is set to "0: Execution memory"**

If the TRIG is turned from OFF to ON or the data corresponding to the trigger is changed, the data during operation can be rewritten to the next direct data. When the next direct data is saved in the buffer memory, the data in the buffer memory is deleted.



- **When the forwarding destination is set to "1: Buffer memory"**

If the TRIG is turned from OFF to ON or the data corresponding to the trigger is changed, the next direct data is saved in the buffer memory. When the data during operation is complete, operation of the buffer memory is automatically started. One direct data can be saved in the buffer memory.
If the next direct data is written to the buffer memory, the DCMD-FULL output is turned ON.
During stopping or continuous operation, if the "Buffer memory" is specified, the data is not saved in the buffer memory and rewritten to the next direct data immediately.



6-3 Operation example

A condition to execute direct data operation can be selected from the ON edge or ON level of TRIG of fixed I/O (IN).
A condition can be selected with the TRIG-MODE of fixed I/O (IN).

Note Before operating the motor, check the condition of the surrounding area to ensure safety.

■ When direct data operation is executed at ON edge of TRIG

As an example, this section explains how to perform the following direct data operation.

● Setting example

- Operation type: Absolute positioning
- Position: 5,000 steps
- Operating speed: 1,000 Hz
- Starting/changing speed rate: 1,000 kHz/s
- Stopping deceleration: 1,000 kHz/s
- Operating current: 100 %
- Forwarding destination: Execution memory

● Operation processing flow

Descriptions are given using the scanner as the subject.

1. Check the DCMD-RDY has been turned ON.
2. Set the following data.

• Output (scanner → driver)

Byte	Description	Setting value	Note
4, 5	TRIG-MODE [bit 9 of fixed I/O (IN)]	0	Start at ON edge
6, 7	Direct data operation operation type	1	Absolute positioning
8 to 11	Direct data operation position	5,000	5,000 steps
12 to 15	Direct data operation operating speed	1,000	1,000 Hz
16 to 19	Direct data operation starting/changing rate	1,000,000	1,000 kHz/s
20 to 23	Direct data operation stopping deceleration	1,000,000	1,000 kHz/s
24, 25	Direct data operation operating current	1,000	100.0 %
26, 27	Direct data operation forwarding destination	0	Execution memory

3. Turn the TRIG ON.
   Direct data operation is started.
4. Check the TRIG_R has been turned ON, and turn the TRIG OFF.

■ When direct data operation is executed at ON level of TRIG

This section explains how to execute the following direct data operation with setting the trigger to "position."
Set the trigger with the "Direct data operation trigger setting" parameter.

● Setting example

- Operation 1
  Position: 7,000 steps
- Operation 2
  Position: 3,000 steps
- Other settings

Description	Setting value
Operation type	Absolute positioning
Operating speed	1,000 Hz
Starting/changing speed rate	1,000 kHz/s

Description	Setting value
Stopping deceleration	1,000 kHz/s
Operating current	100 %
Forwarding destination	Execution memory

● Operation processing flow

Descriptions are given using the scanner as the subject.

1. Set the following parameters to turn the WR-REQ ON.
   The parameter information is set to the driver. When the setting is complete, the WR-END is turned ON.

   • Output (scanner → driver)

Byte	Description	Setting value	Note
34, 35	Write parameter ID	24852	Parameter ID of "Direct data operation trigger setting"
36 to 39	Write data	–5	Position

2. Turn the WR-REQ OFF.
   The WR-END is returned to OFF.
3. Check the DCMD-RDY has been turned ON.
4. Set the following data.

   • Output (scanner → driver)

Byte	Description	Setting value	Note
4, 5	TRIG-MODE [bit 9 of fixed I/O (IN)]	1	Start at ON level
6, 7	Direct data operation operation type	1	Absolute positioning
8 to 11	Direct data operation position	7,000	7,000 steps
12 to 15	Direct data operation operating speed	1,000	1,000 Hz
16 to 19	Direct data operation starting/changing rate	1,000,000	1,000 kHz/s
20 to 23	Direct data operation stopping deceleration	1,000,000	1,000 kHz/s
24, 25	Direct data operation operating current	1,000	100 %
26, 27	Direct data operation forwarding destination	0	Execution memory

5. Turn the TRIG ON.
   Direct data operation of the operation 1 is started.
6. Check the operation 1 is complete and then set the following data.
   Direct data operation of the operation 2 is started.

   • Output (scanner → driver)

Byte	Description	Setting value	Note
8 to 11	Direct data operation position	3,000	3,000 steps

memo
- To execute direct data operation of the operation 2, set a different value from the operation 1 in the "position" of the operation 2.
- If a value other than the "position" is changed, direct data operation of the operation 2 will not be executed.

5 Parameter ID lists

This part describes the parameter ID lists to be set via EtherNet/IP.
Data and parameters described here can also be set using the MEXE02.

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1 Timing for parameter to update

All data used by the driver is 32-bit wide.
Parameters are saved in the RAM or non-volatile memory. The parameters in the RAM are erased once the control power supply is shut off, but the parameters in the non-volatile memory are remained to store even if the control power supply is shut off.
When the control power supply of the driver is turned on, the parameters stored in the non-volatile memory will be sent to the RAM, and the recalculation and setup for the parameters will be executed in the RAM.

Parameters set via Implicit communication are saved in the RAM. To save the parameters stored in the RAM to the non-volatile memory, execute the "Write batch NV memory" of the maintenance command.

When a parameter is changed, the timing to update the new value varies depending on the parameter. Refer to the following four types.

Update timing	Description
Update immediately	Recalculation and setup are immediately executed when the parameter is written.
Update after operation stop	Recalculation and setup are executed when the operation is stopped.
Update after executing configuration	Recalculation and setup are executed after configuration is executed.
Update after turning on the control power supply again	Recalculation and setup are executed after the control power supply is turned on again.

memo

- Parameters set via Implicit communication are saved in the RAM. For parameters required for turning on the control power supply again, be sure to save them in the non-volatile memory before turning off the power.
- The non-volatile memory can be rewritten approximately 100,000 times.

■ Notation rules

In this part, each update timing is represented in an alphabet.

A: Update immediately
B: Update after operation stop
C: Update after executing configuration or turning the control power supply again
D: Update after turning on the control power supply again

READ/WRITE may be represented as "R/W" in this part.

2 Maintenance commands

Maintenance commands are used for resetting alarms, clearing latch information, batch processing of the non-volatile memory or the like are executed.
Refer to the OPERATING MANUAL **AZ** Series Function Edition for details about parameters. When checking the OPERATING MANUAL **AZ** Series Function Edition, use the parameter name instead of the parameter ID.

Note The maintenance commands include processing in which the memory is operated, such as batch processing of the non-volatile memory and P-PRESET. Be careful not to execute them unnecessarily in succession.

Parameter ID		Name	Setting range	Initial value
Dec	Hex			
192	00C0h	Alarm reset	–	–
194	00C2h	Clear alarm history		
196	00C4h	Clear communication error history		
197	00C5h	P-PRESET execution		
198	00C6h	Configuration		
199	00C7h	Batch data initialization (excluding communication parameters)		
200	00C8h	Read batch NV memory		
201	00C9h	Write batch NV memory		
202	00CAh	All data batch initialization (including communication parameters)		
203	00CBh	Read from backup		
204	00CCh	Write to backup		
205	00CDh	Clear latch information		
206	00CEh	Clear sequence history		
207	00CFh	Clear tripmeter		
208	00D0h	Clear ETO		
209	00D1h	ZSG-PRESET		
210	00D2h	Clear ZSG-PRESET		
211	00D3h	Clear information		
212	00D4h	Clear information history		
213	00D5h	Alarm history details	1 to 10: Alarm history 1 to 10	0: Not selected

3 Monitor commands

These commands are used to monitor the command position, command speed, alarm and information history, etc. All commands are used for read (READ).
Refer to the OPERATING MANUAL **AZ** Series Function Edition for details about parameters. When checking the OPERATING MANUAL **AZ** Series Function Edition, use the parameter name instead of the parameter ID.

Parameter ID		Name
Dec	Hex	
64	0040h	Present alarm
65	0041h	Alarm history 1
66	0042h	Alarm history 2
67	0043h	Alarm history 3
68	0044h	Alarm history 4
69	0045h	Alarm history 5
70	0046h	Alarm history 6
71	0047h	Alarm history 7
72	0048h	Alarm history 8
73	0049h	Alarm history 9
74	004Ah	Alarm history 10
97	0061h	Present selected data number
98	0062h	Present operation data number
99	0063h	Command position
100	0064h	Command speed (r/min)
101	0065h	Command speed (Hz)
102	0066h	Feedback position
103	0067h	Feedback speed (r/min)
104	0068h	Feedback speed (Hz)
105	0069h	Remaining dwell time
106	006Ah	Direct I/O
107	006Bh	Torque monitor (1=0.1 %)
109	006Dh	Cumulative load monitor
111	006Fh	Target position
112	0070h	Next number
113	0071h	Loop origin number
114	0072h	Loop count
115	0073h	Event monitor command position (NEXT)
116	0074h	Event monitor feedback position (NEXT)
117	0075h	Event monitor command position (JUMP0 – Low event)
118	0076h	Event monitor feedback position (JUMP0 – Low event)
119	0077h	Event monitor command position (JUMP1 – High event)
120	0078h	Event monitor feedback position (JUMP1 – High event)
121	0079h	Event monitor command position (STOP)
122	007Ah	Event monitor feedback position (STOP)
123	007Bh	Information
124	007Ch	Driver temperature (1=0.1 °C)
125	007Dh	Motor temperature (1=0.1 °C)
126	007Eh	Odometer (1=0.1 kRev)
127	007Fh	Tripmeter (1=0.1 kRev)

Parameter ID		Name
Dec	Hex	
128	0080h	Sequence history 1
129	0081h	Sequence history 2
130	0082h	Sequence history 3
131	0083h	Sequence history 4
132	0084h	Sequence history 5
133	0085h	Sequence history 6
134	0086h	Sequence history 7
135	0087h	Sequence history 8
136	0088h	Sequence history 9
137	0089h	Sequence history 10
138	008Ah	Sequence history 11
139	008Bh	Sequence history 12
140	008Ch	Sequence history 13
141	008Dh	Sequence history 14
142	008Eh	Sequence history 15
143	008Fh	Sequence history 16
144	0090h	Feedback position 32-bit counter
145	0091h	Command position 32-bit counter
146	0092h	CST operating current (1=0.1 %)
147	0093h	Loop count buffer
160	00A0h	Main power supply count
161	00A1h	Main power supply time (min)
162	00A2h	Control power supply count
163	00A3h	Inverter voltage (1=0.1 V)
164	00A4h	Main power voltage (DC power input driver only) [1=0.1 V]
166	00A6h	ROT SW0
167	00A7h	ROT SW1
169	00A9h	Elapsed time from BOOT (ms)
184	00B8h	I/O status 1
185	00B9h	I/O status 2
186	00BAh	I/O status 3
187	00BBh	I/O status 4
188	00BCh	I/O status 5
189	00BDh	I/O status 6
190	00BEh	I/O status 7
191	00BFh	I/O status 8
1280	0500h	Alarm history details (Alarm code)
1281	0501h	Alarm history details (Sub code)
1282	0502h	Alarm history details (Driver temperature)
1283	0503h	Alarm history details (Motor temperature)
1284	0504h	Alarm history details (Inverter voltage)
1285	0505h	Alarm history details (Physical I/O input)
1286	0506h	Alarm history details (R-I/O output)
1287	0507h	Alarm history details (Operation information 0)
1288	0508h	Alarm history details (Operation information 1)
1289	0509h	Alarm history details (Feedback position)
1290	050Ah	Alarm history details (Elapsed time from Boot) [ms]

Parameter ID		Name
Dec	Hex	
1291	050Bh	Alarm history details (elapsed time from starting operation) [ms]
1292	050Ch	Alarm history details (main power supply time) [min]
1296	0510h	Information history 1
1297	0511h	Information history 2
1298	0512h	Information history 3
1299	0513h	Information history 4
1300	0514h	Information history 5
1301	0515h	Information history 6
1302	0516h	Information history 7
1303	0517h	Information history 8
1304	0518h	Information history 9
1305	0519h	Information history 10
1306	051Ah	Information history 11
1307	051Bh	Information history 12
1308	051Ch	Information history 13
1309	051Dh	Information history 14
1310	051Eh	Information history 15
1311	051Fh	Information history 16
1312	0520h	Information time history 1 (ms)
1313	0521h	Information time history 2 (ms)
1314	0522h	Information time history 3 (ms)
1315	0523h	Information time history 4 (ms)
1316	0524h	Information time history 5 (ms)
1317	0525h	Information time history 6 (ms)
1318	0526h	Information time history 7 (ms)
1319	0527h	Information time history 8 (ms)
1320	0528h	Information time history 9 (ms)
1321	0529h	Information time history 10 (ms)
1322	052Ah	Information time history 11 (ms)
1323	052Bh	Information time history 12 (ms)
1324	052Ch	Information time history 13 (ms)
1325	052Dh	Information time history 14 (ms)
1326	052Eh	Information time history 15 (ms)
1327	052Fh	Information time history 16 (ms)
1472	05C0h	Latch monitor status (NEXT)
1473	05C1h	Latch monitor command position (NEXT)
1474	05C2h	Latch monitor feedback position (NEXT)
1475	05C3h	Latch monitor target position (NEXT)
1476	05C4h	Latch monitor operation number (NEXT)
1477	05C5h	Latch monitor number of loop (NEXT)
1480	05C8h	Latch monitor status (I/O event – Low event)
1481	05C9h	Latch monitor command position (I/O event – Low event)
1482	05CAh	Latch monitor feedback position (I/O event – Low event)
1483	05CBh	Latch monitor target position (I/O event – Low event)
1484	05CCh	Latch monitor operation number (I/O event – Low event)
1485	05CDh	Latch monitor number of loop (I/O event – Low event)
1488	05D0h	Latch monitor status (I/O event – High event)

Parameter ID		Name
Dec	Hex	
1489	05D1h	Latch monitor command position (I/O event – High event)
1490	05D2h	Latch monitor feedback position (I/O event – High event)
1491	05D3h	Latch monitor target position (I/O event – High event)
1492	05D4h	Latch monitor operation number (I/O event – High event)
1493	05D5h	Latch monitor number of loop (I/O event – High event)
1496	05D8h	Latch monitor status (STOP)
1497	05D9h	Latch monitor command position (STOP)
1498	05DAh	Latch monitor feedback position (STOP)
1499	05DBh	Latch monitor target position (STOP)
1500	05DCh	Latch monitor operation number (STOP)
1501	05DDh	Latch monitor number of loop (STOP)

4 Operation data R/W commands

This is a method in which the parameter ID (base address) of the base operation data number is specified to input data.
Refer to "4-3 Setting example" on p.121 for how to use the base address.

4-1 Base address of each operation data number

Base address		Operation data No.	Base address		Operation data No.	Base address		Operation data No.	Base address		Operation data No.
Dec	Hex		Dec	Hex		Dec	Hex		Dec	Hex	
3072	0C00h	No. 0	4288	10C0h	No. 38	5504	1580h	No. 76	6720	1A40h	No. 114
3104	0C20h	No. 1	4320	10E0h	No. 39	5536	15A0h	No. 77	6752	1A60h	No. 115
3136	0C40h	No. 2	4352	1100h	No. 40	5568	15C0h	No. 78	6784	1A80h	No. 116
3168	0C60h	No. 3	4384	1120h	No. 41	5600	15E0h	No. 79	6816	1AA0h	No. 117
3200	0C80h	No. 4	4416	1140h	No. 42	5632	1600h	No. 80	6848	1AC0h	No. 118
3232	0CA0h	No. 5	4448	1160h	No. 43	5664	1620h	No. 81	6880	1AE0h	No. 119
3264	0CC0h	No. 6	4480	1180h	No. 44	5696	1640h	No. 82	6912	1B00h	No. 120
3296	0CE0h	No. 7	4512	11A0h	No. 45	5728	1660h	No. 83	6944	1B20h	No. 121
3328	0D00h	No. 8	4544	11C0h	No. 46	5760	1680h	No. 84	6976	1B40h	No. 122
3360	0D20h	No. 9	4576	11E0h	No. 47	5792	16A0h	No. 85	7008	1B60h	No. 123
3392	0D40h	No. 10	4608	1200h	No. 48	5824	16C0h	No. 86	7040	1B80h	No. 124
3424	0D60h	No. 11	4640	1220h	No. 49	5856	16E0h	No. 87	7072	1BA0h	No. 125
3456	0D80h	No. 12	4672	1240h	No. 50	5888	1700h	No. 88	7104	1BC0h	No. 126
3488	0DA0h	No. 13	4704	1260h	No. 51	5920	1720h	No. 89	7136	1BE0h	No. 127
3520	0DC0h	No. 14	4736	1280h	No. 52	5952	1740h	No. 90	7168	1C00h	No. 128
3552	0DE0h	No. 15	4768	12A0h	No. 53	5984	1760h	No. 91	7200	1C20h	No. 129
3584	0E00h	No. 16	4800	12C0h	No. 54	6016	1780h	No. 92	7232	1C40h	No. 130
3616	0E20h	No. 17	4832	12E0h	No. 55	6048	17A0h	No. 93	7264	1C60h	No. 131
3648	0E40h	No. 18	4864	1300h	No. 56	6080	17C0h	No. 94	7296	1C80h	No. 132
3680	0E60h	No. 19	4896	1320h	No. 57	6112	17E0h	No. 95	7328	1CA0h	No. 133
3712	0E80h	No. 20	4928	1340h	No. 58	6144	1800h	No. 96	7360	1CC0h	No. 134
3744	0EA0h	No. 21	4960	1360h	No. 59	6176	1820h	No. 97	7392	1CE0h	No. 135
3776	0EC0h	No. 22	4992	1380h	No. 60	6208	1840h	No. 98	7424	1D00h	No. 136
3808	0EE0h	No. 23	5024	13A0h	No. 61	6240	1860h	No. 99	7456	1D20h	No. 137
3840	0F00h	No. 24	5056	13C0h	No. 62	6272	1880h	No. 100	7488	1D40h	No. 138
3872	0F20h	No. 25	5088	13E0h	No. 63	6304	18A0h	No. 101	7520	1D60h	No. 139
3904	0F40h	No. 26	5120	1400h	No. 64	6336	18C0h	No. 102	7552	1D80h	No. 140
3936	0F60h	No. 27	5152	1420h	No. 65	6368	18E0h	No. 103	7584	1DA0h	No. 141
3968	0F80h	No. 28	5184	1440h	No. 66	6400	1900h	No. 104	7616	1DC0h	No. 142
4000	0FA0h	No. 29	5216	1460h	No. 67	6432	1920h	No. 105	7648	1DE0h	No. 143
4032	0FC0h	No. 30	5248	1480h	No. 68	6464	1940h	No. 106	7680	1E00h	No. 144
4064	0FE0h	No. 31	5280	14A0h	No. 69	6496	1960h	No. 107	7712	1E20h	No. 145
4096	1000h	No. 32	5312	14C0h	No. 70	6528	1980h	No. 108	7744	1E40h	No. 146
4128	1020h	No. 33	5344	14E0h	No. 71	6560	19A0h	No. 109	7776	1E60h	No. 147
4160	1040h	No. 34	5376	1500h	No. 72	6592	19C0h	No. 110	7808	1E80h	No. 148
4192	1060h	No. 35	5408	1520h	No. 73	6624	19E0h	No. 111	7840	1EA0h	No. 149
4224	1080h	No. 36	5440	1540h	No. 74	6656	1A00h	No. 112	7872	1EC0h	No. 150
4256	10A0h	No. 37	5472	1560h	No. 75	6688	1A20h	No. 113	7904	1EE0h	No. 151

Base address		Operation data No.
Dec	Hex	
7936	1F00h	No. 152
7968	1F20h	No. 153
8000	1F40h	No. 154
8032	1F60h	No. 155
8064	1F80h	No. 156
8096	1FA0h	No. 157
8128	1FC0h	No. 158
8160	1FE0h	No. 159
8192	2000h	No. 160
8224	2020h	No. 161
8256	2040h	No. 162
8288	2060h	No. 163
8320	2080h	No. 164
8352	20A0h	No. 165
8384	20C0h	No. 166
8416	20E0h	No. 167
8448	2100h	No. 168
8480	2120h	No. 169
8512	2140h	No. 170
8544	2160h	No. 171
8576	2180h	No. 172
8608	21A0h	No. 173
8640	21C0h	No. 174
8672	21E0h	No. 175
8704	2200h	No. 176
8736	2220h	No. 177

Base address		Operation data No.
Dec	Hex	
8768	2240h	No. 178
8800	2260h	No. 179
8832	2280h	No. 180
8864	22A0h	No. 181
8896	22C0h	No. 182
8928	22E0h	No. 183
8960	2300h	No. 184
8992	2320h	No. 185
9024	2340h	No. 186
9056	2360h	No. 187
9088	2380h	No. 188
9120	23A0h	No. 189
9152	23C0h	No. 190
9184	23E0h	No. 191
9216	2400h	No. 192
9248	2420h	No. 193
9280	2440h	No. 194
9312	2460h	No. 195
9344	2480h	No. 196
9376	24A0h	No. 197
9408	24C0h	No. 198
9440	24E0h	No. 199
9472	2500h	No. 200
9504	2520h	No. 201
9536	2540h	No. 202
9568	2560h	No. 203

Base address		Operation data No.
Dec	Hex	
9600	2580h	No. 204
9632	25A0h	No. 205
9664	25C0h	No. 206
9696	25E0h	No. 207
9728	2600h	No. 208
9760	2620h	No. 209
9792	2640h	No. 210
9824	2660h	No. 211
9856	2680h	No. 212
9888	26A0h	No. 213
9920	26C0h	No. 214
9952	26E0h	No. 215
9984	2700h	No. 216
10016	2720h	No. 217
10048	2740h	No. 218
10080	2760h	No. 219
10112	2780h	No. 220
10144	27A0h	No. 221
10176	27C0h	No. 222
10208	27E0h	No. 223
10240	2800h	No. 224
10272	2820h	No. 225
10304	2840h	No. 226
10336	2860h	No. 227
10368	2880h	No. 228
10400	28A0h	No. 229

Base address		Operation data No.
Dec	Hex	
10432	28C0h	No. 230
10464	28E0h	No. 231
10496	2900h	No. 232
10528	2920h	No. 233
10560	2940h	No. 234
10592	2960h	No. 235
10624	2980h	No. 236
10656	29A0h	No. 237
10688	29C0h	No. 238
10720	29E0h	No. 239
10752	2A00h	No. 240
10784	2A20h	No. 241
10816	2A40h	No. 242
10848	2A60h	No. 243
10880	2A80h	No. 244
10912	2AA0h	No. 245
10944	2AC0h	No. 246
10976	2AE0h	No. 247
11008	2B00h	No. 248
11040	2B20h	No. 249
11072	2B40h	No. 250
11104	2B60h	No. 251
11136	2B80h	No. 252
11168	2BA0h	No. 253
11200	2BC0h	No. 254
11232	2BE0h	No. 255

4-2 Parameter ID

The setting item of operation data is set with the operation data R/W command.
The parameter ID for the setting item is arranged based on the base address of the operation data number.
(Base address ⇨p.118)
For example, in the case of the setting item "Position," 1 is added to the base address.

Parameter ID	Name	Setting range	Initial value	Update
Base address +0	Operation type	1: Absolute positioning 2: Incremental positioning (based on command position) 3: Incremental positioning (based on feedback position) 7: Continuous operation (position control) 8: Wrap absolute positioning 9: Wrap proximity positioning 10: Wrap forward direction absolute positioning 11: Wrap reverse direction absolute positioning 12: Wrap absolute push-motion 13: Wrap proximity push-motion 14: Wrap forward direction push-motion 15: Wrap reverse direction push-motion 16: Continuous operation (speed control) 17: Continuous operation (push-motion) 18: Continuous operation (torque control) 20: Absolute positioning push-motion 21: Incremental positioning push-motion (based on command position) 22: Incremental positioning push-motion (based on feedback position)	2	B
Base address +1	Position	–2,147,483,648 to 2,147,483,647 steps	0	
Base address +2	Operating speed	–4,000,000 to 4,000,000 Hz	1,000	
Base address +3	Starting/changing rate	1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000	
Base address +4	Stop	1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000	
Base address +5	Operating current	0 to 1,000 (1=0.1 %)	1,000	
Base address +6	Drive-complete delay time	0 to 65,535 (1=0.001 s)	0	
Base address +7	Link	0: No link 1: Manual sequential 2: Automatic sequential 3: Continuous sequential operation	0	
Base address +8	Next data number	–256: Stop –2: ↓↓ (+2) –1: ↓ (+1) 0 to 255: Operation data number	–1	
Base address +9	Area offset	–2,147,483,648 to 2,147,483,647 steps	0	
Base address +10	Area width	–1: Disable 0 to 4,194,303: Set by 1 step	–1	
Base address +11	Loop count	0: None (–) 2 to 255: Number of loops (loop 2 { to loop 255 {)	0	
Base address +12	Loop offset	–4,194,304 to 4,194,303 steps	0	
Base address +13	Loop end number	0: None (–) 1: } L-End	0	
Base address +14	(Low) I/O event number	–1: None (–) 0 to 31: Operation I/O event number (0 to 31)	–1	

Parameter ID	Name	Setting range	Initial value	Update
Base address +15	(High) I/O event number	−1: None (–) 0 to 31: Operation I/O event number (0 to 31)	−1	B

4-3 Setting example

As an example, this section explains how to set the following operation data to the operation data No. 0 to No. 2.

Setting item	Operation data No. 0	Operation data No. 1	Operation data No. 2
Operation type	Absolute positioning	Incremental positioning (based on command position)	Incremental positioning (based on feedback position)
Position [step]	1,000	1,000	1,000
Operating speed [Hz]	1,000	1,000	1,000
Operating current [%]	50.0	70.0	100.0

■ Setting of operation data No. 0

From the table on p.118, we can find that the base address of the operation data No. 0 is "3072 (0C00h)."
Based on this base address, the parameter ID for the setting item is calculated from the table on p.120.

Base address
3072 (0C00h)

Setting item	Parameter ID			Setting value
	Calculation method	Dec	Hex	
Operation type	Base address +0	3072 + 0 = 3072	0C00h	1
Position	Base address +1	3072 + 1 = 3073	0C01h	1,000
Operating speed	Base address +2	3072 + 2 = 3074	0C02h	1,000
Operating current	Base address +5	3072 + 5 = 3077	0C05h	500

■ Setting of operation data No. 1

From the table on p.118, we can find that the base address of the operation data No. 1 is "3104 (0C20h)."
Based on this base address, the parameter ID for the setting item is calculated from the table on p.120.

Base address
3104 (0C20h)

Setting item	Parameter ID			Setting value
	Calculation method	Dec	Hex	
Operation type	Base address +0	3104 + 0 = 3104	0C20h	2
Position	Base address +1	3104 + 1 = 3105	0C21h	1,000
Operating speed	Base address +2	3104 + 2 = 3106	0C22h	1,000
Operating current	Base address +5	3104 + 5 = 3109	0C25h	700

■ Setting of operation data No. 2

From the table on p.118, we can find that the base address of the operation data No. 2 is "3136 (0C40h)."
Based on this base address, the parameter ID for the setting item is calculated from the table on p.120.

Base address
3136 (0C40h)

Setting item	Parameter ID			Setting value
	Calculation method	Dec	Hex	
Operation type	Base address +0	3136 + 0 = 3136	0C40h	3
Position	Base address +1	3136 + 1 = 3137	0C41h	1,000
Operating speed	Base address +2	3136 + 2 = 3138	0C42h	1,000
Operating current	Base address +5	3136 + 5 = 3141	0C45h	1,000

5 Operation I/O event R/W commands

If a specified event (ON/OFF of I/O) is generated during operation of the motor, another operation can be started. This is called operation I/O event. This chapter explains the address to execute the operation I/O event.

5-1 Base address of operation I/O event

Base address		Operation I/O event number
Dec	Hex	
2560	0A00h	0
2568	0A08h	1
2576	0A10h	2
2584	0A18h	3
2592	0A20h	4
2600	0A28h	5
2608	0A30h	6
2616	0A38h	7
2624	0A40h	8
2632	0A48h	9
2640	0A50h	10

Base address		Operation I/O event number
Dec	Hex	
2648	0A58h	11
2656	0A60h	12
2664	0A68h	13
2672	0A70h	14
2680	0A78h	15
2688	0A80h	16
2696	0A88h	17
2704	0A90h	18
2712	0A98h	19
2720	0AA0h	20
2728	0AA8h	21

Base address		Operation I/O event number
Dec	Hex	
2736	0AB0h	22
2744	0AB8h	23
2752	0AC0h	24
2760	0AC8h	25
2768	0AD0h	26
2776	0AD8h	27
2784	0AE0h	28
2792	0AE8h	29
2800	0AF0h	30
2808	0AF8h	31

5-2 Parameter ID for operation I/O event R/W command

The setting item of operation I/O event is set with the operation I/O event R/W command.
The parameter ID for the setting item is arranged based on the base address of the operation I/O event.
For example, in the case of the setting item "Event waiting time," 2 is added to the base address.

Parameter ID	Name	Setting range	Initial value	Update
Base address +0	Event link	0: No link 1: Manual sequential 2: Automatic sequential 3: Continuous sequential operation	0	B
Base address +1	Event jump destination	−256: Stop −2: ↓↓ (+2) −1: ↓ (+1) 0 to 255: Operation data number	−256	
Base address +2	Event waiting time	0 to 65,535 (1=0.001 s)	0	
Base address +3	Event trigger I/O	Input signal list ⇨ p.141 Output signal list ⇨ p.142	0: Not used	
Base address +4	Event trigger type	0: No setting 1: ON (calculated cumulative ms) 2: ON (ms) 3: OFF (calculated cumulative ms) 4: OFF (ms) 5: ON edge 6: OFF edge 7: ON (cumulative ms) 8: OFF (cumulative ms)	0	
Base address +5	Event trigger counter	0 to 65,535 (1=1 ms or 1=once)	0	

6 I/O commands

These are commands related to I/O.
Refer to the OPERATING MANUAL **AZ** Series Function Edition for details about parameters. When checking the OPERATING MANUAL **AZ** Series Function Edition, use the parameter name instead of the parameter ID.

Parameter ID		Name	Initial value	R/W
Dec	Hex			
58	003Ah	Driver input command (2nd)	0	R/W
60	003Ch	Driver input command (automatic OFF)	0	R/W
63	003Fh	Driver output status	–	R

7 Protect release commands

The key codes for reading/writing of data from/to the backup area and the key codes for release of function limitation by the HMI input are set.
Refer to the OPERATING MANUAL **AZ** Series Function Edition for details about parameters. When checking the OPERATING MANUAL **AZ** Series Function Edition, use the parameter name instead of the parameter ID.

Parameter ID		Name	Setting range	Initial value
Dec	Hex			
32	0020h	Backup DATA access key	Refer to the next table.	0
33	0021h	Backup DATA write key		
34	0022h	HMI release key		

Key code table

Process that requires protect release	Command name	Key code
Data writing to backup area	Backup DATA access key	20519253 (01391955h)
	Backup DATA write key	1977326743 (75DB9C97h)
Data reading from backup area	Backup DATA access key	20519253 (01391955h)
Release of limitation by HMI input	HMI release key	864617234 (33890312h)

8 Extended operation data setting R/W command

Parameters for extended operation data setting can be set.
Refer to the OPERATING MANUAL **AZ** Series Function Edition for details about parameters. When checking the OPERATING MANUAL **AZ** Series Function Edition, use the parameter name instead of the parameter ID.

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
320	0140h	Common acceleration rate or time	1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000	A
321	0141h	Common stopping deceleration	1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000	
326	0146h	Rate selection	0: Common 1: Separate	1	
2048	0800h	Repeat start operation data number	−1: Disable 0 to 255: Operation data number	−1	
2049	0801h	Repeat end operation data number	−1: Disable 0 to 255: Operation data number	−1	
2050	0802h	Repeat time	−1: Disable 0 to 100,000,000	−1	

Note Rewrite the parameter of the extended operation data setting R/W command while operation is stopped.

9 Parameter R/W commands

These commands are used to write or read parameters.
Refer to the OPERATING MANUAL **AZ** Series Function Edition for details about parameters. When checking the OPERATING MANUAL **AZ** Series Function Edition, use the parameter name instead of the parameter ID.

9-1 Driver action simulation setting parameter

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
511	01FFh	Driver simulation mode	0: Use real motor 1: Virtual motor (when ABZO not connected = no ABZO information) 2: Virtual motor (when ABZO not connected = 1,800 rev wrap enable) 3: Virtual motor (when ABZO not connected = 900 rev wrap enable)	0	D

9-2 Basic setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
294	0126h	Base current	0 to 1,000 (1=0.1 %)	1,000	A
296	0128h	Stop current	0 to 1,000 (1=0.1 %)	500	
297	0129h	Command filter setting	1: LPF (speed filter) 2: Moving average filter	1	B
298	012Ah	Command filter time constant	0 to 200 ms	1	
300	012Ch	Smooth drive function	0: Disable 1: Enable	1	C
301	012Dh	Current control mode	0: Follow the CCM input 1: Alpha control mode (CST) 2: Servo emulation mode (SVE)	0	A
302	012Eh	Servo emulation (SVE) ratio	0 to 1,000 (1=0.1 %)	1,000	
303	012Fh	SVE position loop gain	1 to 50	10	
304	0130h	SVE speed loop gain	10 to 200	180	
305	0131h	SVE speed loop integral time constant	100 to 2,000 (1=0.1 ms)	1,000	
306	0132h	Automatic current cutback function	0: Disable 1: Enable	1	
307	0133h	Automatic current cutback switching time	0 to 1,000 ms	100	
308	0134h	Operating current ramp up rate	0 to 100 ms/100 %	0	
309	0135h	Operating current ramp down rate	0 to 100 ms/100 %	0	
311	0137h	Resonance suppression control frequency	100 to 2,000 Hz	1,000	
312	0138h	Resonance suppression control gain	–500 to 500	0	
313	0139h	Deviation acceleration suppressing gain	0 to 500	45	

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
506	01FAh	Main power mode*	−1: Automatic discrimination (Discriminates the input power supply voltage automatically.) 0: 24 VDC 1: 48 VDC	−1	D

* This is the parameter the voltage mode of the main power supply is set.

9-3 Position coordinate parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
451	01C3h	Software overtravel	−1: Disable 0: Immediate stop 1: Deceleration stop 2: Immediate stop with alarm 3: Deceleration stop with alarm	3	A
452	01C4h	Positive software limit	−2,147,483,648 to 2,147,483,647 steps	2,147,483,647	
453	01C5h	Negative software limit	−2,147,483,648 to 2,147,483,647 steps	−2,147,483,648	
454	01C6h	Preset position	−2,147,483,648 to 2,147,483,647 steps	0	

9-4 Operation parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
322	0142h	Starting speed	0 to 4,000,000 Hz	500	B
327	0147h	Acceleration/deceleration unit	0: kHz/s 1: s 2: ms/kHz	0	C
328	0148h	Permission of absolute positioning without setting absolute coordinates	0: Disable 1: Enable	0	B

9-5 Direct data operation parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
272	0110h	Direct data operation zero speed command action	0: Deceleration stop 1: ZERO speed	0	B
24852	6114h	Direct data operation trigger setting	−6: Operation type −5: Position −4: Speed −3: Starting/changing rate −2: Stopping deceleration −1: Operating current 0: Disable 1: Apply all data	1	A

9-6 ABZO sensor setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2032	07F0h	Mechanism settings	0: Prioritize ABZO setting 1: Manual setting	0	D
2034	07F2h	Initial coordinate generation & wrap coordinate setting	0: Prioritize ABZO setting 1: Manual setting	0	
2035	07F3h	Mechanism limit parameter setting	0: Follow ABZO setting 1: Disable	0	
2036	07F4h	Mechanism protection parameter setting	0: Follow ABZO setting 1: Disable	0	
2037	07F5h	JOG/HOME/ZHOME operation setting	0: Prioritize ABZO setting 1: Manual setting	0	

9-7 Mechanism settings parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
448	01C0h	Electronic gear A	1 to 65,535	1	C
449	01C1h	Electronic gear B	1 to 65,535	1	
450	01C2h	Motor rotation direction	0: Positive side=Counterclockwise 1: Positive side=Clockwise 2: Positive side=Counterclockwise (the driver parameter is applied) 3: Positive side=Clockwise (the driver parameter is applied)	1	
2017	07E1h	Mechanism lead	1 to 32,767	1	
2033	07F1h	Gear ratio setting	0: Gear ratio setting disable 1 to 32,767: Gear ratio (1=0.01)	0	
2553	09F9h	Mechanism lead decimal digit setting	0: ×1 [mm] 1: ×0.1 [mm] 2: ×0.01 [mm] 3: ×0.001 [mm]	0	

9-8 Initial coordinate generation & wrap coordinate parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
455	01C7h	Wrap setting	0: Disable 1: Enable	1	C
457	01C9h	Initial coordinate generation & wrap setting range	Refer to the next table.	10	
459	01CBh	Initial coordinate generation & wrap range offset ratio	0 to 10,000 (1=0.01 %)	5,000	
460	01CCh	Initial coordinate generation & wrap range offset value	–536,870,912 to 536,870,911 steps	0	
461	01CDh	The number of the RND-ZERO output in wrap range	1 to 536,870,911 divisions	1	

- **Value that can be set in the "Initial coordinate generation & wrap setting range" parameter (1=0.1 rev)**

  In the table, the values which are surrounded with thick box border cannot be set in 900 rev.

Wrap setting range [rev]						
5	18	48	120	250	720	2,000
6	20	50	125	300	750	2,250
8	24	60	144	360	900	3,000
9	25	72	150	375	1,000	3,600
10	30	75	180	400	1,125	4,500
12	36	80	200	450	1,200	6,000
15	40	90	225	500	1,500	9,000
16	45	100	240	600	1,800	18,000

9-9 JOG/HOME/ZHOME operation information setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
336	0150h	(JOG) Travel amount	1 to 8,388,607 steps	1	
337	0151h	(JOG) Operating speed	1 to 4,000,000 Hz	1,000	
338	0152h	(JOG) Acceleration/deceleration	1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000	
339	0153h	(JOG) Starting speed	0 to 4,000,000 Hz	500	
340	0154h	(JOG) Operating speed (high)	1 to 4,000,000 Hz	5,000	
344	0158h	(ZHOME) Operating speed	1 to 4,000,000 Hz	5,000	
345	0159h	(ZHOME) Acceleration/deceleration	1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000	
346	015Ah	(ZHOME) Starting speed	0 to 4,000,000 Hz	500	
350	015Eh	JOG/HOME/ZHOME command filter time constant	1 to 200 ms	1	
351	015Fh	JOG/HOME/ZHOME operating current	0 to 1,000 (1=0.1 %)	1,000	
352	0160h	(HOME) Home-seeking mode	0: 2-sensor 1: 3-sensor 2: One-way rotation 3: Push-motion	1	
353	0161h	(HOME) Starting direction	0: Negative side 1: Positive side	1	B
354	0162h	(HOME) Acceleration/deceleration	1 to 1,000,000,000 (1=0.001 kHz/s, 1=0.001 s, or 1=0.001 ms/kHz)	1,000,000	
355	0163h	(HOME) Starting speed	1 to 4,000,000 Hz	500	
356	0164h	(HOME) Operating speed	1 to 4,000,000 Hz	1,000	
357	0165h	(HOME) Last speed	1 to 10,000 Hz	500	
358	0166h	(HOME) SLIT detection	0: Disable 1: Enable	0	
359	0167h	(HOME) TIM/ZSG signal detection	0: Disable 1: TIM 2: ZSG	0	
360	0168h	(HOME) Position offset	–2,147,483,647 to 2,147,483,647 steps	0	
361	0169h	(HOME) Backward steps in 2 sensor home-seeking	0 to 8,388,607 steps	500	
362	016Ah	(HOME) Operating amount in uni-directional home-seeking	0 to 8,388,607 steps	500	

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
363	016Bh	(HOME) Operating current for push-home-seeking	0 to 1,000 (1=0.1 %)	1,000	B
364	016Ch	(HOME) Backward steps after first entry in push-home-seeking	0 to 8,388,607 steps	0	
365	016Dh	(HOME) Pushing time in push-home-seeking	1 to 65,535 ms	200	
366	016Eh	(HOME) Backward steps in push-home-seeking	0 to 8,388,607 steps	500	

9-10 Power removal function setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
400	0190h	HWTO mode selection	0: ETO-mode 1: Alarm-shutdown	0	A
401	0191h	HWTO delay time of checking dual system	0 to 10: Disable 11 to 100 ms	0	
408	0198h	ETO reset ineffective period	0 to 100 ms	0	
409	0199h	ETO reset action (ETO-CLR)	1: ON-Edge 2: ON-Level	1	
410	019Ah	ETO reset action (ALM-RST)	0: ETO-CLR ineffective 1: ON-Edge	0	
411	019Bh	ETO reset action (C-ON)	0: ETO-CLR ineffective 1: ON-Edge	0	
412	019Ch	ETO reset action (STOP)	0: ETO-CLR ineffective 1: ON-Edge	1	

9-11 Alarm setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
384	0180h	Overload alarm	1 to 300 (1=0.1 s)	50	A
385	0181h	Excessive position deviation alarm	1 to 30,000 (1=0.01 rev)	300	
24968	6188h	Network bus error alarm	0: Disable 1: Enable	1	

9-12 Information setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
416	01A0h	Driver temperature information (INFO-DRVTMP)	40 to 85 °C	85	A
417	01A1h	Overload time information (INFO-OLTIME)	1 to 300 (1=0.1 s)	50	
418	01A2h	Overspeed information (INFO-SPD)	0: Disable 1 to 12,000 r/min	0	
421	01A5h	Position deviation information (INFO-POSERR)	1 to 30,000 (1=0.01 rev)	300	
424	01A8h	Motor temperature information (INFO-MTRTMP)	40 to 120 °C	85	

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
425	01A9h	Overvoltage information (INFO-OVOLT) (AC power input type driver)	120 to 450 V	435	A
426	01AAh	Undervoltage information (INFO-UVOLT) (AC power input type driver)	120 to 280 V	120	
427	01ABh	Overvoltage information (INFO-OVOLT) (DC power input type driver)	150 to 630 (1=0.1 V)	630	
428	01ACh	Undervoltage information (INFO-UVOLT) (DC power input type driver)	150 to 630 (1=0.1 V)	180	
431	01AFh	Tripmeter information (INFO-TRIP)	0: Disable 1 to 2,147,483,647 (1=0.1 kRev)	0	
432	01B0h	Odometer information (INFO-ODO)	0: Disable 1 to 2,147,483,647 (1=0.1 kRev)	0	
433	01B1h	Cumulative load 0 information (INFO-CULD0)	0 to 2,147,483,647	0	
434	01B2h	Cumulative load 1 information (INFO-CULD1)	0 to 2,147,483,647	0	
435	01B3h	Cumulative load value auto clear	0: Disable 1: Enable	1	
436	01B4h	Cumulative load value count divisor	1 to 32,767	1	
444	01BCh	INFO-USRIO output selection	Output signals list⇨p.142	128: CONST-OFF	
445	01BDh	INFO-USRIO output inversion	0: Not invert 1: Invert	0	
446	01BEh	Information LED condition	0: Disable 1: Enable	1	
447	01BFh	Information auto clear	0: Disable 1: Enable	1	
1952	07A0h	INFO action (assigned I/O status information (INFO-USRIO))	0: No info reflect (Only the bit output is ON.) 1: Info reflect (The bit output and the INFO output are ON and the LED blinks.)	1	
1953	07A1h	INFO action (position deviation information (INFO-POSERR))			
1954	07A2h	INFO action (driver temperature information (INFO-DRVTMP))			
1955	07A3h	INFO action (motor temperature information (INFO-MTRTMP))			
1956	07A4h	INFO action (overvoltage information (INFO-OVOLT))			
1957	07A5h	INFO action (undervoltage information (INFO-UVOLT))			
1958	07A6h	INFO action (overload time information (INFO-OLTIME))			
1960	07A8h	INFO action (speed information (INFO-SPD))			
1961	07A9h	INFO action (start operation error information (INFO-START))			
1962	07AAh	INFO action (start ZHOME error information (INFO-ZHOME))			
1963	07ABh	INFO action (PRESET request information (INFO-PR-REQ))			
1965	07ADh	INFO action (electronic gear setting error information (INFO-EGR-E))			
1966	07AEh	INFO action (wrap setting error information (INFO-RND-E))			

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
1968	07B0h	INFO action (forward operation prohibition information (INFO-FW-OT))	0: No info reflect (Only the bit output is ON.) 1: Info reflect (The bit output and the INFO output are ON and the LED blinks.)	1	A
1969	07B1h	INFO action (reverse operation prohibition information (INFO-RV-OT))			
1970	07B2h	INFO action (cumulative load 0 information (INFO-CULD0))			
1971	07B3h	INFO action (cumulative load 1 information (INFO-CULD1))			
1972	07B4h	INFO action (tripmeter information (INFO-TRIP))			
1973	07B5h	INFO action (odometer information (INFO-ODO))			
1980	07BCh	INFO action (start operation restricted mode information (INFO-DSLMTD))			
1981	07BDh	INFO action (I/O test mode information (INFO-IOTEST))			
1982	07BEh	INFO action (configuration request information (INFO-CFG))			
1983	07BFh	INFO action (reboot request information (INFO-RBT))			

9-13 I/O parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
1792	0700h	STOP/STOP-COFF input action	0: Both are immediate 1: (STOP) Dec. & (STOP-COFF) Imm. 2: (STOP) Imm. & (STOP-COFF) Dec. 3: Both are deceleration	3	A
1793	0701h	FW-LS/RV-LS input action	−1: For homing sensor 0: Immediate stop 1: Deceleration stop 2: Immediate stop with alarm 3: Deceleration stop with alarm	2	
1794	0702h	FW-BLK/RV-BLK input action	0: Immediate stop 1: Deceleration stop	1	
1795	0703h	IN-POS positioning completion signal range	0 to 180 (1=0.1°)	18	
1796	0704h	IN-POS positioning completion signal offset	−18 to 18 (1=0.1°)	0	
1797	0705h	D-SEL drive start function	0: Without START-Func. (only select data) (Only operation data number selection) 1: With START-Func (Operation data number selection + START function)	1	
1798	0706h	TEACH operation type setting	−1: Not set 1: Absolute positioning 8: Wrap absolute positioning	1	
1799	0707h	ZSG signal width	1 to 1,800 (1=0.1°)	18	
1800	0708h	RND-ZERO signal width	1 to 10,000 steps	10	

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
1801	0709h	RND-ZERO signal source	0: Based on feedback position 1: Based on command position	0	A
1802	070Ah	MOVE minimum ON time	0 to 255 ms	0	
1803	070Bh	PAUSE standby condition selection	0: Standstill mode (current cutback) 1: Operation mode (operating current is retained)	0	
1804	070Ch	PLS-XMODE pulse multiplying factor	2 to 30 times	10	
1805	070Dh	CRNT-LMT operating current limit value	0 to 1,000 (1=0.1 %)	500	
1806	070Eh	SPD-LMT speed limit type selection	0: Ratio 1: Value	0	
1807	070Fh	SPD-LMT speed limit ratio	1 to 100 %	50	
1808	0710h	SPD-LMT speed limit value	1 to 4,000,000 Hz	1,000	
1809	0711h	JOG-C time from JOG-P to JOG	1 to 5,000 (1=0.001 s)	500	B
1810	0712h	JOG-C time from JOG to JOG-H	1 to 5,000 (1=0.001 s)	1,000	
1811	0713h	PLS-LOST check algorithm	0: Unsigned 1: Signed	0	A
1812	0714h	MON-REQ0 output data selection	1: Feedback position 2: Feedback position (32-bit counter) 3: Command position 4: Command position (32-bit counter) 8: Alarm code (8 bits) 9: Feedback position and alarm code 10: Feedback position (32-bit counter) and alarm code 11: Command position and alarm code 12: Command position (32-bit counter) and alarm code	1	B
1813	0715h	MON-REQ1 output data selection		8	
1814	0716h	PLS-OUT output data selection	0: Command position 1: Command position (32-bit counter) 2: Feedback position 3: Feedback position (32-bit counter)	0	
1815	0717h	PLS-OUT maximum frequency	1 to 10,000 (1=0.1 kHz)	100	
1816	0718h	VA mode selection	0: Feedback speed attainment (speed at feedback position) 1: Speed at command position (only internal profile) 2: Speed at feedback position & command position (only internal profile)	0	
1817	0719h	VA detection speed range	1 to 200 r/min	30	
1818	071Ah	MAREA output source	0: Feedback position (ON after operation) 1: Command position (ON after operation) 2: Feedback position (MAREA output OFF at completion) 3: Command position (MAREA output OFF at completion)	0	A
1856	0740h	AREA0 positive direction position/offset	−2,147,483,648 to 2,147,483,647 steps	0	
1857	0741h	AREA0 negative direction position/detection range			

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
1858	0742h	AREA1 positive direction position/offset	−2,147,483,648 to 2,147,483,647 steps	0	A
1859	0743h	AREA1 negative direction position/detection range			
1860	0744h	AREA2 positive direction position/offset			
1861	0745h	AREA2 negative direction position/detection range			
1862	0746h	AREA3 positive direction position/offset			
1863	0747h	AREA3 negative direction position/detection range			
1864	0748h	AREA4 positive direction position/offset			
1865	0749h	AREA4 negative direction position/detection range			
1866	074Ah	AREA5 positive direction position/offset			
1867	074Bh	AREA5 negative direction position/detection range			
1868	074Ch	AREA6 positive direction position/offset			
1869	074Dh	AREA6 negative direction position/detection range			
1870	074Eh	AREA7 positive direction position/offset			
1871	074Fh	AREA7 negative direction position/detection range			
1872	0750h	AREA0 range setting mode	0: Absolute pos 1: Offset/width setting from the target position	0	
1873	0751h	AREA1 range setting mode			
1874	0752h	AREA2 range setting mode			
1875	0753h	AREA3 range setting mode			
1876	0754h	AREA4 range setting mode			
1877	0755h	AREA5 range setting mode			
1878	0756h	AREA6 range setting mode			
1879	0757h	AREA7 range setting mode			
1880	0758h	AREA0 positioning standard	0: Based on feedback position 1: Based on command position	0	
1881	0759h	AREA1 positioning standard			
1882	075Ah	AREA2 positioning standard			
1883	075Bh	AREA3 positioning standard			
1884	075Ch	AREA4 positioning standard			
1885	075Dh	AREA5 positioning standard			
1886	075Eh	AREA6 positioning standard			
1887	075Fh	AREA7 positioning standard			
1888	0760h	D-SEL0 operation number selection	0 to 255: Operation data number	0	
1889	0761h	D-SEL1 operation number selection		1	
1890	0762h	D-SEL2 operation number selection		2	
1891	0763h	D-SEL3 operation number selection		3	

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
1892	0764h	D-SEL4 operation number selection	0 to 255: Operation data number	4	A
1893	0765h	D-SEL5 operation number selection		5	
1894	0766h	D-SEL6 operation number selection		6	
1895	0767h	D-SEL7 operation number selection		7	
1896	0768h	D-END0 operation number selection	0 to 255: Operation data number	0	
1897	0769h	D-END1 operation number selection		1	
1898	076Ah	D-END2 operation number selection		2	
1899	076Bh	D-END3 operation number selection		3	
1900	076Ch	D-END4 operation number selection		4	
1901	076Dh	D-END5 operation number selection		5	
1902	076Eh	D-END6 operation number selection		6	
1903	076Fh	D-END7 operation number selection		7	
2554	09FAh	Current setting during motor standstill at T-MODE	0: Stop current 1: Operating current	0	

9-14 Direct I/O setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2112	0840h	DIN0 input function	Input signals list ⇨p.141	37: ZHOME	C
2113	0841h	DIN1 input function		1: FREE	
2114	0842h	DIN2 input function		5: STOP	
2115	0843h	DIN3 input function		8: ALM-RST	
2116	0844h	DIN4 input function		48: FW-JOG	
2117	0845h	DIN5 input function		49: RV-JOG	
2128	0850h	DIN0 inverting mode	0: Non invert 1: Invert	0	
2129	0851h	DIN1 inverting mode			
2130	0852h	DIN2 inverting mode			
2131	0853h	DIN3 inverting mode			
2132	0854h	DIN4 inverting mode			
2133	0855h	DIN5 inverting mode			
2144	0860h	DOUT0 (normal) output function	Output signals list ⇨p.142	144: HOME-END	
2145	0861h	DOUT1 (normal) output function		138: IN-POS	
2146	0862h	DOUT2 (normal) output function		133: PLS-RDY	
2147	0863h	DOUT3 (normal) output function		132: READY	
2148	0864h	DOUT4 (normal) output function		134: MOVE	
2149	0865h	DOUT5 (normal) output function		130: ALM-B	

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2160	0870h	DOUT0 inverting mode	0: Non invert 1: Invert	0	C
2161	0871h	DOUT1 inverting mode			
2162	0872h	DOUT2 inverting mode			
2163	0873h	DOUT3 inverting mode			
2164	0874h	DOUT4 inverting mode			
2165	0875h	DOUT5 inverting mode			
2176	0880h	DIN0 composite input function	Input signals list ⇨p.141	0: No function	
2177	0881h	DIN1 composite input function			
2178	0882h	DIN2 composite input function			
2179	0883h	DIN3 composite input function			
2180	0884h	DIN4 composite input function			
2181	0885h	DIN5 composite input function			
2192	0890h	DOUT0 composite output function	Output signals list ⇨p.142	128: CONST-OFF	
2193	0891h	DOUT1 composite output function			
2194	0892h	DOUT2 composite output function			
2195	0893h	DOUT3 composite output function			
2196	0894h	DOUT4 composite output function			
2197	0895h	DOUT5 composite output function			
2208	08A0h	DOUT0 composite inverting mode	0: Non invert 1: Invert	0	
2209	08A1h	DOUT1 composite inverting mode			
2210	08A2h	DOUT2 composite inverting mode			
2211	08A3h	DOUT3 composite inverting mode			
2212	08A4h	DOUT4 composite inverting mode			
2213	08A5h	DOUT5 composite inverting mode			
2224	08B0h	DOUT0 composite logical combination	0: AND 1: OR	1	
2225	08B1h	DOUT1 composite logical combination			
2226	08B2h	DOUT2 composite logical combination			
2227	08B3h	DOUT3 composite logical combination			
2228	08B4h	DOUT4 composite logical combination			
2229	08B5h	DOUT5 composite logical combination			
2240	08C0h	DIN0 ON signal dead-time	0 to 250 ms	0	
2241	08C1h	DIN1 ON signal dead-time			
2242	08C2h	DIN2 ON signal dead-time			
2243	08C3h	DIN3 ON signal dead-time			
2244	08C4h	DIN4 ON signal dead-time			
2245	08C5h	DIN5 ON signal dead-time			
2256	08D0h	DIN0 1 shot signal	0: Disable 1: Enable	0	
2257	08D1h	DIN1 1 shot signal			
2258	08D2h	DIN2 1 shot signal			
2259	08D3h	DIN3 1 shot signal			
2260	08D4h	DIN4 1 shot signal			
2261	08D5h	DIN5 1 shot signal			
2272	08E0h	DOUT0 OFF delay time	0 to 250 ms	0	
2273	08E1h	DOUT1 OFF delay time			
2274	08E2h	DOUT2 OFF delay time			
2275	08E3h	DOUT3 OFF delay time			
2276	08E4h	DOUT4 OFF delay time			

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2277	08E5h	DOUT5 OFF delay time	0 to 250 ms	0	C

9-15 Remote I/O setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2304	0900h	R-IN0 input function	Input signals list ⇨p.141	0: No function	C
2305	0901h	R-IN1 input function			
2306	0902h	R-IN2 input function			
2307	0903h	R-IN3 input function			
2308	0904h	R-IN4 input function			
2309	0905h	R-IN5 input function			
2310	0906h	R-IN6 input function			
2311	0907h	R-IN7 input function			
2312	0908h	R-IN8 input function			
2313	0909h	R-IN9 input function			
2314	090Ah	R-IN10 input function			
2315	090Bh	R-IN11 input function			
2316	090Ch	R-IN12 input function			
2317	090Dh	R-IN13 input function			
2318	090Eh	R-IN14 input function			
2319	090Fh	R-IN15 input function			
2320	0910h	R-OUT0 output function	Output signals list ⇨p.142	64: M0_R	
2321	0911h	R-OUT1 output function		65: M1_R	
2322	0912h	R-OUT2 output function		66: M2_R	
2323	0913h	R-OUT3 output function		32: START_R	
2324	0914h	R-OUT4 output function		144: HOME-END	
2325	0915h	R-OUT5 output function		132: READY	
2326	0916h	R-OUT6 output function		135: INFO	
2327	0917h	R-OUT7 output function		129: ALM-A	
2328	0918h	R-OUT8 output function		136: SYS-BSY	
2329	0919h	R-OUT9 output function		160: AREA0	
2330	091Ah	R-OUT10 output function		161: AREA1	
2331	091Bh	R-OUT11 output function		162: AREA2	
2332	091Ch	R-OUT12 output function		157: TIM	
2333	091Dh	R-OUT13 output function		134: MOVE	
2334	091Eh	R-OUT14 output function		138: IN-POS	
2335	091Fh	R-OUT15 output function		140: TLC	
2352	0930h	R-OUT0 OFF delay time	0 to 250 ms	0	
2353	0931h	R-OUT1 OFF delay time			
2354	0932h	R-OUT2 OFF delay time			
2355	0933h	R-OUT3 OFF delay time			
2356	0934h	R-OUT4 OFF delay time			
2357	0935h	R-OUT5 OFF delay time			
2358	0936h	R-OUT6 OFF delay time			
2359	0937h	R-OUT7 OFF delay time			

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2360	0938h	R-OUT8 OFF delay time	0 to 250 ms	0	C
2361	0939h	R-OUT9 OFF delay time			
2362	093Ah	R-OUT10 OFF delay time			
2363	093Bh	R-OUT11 OFF delay time			
2364	093Ch	R-OUT12 OFF delay time			
2365	093Dh	R-OUT13 OFF delay time			
2366	093Eh	R-OUT14 OFF delay time			
2367	093Fh	R-OUT15 OFF delay time			

9-16 Extended input setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2416	0970h	Extended input (EXT-IN) function	Input signals list⇨p.141	9: P-PRESET	C
2417	0971h	Extended input (EXT-IN) inverting mode	0: Non invert 1: Invert	0	
2418	0972h	Extended input (EXT-IN) interlock releasing time	0: Interlock disabled 1 to 50 (1=0.1 s)	10	A
2419	0973h	Extended input (EXT-IN) interlock releasing duration	0 to 50 (1=0.1 s)	30	
2420	0974h	Extended input (EXT-IN) ON monitor time	0 to 50 (1=0.1 s)	10	

9-17 Differential output setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2424	0978h	Differential output mode selection	−1: Non-out 0: PLS (FB-POS) 8: IO-OUT	0	C
2426	097Ah	Differential output (EXT-OUTA) function selection on I/O mode	Output signals list ⇨p.142	128: CONST-OFF	
2427	097Bh	Differential output (EXT-OUTB) function selection on I/O mode			
2428	097Ch	Differential output (EXT-OUTA) inverting mode on I/O mode	0: Non invert 1: Invert	0	
2429	097Dh	Differential output (EXT-OUTB) inverting mode on I/O mode			
2430	097Eh	Differential output (EXT-OUTA) OFF delay time on I/O mode	0 to 250 ms	0	
2431	097Fh	Differential output (EXT-OUTB) OFF delay time on I/O mode			

9-18 Virtual input parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2368	0940h	Virtual input (VIR-IN0) function	Input signals list ⇨p.141	0: No function	C
2369	0941h	Virtual input (VIR-IN1) function			
2370	0942h	Virtual input (VIR-IN2) function			
2371	0943h	Virtual input (VIR-IN3) function			
2372	0944h	Virtual input (VIR-IN0) source selection	Output signals list ⇨p.142	128: CONST-OFF	
2373	0945h	Virtual input (VIR-IN1) source selection			
2374	0946h	Virtual input (VIR-IN2) source selection			
2375	0947h	Virtual input (VIR-IN3) source selection			
2376	0948h	Virtual input (VIR-IN0) inverting mode	0: Non invert 1: Invert	0	
2377	0949h	Virtual input (VIR-IN1) inverting mode			
2378	094Ah	Virtual input (VIR-IN2) inverting mode			
2379	094Bh	Virtual input (VIR-IN3) inverting mode			
2380	094Ch	Virtual input (VIR-IN0) ON signal dead time	0 to 250 ms	0	
2381	094Dh	Virtual input (VIR-IN1) ON signal dead time			
2382	094Eh	Virtual input (VIR-IN2) ON signal dead time			
2383	094Fh	Virtual input (VIR-IN3) ON signal dead time			
2384	0950h	Virtual input (VIR-IN0) 1 shot signal mode	0: Disable 1: Enable	0	
2385	0951h	Virtual input (VIR-IN1) 1 shot signal mode			
2386	0952h	Virtual input (VIR-IN2) 1 shot signal mode			
2387	0953h	Virtual input (VIR-IN3) 1 shot signal mode			

9-19 User output setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
2400	0960h	User output (USR-OUT0) source A function	Output signals list ⇨p.142	128: CONST-OFF	C
2401	0961h	User output (USR-OUT1) source A function			
2402	0962h	User output (USR-OUT0) source A inverting mode	0: Non invert 1: Invert	0	
2403	0963h	User output (USR-OUT1) source A inverting mode			
2404	0964h	User output (USR-OUT0) source B function	Output signals list ⇨p.142	128: CONST-OFF	
2405	0965h	User output (USR-OUT1) source B function			
2406	0966h	User output (USR-OUT0) source B inverting mode	0: Non invert 1: Invert	0	
2407	0967h	User output (USR-OUT1) source B inverting mode			
2408	0968h	User output (USR-OUT0) logical operation	0: AND 1: OR	1	
2409	0969h	User output (USR-OUT1) logical operation			

9-20 Driver mode setting parameters

Parameter ID		Name	Setting range	Initial value	Update
Dec	Hex				
496	01F0h	PULSE-I/F mode selection	–1: Disable 1: 2 pulse input mode 2: 1 pulse input mode 3: Phase-shifted pulses input mode (×1) 4: Phase-shifted pulses input mode (×2) 5: Phase-shifted pulses input mode (×4)	1	D
498	01F2h	USB-ID enable	0: Disable 1: Enable	1	
499	01F3h	USB-ID	0 to 999,999,999	0	
2555	09FBh	USB-PID	0 to 31	0	

9-21 EtherNet/IP communication setting parameters

- **Assignable monitor setting parameters**

Parameter ID		Name	Description	Setting range	Initial value	Update
Dec	Hex					
25600	6400h	Assignable monitor address 0	Sets the parameter ID to show on the assignable monitor.	Set from items of "5 Parameter ID lists."	124: Driver temperature	A
25601	6401h	Assignable monitor address 1			125: Motor temperature	
25602	6402h	Assignable monitor address 2			109: Cumulative load monitor	
25603	6403h	Assignable monitor address 3			127: Tripmeter	

- **IP address setting parameters**

These are parameters to be set via Explicit communication. There is no parameter ID.

Parameter ID		Name	Description	Setting range	Initial value	Update
Dec	Hex					
–	–	Configuration control	Sets how to obtain the IP address.	0: Parameter 2: DHCP server	2	D
–	–	IP address 1	Sets the IP address.	0 to 255	192	
–	–	IP address 2			168	
–	–	IP address 3			1	
–	–	IP address 4			1	
–	–	Network mask 1	Sets the subnet mask.	0 to 255	255	
–	–	Network mask 2			255	
–	–	Network mask 3			255	
–	–	Network mask 4			0	
–	–	Gateway address 1	Sets the default gateway.	0 to 255	0	
–	–	Gateway address 2			0	
–	–	Gateway address 3			0	
–	–	Gateway address 4			0	

10 I/O signals assignment list

10-1 Input signals

To assign signals via network, use the "assignment number" in the table instead of the signal names.

Assignment number	Signal name
0	No function
1	FREE
2	C-ON
3	CLR
4	STOP-COFF
5	STOP
6	PAUSE
7	BREAK-ATSQ
8	ALM-RST
9	P-PRESET
10	EL-PRST
12	ETO-CLR
13	LAT-CLR
14	INFO-CLR
16	HMI
18	CCM
19	PLS-XMODE
20	PLS-DIS
21	T-MODE
22	CRNT-LMT
23	SPD-LMT
26	FW-BLK
27	RV-BLK
28	FW-LS
29	RV-LS
30	HOMES
31	SLIT
32	START

Assignment number	Signal name
33	SSTART
35	NEXT
36	HOME
37	ZHOME
40	D-SEL0
41	D-SEL1
42	D-SEL2
43	D-SEL3
44	D-SEL4
45	D-SEL5
46	D-SEL6
47	D-SEL7
48	FW-JOG
49	RV-JOG
50	FW-JOG-H
51	RV-JOG-H
52	FW-JOG-P
53	RV-JOG-P
54	FW-JOG-C
55	RV-JOG-C
56	FW-POS
57	RV-POS
58	FW-SPD
59	RV-SPD
60	FW-PSH
61	RV-PSH
64	M0
65	M1

Assignment number	Signal name
66	M2
67	M3
68	M4
69	M5
70	M6
71	M7
75	TEACH
76	MON-REQ0
77	MON-REQ1
78	MON-CLK
79	PLSM-REQ
80	R0
81	R1
82	R2
83	R3
84	R4
85	R5
86	R6
87	R7
88	R8
89	R9
90	R10
91	R11
92	R12
93	R13
94	R14
95	R15

10-2 Output signals

To assign signals via network, use the "assignment number" in the table instead of the signal names.

Assignment number	Signal name
0	No function
1	FREE_R
2	C-ON_R
3	CLR_R
4	STOP-COFF_R
5	STOP_R
6	PAUSE_R
7	BREAK-ATSQ_R
8	ALM-RST_R
9	P-PRESET_R
10	EL-PRST_R
12	ETO-CLR_R
13	LAT-CLR_R
14	INFO-CLR_R
16	HMI_R
18	CCM_R
19	PLS-XMODE_R
20	PLS-DIS_R
21	T-MODE_R
22	CRNT-LMT_R
23	SPD-LMT_R
26	FW-BLK_R
27	RV-BLK_R
28	FW-LS_R
29	RV-LS_R
30	HOMES_R
31	SLIT_R
32	START_R
33	SSTART_R
35	NEXT_R
36	HOME_R
37	ZHOME_R
40	D-SEL0_R
41	D-SEL1_R
42	D-SEL2_R
43	D-SEL3_R
44	D-SEL4_R
45	D-SEL5_R
46	D-SEL6_R
47	D-SEL7_R
48	FW-JOG_R
49	RV-JOG_R
50	FW-JOG-H_R
51	RV-JOG-H_R

Assignment number	Signal name
52	FW-JOG-P_R
53	RV-JOG-P_R
54	FW-JOG-C_R
55	RV-JOG-C_R
56	FW-POS_R
57	RV-POS_R
58	FW-SPD_R
59	RV-SPD_R
60	FW-PSH_R
61	RV-PSH_R
64	M0_R
65	M1_R
66	M2_R
67	M3_R
68	M4_R
69	M5_R
70	M6_R
71	M7_R
75	TEACH_R
76	MON-REQ0_R
77	MON-REQ1_R
78	MON-CLK_R
79	PLSM-REQ_R
80	R0_R
81	R1_R
82	R2_R
83	R3_R
84	R4_R
85	R5_R
86	R6_R
87	R7_R
88	R8_R
89	R9_R
90	R10_R
91	R11_R
92	R12_R
93	R13_R
94	R14_R
95	R15_R
128	CONST-OFF
129	ALM-A
130	ALM-B
131	SYS-RDY
132	READY

Assignment number	Signal name
133	PLS-RDY
134	MOVE
135	INFO
136	SYS-BSY
137	ETO-MON
138	IN-POS
140	TLC
141	VA
142	CRNT
143	AUTO-CD
144	HOME-END
145	ABSPEN
146	ELPRST-MON
149	PRST-DIS
150	PRST-STLD
151	ORGN-STLD
152	RND-OVF
153	FW-SLS
154	RV-SLS
155	ZSG
156	RND-ZERO
157	TIM
159	MAREA
160	AREA0
161	AREA1
162	AREA2
163	AREA3
164	AREA4
165	AREA5
166	AREA6
167	AREA7
168	MPS
169	MBC
170	RG
172	EDM
173	HWTOIN-MON
176	MON-OUT
177	PLS-OUTR
180	USR-OUT0
181	USR-OUT1
192	CRNT-LMTD
193	SPD-LMTD
196	OPE-BSY
197	PAUSE-BSY

Assignment number	Signal name
198	SEQ-BSY
199	DELAY-BSY
200	JUMP0-LAT
201	JUMP1-LAT
202	NEXT-LAT
203	PLS-LOST
204	DCMD-RDY
205	DCMD-FULL
207	M-CHG
208	M-ACT0
209	M-ACT1
210	M-ACT2
211	M-ACT3
212	M-ACT4
213	M-ACT5
214	M-ACT6
215	M-ACT7
216	D-END0
217	D-END1
218	D-END2
219	D-END3
220	D-END4
221	D-END5
222	D-END6

Assignment number	Signal name
223	D-END7
224	INFO-USRIO
225	INFO-POSERR
226	INFO-DRVTMP
227	INFO-MTRTMP
228	INFO-OVOLT
229	INFO-UVOLT
230	INFO-OLTIME
232	INFO-SPD
233	INFO-START
234	INFO-ZHOME
235	INFO-PR-REQ
237	INFO-EGR-E
238	INFO-RND-E
240	INFO-FW-OT
241	INFO-RV-OT
242	INFO-CULD0
243	INFO-CULD1
244	INFO-TRIP
245	INFO-ODO
252	INFO-DSLMTD
253	INFO-IOTEST
254	INFO-CFG
255	INFO-RBT

6 Troubleshooting

This part describes alarm and information functions.

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1 Detection of communication errors

This chapter explains a function to detect that an error occurred in EtherNet/IP.

1-1 Communication timeout

If Implicit communication is interrupted due to disconnection of the EtherNet/IP communication cable or other reasons, the communication timeout is detected.
When the communication timeout is detected, the NS LED on the driver blinks in red.
When connection with the scanner is established again, the communication timeout is automatically cleared, and the NS LED on the driver returns to be lit in green.
If the communication timeout is detected, check the following points.

- Is the EtherNet/IP communication cable disconnected?
- Is the power supply for the scanner is turned on?

1-2 IP address conflict

If an IP address of the EtherNet/IP compatible products is duplicated in the same system, the IP address conflict is detected.
When the IP address conflict is detected, the NS LED on the driver is lit in red.
If the IP address conflict is detected, change the setting so that an IP address of the EtherNet/IP compatible products is not duplicated.
Check the IP address is not duplicated, and then turn on the control power supply again.

2 Alarms

This driver has the alarm function to protect from temperature rise, poor connection, error in operation, and others. If an alarm is generated, the ALM-A output is turned ON and the ALM-B output is turned OFF to stop the motor. At the same time, the PWR/ALM LED blinks in red.
Details of the alarm being generated can be checked by counting the number of times the PWR/ALM LED blinks, or using EtherNet/IP or the **MEXE02**.

2-1 Alarm reset

Before resetting an alarm, always remove the cause of the alarm and ensure safety, and perform one of the reset operations specified next.

- Turn the ALM-RST input ON. (The alarm will be reset at the ON edge of the input.)
- Execute the alarm reset of the maintenance command via EtherNet/IP.
- Execute the alarm reset using the **MEXE02**.
- Turn on the control power supply again.

Note

- Some alarms cannot be reset by other methods than turning on the control power supply again. Check with "2-4 Alarm list" on p.148.
- An alarm of the absolute position error can be reset if the position preset or return-to-home operation is performed. If it cannot be reset by these methods, the ABZO sensor may be damaged.

2-2 Alarm history

Up to 10 generated alarms are saved in the non-volatile memory in order of the latest to oldest. Alarm history stored in the non-volatile memory can be read and cleared if one of the following reset operations is performed.

- Read the alarm history by the monitor command via EtherNet/IP.
- Clear the alarm history by the maintenance command via EtherNet/IP.
- Read and clear the alarm history using the **MEXE02**.

2-3 Generation condition of alarms

Alarms shown in the table will be generated if the generation condition is exceeded.

Alarm code	Alarm name	Motor model	Generation condition	
			AC power input driver	DC power input driver
21h	Main circuit overheat [°C (°F)]	–	85 (185)	85 (185)
22h	Overvoltage (V)	–	430	63
26h	Motor overheat [°C (°F)]	–	85 (185)	85 (185)
31h	Overspeed (r/min)	**AZM14 AZM15 AZM24 AZM26**	–	8,000
		AZM46 AZM48 AZM66	8,000	4,500
		AZM69	8,000	2,500
		AZM98 AZM911	5,000	–
34h	Command pulse error (r/min)	–	38,400	38,400

2-4 Alarm list

Alarm code	Number of times LED blinks	Alarm type	Cause
10h	4	Excessive position deviation	• When the motor was in a state of current ON, the deviation between the command position and feedback position exceeded the value set in the "Excessive position deviation alarm" parameter in the motor shaft. • A load is large, or the acceleration/deceleration time or the acceleration/deceleration rate is too short against the load. • The operating range of positioning push-motion SD operation was exceeded.
20h	5	Overcurrent	The motor, the cable, and the driver output circuit were short-circuited.
21h	2	Main circuit overheat	The internal temperature of the driver reached the upper limit of the specification value.
22h	3	Overvoltage (AC power input driver)	• The main power supply voltage exceeded the permissible value. • A large load inertia was suddenly stopped. • Vertical operation (elevating operation) was performed.
22h	3	Overvoltage (DC power input driver)	• The main power supply voltage exceeded the permissible value. • A large load inertia was suddenly stopped. • Vertical operation (elevating operation) was performed.
23h	3	Main power supply OFF	The main power supply was shut off during operation.
25h	3	Undervoltage	The main power supply was shut off momentarily or the voltage became low.
26h	8	Motor overheat	The detection temperature of the ABZO sensor reached the upper limit of the specification value.
28h	8	Sensor error	An error of the sensor was detected during operation.
2Ah	8	ABZO sensor communication error	An error occurred between the driver and the ABZO sensor.
30h	2	Overload	A load exceeding the maximum torque was applied for the time exceeded the value set in the "Overload alarm" parameter.
31h	2	Overspeed	The feedback speed of the motor output shaft exceeded the specification value.
33h	7	Absolute position error	The home position information of the ABZO sensor was damaged.
34h	2	Command pulse error	The command pulse frequency exceeded the specification value.

Remedial action	How to reset	Motor excitation *
• Decrease the load. • Increase the acceleration/deceleration time or slow the acceleration/deceleration rate. • Increase the operating current. • Reconsider the operation data.	Any of reset operations	Non-excitation
Turn off the main power supply and the control power supply first, and check the motor, the cable, and the driver are not damaged. After that, turn on the main power supply and the control power supply again. If the alarm is still not reset, the motor, the cable, or the driver may be damaged. Contact your nearest Oriental Motor sales office.	Turn on the control power supply again	Non-excitation
Reconsider the ventilation condition.	Any of reset operations	Non-excitation
• Check the input voltage of the main power supply. • Decrease the load. • Increase the acceleration/deceleration time or slow the acceleration/deceleration rate. • Connect our regeneration resistor **RGB100**.	Turn on the control power supply again	Non-excitation
• Check the input voltage of the main power supply. • Decrease the load. • Increase the acceleration/deceleration time or slow the acceleration/deceleration rate.	Any of reset operations	Non-excitation
Check if the main power supply is applied properly.	Any of reset operations	Non-excitation
Check the input voltage of the main power supply.	Any of reset operations	Non-excitation
• Check the heat radiation condition of the motor. • Reconsider the ventilation condition.	Any of reset operations	Non-excitation
Turn off the main power supply and control power supply, and check the connection of the motor. After that, turn on the main power supply and control power supply again.	Turn on the control power supply again	Non-excitation
Turn off the main power supply and control power supply, and check the connection of the ABZO sensor. After that, turn on the main power supply and control power supply again.	Turn on the control power supply again	Non-excitation
• Decrease the load. • Increase the acceleration/deceleration time or slow the acceleration/deceleration rate. • Increase the operating current.	Any of reset operations	Non-excitation
• Reconsider the "Electronic gear" parameter and set the speed of the motor output shaft to a value lower than the specification value. • If an overshoot is occurred at the time of accelerating, increase the acceleration time or slow the acceleration rate.	Any of reset operations	Non-excitation
Perform the position preset or return-to-home operation to set the home position again.	Turn on the control power supply again	Non-excitation
Decrease the frequency of the command pulse.	Any of reset operations	Non-excitation

Alarm code	Number of times LED blinks	Alarm type	Cause
41h	9	EEPROM error	The data stored in the driver was damaged.
42h	8	Sensor error at power-on	An error of the ABZO sensor was detected when the control power supply was turned on.
43h	8	Rotation error at power on	The motor was being rotated when the control power supply was turned on.
44h	8	Encoder EEPROM error	The data stored in the ABZO sensor was damaged.
45h	8	Motor combination error	A motor not allowed to combine with the driver was connected. (⇨ Refer to p.154 for details.)
4Ah	7	Return-to-home incomplete	Absolute positioning operation was started in a state where the position coordinate had not been set.
51h	2	Regeneration resistor overheat (AC power input driver only)	• The regeneration resistor **RGB100** is not connected properly. • The regeneration resistor **RGB100** was overheated extraordinarily.
53h	2	Emergency stop circuit error	• The allowable time from when one of the HWTO input is turned OFF until when the other is turned OFF exceeded the value set in the "HWTO delay time of checking dual system" parameter. • An error of the circuit corresponding to the phenomenon above was detected.
60h	7	±LS both sides active	When the "FW-LS/RV-LS input action" parameter is set to "2: Immediate stop with alarm" or "3: Deceleration stop with alarm," both the FW-LS input and the RV-LS input were detected.
61h	7	Reverse ±LS connection	The LS input opposite to the operating direction was detected while return-to-home operation in 2-sensor mode or 3-sensor mode was performed.
62h	7	Return-to-home operation error	• An unanticipated load was applied while return-to-home operation was performed. • The installation positions of the FW-LS and RV-LS sensors and the HOME sensor are near to each other. • Return-to-home operation was executed in a state where both the FW-LS input and the RV-LS input were detected. • Position preset processing upon completion of return-to-home operation was failed. • In return-to-home operation in one-way rotation mode, the motor passed by the HOME sensor during deceleration stop.
63h	7	No HOMES	The HOMES input was not detected at a position between the FW-LS input and the RV-LS input while return-to-home operation in 3-sensor mode was performed.

Remedial action	How to reset	Motor excitation *
Initialize all parameters.	Turn on the control power supply again	Non-excitation
Turn off the main power supply and control power supply, and check the connection of the ABZO sensor. After that, turn on the main power supply and control power supply again.	Turn on the control power supply again	Non-excitation
Reconsider the load conditions so that the motor output shaft does not rotate by an external force when the control power supply is turned on.	Turn on the control power supply again	Non-excitation
Execute either of the following operations. If the same alarm is still generated, the ABZO sensor has been damaged. Contact your nearest Oriental Motor sales office. • Set phase Z again with the "ZSG-PRESET" of the maintenance command. • Execute the "Clear tripmeter" of the maintenance command.	Turn on the control power supply again	Non-excitation
Check the motor model name and the driver model name, and connect them in the correct combination.	Turn on the control power supply again	Non-excitation
Execute the position preset or return-to-home operation.	Any of reset operations	Excitation
• If the regeneration resistor **RGB100** is not used, short the TH1 and TH2 terminals of the CN1. • Connect the regeneration resistor **RGB100** properly. • The allowable regenerative power of the regeneration resistor **RGB100** is exceeded. Reconsider the load and operating conditions.	Turn on the control power supply again	Non-excitation
• Increase the value set in the "HWTO delay time of checking dual system" parameter. • Check the wiring of the HWTO input.	Turn on the control power supply again	Non-excitation
Check the sensor logic installed and the "Inverting mode" parameter.	Any of reset operations	Excitation
Check the wiring of the sensor.	Any of reset operations	Excitation
• Check the load. • Reconsider the sensor installation positions and the starting direction of motor operation. • Check the sensor logic installed and the "Inverting mode" parameter. • See that a load exceeding the maximum torque is not applied upon completion of return-to-home operation. • Reconsider the specification of the HOME sensor and the "(HOME) Acceleration/deceleration" parameter.	Any of reset operations	Excitation
Install the HOME sensor at a position between the FW-LS and RV-LS sensors.	Any of reset operations	Excitation

Alarm code	Number of times LED blinks	Alarm type	Cause
64h	7	TIM, Z, SLIT signal error	None of the TIM output, the ZSG output, or the SLIT input could be detected during return-to-home operation.
66h	7	Hardware overtravel	When the "FW-LS/RV-LS input action" parameter is set to "2: Immediate stop with alarm" or "3: Deceleration stop with alarm," the FW-LS input or the RV-LS input was detected.
67h	7	Software overtravel	When the "Software overtravel" parameter is set to "2: Immediate stop with alarm" or "3: Deceleration stop with alarm," the motor position reached the set value of the software limit.
68h	1	Emergency stop	When the "HWTO mode selection" parameter is set to "1: Alarm-shutdown," both the HWTO1 input and the HWTO2 input were turned OFF.
6Ah	7	Return-to-home operation offset error	When offset movement as part of return-to-home operation is performed, the FW-LS input or the RV-LS input was detected.
6Dh	7	Mechanical overtravel	The product having set the home position reached the mechanism limit stored in the ABZO sensor.
70h	7	Operation data error	• Stored data operation was performed with data whose operating speed was 0. • Operation was performed at the operating speed or operating current exceeding the value set in the "Mechanism protection parameter." • Wrap operation was executed when wrap setting was disabled. • Push-motion operation or push-motion return-to-home operation was performed with the **DG**II Series.
71h	7	Electronic gear setting error	The resolution set in the "Electronic gear" parameter was out of the specification.
72h	7	Wrap setting error	The control power supply was turned on with the value set in the "Wrap setting" parameter that is inconsistent with the resolution set in the "Electronic gear" parameter.
81h	7	Network bus error	Implicit communication of Exclusive Owner connection was disconnected during operation.
82h	7	Network module error	An error was detected in the network module.
F0h	Lit	CPU error	CPU malfunctioned.

* The motor excitation when an alarm is generated is as follows.
Non-excitation: If an alarm is generated, the motor current is cut off and the motor holding force is lost.
In the case of the electromagnetic brake motor, the electromagnetic brake automatically holds the position.
Excitation: Even if an alarm is generated, the motor current is not cut off and the motor position is held.

Remedial action	How to reset	Motor excitation *
• Reconsider the connection status of the load and the position of the HOME sensor so that these signals should be ON while the HOMES input is ON. • When a signal is not used, set the "(HOME) TIM/ZSG signal detection" parameter or the "(HOME) SLIT detection" parameter to "0: Disable."	Any of reset operations	Excitation
Reset the alarm and then escape from the sensor by operating the motor or manually.	Any of reset operations	Excitation
• Reconsider the operation data. • Reset the alarm and then escape from the sensor by operating the motor or manually.	Any of reset operations	Excitation
Release the emergency stop state.	Any of reset operations	Non-excitation
Check the offset value.	Any of reset operations	Excitation
• Check the travel amount (position). • Reset the alarm and then escape from the sensor by operating the motor or manually.	Any of reset operations	Excitation
• Check the operation data. • Check the value set in the "Mechanism protection parameter" using the unit information monitor of the **MEXE02**. • Check the wrap setting. • Push-motion operation as well as push-motion return-to-home operation cannot be performed with the **DG**II Series.	Any of reset operations	Excitation
Reconsider the "Electronic gear" parameter, and set so that the resolution should be in the range of the specification.	Turn on the control power supply again	Non-excitation
Set the wrap setting properly, and turn on the control power supply again.	Turn on the control power supply again	Non-excitation
Check the connection with the scanner and the condition of the power supply of the scanner.	Any of reset operations	Excitation
Turn on the control power supply again.	Turn on the control power supply again	Non-excitation
Turn on the control power supply again.	–	–

Related parameters

Parameter ID		Parameter name	Description	Initial value
Dec	Hex			
384	0180h	Overload alarm	Sets the condition in which the overload alarm is generated. **Setting range** 1 to 300 (1=0.1 s)	50
385	0181h	Excessive position deviation alarm	Sets the condition in which the excessive position deviation alarm is generated. **Setting range** 1 to 30,000 (1=0.01 rev)	300
24968	6188h	Network bus error alarm	Sets the function of the network bus error alarm. **Setting range** 0: Network bus error alarm is disabled 1: Network bus error alarm is enabled	1

■ About causes of the motor combination error (alarm code 45h)

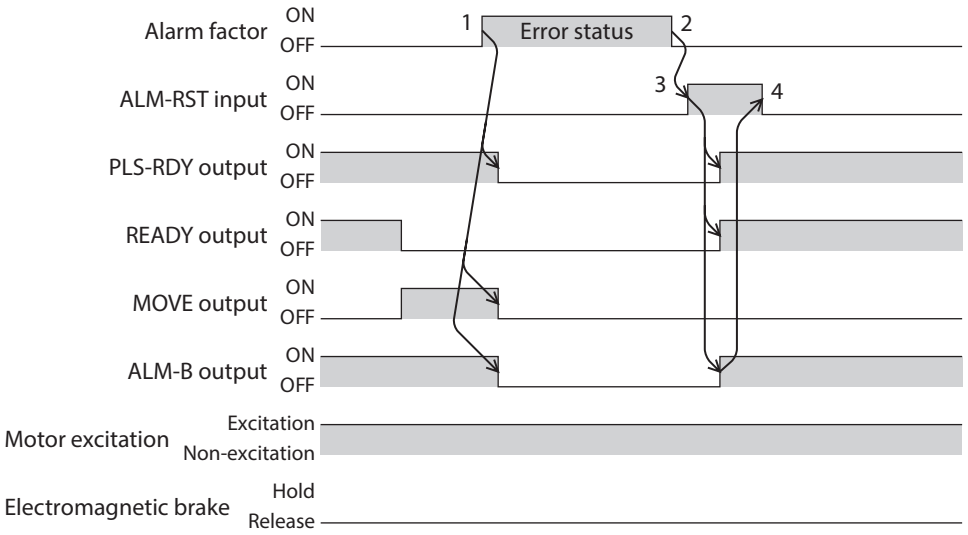
An alarm of the motor combination error is generated in the following conditions.

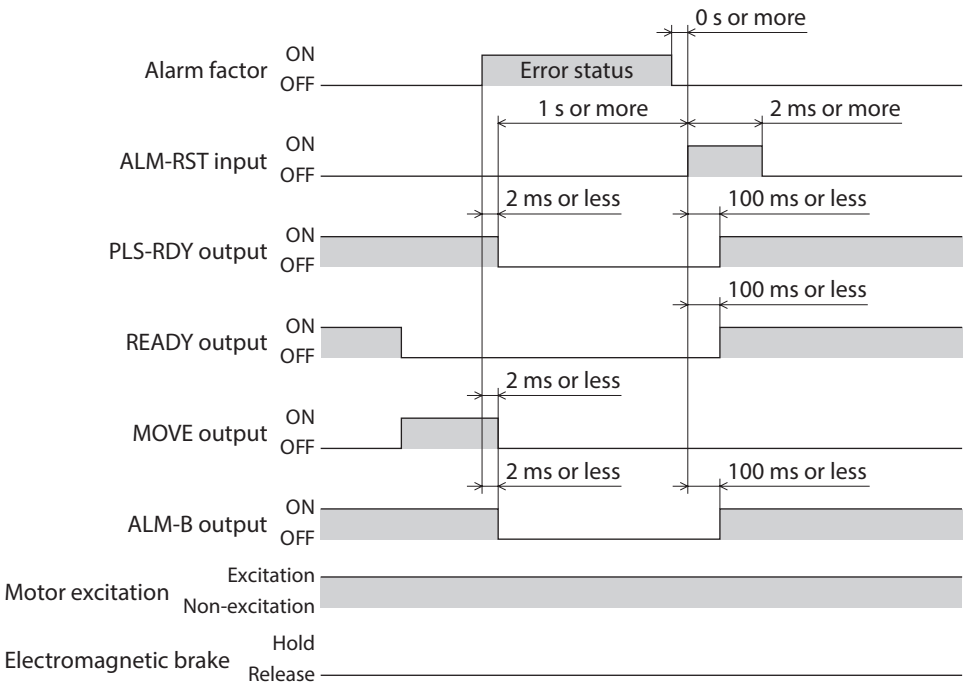
- When the motor for a DC power supply was connected to the AC power input driver.
- When the motor for an AC power supply was connected to the DC power input driver.
- When the motor of frame size 20 mm (0.79 in.) or 28 mm (1.10 in.) was connected to the DC power input driver and 48 VDC was applied.

2-5 Timing chart

■ When the motor remains in an excitation state even if an alarm is generated

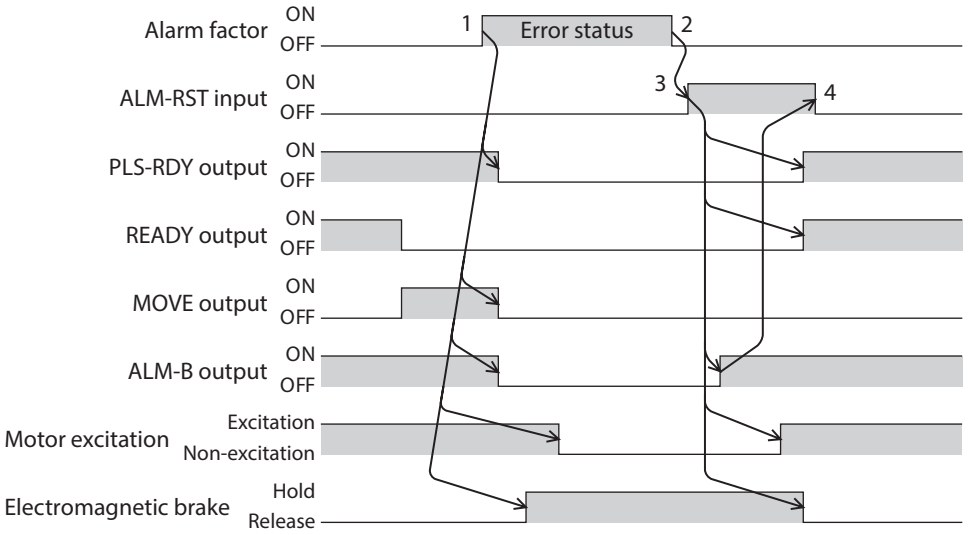
1. If an error occurs, the ALM-B output, the MOVE output, and the PLS-RDY output are turned OFF. At the same time, the motor stops immediately.
2. When resetting the alarm, stop the pulse input. If the alarm is reset in a state of inputting pulses, the motor may start suddenly, causing injury or damage to equipment.
3. Remove the cause of the alarm and then turn the ALM-RST input ON. The alarm is reset, and the ALM-B output, the READY output, and the PLS-RDY output are turned ON.
4. Check the ALM-B output has been turned ON and then turn the ALM-RST input OFF.

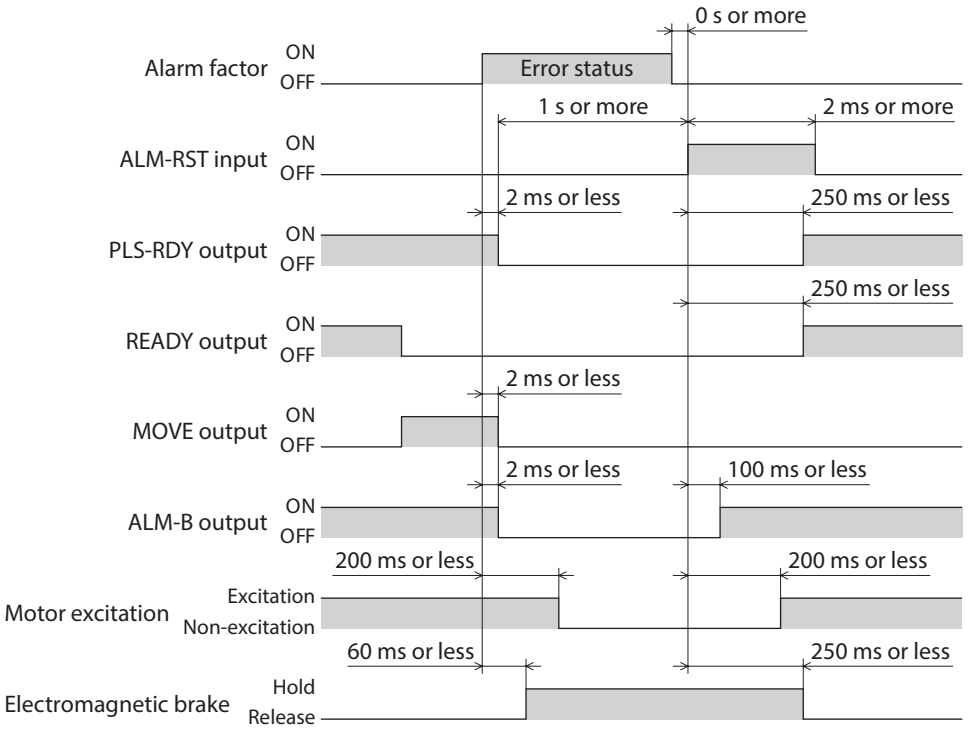




■ When the motor puts into a non-excitation state if an alarm is generated

1. If an error occurs, the ALM-B output, the MOVE output, and the PLS-RDY output are turned OFF.
   At the same time, the motor stops immediately.
2. When resetting the alarm, stop the pulse input. If the alarm is reset in a state of inputting pulses, the motor may start suddenly, causing injury or damage to equipment.
3. Remove the cause of the alarm and then turn the ALM-RST input ON.
   The alarm is reset, and the ALM-B output, the READY output, and the PLS-RDY output are turned ON.
4. Check the ALM-B output has been turned ON and then turn the ALM-RST input OFF.





3 Informations

The driver is equipped with a function to generate information output before an alarm is generated.
This function can be utilized for periodic maintenance of equipment by setting a suitable value in the parameter of each information.
For example, utilizing the "Motor temperature information" parameter can prevent equipment malfunction or production stoppage due to motor overheat. In addition, the "Tripmeter information" parameter can be utilized as a reference to do maintenances every time a certain travel distance is reached.

■ Status when information is generated

- **Information bit output**

  If information is generated, a bit output (INFO-∗∗ output) of the corresponding information is turned ON.
  A desired output signal can be assigned to the INFO-USRIO output among bit outputs and used. If the assigned output signal is turned ON, the INFO-USRIO output is also turned ON. (Details of bit output ⇨p.160)

- **INFO output**

  If information is generated, the INFO output is turned ON.

- **LED indicator**

  If information is generated, the PWR/ALM LED will simultaneously blink in red and green twice. (Red and green colors may overlap and it may be visible to orange.)

- **Motor operation**

  The motor continues to operate during information unlike in the case of an alarm.

- **Parameter**

  Each information has a corresponding "INFO action" parameter. If the parameter is set to "0: No Info reflect (Only the bit output is ON.)," only the bit output of information is turned ON, and the INFO output and LED are not changed.

Related parameters

Parameter ID		Parameter name	Description	Initial value
Dec	Hex			
416	01A0h	Driver temperature information (INFO-DRVTMP)	Sets the generation condition of the driver temperature information (INFO-DRVTMP). **Setting range** 40 to 85 °C	85
417	01A1h	Overload time information (INFO-OLTIME)	Sets the generation condition of the overload time information (INFO-OLTIME). **Setting range** 1 to 300 (1=0.1 s)	50
418	01A2h	Overspeed information (INFO-SPD)	Sets the generation condition of the speed information (INFO-SPD). **Setting range** 0: Disable 1 to 12,000 r/min	0
421	01A5h	Position deviation information (INFO-POSERR)	Sets the generation condition of the position deviation information (INFO-POSERR). **Setting range** 1 to 30,000 (1=0.01 rev)	300
424	01A8h	Motor temperature information (INFO-MTRTMP)	Sets the generation condition of the motor temperature information (INFO-MTRTMP). **Setting range** 40 to 120 °C	85

Parameter ID		Parameter name	Description	Initial value
Dec	Hex			
425	01A9h	Overvoltage information (INFO-OVOLT) [AC power input driver]	Sets the generation condition of the overvoltage information (INFO-OVOLT). [AC power input driver only] **Setting range** 120 to 450 V	435
426	01AAh	Undervoltage information (INFO-UVOLT) [AC power input driver]	Sets the generation condition of the undervoltage information (INFO-UVOLT). [AC power input driver only] **Setting range** 120 to 280 V	120
427	01ABh	Overvoltage information (INFO-OVOLT) [DC power input driver]	Sets the generation condition of the overvoltage information (INFO-OVOLT). [DC power input driver only] **Setting range** 150 to 630 (1=0.1 V)	630
428	01ACh	Undervoltage information (INFO-UVOLT) [DC power input driver]	Sets the generation condition of the undervoltage information (INFO-UVOLT). [DC power input driver only] **Setting range** 150 to 630 (1=0.1 V)	180
431	01AFh	Tripmeter information (INFO-TRIP)	Sets the generation condition of the tripmeter information (INFO-TRIP). **Setting range** 0: Disable 1 to 2,147,483,647 (1=0.1 kRev)	0
432	01B0h	Odometer information (INFO-ODO)	Sets the generation condition of the odometer information (INFO-ODO). **Setting range** 0: Disable 1 to 2,147,483,647 (1=0.1 kRev)	0
433	01B1h	Cumulative load 0 information (INFO-CULD0)	Sets the generation condition of the cumulative load 0 information (INFO-CULD0). **Setting range** 0 to 2,147,483,647	0
434	01B2h	Cumulative load 1 information (INFO-CULD1)	Sets the generation condition of the cumulative load 1 information (INFO-CULD1). **Setting range** 0 to 2,147,483,647	0
435	01B3h	Cumulative load value auto clear	Clears the cumulative load when operation is started (ON edge of the MOVE output). **Setting range** 0: Disable 1: Enable	1
436	01B4h	Cumulative load value count divisor	Sets the divisor of the cumulative load. **Setting range** 1 to 32,767	1
444	01BCh	INFO-USRIO output selection	Selects the output signal to be checked in the INFO-USRIO output. **Setting range** Output signal⇨p.142	128: CONST-OFF
445	01BDh	INFO-USRIO output inversion	Sets the output logic of the INFO-USRIO output. **Setting range** 0: Not invert 1: Invert	0

Parameter ID		Parameter name	Description	Initial value
Dec	Hex			
446	01BEh	Information LED condition	Sets the LED status when information is generated. **Setting range** 0: Disable 1: Enable	1
447	01BFh	Information auto clear	When the cause of information is eliminated, the INFO output and the bit output of the corresponding information are turned OFF automatically. **Setting range** 0: Disable 1: Enable	1
1952	07A0h	INFO action (Assigned I/O status information (INFO-USRIO))	Sets the bit output, the INFO output, and the LED status when information is generated. **Setting range** 0: No Info reflect (Only the bit output is ON.) 1: Info reflect (The bit output and the INFO output are ON and the LED blinks.)	1
1953	07A1h	INFO action (Position deviation information (INFO-POSERR))		
1954	07A2h	INFO action (Driver temperature information (INFO-DRVTMP))		
1955	07A3h	INFO action (Motor temperature information (INFO-MTRTMP))		
1956	07A4h	INFO action (Overvoltage information (INFO-OVOLT))		
1957	07A5h	INFO action (Undervoltage information (INFO-UVOLT))		
1958	07A6h	INFO action (Overload time information (INFO-OLTIME))		
1960	07A8h	INFO action (Speed information (INFO-SPD))		
1961	07A9h	INFO action (Start operation error information (INFO-START))		
1962	07AAh	INFO action (Start ZHOME error information (INFO-ZHOME))		
1963	07ABh	INFO action (PRESET request information (INFO-PR-REQ))		
1965	07ADh	INFO action (Electronic gear setting error information (INFO-EGR-E))		
1966	07AEh	INFO action (Wrap setting error information (INFO-RND-E))		
1968	07B0h	INFO action (Forward operation prohibition information (INFO-FW-OT))		
1969	07B1h	INFO action (Reverse operation prohibition information (INFO-RV-OT))		
1970	07B2h	INFO action (Cumulative load 0 information (INFO-CULD0))		
1971	07B3h	INFO action (Cumulative load 1 information (INFO-CULD1))		
1972	07B4h	INFO action (Tripmeter information (INFO-TRIP))		
1973	07B5h	INFO action (Odometer information (INFO-ODO))		
1980	07BCh	INFO action (Start operation restricted mode information (INFO-DSLMTD))		

Parameter ID		Parameter name	Description	Initial value
Dec	Hex			
1981	07BDh	INFO action (I/O test mode information (INFO-IOTEST))	Sets the bit output, the INFO output, and the LED status when information is generated. **Setting range** 0: No Info reflect (Only the bit output is ON.) 1: Info reflect (The bit output and the INFO output are ON and the LED blinks.)	1
1982	07BEh	INFO action (Configuration request information (INFO-CFG))		
1983	07BFh	INFO action (Reboot request information (INFO-RBT))		

3-1 Information history

Up to 16 generated information items are saved in the RAM in order of the latest to oldest. Information items stored as the information history are the information code, generation time, and contents of information.
The information history can be read and cleared when one of the following items is performed.

- Read the information history by the monitor command via EtherNet/IP.
- Clear the information history by the maintenance command via EtherNet/IP.
- Read and clear the information history using the **MEXE02**.

Note Information history is saved in the RAM, so they are cleared when the control power supply of the driver is turned OFF.

3-2 Information list

Information item	Information bit output signal	Cause	Reset condition
Assigned I/O status	INFO-USRIO	The I/O signal set in the "INFO-USRIO output selection" parameter was turned ON.	The I/O signal set in the "INFO-USRIO output selection" parameter was turned OFF.
Position deviation	INFO-POSERR	The deviation between the command position and the feedback position exceeded the value set in the "Position deviation information" parameter in the motor output shaft.	The deviation between the command position and the feedback position fell below the value set in the "Position deviation information" parameter in the motor output shaft.
Driver temperature	INFO-DRVTMP	The internal temperature of the driver exceeded the value set in the "Driver temperature information" parameter.	The internal temperature of the driver fell below the setting value of the "Driver temperature information" parameter.
Motor temperature	INFO-MTRTMP	The detection temperature of the encoder exceeded the value set in the "Motor temperature information" parameter.	The detection temperature of the encoder fell below the value set in the "Motor temperature information" parameter.
Overvoltage	INFO-OVOLT	• The voltage of the main power supply exceeded the value set in the "Overvoltage information" parameter. • A large load inertia was suddenly stopped. • Vertical operation (elevating operation) was performed.	The voltage of the main power supply fell below the value set in the "Overvoltage information" parameter.
Undervoltage	INFO-UVOLT	• The voltage of the main power supply fell below the value set in the "Undervoltage information" parameter. • The main power supply was shut off momentarily or a voltage shortage was generated.	The voltage of the main power supply exceeded the value set in the "Undervoltage information" parameter.

Information item	Information bit output signal	Cause	Reset condition
Overload time	INFO-OLTIME	A load exceeding the maximum torque was applied for a time period exceeding the value set in the "Overload time information" parameter.	The overload counter fell below the value set in the "Overload time information" parameter.
Speed	INFO-SPD	The feedback speed of the motor exceeded the value set in the “Overspeed information” parameter.	The feedback speed of the motor fell below the value set in the "Overspeed information" parameter.
Start operation error	INFO-START	• The operation start signal in the direction having been stopped by the FW-BLK input or RV-BLK input was turned ON. • The operation start signal in the direction having been stopped by the FW-LS input or RV-LS input was turned ON. • The operation start signal in the direction having been stopped by the software limit was turned ON. • When operation could not be executed (e.g., the READY output was OFF), the operation start signal was turned ON.	Operation was started normally.
Start ZHOME error	INFO-ZHOME	• When the position coordinate was not set (the ABSPEN output was OFF), the ZHOME input was turned ON. • When the motor was used with the electrical home position coordinate system (the EL-PRST input was ON), return-to-home operation was performed.	Operation was started normally.
Preset request	INFO-PR-REQ	Preset was executed by the position preset or return-to-home operation.	Preset was complete.
Electronic gear setting error	INFO-EGR-E	The resolution set in the “Electronic gear” parameter was out of the specification.	The resolution was set in the range of the specification.
Wrap setting error	INFO-RND-E	The resolution and the “Initial coordinate generation & wrap setting range” parameter were inconsistent.	The “Initial coordinate generation & wrap setting range” parameter was set in the range of the specification.
Forward operation prohibition	INFO-FW-OT	• The positive software limit was exceeded. • Either the FW-LS input or the FW-BLK input was turned ON.	The position coordinate of the motor was in the range of the positive software limit, and in addition, both the FW-LS input and the FW-BLK input were turned OFF.
Reverse operation prohibition	INFO-RV-OT	• The negative software limit was exceeded. • Either the RV-LS input or the RV-BLK input was turned ON.	The position coordinate of the motor was in the range of the negative software limit, and in addition, both the RV-LS input and the RV-BLK input were turned OFF.
Cumulative load 0	INFO-CULD0	The cumulative load exceeded the value set in the "Cumulative load 0 information” parameter.	The cumulative load fell below the value set in the "Cumulative load 0 information” parameter.
Cumulative load 1	INFO-CULD1	The cumulative load exceeded the value set in the "Cumulative load 1 information” parameter.	The cumulative load fell below the value set in the "Cumulative load 1 information” parameter.

Information item	Information bit output signal	Cause	Reset condition
Tripmeter	INFO-TRIP	The travel distance of the motor exceeded the value set in the "Tripmeter information" parameter.	After one of the following operation was performed, the travel distance (Tripmeter) of the motor fell below the value set in the "Tripmeter information" parameter. • The "Tripmeter information" parameter was set again. • The "Clear tripmeter" of the maintenance command was executed.
Odometer	INFO-ODO	The cumulative travel distance of the motor exceeded the value set in the "Odometer information" parameter.	After the following operation was performed, the cumulative travel distance (Odometer) of the motor fell below the value set in the "Odometer information" parameter. • The "Odometer information" parameter was set again.
Start operation restricted mode	INFO-DSLMTD	• "Teaching, remote operation" was executed using the **MEXE02**. • Configuration was executed. • Data was written to the driver from the **MEXE02**. • "Restored to the factory setting" was executed with the **MEXE02**.	• Teaching, remote operation was canceled. • Configuration was complete. • Writing data was complete. • Data was restored to the factory setting.
I/O test mode	INFO-IOTEST	• "I/O test" was executed with the **MEXE02**. • Configuration was executed.	• The I/O test mode was canceled. • Configuration was complete.
Configuration request	INFO-CFG	The parameter that required executing the configuration was changed.	Configuration was executed.
Reboot request	INFO-RBT	The parameter that required rebooting was changed.	Reboot was executed.

memo If the "Preset request" information was generated for 100 ms or more in a state where the "Information auto clear" parameter was set to disable, the preset may have been failed. There are the following two possible reasons that the preset was failed.
· The ABZO sensor is not connected to the driver.
· The preset was executed in a state where the position deviation between the command position and the feedback position was 1.8° or more.

4 Troubleshooting and remedial actions

In motor operation, the motor or driver may not function properly due to an improper setting or wrong connection. When the motor cannot be operated properly, refer to the contents provided in this chapter and take an appropriate remedial action.
If the problem persists, contact your nearest Oriental Motor sales office.

This chapter describes problems that may occur in operation other than the initial settings. Refer to the OPERATING MANUAL AZ Function Edition for these contents.

Phenomenon	Possible cause	Remedial action
• The motor is not excited. • The motor output shaft can be moved by hand.	Connection error of the motor cable.	Check the motor connection.
	The FREE input is being ON.	Turn the FREE input OFF.
The motor has a holding torque even if it is put into a non-excitation state.	Effect of dynamic brake.	If the motor is put into a non-excitation state using the C-ON input or the STOP-COFF input, the motor windings is in a state of being short-circuited in the driver, and the holding torque larger than when the power is shut off is generated (dynamic brake). To release the dynamic brake, shut off the power or turn the FREE input ON.
The motor does not operate.	When an electromagnetic brake motor is used, the electromagnetic brake is in a holding state.	Check the connection of the electromagnetic brake.
	The STOP input is being ON.	Turn the STOP input OFF.
	The position (travel amount) is not set in the operation data when positioning operation is performed.	Check the operation data.
	Both the FW-JOG input and the RV-JOG input are turned ON simultaneously when JOG operation is performed.	Turn both the FW-JOG input and the RV-JOG input OFF and then turn either one of them ON.
The motor rotates in the direction opposite to the specified direction.	The "Motor rotation direction" parameter is set wrongly.	Check the setting of the "Motor rotation direction" parameter.
The gearhead output shaft rotates in the direction opposite to the motor.	The geared motor that rotates in the direction opposite to the motor shaft is used.	• With **TS** geared type, the gear output shaft rotates in the direction opposite to the motor when the gear ratio is 20 or 30. • With Harmonic geared type, the gear output shaft always rotates in the direction opposite to the motor.
Motor operation is unstable.	Connection error in the motor cable or the power supply cable.	Check the connections between the driver, the motor, and the power supply.
	The setting of the base current rate is too low.	Check the setting of the "Base current" parameter.
Motor vibration is too large.	Load is too small.	Lower the current with the "Base current" parameter. If the motor output torque is too large relative to the load, vibration will increase.
The electromagnetic brake is not released.	The power is not supplied to the electromagnetic brake.	Check the connection of the electromagnetic brake.

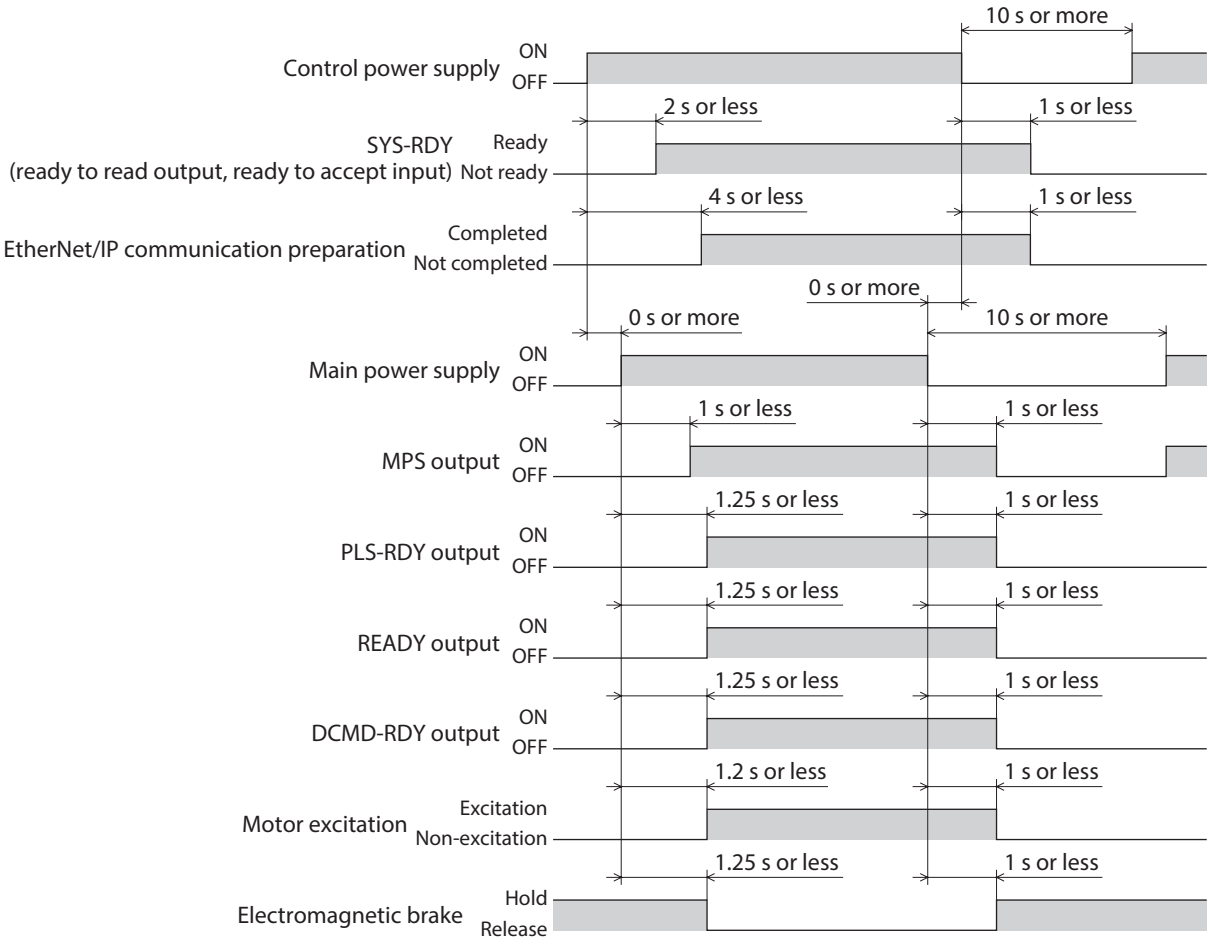
memo Check the alarm message using EtherNet/IP or the **MEXE02** when the alarm is being generated.

7 Reference materials

◆Table of contents

1 Timing chart

■ Power ON



memo There are two types of timings when an output signal is turned ON.
· A signal is turned ON by only turning on the control power supply.
· A signal is turned ON by turning on the control power supply and the main power supply.

2 Specifications

2-1 General specifications

■ AC power input driver

Degree of protection		IP10
Operating environment	Ambient temperature	0 to +55 °C (+32 to +131 °F) * (non-freezing)
	Humidity	85 % or less (non-condensing)
	Altitude	Up to 1,000 m (3,300 ft.) above sea level
	Surrounding atmosphere	No corrosive gas, dust, water, or oil.
Storage environment Shipping environment	Ambient temperature	−25 to +70 °C (−13 to +158 °F) (non-freezing)
	Humidity	85 % or less (non-condensing)
	Altitude	Up to 3,000 m (10,000 ft.) above sea level
	Surrounding atmosphere	No corrosive gas, dust, water, or oil.
Insulation resistance		100 MΩ or more when 500 VDC megger is applied between the following places: · Protective Earth Terminal - Main power supply input terminal · Encoder connector - Main power supply input terminal · I/O signal connector - Main power supply input terminal
Dielectric strength		Sufficient to withstand the specified voltage applied between the following places for 1 minute: · Protective Earth Terminal - Main power supply input terminal 1.5 kVAC 50/60 Hz · Encoder connector - Main power supply input terminal 1.8 kVAC 50/60 Hz · I/O signal connector - Main power supply input terminal 1.8 kVAC 50/60 Hz

* When installing a driver on a heat sink [material: aluminum, 200×200×2 mm (7.87×7.87×0.08 in.) equivalent].

■ DC power input driver

Degree of protection		IP10
Operating environment	Ambient temperature	0 to +50 °C (+32 to +122 °F) (non-freezing)
	Humidity	85 % or less (non-condensing)
	Altitude	Up to 1,000 m (3,300 ft.) above sea level
	Surrounding atmosphere	No corrosive gas, dust, water, or oil.
Storage environment Shipping environment	Ambient temperature	−25 to +70 °C (−13 to +158 °F) (non-freezing)
	Humidity	85 % or less (non-condensing)
	Altitude	Up to 3,000 m (10,000 ft.) above sea level
	Surrounding atmosphere	No corrosive gas, dust, water, or oil.
Insulation resistance		100 MΩ or more when 500 VDC megger is applied between the following places: · Protective Earth Terminal - Power supply input terminal *

* The main power supply input terminals and the control power supply input terminals are not electrically insulated. Check using either of terminals.

2-2 Product specifications

■ AC power input driver

Driver model		AZD-AEP	AZD-CEP
Main power supply	Input voltage	Single-phase 100-120 VAC −15 to +6 % 50/60 Hz	• Single-phase 200-240 VAC −15 to +6 % 50/60 Hz • Three-phase 200-240 VAC −15 to +6 % 50/60 Hz
	Input current	2.7 to 6.4 A *1	Single-phase: 1.6 to 3.9 A *1 Three-phase: 1.0 to 2.3 A *1
Control power supply	Input voltage	24 VDC±5 % *2	
	Input current	0.25 A (0.5 A) *3	
Interface	Pulse input	• Number of input points: 2, photocoupler • Maximum input pulse frequency Line driver output of scanner: 1 MHz (duty cycle 50 %) Open-collector output of scanner: 250 kHz (duty cycle 50 %)	
	Control input	Number of input points: 6, photocoupler	
	Pulse output	Number of output points: 2, line driver	
	Control output	Number of output points: 6, photocoupler/open collector	
	Power removal signal input	Number of input points: 2, photocoupler	
	Power removal monitor output	Number of output point: 1, photocoupler/open collector	
	Field network	EtherNet/IP	

*1 The input current varies depending on the motor combined. Check with p.29
*2 When an electromagnetic brake motor is used, if the wiring distance between the motor and driver is extended to 20 m (65.6 ft.) using our cable, the input voltage is 24 VDC±4 %.
*3 The value in parentheses ( ) is the one when the electromagnetic brake motor is connected. The **AZM46** type is 0.33 A.

■ DC power input driver

Driver model		AZD-KEP
Main power supply	Input voltage	• 24 VDC±5 % • 48 VDC±5 %
	Input current	0.4 to 3.3 A *1
Control power supply	Input voltage	24 VDC±5 % *2
	Input current	0.15 A (0.4 A) *3
Interface	Pulse input	• Number of input points: 2, photocoupler • Maximum input pulse frequency Line driver output of scanner: 1 MHz (duty cycle 50 %) Open-collector output of scanner: 250 kHz (duty cycle 50 %)
	Control input	Number of input points: 6, photocoupler
	Pulse output	Number of output points: 2, line driver
	Control output	Number of output points: 6, photocoupler/open collector
	Power removal signal input	Number of input points: 2, photocoupler
	Power removal monitor output	Number of output point: 1, photocoupler/open collector
	Field network	EtherNet/IP

*1 The input current varies depending on the motor combined. Check with p.60.
*2 When an electromagnetic brake motor is used, if the wiring distance between the motor and driver is extended to 20 m (65.6 ft.) using our cable, the input voltage is 24 VDC±4 %.
*3 The value in parentheses ( ) is the one when the electromagnetic brake motor is connected. The **AZM46** type is 0.23 A.

3 Regulations and standards

3-1 UL Standards (AC power input driver only)

Check the "APPENDIX UL Standards for **AZ** Series AC power input type" for recognition information about UL Standards.

3-2 EU Directives

■ CE Marking (AC power input driver)

This product is affixed the CE Marking under the Low Voltage Directive and EMC Directive.

- **Low Voltage Directive**

Applicable standards	EN 61800-5-1
Installation conditions (EN Standards)	To be incorporated in equipment. Overvoltage category: II Pollution degree: 2 Degree of protection: IP10 Protection against electric shock: Class I equipment

- This product cannot be used in IT power distribution systems.
- Install the product inside an enclosure in order to avoid contact with hands.
- Be sure to maintain a protective ground in case hands should make contact with the product. When installing the motor and driver, securely connect their Protective Earth Terminals.
- To protect against electric shock using an earth leakage breaker (RCD), connect a type B earth leakage breaker to the power supply side of the driver.
- Use a molded case circuit breaker (MCCB) that conforms to EN standards or IEC Standards.
- Isolate the motor cable, the power supply cable and other drive cables from the signal cables by means of double insulation.
- The temperature of the driver's heat sink may exceed 90 °C (194 °F) depending on the driving condition. Observe the followings.
  · Do not touch the driver while operating.
  · Do not use the driver near combustibles.
  · Be sure to perform a test operation and check the driver temperature.

- **EMC Directive**

This product is conducted EMC testing under the conditions specified in "Example of installation and wiring" on p.37. The conformance of your mechanical equipment with the EMC Directive will vary depending on such factors as the configuration, wiring, and layout for other control system devices and electrical parts used with this product. It therefore must be verified through conducting EMC measures in a state where all parts including this product have been installed in the equipment.

Applicable Standards

EMI	EN 55011 Group1 Class A EN 61000-6-4 EN 61800-3
EMS	EN 61000-6-2 EN 61800-3

⚠CAUTION This equipment is not intended for use in residential environments nor for use on a low-voltage public network supplied in residential premises, and it may not provide adequate protection to radio reception interference in such environments.

■ CE Marking (DC power input driver)

This product is affixed the CE Marking under the EMC Directive.

- **Low Voltage Directive**

The input power supply voltage of this product is 24 VDC/48 VDC. Therefore this product is not subject to the Low Voltage Directive, but install and connect it as follows.

- This product is designed and manufactured to be incorporated in an equipment. Be sure to install the product inside an enclosure.
- For the driver power supply, use a DC power supply with reinforced insulation on its primary and secondary sides.

- **EMC Directive**

This product is conducted EMC testing under the conditions specified in "Example of installation and wiring" on p.68. The conformance of your mechanical equipment with the EMC Directive will vary depending on such factors as the configuration, wiring, and layout for other control system devices and electrical parts used with this product. It therefore must be verified through conducting EMC measures in a state where all parts including this product have been installed in the equipment.

Applicable Standards

EMI	EN 55011 Group1 Class A EN 61000-6-4
EMS	EN 61000-6-2

⚠CAUTION This equipment is not intended for use in residential environments nor for use on a low-voltage public network supplied in residential premises, and it may not provide adequate protection to radio reception interference in such environments.

3-3 Republic of Korea, Radio Waves Act (AC power input driver only)

This product is affixed the KC Mark under the Republic of Korea, Radio Waves Act.

3-4 RoHS Directive

The products do not contain the substances exceeding the restriction values of RoHS Directive (2011/65/EU).

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ORIENTAL MOTOR U.S.A. CORP.
Technical Support Tel:(800)468-3982
8:30 A.M. to 5:00 P.M., P.S.T. (M-F)
7:30 A.M. to 5:00 P.M., C.S.T. (M-F)
www.orientalmotor.com

ORIENTAL MOTOR DO BRASIL LTDA.
Tel:+55-11-3266-6018
www.orientalmotor.com.br

ORIENTAL MOTOR (EUROPA) GmbH
Schiessstraße 44, 40549 Düsseldorf, Germany
Technical Support Tel:00 800/22 55 66 22
www.orientalmotor.de

ORIENTAL MOTOR (UK) LTD.
Tel:01256-347090
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Tel:01 47 86 97 50
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Tel:1800-888-881
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ORIENTAL MOTOR (INDIA) PVT. LTD.
Tel:+91-80-41125586
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Tel:0800-060708
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SHANGHAI ORIENTAL MOTOR CO., LTD.
Tel:400-820-6516
www.orientalmotor.com.cn

INA ORIENTAL MOTOR CO., LTD.
Korea
Tel:080-777-2042
www.inaom.co.kr

ORIENTAL MOTOR CO., LTD.
Hong Kong Branch
Tel:+852-2427-9800

ORIENTAL MOTOR CO., LTD.
4-8-1 Higashiueno, Taito-ku, Tokyo
110-8536 Japan
Tel:03-6744-0361
www.orientalmotor.co.jp