# PREFACE

Thank you for choosing the VFD-S General Purpose Series Variable Frequency Drives. This manual will provide you with the detailed steps and precautions regarding installation, wiring, setting of functional parameters, routine maintenance, malfunction diagnosis and solution etc.

The VFD-S series of drives focuses on providing you with the best levels of scalar control of asynchronous AC motors. Through the adoption of the most advanced PWM technologies driven through one of the most powerful DSP control systems, this drive is armed with optimized functions and flexibility to drive a myriad of applications with stable performances as per your requirements.

To utilize the drive to its full function and ensure the safety of both users and the product, please read this manual carefully before using the drive. Any incorrect operations may lead to fault, malfunction or shortened lifetime, even damage to the device or the people around it.

This manual is available on our website and is accessible through the QR code provided on the unit We request you to keep it safety considering its importance in commissioning, inspection, and maintaining the product. In the pursuit of constant improvement, kindly note, that this manual is subject to modification without any notice.

## CONTENTS

**1. Safety precautions** 6
1.1 Warning 6
1.2 Safety guidelines 6
1.3 Delivery and Installation 6
**2. Installation** 7
2.1 Installation environment 7
2.2 Installation instructions and space limit 7
**3. Wiring** 8
3-1 Connection methods for assorted devices 8
3-2 Standard wiring diagram 9
3-3 Description of terminals 10
3-3-1 Connection of input power terminals 10
3-3-2 Connection of output power terminals 10
3-3-3 Braking resistors and Braking unit 11
3-3-4 Earth terminal PE 11
3-4 Explanation of control loop terminals 11
**4. Keyboard and Panel** 12
4.1 Illustration of Keypad 12
4.2 Units LEDs descriptions- 13
4.3 Function LEDs descriptions- 13
4.4 Keys Description- 13
4.5 Illustrations of keyboard operations- 14
**5. Running** 15
5-1 Commissioning 15
5-1-1 Check before running 15
5-1-2 Commissioning 15
5-1-3 Quick commissioning 16
**6. Specifications of functional parameters** 17
6-1 Functional parameters table 17
P0- Basic functional parameters 17
P1- Keypad parameters 18
P2- Start and Stop parameters 19
P3- Motor parameters 20
P4- Scalar control parameters 20
P5- Input function parameters 21
P6- Output function parameters 23
P7- PI Control parameters 23

P8 - Simple PLC and multispeed options 24
P9 - Protection parameters 26
P10 - Fault history 28
P11 - Communication parameters 28
P12 - Enhanced parameters 29
6-2 Detailed explanation of functional parameters 30
P0 - Basic parameters 30
P1 - Keypad parameters 33
P2 - Start and stop parameters 35
P3 - Motor parameters 39
P4 - Scalar control parameters 40
P5 - Input function parameters 43
P6 - Output function terminals 48
P7 - PI Control parameters 50
P8 - Simple PLC and Multispeed parameters 53
P9 - Protection parameters 57
P10 - Fault history 60
P11 - Communication parameters 60
P12 - Enhanced parameters 61
**7. Fault handling and Troubleshooting** 64
7.1 Malfunction and solutions 64
7.2. Common faults and processing schemes 65
**8. Maintenance** 66
8.1. General maintenance and upkeep 66
8.2. Inspection and replacing damaged parts 66
8.3. Storage 67
8.4. Product warranty 67
**9. External communication** 67
9.1. Protocol content 67
9.2. Protocol instructions 68
9.3. Frame structure 68
9.4. Command code and data description 69
9.5. Read - write rules of parameter address for function code 71
**10. Appendix** 72
10.1. Braking resistor calculations 72
10.2. Technical specifications 72
10.3. Product dimensions 74
10.4. Recommended choke value 75
10.5. Recommended lugs size 75
10.6. Recommended wire guages 76

## List of figures and tables


| Sr.No. | Figure Name | Page No. |
|---|---|---|
| Fig.2.1 | Separation While Installation | 7 |
| Fig.3.1 | Connection Method for Assorted Devices | 8 |
| Fig.3.2 | Standard Wiring Diagram | 9 |
| Fig.3.3 | Eathing Method | 12 |
| Fig.4.1 | Illustration of Keyboard | 13 |
| Fig.4.2 | Illustration of Keyboard Operations | 15 |
| Fig.6.1 | Acceleration and Deceleration | 32 |
| Fig.6.2 | Direct Start and DC Brake Assisted Start | 36 |
| Fig.6.3 | Different types of stop modes | 38 |
| Fig.6.4 | Dead Time | 39 |
| Fig.6.5 | Hibernation | 40 |
| Fig.6.6 | Motor Parameters | 41 |
| Fig.6.7 | V/f Curve Settings | 41 |
| Fig.6.8 | Multipoint V/f | 42 |
| Fig.6.9 | Torque Boost | 43 |
| Fig.6.10 | AI With and Without Scaling | 45 |
| Fig.6.11 | AI With and Without Filtering | 45 |
| Fig.6.12 | Deviation Limit | 55 |
| Fig.6.13 | Multispeed Operation | 57 |
| Fig.6.14 | Frequency Hopping | 64 |
| Fig.6.15 | Frequency Detection Level | 64 |
| Fig.6.16 | Amplitude of Frequency Arrival | 65 |
| Fig.10.1 | Keypad Dimension | 77 |
| Fig.10.2 | Product Dimension | 77 |

## 1. Safety precautions

Read this manual carefully and follow all safety precautions before moving, installing, operating and servicing the variable frequency drive (VFD). Ignoring the safety protocol can damage the product

### 1.1 Warning

People working on the device should take part in professional electrical and safety training, receive relevant certification and be familiar with all steps and requirements of installing, commissioning, operating and maintaining the device to avoid any hazards.

### 1.2 Safety guidelines

- Power must be shut off completely before performing any kind of wiring on the control or power terminals.
- Earth wire must be connected correctly.
- In any case, the AC power lines SHOULD NOT be connected to the output terminals viz. U, V or W.
- Do not touch the internal components for your own and the product's safety.
- Only qualified professional engineers are allowed to assemble, wire, commission or maintain the converter.
- The drive must be installed in an appropriate operating environment and far away from humidity or water drops; care must be taken to protect it from direct sunlight or being overheated.
- Do not conduct the procedure of inspection or maintenance until the drive has been shut down for at least 3 minutes or as mentioned on the drive terminal cover.
- No permission is granted to change or modify the internal components or circuits.

### 1.3 Delivery and Installation

Pre-dispatch inspection for each drive is implemented strictly by our QC Department. The packaging is adequately strengthened with special packing materials which to protect it from justifiable levels of harm that could come its way during handling and transportation. However, as an added precaution, we request you to kindly check the following points upon receipt of the device-

- Please check for any damage caused during the transportation.
- Please check if the enclosed documents are all inside the case namely the manual and test report.
- Please check if this is the model of the product for which you placed an order.
- Please check if you have received the right converter accessories as per your order.

## 2. Installation

### 2.1 Installation environment

- The surroundings must be free from dust, caustic/corrosive/inflammable gases/liquids.
- There shouldn't be any conductive particulates in the surrounding air.
- The ambient temperature should be -10°C ~ +55°C. Sufficient ventilation should be available.
- Ensure a solid base without vibration.

### 2.2 Installation instructions and Space limit

- To minimize the heat effect on each other, if two or more converters are installed in the same control cabinet, they should be installed horizontally abreast; A baffle plate must be set up between them if, for some reason, they have to be installed vertically.
- It should be installed on a fire and heat proof frame, for example, a metal frame, to prevent risks of a fire hazard.
- It should be mounted by screws vertically; upside-down, slant or horizontal mountings are not allowed.
- Ensure spare space around the drive to enable adequate ventilation for it to maintain to allow it to maintain its temperature during operation.
- Care must be taken into consideration to ensure that ambient temperature is within the operating range when the drive is installed inside a control cabinet.

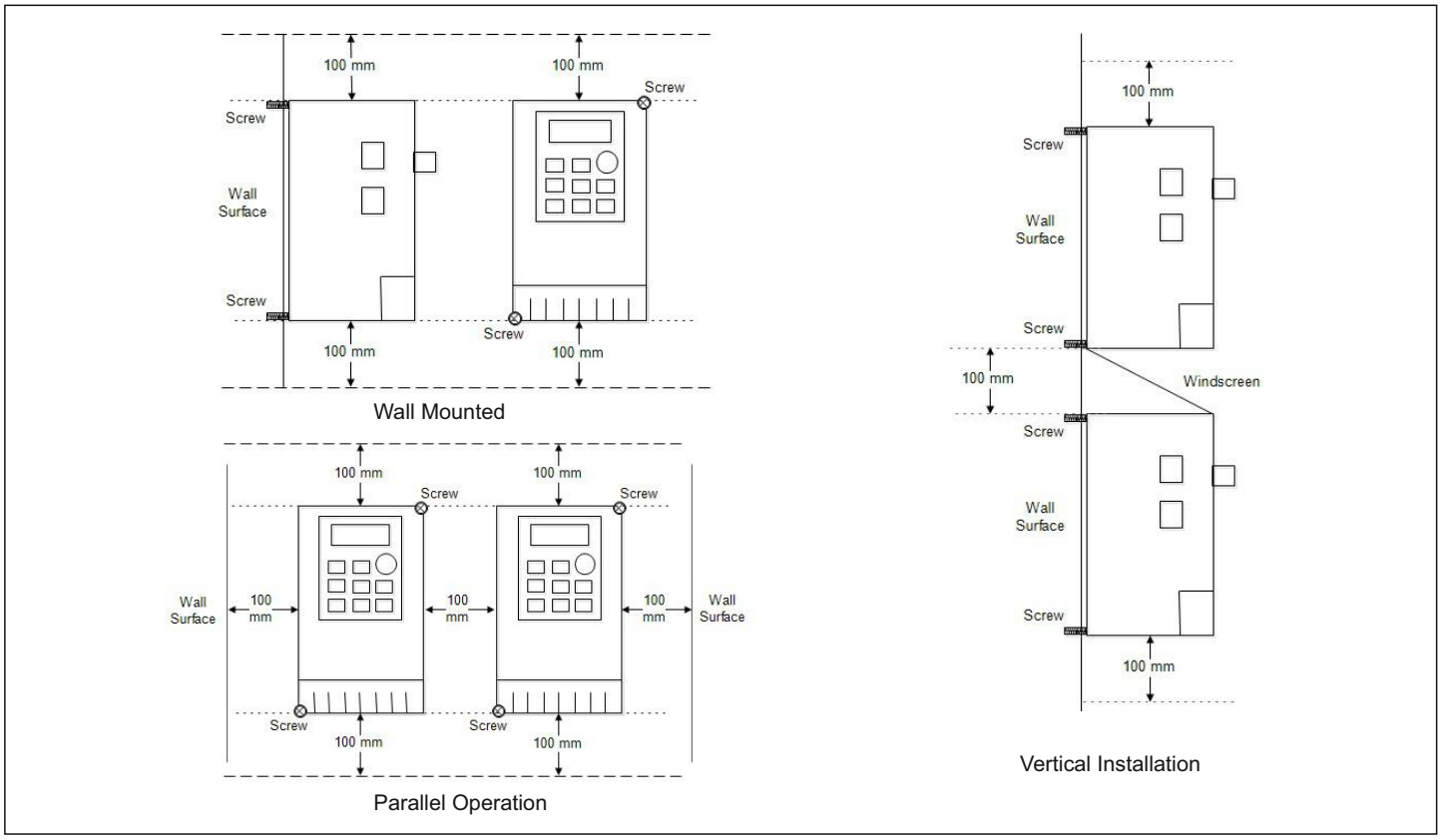



Fig.2.1 Separation While Installation

## 3. WIRING

1. For the safety of user as well as device, only professional engineers or equally qualified persons are allowed to operate it. Please pay attention to the following precautions while wiring.
2. The device must be isolated from any type of power supply before accessing the terminals of the drive. If the drive is already installed and is in working condition, then to change the wiring, first turn off the drive, wait for the capacitors to get fully discharged and then isolate it from input supply. Afterwards it is allowed to do required changes in the wiring.
3. Ensure that the PE earth terminal of the device is properly connected to earth. The earth connection impedance must not be greater than 10 Ohms.
4. Input power must be connected to terminals R, Y and B while motor terminals must be connected to U, V and W. Use lugs to avoid connections error such as loose connections or short circuit of wires. (Kindly refer Appendix B for lugs sizes). Any miss-matched connection can cause damage to the device.
5. The reliablity of wires and terminals must be evaluated before wiring.
6. To avoid contact with the terminals, always keep the terminal cover closed and do not touch them.

### 3-1 Connection methods for assorted devices

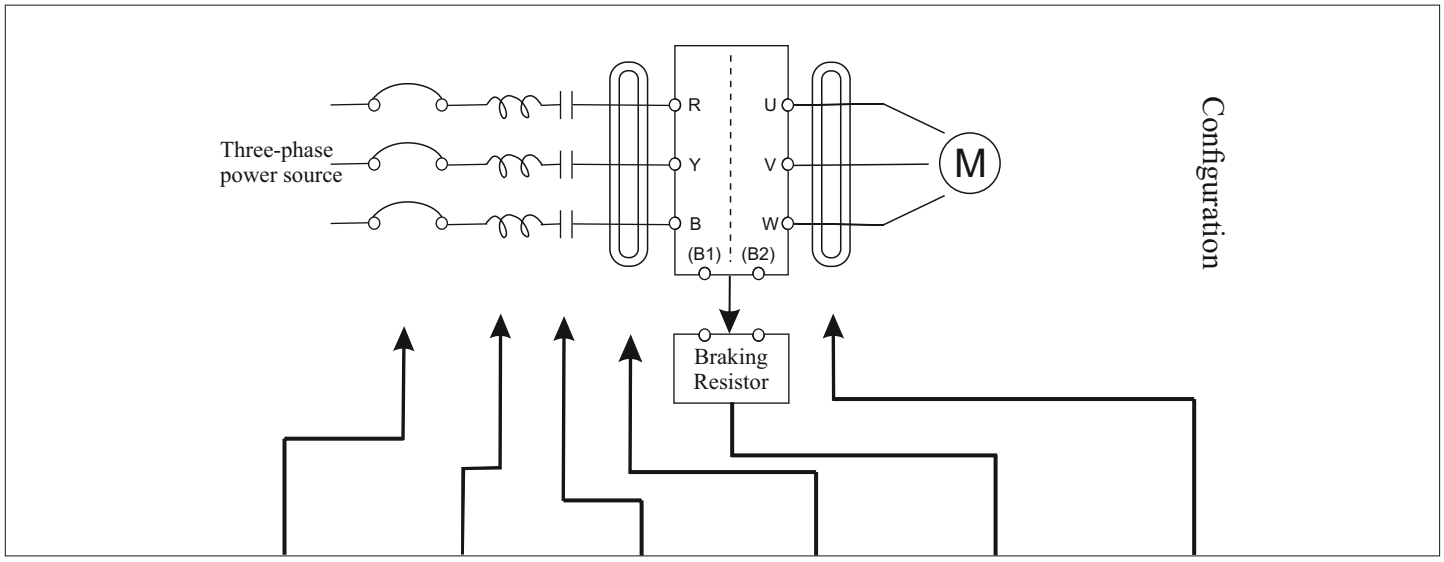
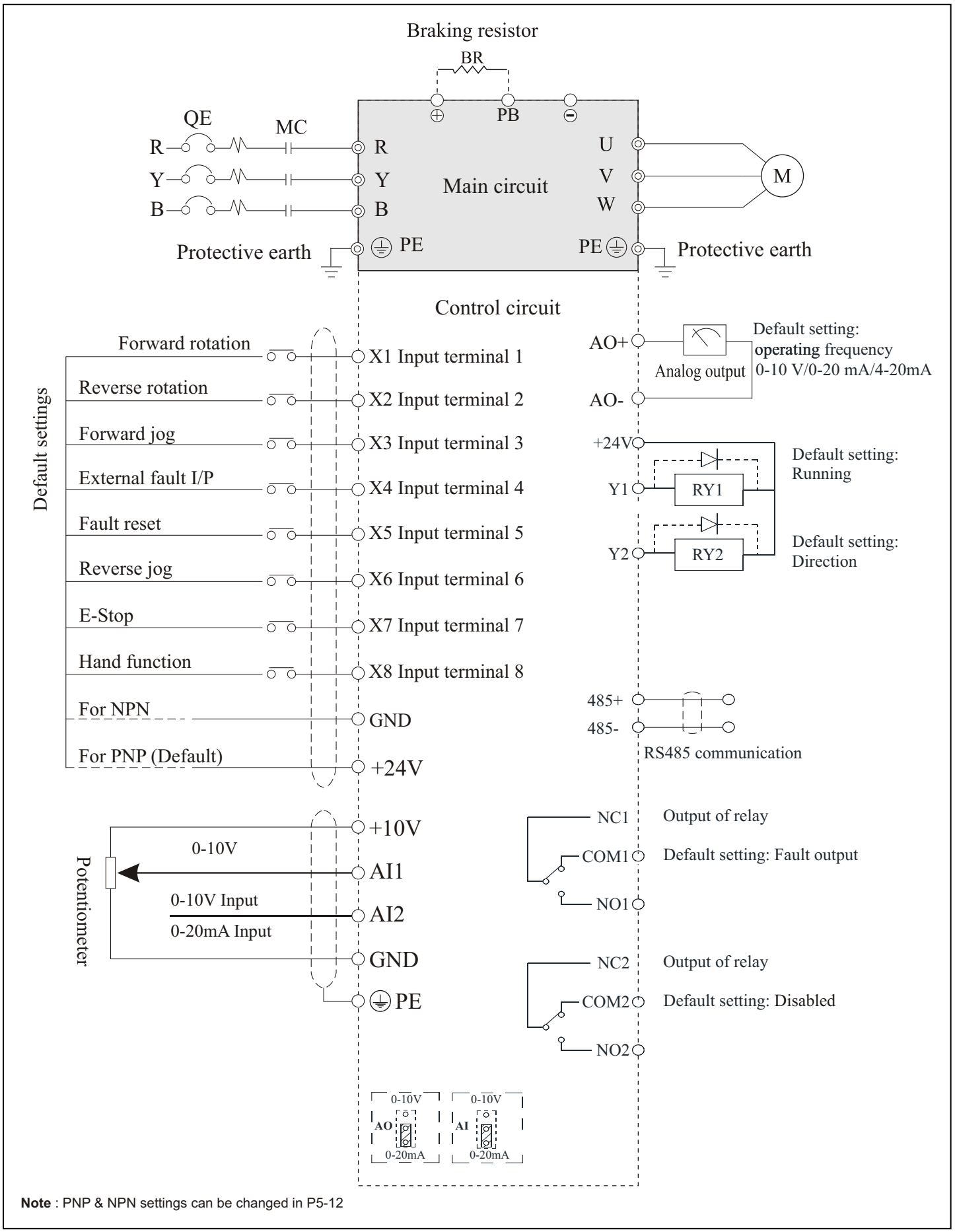



Fig.3.1 Connection Method for Assorted Devices

| **Name** | Fuse | AC Reactor | Electromagnetic contactor | Filter | Braking resistor | Filter |
|---|---|---|---|---|---|---|
| **Descriptions** | Appropriate model should be selected; its rated current must be no less than 1.5 times the rated current of converter | it's applied for the improvement of input power factors | it's used to control the switching of power source | it's used to reduce the radio interfer-ence generated by converter | it's applicable when the braking torque doesn't meet basic requir-ements, or when inertia load is so large that converter needs to be stopped frequently or in a short time. Refer appendix. | It's used to reduce the radio interference generated when the motor is situated at long distances from the drive. |

### 3-2 Standard Wiring Diagram for H2 and H3




**Note** : PNP & NPN settings can be changed in P5-12

### 3-3 Description of Terminals

| Terminal symbol (code) | Functional descriptions |
|---|---|
| R, Y, B (POWER) | Terminals for three-phase AC input 415V |
| U, V, W (MOTOR) | Output terminals, connect with three-phase AC electromotor |
| +, PB (BR) | Terminals for braking resistor (Optional) |
| ⏚ / PE | Terminal of ground (Earth terminal) |
| — | +, - DC Bus +VE and -VE terminal |

For safety's sake, please connect wires according to the regulations of National Electrical Code while proceeding wiring.

#### 3-3-1 Connection of input power terminals

The input supply to the converter must be connected via additional circuit breaker / contactor to protect the device from any input fault. (Tip : R-C surge absorbers should be added to the ends of electromagnetic contactors). An additional Earth Leakage Relay (preferred Selec make) can also be installed as a protective device for electric leakage, the sensitivity should be more than 200 mA and actuation time should not be less than 0.1 seconds to prevent Earth Leakage Relay from malfunctioning. After the input circuit breaker / contactor an AC reactor should be used to protect the converter from high voltage and high current spikes from the grid. AC reactor also helps in improvement of power factor. Refer appendix A for the recommended reactor values for the specific drive rating that you've chosen. The turn on and off action of the motor should not be controlled by directly controlling the input supply to the drive. Instead it is recommended to control it by using the RUN / STOP command buttons on the VFD across the various control sources available. If it not possible to control the turn on and off using the drive controls and has to be controlled using the terminal supply, then it is recommended to perform minimum attempts of switching as it can cause the drive components to degrade. The VFD must not be power cycled more than 2 times per hour in that case with the time between each power cycle no shorter than 30 mins. Always operate the drive under the recommended operating conditions. In cases where this is not possible, kindly contact Selec's helpline to check for the suitability of the VFD in the operating conditions of your site.

#### 3-3-2 Connection of output power terminals

Output terminals must be connected in proper sequence to the terminals. If the sequence is interchanged the motor will run in opposite direction. If such case is encountered, exchange any two wires among U, V, and W. Alternatively, the direction can be changed from the drive settings, also. Never connect output terminals to phasing capacitors or surge-absorber. If the length of wire connected to converter at output side is more than 50 meters, a large amount of leakage will be caused due to capacitors between the wiring, which may lead to over current. In this case output filter is highly recommended. To protect the motor insulation from getting damaged, an additional output reactor must be installed. An additional noise filter should be installed to minimize the radio interference generated by the converter.

### 3-3-3 Braking resistors and Braking unit

If the motor is driving a very high load, then at the time of turn off, a high inertia can cause the rotor to take large time to stop completely. In operations where a short time turn off or frequent switching is required, braking resistor or braking units must be selected and installed. Depending on the drive that you've selected, either an internal braking unit OR DC bus terminals may be available on the power terminals. Braking resistors or braking unit improve braking capacity by improving braking torque. Terminals B1 and B2 must be connected to braking resisitor (Note : If B1 and B2 terminals are present then it represents that the drive has built in braking unit). If there are no B1 and B2 terminals present; and instead positive (+) and negative (-) terminals are present, then these should be connected to external braking unit. Do not connect these terminals to external braking resistor. The recommended values for the braking resistors for diffrent variants of VFD are given in Appendix B, kindly refer to it.

### 3-3-4 Earth terminal PE ⏚

For safety purpose, earth terminal must be properly grounded to reduce the chance of any shock from the body and noise. It is highly recommended to use the standard ground lead which should be short and thick (its grounding impedance should not exceed 10 Ohm). Do not connect the grounding lead of the converter to that of any other devices terminals. The correct method of providing the grounding to the unit is specified in the figure below. All the converters must be connected to the same earth terminal directly if two or more converters are installed together.

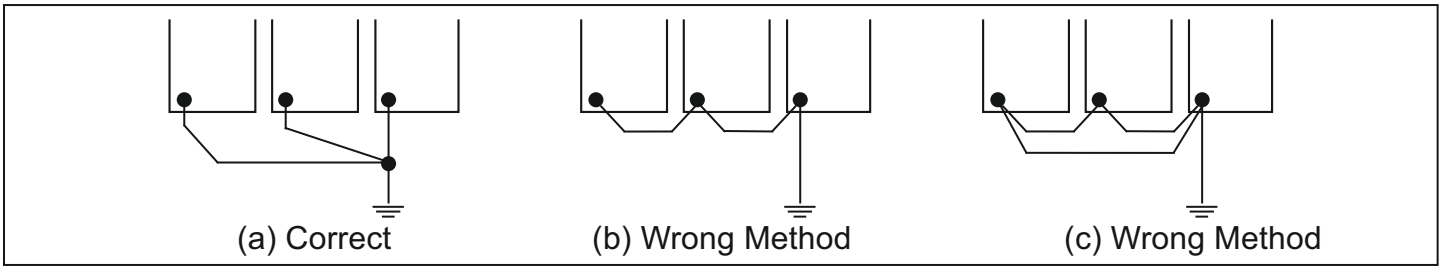



Fig.3.3 Eathing Method

| BR | | | POWER | | | ⏚ | MOTOR | | |
|---|---|---|---|---|---|---|---|---|---|
| ⊕ | PB | ⊖ | R | Y | B | PE | U | V | W |

### 3-4 Explanations of control loop terminals

| | | | | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|---|---|---|
| NO1 | COM1 | NC1 | NO2 | COM2 | NC2 | +24V | X1 | X2 | X3 | X4 | X5 | X6 |
| +10V | GND | AI1 | AI2 | AO+ | AO- | GND | Y1 | Y2 | X7 | X8 | 485+ | 485- |

| Items | Symbol | Terminal name | Description / Default setting |
|---|---|---|---|
| 1 | AO+ | Analog output signal positive terminal | Positive terminal for Analog output (0 - 10V/0-20mA) signal generation |
| 2 | AO- | Analog output signal negative terminal | Negative terminal for Analog output (0 - 10V/0-20mA) signal generation |
| 3 | AI1 | Analog input terminal 1 | Terminal for Analog input (0-10 V) signal |

| Items | Symbol | Terminal name | Description / Default setting |
|---|---|---|---|
| 4 | AI2 | Analog input terminal 2 | Terminal for analog input (0-10V/ 0-20mA) signal |
| 5 | GND | Control terminals ground | Ground for control terminals |
| 6 | X1 | Multifunction input terminal 1 | Default setting : FWD |
| 7 | X2 | Multifunction input terminal 2 | Default setting : REV |
| 8 | X3 | Multifunction input terminal 3 | Default setting : FWD JOG |
| 9 | X4 | Multifunction input terminal 4 | Default setting : Ext Fault |
| 10 | X5 | Multifunction input terminal 5 | Default setting : Fault Reset |
| 11 | X6 | Multifunction input terminal 6 | Default setting : Reverse Jog |
| 12 | X7 | Multifunction input terminal 7 | Default setting : E-Stop |
| 13 | X8 | Multifunction input terminal 8 | Default setting : Hand Function |
| 14 | GND | Control terminals ground | Ground for control terminals |
| 15 | Y1 | Multifunction transistor output 1 | Default setting : Running |
| 16 | Y2 | Multifunction transistor output 2 | Default setting : Direction |
| 17 | +24V | 24V supply | +24VDC 50mA |
| 18 | NC1 | Multifunction relay output NC terminal | Default setting: Fault output |
| 19 | COM1 | Multifunction relay output COM terminal | |
| 20 | NO1 | Multifunction relay output NO terminal | |
| 21 | NC2 | Multifunction relay output NC terminal | Default setting: Disable |
| 22 | COM2 | Multifunction relay output COM terminal | |
| 23 | NO2 | Multifunction relay output NO terminal | |
| 24 | +10V | 10V supply | +10V DC 15mA |
| 25 | +485 | RS 485+ | Communication input positive terminal |
| 26 | -485 | RS 485- | Communication input negative terminal |

Multi-core shielded cable or stranded wire should be used to connect control terminals. The terminal which is closed to the converter must be connected to earth terminal PE. When wiring, the control cables must be kept away from the main circuit and high-current circuit by at least 30cm. Instead of parallel wiring, vertical wiring should be adopted to prevent the drive from malfunctions resulting from external interference.

## 4. Keyboard and Panel

### 4.1 Illustration of Keypad

Fig.4.1 Illustration of Keyboard

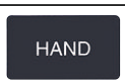
### 4.2 Units LEDs descriptions

| LED | Function |
|---|---|
| V | Denotes that the value being shown is a voltage |
| A | Denotes that the value being shown is a current |
| Hz | Denotes that the value being shown is a frequency |

### 4.3 Function LEDs descriptions

| LED | Function |
|---|---|
| RUN | Denotes that the drive is in RUN operation |
| F/R | Denotes the direction of operation of the drive.<br>OFF - Forward ON - Reverse |
| L/R | Denotes the source of control for the drive.<br>OFF - Local control using the keypad , ON - Remote control |
| ERR | Denotes presence of error condition<br>BLINKING - Pre-alarm condition triggered<br>STEADY - Fault condition triggered |

### 4.4 Keys Description

| Name | Key | Function |
|---|---|---|
| ESC | | 1. Go to the previous programming level,<br>2. Cycle online display pages |
| PRG | | 1. Enter Programming menu, 2. Save setting value |
| STP/RST | | 1. Stop drive operation, 2. Reset Fault |
| RUN | | 1. Start Drive operation |
| JOG / REV | | 1. Perform jogging operation, 2. Perform direction reversal |
| Panel Encoder | | 1. Clockwise- Increment editable value being shown on screen<br>2. Anti-Clockwise- Decrement editable value being shown on screen<br>3. Press- Enter programming menu; Save setting value |
| Up key (△) | | 1. Increment displayed editable value |
| Down key (▽) | | 2. Decrement displayed editable value |
| HAND |  | 1. Triggers the Hand function |

## 4.5 Illustrations of keyboard operations

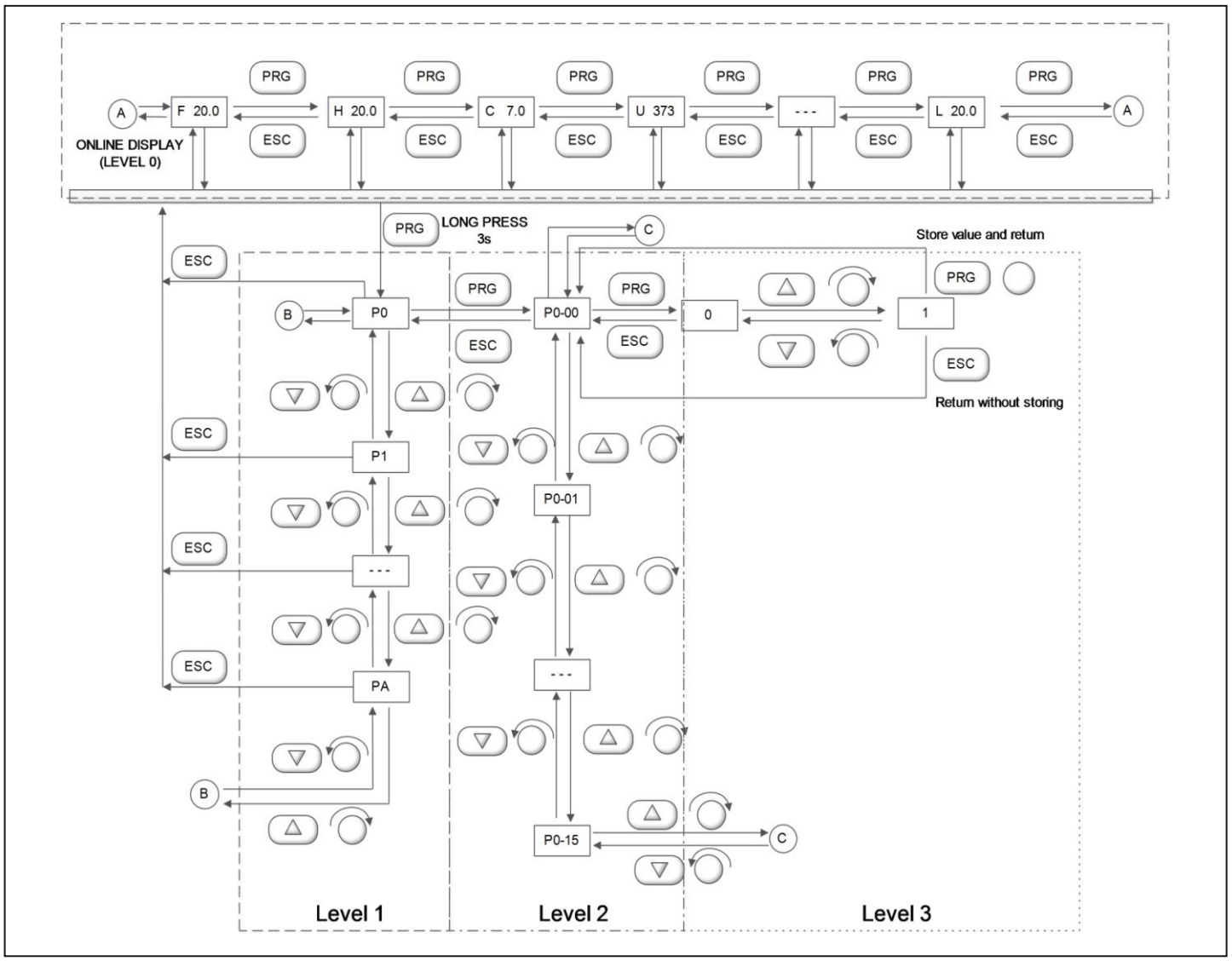



Fig.4.2 Illustration of Keyboard Operations

# 5. RUNNING

## 5-1 Commissioning

### 5-1-1 Check before running

- Please confirm that there is no short circuit between terminals or any exposed charged component.
- Do not connect the unit to the power supply until the enclosure is assembled and closed.
- Please check whether the wiring is correct or not, especially output terminals (U, V, W) which mustn't be connected to the power source; additionally, earth terminals PE must be well-grounded as well.
- Please confirm that all the components, such as terminals, pluggable connectors, or screws are fastened.
- Make sure that all the switches are off before it's connected to a power source, and that the converter will not malfunction or be accidentally started when switched on.
- It is recommended to use appropriately sized lugs instead of free wires to prevent rogue strands from creating a short between adjacent terminals.

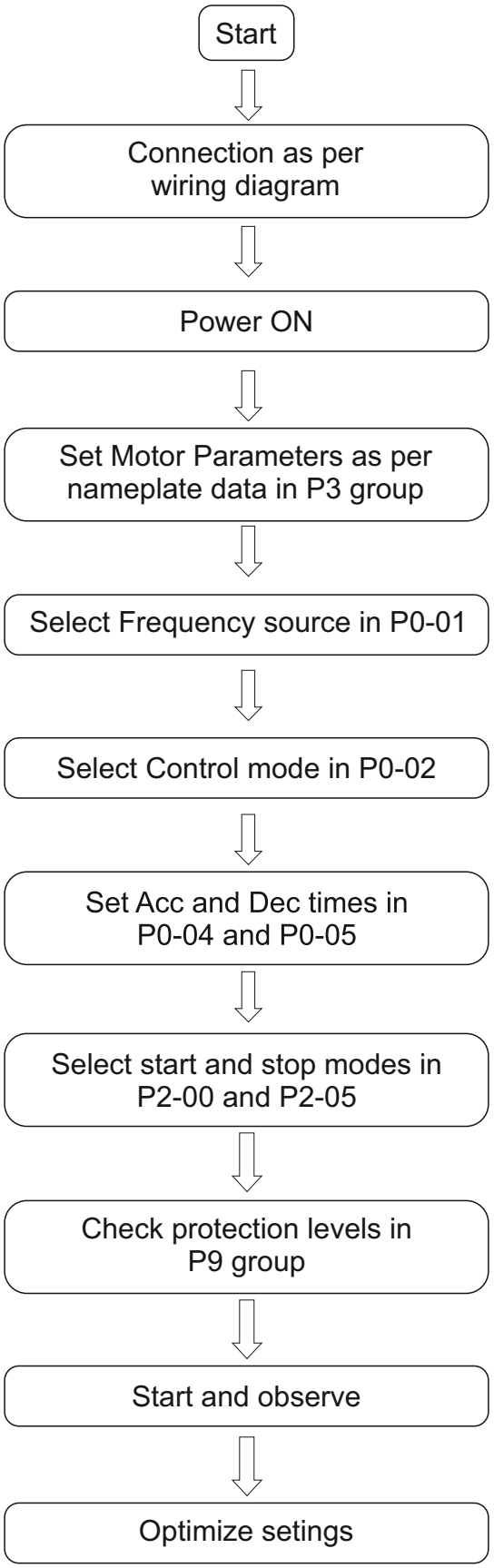
### 5-1-2 Commissioning

- The drive wirings must be checked and confirmed comprehensively before commissioning.
- Its default running mode is to be controlled through the keyboard and panel.
- It is recommended that post initial settings, the user start by checking the jogging function. The default jog frequency is 5.0Hz.
- Check whether the motor is rotating in the right direction.
- Check if its rotation is smooth (No abnormal noise or vibration should be observed).
- Check if the acceleration or deceleration of the motor is stable.
- If the drive functions properly, please preset its operating frequency first; please press the START button to start running and check whether its output current/voltage is normal.
- Only then start using the drive in your regular operations.

If the drive or the system as a whole responds unexpectedly, use the STOP/RST key to stop the operation of the drive immediately. Meanwhile, check Chapter 7 for a guide on debugging the commonly faced faults.

Even after drive operation is stopped, there could be a risk of electrical shock on the terminals of the unit as long as the mains are connected. It is therefore strongly advised that any kind of operation on the terminals should only be undertaken after switching OFF the mains and waiting for adequate time for the DC bus capacitors to discharge.

### 5-1-3 Quick commissioning



## 6. SPECIFICATIONS OF FUNCTIONAL PARAMETERS

### 6-1 Functional parameters table

For ease of programming, the settings have been classified into basic and advanced as mentioned in the table below.

"○": It indicates that the specified parameter can be varied irrespective of the drive's run-state

"●": It indicates that specified code parameters cannot be changed or modified while the drive is running.

"×": It indicates that code parameters are read-only, which cannot be changed or modified.

### P0- BASIC FUNCTIONAL PARAMETERS

| FX Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P0-00 | Parameter setting mode | 0: Display only basic parameters<br>1: Display all settable parameters<br>2: Disable parameter settings<br>3: Factory reset | 0 | Yes | ● | 40000 |
| P0-01 | Frequency setting mode | 0: Keypad UP / DOWN keys<br>1: Keypad encoder; 2: External AI1<br>3: External AI2; 4: PI Regulation<br>5: Terminal setting using step size<br>6: Terminal setting using step size set frequency 0Hz after stop<br>7: Communication | 1 | Yes | ● | 40001 |
| P0-02 | Control mode for running | 0: Controlled by keyboard<br>1: Controlled by terminal & stop key disabled<br>2: Controlled by terminal & stop key enabled<br>3: Controlled by communication | 0 | Yes | ● | 40002 |
| P0-03 | Frequency setting | Lower limiting frequency (P0-10)-Upper limiting frequency (P0-09) | 50.0 Hz | Yes | x | 40003 |
| P0-04 | Acc. time 0 | 0.1 s – 3600.0 s | 10.0 s | Yes | ○ | 40004 |
| P0-05 | Dec. time 0 | 0.1 s – 3600.0 s | 10.0 s | Yes | ○ | 40005 |
| P0-06 | Default running direction | 0: Default direction<br>1: Reverse direction | 0 | Yes | ● | 40006 |
| P0-07 | Anti-reversion setting | 0: Disable, 1: Enable | 0 | Yes | ● | 40007 |
| P0-08 | Max. frequency | Upper limiting frequency (P0-09) - 400 Hz | 60.0 Hz | Yes | ● | 40008 |
| P0-09 | Upper limiting frequency | Lower limiting frequency (P0-10) - maximum frequency (P0-08) | 50.0 Hz | Yes | ● | 40009 |

| FX Code | Description | Settings and Range | Default Value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P0-10 | Lower limiting frequency | 0.0Hz- Upper limiting frequency (P0-09) | 0.0 Hz | Yes | ● | 40010 |
| P0-11 | Jog Frequency | 0.0Hz- Upper limiting frequency (P0-09) | 5.0 Hz | Yes | ○ | 40011 |
| P0-12 | Carrier frequency | Depends on model | Depends on model | No | ● | 40012 |
| P0-13 | Auto storage of keyboard frequency in case of power down | 0: Retention after power down<br>1: No retention on power down | 0 | No | ○ | 40013 |

**P1- KEYPAD PARAMETERS**

| FX Code | Description | Settings and Range | Default value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P1-00 | Default startup display parameter | 0: Setting frequency<br>1: Output frequency<br>2: Output current;<br>3: Bus voltage<br>4: Rotational speed of motor<br>5: IGBT Temperature<br>6: Output voltage<br>7: Output power<br>8: Percentage of output current<br>9: Linear speed<br>10: Count value<br>11: PI Index value<br>12: PI Feedback value<br>13: Input terminal status<br>14: Output terminal status<br>15: Power | 0 | Yes | ○ | 40100 |
| P1-01 | Selection of display information | Count from 0 to 15 as given in P1-00 | 4 | Yes | ○ | 40101 |
| P1-02 | Display co-efficient of frequency | 0.1 – 10.0 | 1.0 | No | ○ | 40102 |
| P1-03 | Display coefficient of mechanical speed | 1.0 - 25.0 | 1.0 | No | ○ | 40103 |

| FX Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P1-04 | Display co-efficient of linear speed | 0.1 - 25.0 | 1.0 | No | ○ | 40104 |
| P1-05 | Jog/Rev function selection | 0: Jog ; 1: FWD/REV switching | 0 | Yes | ● | 40105 |
| P1-06 | Password | 0: Disable ; 1: Enable | 0 | Yes | ○ | 40106 |
| P1-07 | Set password | 1 - 9999 | 1 | Yes | ○ | 40107 |
| P1-08 | Frequency switch source | 0: Keypad UP / DOWN keys<br>1: Keypad encoder<br>2: AI1 (Pot input)<br>3: AI2 (Analog input)<br>4: Communication | 0 | Yes | ○ | 40108 |
| P1-09 | Reference frequency | Lower limit frequency to Upper limit frequency | 0.0 Hz | Yes | ○ | 40109 |

## P2- START AND STOP PARAMETERS

| FX Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P2-00 | Start mode | 0: Direct Start<br>1: DC Braking Start | 0 | Yes | ● | 40200 |
| P2-01 | Starting frequency | Lower Limiting Frequency (P0-10) – Upper Limiting Frequency (P0-09) | 0.5 Hz | Yes | ● | 40201 |
| P2-02 | Retention time for starting | 0.0 – 50.0 s | 0 s | Yes | ● | 40202 |
| P2-03 | Braking current before starting | 0 – 150 % | 50 % | Yes | ● | 40203 |
| P2-04 | Braking time before starting | 0.0 – 50.0 s | 0 s | Yes | ● | 40204 |
| P2-05 | Stop mode | 0: Coast to stop<br>1: Ramp to stop<br>2: DC Braking stop | 1 | Yes | ● | 40205 |
| P2-06 | Start frequency of DC Braking | Lower limiting frequency (P0-10) – Upper limiting Frequency (P0-09) | 2.0 Hz | Yes | ● | 40206 |
| P2-07 | Braking current for stopping | 0 - 150 % | 50 % | Yes | ● | 40207 |
| P2-08 | Braking time for stopping | 0.0 – 50.0 s | 0.0 s | Yes | ● | 40208 |
| P2-09 | Demagnetizing time | 0.0 – 30.0 s | 0.1 s | Yes | ● | 40209 |

| FX Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P2-10 | Dead time between FWD/REV | 0.0 – 50.0 s | 0.2 s | Yes | • | 40210 |
| P2-11 | Lower frequency limit crossing action | 0: Running with low Limit Frequency<br>1: Stopping<br>2: Standby<br>3: Hibernation | 0 | Yes | • | 40211 |
| P2-12 | Hibernation Restore Delay Time | 0 – 50.0 s | 0.0 s | Yes | • | 40212 |

**P3 – MOTOR PARAMETERS**

| FX Code | Description | Settings and Range | Default Value | Basic Setting | Modification | Modbus Address |
|---|---|---|---|---|---|---|
| P3-00 | Rated frequency | F3 (P4-05) – 400.0 Hz | 50.0 Hz | Yes | • | 40300 |
| P3-01 | Rated voltage | Depends on Model | Depends on Model | Yes | • | 40301 |
| P3-02 | Rated current | Depends on Model | Depends on Model | Yes | • | 40302 |
| P3-03 | Rated power | Depends on Model | Depends on Model | Yes | • | 40303 |
| P3-04 | Rated speed | 1 – 36000 RPM | 1500 | Yes | • | 40304 |
| P3-05 | No. of poles | 2 – 8 | 4 | No | • | 40305 |
| P3-06 | No load current | 0.1-(P3-02) | Depends on Model | No | • | 40306 |
| P3-07 | Stator resistance | Depends on Model | Depends on Model | No | • | 40307 |
| P3-08 | Magnetic inductance | Depends on Model | Depends on Model | No | • | 40308 |

**P4 – SCALAR CONTROL PARAMETERS**

| FX Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P4-00 | V/f curve setting | 0: General V/f<br>1: 1.5 Power V/f<br>2: 1.7 Power V/f<br>3: 2 Power V/f<br>4: Multipoint V/f | 0 | Yes | • | 40400 |
| P4-01 | V/f Intermediate frequency 1 (F1) | 0.0 Hz – F2 (P4-03) | 1.0 Hz | Yes | • | 40401 |
| P4-02 | V/f Intermediate voltage 1 | 0 – Rated voltage (P3-01) | 5 V | Yes | • | 40402 |

| FX Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P4-03 | V/f Intermediate frequency 2(F2) | F1 (P4-01) – F3 (P4-05) | 5.0 Hz | Yes | ● | 40403 |
| P4-04 | V/f Intermediate frequency 2 | 0 – Rated voltage (P3-01) | 25 V | Yes | ● | 40404 |
| P4-05 | V/f Intermediate frequency 3(F3) | F2 (P4-03) – Rated frequency (P3-00) | 25.0 Hz | Yes | ● | 40405 |
| P4-06 | V/f Intermediate voltage 3 | 0 – Rated voltage (P3-01) | 115 V | Yes | ● | 40406 |
| P4-07 | Torque boost | 0-15.0 % | 1.00 % | Yes | ● | 40407 |
| P4-08 | AVR Function | 0: Disabled<br>1: Always Enable<br>2: Only Enable during deceleration | 0 | Yes | ● | 40408 |
| P4-09 | Energy-efficient running (EER) | 0: Disable ; 1: Enable | 0 | Yes | ● | 40409 |
| P4-10 | Braking unit enable | 0: Disable<br>300-400: Enable level (1Ø)<br>600-700:Enable level (3Ø) | 0 | Yes | ● | 40410 |

**P5- INPUT FUNCTION PARAMETERS**

| FX Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P5-00 | Lower limit of AI1 | 0.0 – Upper limit of AI1(P5-02) | 0.5 % | Yes | ○ | 40500 |
| P5-01 | Corresponding setting of AI1 lower limit | 0.0 – Corresponding setting of AI1 upper limit(P5-03) | 0.0 % | Yes | ○ | 40501 |
| P5-02 | Upper limit of AI1 | Lower limit of AI1(P5-00) – 100.0 % | 100.0 % | Yes | ○ | 40502 |
| P5-03 | Corresponding setting of AI1 upper limit | Corresponding setting of AI1 lower limit(P5-01) -100% | 100.0 % | Yes | ○ | 40503 |
| P5-04 | AI1 input filtering time | 0.0 s- 10.0 s | 0.1 s | Yes | ○ | 40504 |
| P5-05 | AI1 signal loss threshold | 0.0 – Lower limit of AI1 (P5-00) | 0.5 % | Yes | ○ | 40505 |
| P5-06 | Lower limit OF AI2 | 0.0 – Upper limit of AI2(P5-08) | 0.5 % | Yes | ○ | 40506 |

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P5-07 | Corresponding setting of AI2 lower limit | 0.0 – Corresponding Setting of AI2 Upper Limit(P5-09) | 0.0 % | Yes | ○ | 40507 |
| P5-08 | Upper limit OF AI2 | Lower Limit of AI2 (P5-06) – 100 % | 100.0 % | Yes | ○ | 40508 |
| P5-09 | Corresponding setting of AI2 upper limit | Corresponding setting of AI2 Lower limit(P5-07) – 100 % | 100.0 % | Yes | ○ | 40509 |
| P5-10 | AI2 input filtering time | 0.0 s- 10.0 s | 0.1 s | Yes | ○ | 40510 |
| P5-11 | AI2 signal loss threshold | 0.0 – Lower limit of AI2 (P5-06) | 0.5 % | Yes | ○ | 40511 |
| P5-12 | PNP / NPN selection | 0: NPN; 1: PNP | 1 | Yes | ● | 40512 |
| P5-13 | Multifunction input X1 | 0: Disable<br>1: Forward rotation<br>2: Reverse rotation<br>3: Three - Wire control<br>4: Multiphase reference Velocity 1<br>5: Multiphase reference Velocity 2<br>6: Multiphase reference Velocity 3<br>7: Multiphase Reference velocity 4<br>8: Forward JOG<br>9: Reverse JOG<br>10: Increasing frequency<br>11: Decreasing frequency<br>12: Acc - Dec time option 1<br>13: Acc - Dec time option 2<br>14: Stop of Acc - Dec<br>15: External fault input<br>16: Fault reset<br>17: Regular stopping<br>18: External Count value input<br>19: Count clear<br>20: Program run<br>21: Pause of program run<br>22: DC brake<br>23: E - Stop<br>24: Hand function | 1 | Yes | ● | 40513 |
| P5-14 | Multifunction input X2 | | 2 | Yes | ● | 40514 |
| P5-15 | Multifunction input X3 | | 8 | Yes | ● | 40515 |
| P5-16 | Multifunction input X4 | | 15 | Yes | ● | 40516 |
| P5-17 | Multifunction input X5 | | 16 | Yes | ● | 40517 |
| P5-18 | Multifunction input X6 | | 9 | Yes | ● | 40518 |
| P5-19 | Multifunction input X7 | | 23 | Yes | ● | 40519 |
| P5-20 | Multifunction input X8 | | 24 | Yes | ● | 40520 |
| P5-21 | Terminal control mode | 0: Two - wire control mode 1<br>1: Two - wire control mode 2<br>2: Three - wire control mode 1<br>3: Three - wire control mode 2 | 0 | Yes | ● | 40521 |
| P5-22 | Terminal filtering time | 2 ms- 100 ms | 10 ms | No | ○ | 40522 |

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P5-23 | Terminal frequency updation step size | 0.0 - Upper limit of frequency (P0-09) | 0.1 Hz | No | ○ | 40523 |

## P6- OUTPUT FUNCTION PARAMETERS

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P6-00 | Y1 output options | 0 : Disable<br>1 : Running<br>2 : Direction<br>3 : Fault output<br>4 : Overload Pre - Alarm<br>5 : Standby<br>6 : Frequency arrived<br>7 : Frequency detected<br>8 : Upper limit frequency<br>9 : Lower limit frequency<br>10 : Setting count value received<br>11 : Specified count value Received<br>12 : AI1 signal loss<br>13 : AI2 signal loss | 1 | Yes | ○ | 40600 |
| P6-01 | Y2 Output options | | 2 | Yes | ○ | 40601 |
| P6-02 | Relay 1 output options | | 3 | Yes | ○ | 40602 |
| P6-03 | Relay 2 output options | | 0 | Yes | ○ | 40603 |
| P6-04 | AO options | 0 : Operating frequency<br>1 : Output current<br>2 : Bus voltage; 3 : Output Voltage | 0 | Yes | ○ | 40604 |
| P6-05 | AO correction coefficient | 0.0 to 250.0 % | 100.0 % | Yes | ○ | 40605 |
| P6-06 | AO current range selection | 0 : 0~20 mA; 1: 4~20 mA | 0 | Yes | ○ | 40606 |

## P7- PI CONTROL PARAMETERS

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P7-00 | PI reference source | 0: Keyboard<br>1: Panel encoder<br>2: AI1<br>3: AI2 | 0 | No | ● | 40700 |
| P7-01 | PI reference source | 0.00 to 100.0 % | 0.00% | No | ● | 40701 |
| P7-02 | Feedback source | 0: AI1<br>1: AI2 | 0 | No | ● | 40704 |

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P7-03 | PI output characteristics options | 0: Positive; 1: Negative | 0 | No | ● | 40703 |
| P7-04 | Proportional gain | 0.0 to 10.0 | 1.0 | No | ● | 40704 |
| P7-05 | Integral time | 0.0 to 100.0 s | 1.0 s | No | ● | 40705 |
| P7-06 | Deviation limit | 0.0 to 20.0 | 2.0 | No | ● | 40706 |
| P7-07 | Sampling time | 0.1 to 100.0 s | 0.2 s | No | ● | 40707 |
| P7-08 | Feedback disconnection value | 0.1 % to 50.0 % | 0.1 % | No | ● | 40708 |
| P7-09 | Feedback disconnection detection time | 0.1 to 100.0 s | 10.0 s | No | ● | 40709 |

## P8- SIMPLE PLC AND MULTISPEED OPTIONS

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P8-00 | Program run mode | 0: Disabled; 1: Program stops after running for one cycle<br>2: Program runs for one cycle & then continues at last operating frequency<br>3: Circulatory running of the program | 0 | Yes | ● | 40800 |
| P8-01 | First phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 11.0 Hz | No | ○ | 40801 |
| P8-02 | Second phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 12.0 Hz | No | ○ | 40802 |
| P8-05 | Fifth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 15.0 Hz | No | ○ | 40805 |
| P8-06 | Sixth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 16.0 Hz | No | ○ | 40806 |
| P8-07 | Seventh phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 17.0 Hz | No | ○ | 40807 |
| P8-08 | Eighth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 18.0 Hz | No | ○ | 40808 |
| P8-09 | Ninth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 19.0 Hz | No | ○ | 40809 |
| P8-10 | Tenth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 20.0 Hz | No | ○ | 40810 |
| P8-11 | Eleventh phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 21.0 Hz | No | ○ | 40811 |
| P8-12 | Twelveth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 22.0 Hz | No | ○ | 40812 |

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P8-13 | Thirteenth phase speed | Lower Limiting Frequency (P0-10)<br>Upper Limiting Frequency (P0-09) | 23.0 Hz | No | ○ | 40813 |
| P8-14 | Fourteenth phase speed | Lower Limiting Frequency (P0-10)<br>Upper Limiting Frequency (P0-09) | 24.0 Hz | No | ○ | 40814 |
| P8-15 | Fifteenth phase speed | Lower Limiting Frequency (P0-10)<br>Upper Limiting Frequency (P0-09) | 25.0 Hz | No | ○ | 40815 |
| P8-16 | Runtime of principal frequency | 0.0-6400.0 | 0.0 S | No | ○ | 40816 |
| P8-17 | First phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40817 |
| P8-18 | Second phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40818 |
| P8-19 | Third phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40819 |
| P8-20 | Fourth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40820 |
| P8-21 | Fifth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40821 |
| P8-22 | Sixth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40822 |
| P8-23 | Seventh phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40823 |
| P8-24 | Eighth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40824 |
| P8-25 | Ninth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40825 |
| P8-26 | Tenth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40826 |
| P8-27 | Eleventh phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40827 |
| P8-28 | Twelveth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40828 |
| P8-29 | Thirteenth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40829 |
| P8-30 | Fourteenth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40830 |
| P8-31 | Fifteenth phase time | 0.0-6400.0 | 0.0 S | No | ○ | 40831 |
| P8-32 | Time unit of multi - velocity | 0: Seconds; 1: Minutes<br>2: Hours | 0 | No | ● | 40832 |
| P8-33 | Running direction of programs | 0-65535 BIT0-15 indicates directions for 0-15 (0:FWD 1:REV) | 0 | No | ● | 40833 |

| Fx Code | Description | Settings and Range | Default Value | Basic Setting | Modifi-cation | Modbus Address |
|---|---|---|---|---|---|---|
| P8-34 | Acc - Dec time for each phase 0-7 | 0-65535 BIT0-15 indicated acc / dec times for 0-7 | 0 | No | ○ | 40834 |
| P8-35 | Acc - Dec time for eachphase 8-15 | 0-65535 BIT0-15 indicated acc / dec times for 8-15 | 0 | No | ○ | 40835 |

## P9- PROTECTION PARAMETERS

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P9-00 | Overload prot-ection enable | 0 : Disable; 1 : Enable | 1 | Yes | ● | 40900 |
| P9-01 | Critical value of overload protection | 50 – 200 % | 120 % | Yes | ● | 40901 |
| P9-02 | Overload det-ection time | 0.1 to 3600.0 s | 10 s | Yes | ● | 40902 |
| P9-03 | Overload pre - alarm enabled | 0 : Disabled; 1 : Enabled | 0 | No | ● | 40903 |
| P9-04 | Overload pre - alarm detection level | 50 % to critical value of Overload Protection (P9-01) | 105 % | No | ● | 40904 |
| P9-05 | Overload pre - alarm detection level | 0.1 to 3600.0 s | 0.1s | No | ● | 40905 |
| P9-06 | Overvoltage protection enable | 0 : Disabled; 1 : Enabled | 1 | Yes | ● | 40906 |
| P9-07 | Critical value of OV protection | 415 - 475V | 460V | Yes | ● | 40907 |
| P9-08 | Overvoltage Trip time | 0.1 to 3600.0 s | 0.1s | Yes | ● | 40908 |
| P9-09 | Overvoltage pre - alarm enable | 0 : Disabled; 1 : Enabled | 0 | No | ● | 40909 |
| P9-10 | Overvoltage pre - alarm detection level | 415 - (P9-07) | 450V | No | ● | 40910 |
| P9-11 | Overvoltage pre - alarm detection time | 0.1 to 3600.0 s | 0.1 s | No | ● | 40911 |
| P9-12 | Under voltage protection enable | 0 : Disabled; 1 : Enabled | 1 | Yes | ● | 40912 |
| P9-13 | Critical value of Under - voltage protection | 315-415V | 350V | Yes | ● | 40913 |
| P9-14 | Undervoltage trip time | 0.1 to 3600.0 s | 1.0 s | Yes | ● | 40914 |

| Fx Code | Description | Settings and Range | Default Value | Basic Setting | Modification | Modbus Address |
|---|---|---|---|---|---|---|
| P9-15 | Undervoltage pre-alarm enable | 0 : Disabled; 1 : Enabled | 0 | No | ● | 40915 |
| P9-16 | Undervoltage pre-alarm detection level | (P9 - 13) - 415V | 395V | No | ● | 40916 |
| P9-17 | Undervoltage pre-alarm detection time | 0.1 to 3600.0 s | 0.1 s | No | ● | 40917 |
| P9-18 | Overcurrent protection enable | 0 : Disabled; 1 : Enabled | 1 | Yes | ● | 40918 |
| P9-19 | Critical value of overcurrent protection | 50 - 200% | 120 % | Yes | ● | 40919 |
| P9-20 | Overcurrent trip time | 0.1 to 3600.0 s | 5 s | Yes | ● | 40920 |
| P9-21 | Overcurrent pre-alarm enable | 0 : Disabled; 1 : Enabled | 0 | No | ● | 40921 |
| P9-22 | Overcurrent pre-alarm detection level | 100 % to P9 - 19 | 105 % | No | ● | 40922 |
| P9-23 | Overcurrent pre-alarm detection time | 0.1 to 3600.0 s | 0.1 s | No | ● | 40923 |
| P9-24 | Undercurrent protection enable | 0 : Disabled; 1 : Enabled | 0 | Yes | ● | 40924 |
| P9-25 | Critical value of UC protection | 20 to 90 % | 25 % | Yes | ● | 40925 |
| P9-26 | UC trip time | 0.1 to 3600.0 s | 0.1 s | Yes | ● | 40926 |
| P9-27 | UC pre-alarm enable | 0 : Disabled; 1 : Enabled | 0 | No | ● | 40927 |
| P9-28 | UC pre-alarm detection level | P9 - 25 to 90 % | 50 % | No | ● | 40928 |
| P9-29 | UC pre-alarm detection time | 0.1 to 3600.0 s | 0.1 s | No | ● | 40929 |
| P9-30 | Low power actions | 0 : Coast; 1 : Continue | 1 | Yes | ● | 40930 |
| P9-31 | Automatic current limit | 0 : Disabled; 1 : Enabled | 0 | Yes | ● | 40931 |
| P9-32 | Automatic current limit level | 50 – 180 % | 150 % | No | ● | 40932 |

## P10- FAULT HISTORY

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P10-00 | Previous fault code | 0-20 | - | Yes | × | 41000 |
| P10-01 | 2nd to previous fault code | 0-20 | - | Yes | × | 41001 |
| P10-02 | 3rd to previous fault code | 0-20 | - | Yes | × | 41002 |
| P10-03 | Previous fault operating frequency | - | | No | × | 41003 |
| P10-04 | Previous fault Current | - | - | No | × | 41004 |
| P10-05 | Previous fault bus voltage | - | - | No | × | 41005 |
| P10-06 | Previous fault input state | - | - | No | × | 41006 |
| P10-07 | Previous fault output state | - | - | No | × | 41007 |

## P11- COMMUNICATION PARAMETERS

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modification | Modbus address |
|---|---|---|---|---|---|---|
| P11-00 | Slave address | 1-127 | 1 | Yes | ● | 41100 |
| P11-01 | Communication baud rate | 0 : 1200; 1 : 2400; 2 : 4800;<br>3 : 9600; 4 : 19200; 5 : 38400;<br>P11 - 01; 6 : 57600; 7 : 115200 | 3 | Yes | ● | 41101 |
| P11-02 | Modbus data format | 0: 8-N-1; 1: 8-N-2; 2: 8-E-1<br>3: 8-E-2; 4: 8-O-1; 5: 8-O-2 | 0 | Yes | ● | 41102 |
| P11-03 | Response delay | 0- 200 ms | 20 ms | No | ● | 41103 |
| P11-04 | Serial timeout | 0: Disable; 1: Time setting | 0 | No | ● | 41104 |
| P11-05 | Serial timeout time setting | 0.1- 60.0 s | 5.0 s | No | ● | 41105 |
| P11-06 | Abnormal action selection | 0: Warm & Continue operation<br>1: Continue operation without warning<br>2: Alarm shutdown (Coast to stop)<br>3: Alarm shutdown (Ramp to stop) | 0 | No | ● | 41106 |

## P12- ENHANCED PARAMETERS

| Fx Code | Description | Settings and Range | Default value | Basic setting | Modifi-cation | Modbus address |
|---|---|---|---|---|---|---|
| P12-00 | Acc. time 1 | 0.1 – 3600.0 s | 20.0 s | No | ○ | 41200 |
| P12-01 | Dec. time 1 | 0.1 – 3600.0 s | 20.0 s | No | ○ | 41201 |
| P12-02 | Acc. time 2 | 0.1 – 3600.0 s | 20.0 s | No | ○ | 41202 |
| P12-03 | Dec. time 2 | 0.1 – 3600.0 s | 20.0 s | No | ○ | 41203 |
| P12-04 | Acc. time 3 | 0.1 – 3600.0 s | 20.0 s | No | ○ | 41204 |
| P12-05 | Dec. time 3 | 0.1 – 3600.0 s | 20.0 s | No | ○ | 41205 |
| P12-06 | Jog Acc. time | 0.1 – 3600.0 s | 5.0 s | No | ○ | 41206 |
| P12-07 | Jog Dec. time | 0.1 – 3600.0 s | 5.0 s | No | ○ | 41207 |
| P12-08 | Hopping frequency 1 lower limit | Lower limit frequency (P0-10) to Hopping frequency 1 Upper fimit (P12-09) | 0.0 Hz | No | ○ | 41208 |
| P12-09 | Hopping frequency 1 upper limit | Hopping frequency 1 Lower Limit (P12-08) to Upper limit Frequency (P0-09) | 0.0 Hz | No | ○ | 41209 |
| P12-10 | Hopping frequency 2 lower limit | Lower limit frequency (P0 - 10) to Hopping frequency 2 Upper limit (P12-11) | 0.0 Hz | No | ○ | 41210 |
| P12-11 | Hopping frequency 2 upper limit | Hopping frequency 2 Lower Limit (P12-10) to Upper Limit Frequency (P0-09) | 0.0 Hz | No | ○ | 41211 |
| P12-12 | FDT Level detection value | Lower limiting frequency (P0-10) – Upper limiting Frequency (P0-09) | 0.0 Hz | No | ○ | 41212 |
| P12-13 | FDT Level lagged value | Lower limiting frequency (P0-10) – FDT level Detection value (P12-12) | 0.0 Hz | No | ○ | 41213 |
| P12-14 | Amplitude of frequency arrival | Lower limiting frequency (P0 - 10) – Upper limiting Frequency (P0-09) | 0.0 Hz | No | ○ | 41214 |
| P12-15 | Setting count | 1 – 65535 | 10 | No | ○ | 41215 |
| P12-16 | Specific count | 1 – Setting count (P12-15) | 10 | No | ○ | 41216 |
| P12-17 | DSP code version | NA | NA | No | x | 41217 |
| P12-18 | IO code version | NA | NA | No | x | 41218 |
| P12-19 | HMI code version | NA | NA | No | x | 41219 |

## 6-2 Detailed explanation of functional parameters

### P0 : Basic parameters

| | | | |
|---|---|---|---|
| **P0-00** | Parameter setting mode | 0: Display Only Basic Parameters<br>1: Display All Settable Parameters<br>2: Disable Parameter Settings<br>3: Factory Reset | 0 |

For ease of use, the entire parameter list has been divided into advanced and basic functions. When the setting is 0. only these basic parameters are visible and available for editing. When the setting is 1. all settable parameters are visible and available for editing. When the setting is 2. all parameters are visible, but they cannot be edited. Use this setting post-commissioning to protect accidental updating of parameters. The last setting, 3. will reset the drive to its default factory settings.

| | | | |
|---|---|---|---|
| **P0-01** | Frequency setting mode | 0 : Keypad UP/ DOWN Keys ; 1: Panel encoder<br>2 : External AI1; 3: External AI2<br>4 : PI Regulation; 5: Terminal setting using step size<br>6 : Terminal setting using step size<br>Set frequency 0Hz after stop<br>7 : Communication | 1 |

This setting determines the source of setting frequency that will be considered by the drive for all operations. The explanations are as under-

0: The keypad Up/Down keys are used for manipulating the set frequency. Long pressing either will increase the rate.

1: The panel encoder is used for manipulating the set frequency. Steady, continuous rotation will increase the update rate at which the set frequency value gets updated.

2: External AI1 uses the AI1 terminal for manipulating the set frequency.

3: External AI2 uses the user-selectable Analogue input for updating the set frequency.

4: Set Frequency is manipulated using the inbuilt PI regulator.

5: Set Frequency is updated using the multifunction input terminals.

6: Set frequency is updated using the multifunction input terminals just like in setting 5. The only difference is that once the user stops the drive, the set frequency will shift to 0.0 Hz.

7: The user can use the external communication feature to update the set frequency

| | | | |
|---|---|---|---|
| **P0-02** | Control mode for running | 0: Controlled by Keyboard<br>1: Controlled by Terminal & Stop key disabled<br>2: Controlled by Terminal & Stop key enabled<br>3: Controlled by Communication | 0 |

This setting determines the source of control signals for the drive.
For setting 0, the keypad RUN, JOG and STOP keys will control the operation.
For setting 1, the drive will be controlled by the multifunction terminals. The keypad STOP key will be disabled in this case.
In setting 2, the drive will still be controlled by the multifunction terminals. However, the STOP key on the keypad will be enabled and can be used to stop the drive's operation.
In setting 3, the drive operation will be controlled over external communication

| | | | |
|---|---|---|---|
| **P0-03** | Frequency setting | Lower limiting Frequency (P0-10)<br>-Upper limiting Frequency (P0-09) | 50.0 Hz |

This function reflects the set frequency. When using external communication, this parameter needs to be updated for updating the drive's set frequency.

| | | | |
|---|---|---|---|
| **P0-04** | Acc. time 0 | 0.1 s – 3600.0 s | 10.0 s |
| **P0-05** | Dec. time 0 | 0.1 s – 3600.0 s | 10.0 s |

Acceleration and Deceleration times are defined as the time the drive will take to accelerate from 0.0Hz to Max Running Frequency (P0-08) and from Max Running Frequency (P0-08) to 0.0 Hz respectively. For intermediate frequencies, the acceleration and deceleration times will vary accordingly.

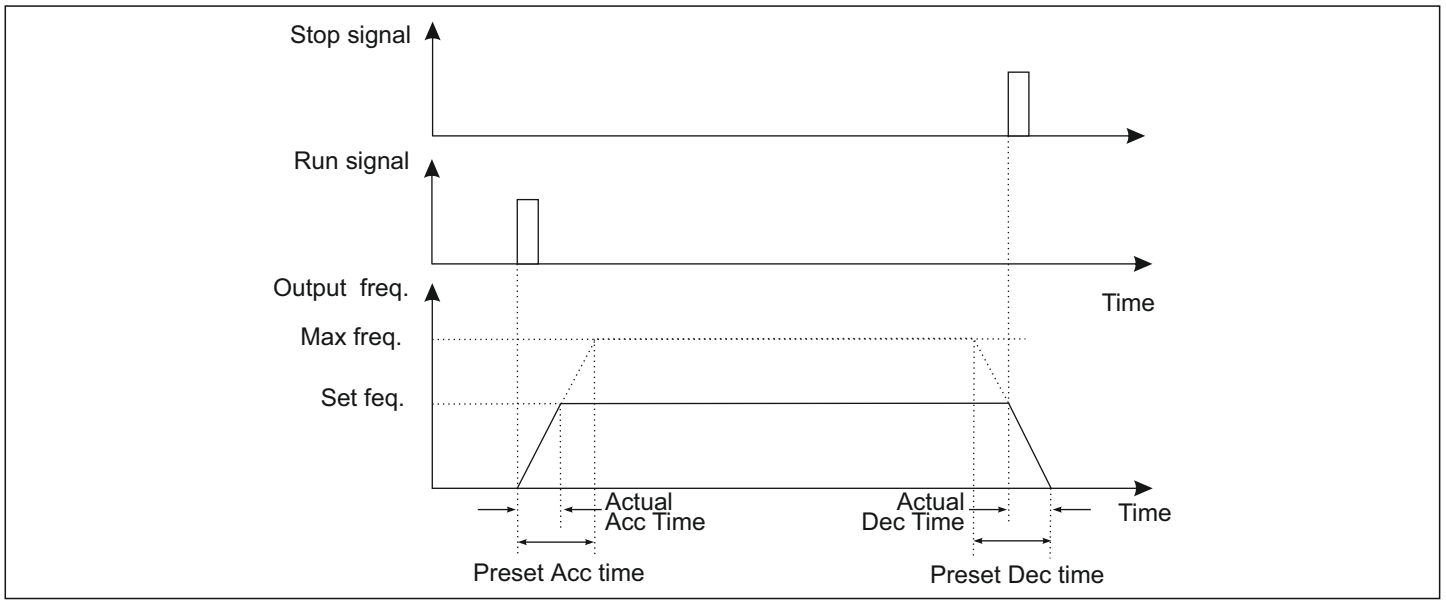



Fig.6.1 Acceleration and Deceleration

| | | | |
|---|---|---|---|
| **P0-06** | Default running direction | 0: Standard direction<br>1: Reverse direction | 0 |

This parameter is used to determine the default running direction of the drive. It is useful when there is a need to permanently change the default direction of the motor. It helps the user as they do not need to manipulate the wiring to change the default direction. The direction chosen here will be treated as FORWARD (FWD) for all drive operations.

| | | | |
|---|---|---|---|
| **P0-07** | Anti-reversion setting | 0: Disable<br>1: Enable | 0 |

This setting determines if the reverse operation will be allowed. If enabled, the drive will only allow operation in the FWD direction as determined through the setting of P0-06. Any attempt to operate the drive in the reverse direction through the keypad, terminals, communication, etc. will be ignored.

| | | | |
|---|---|---|---|
| **P0-08** | Max frequency | Upper Limiting Frequency (P0-09)<br>- 400 Hz | 60.0 Hz |

This setting determines the maximum running frequency of the drive. Its primary use is to define the acceleration and deceleration times of the system.

| | | | |
|---|---|---|---|
| **P0-09** | Upper limiting frequency | Lower Limiting Frequency (P0-10)<br>- Maximum Frequency (P0-08) | 50.0 Hz |
| **P0-10** | Lower limiting frequency | 0.0Hz- Upper limiting Frequency (P0-09) | 0.0 Hz |

These settings determine the bounds of frequency within which the drive will operate. These values are also tied to the corresponding settings of the analogue input channels

| | | | |
|---|---|---|---|
| **P0-11** | Jog Frequency | 0.0Hz- Upper limiting Frequency (P0-09) | 5.0 Hz |

This setting determines the set frequency in case of jog operation. This operation can be activated either through the keypad, terminals, or communication. Jogging refers to the controlled action of the drive used as a fine adjuster. The action is valid till the jogging signal is valid through the relevant control source.

| | | | |
|---|---|---|---|
| **P0-12** | Carrier frequency | Depends on model | Depends on Model |

The carrier frequency determines the switching frequency of the IGBTs used in the Inverter section of the drive. Audible noise and heat generated in the drive are directly affected by the carrier frequency. A higher carrier frequency will reduce the acoustic noise generated by the motor. However, it increases switching losses which result in higher heating of the unit and wastage of energy. In cases where the ambient temperature is too high or in systems that run at higher loads, a lower carrier frequency is suggested to improve the performance of the drive. Kindly note that a higher carrier frequency effectively impedes the heavy load performance of the drive.

The factory default carrier frequency is set as per our calculations for the optimum performance of the drive. Unless absolutely demanded by the application at hand, it doesn't need any modifications or changes. In cases where a significantly higher carrier frequency is being used compared to the factory default value, some derating might be necessary.

| | | | |
|---|---|---|---|
| **P0-13** | Auto storage of keyboard frequency in case of power down | 0: Retention after power down<br>1: No retention on power down | 0 |

This function determines if the frequency set using the keyboard encoder or UP/DOWN keys will be retained post power down.

**P1 : Keypad parameters**

| | | | |
|---|---|---|---|
| **P1-00** | Default startup display parameter | 0 : setting frequency; 1 : Output frequency<br>2 : Output current; 3 : Bus voltage<br>4 : Rotational speed of motor<br>5 : IGBT Temperature; 6 : Output voltage<br>7 : Output power; 8 : Percentage of output current<br>9 : Linear speed; 10 : Count value<br>11 : PI Index value; 12 : PI feedback value<br>13 : Input terminal status<br>14 : Output terminal status; 15 : Power | 0 |

**It's mainly applied to the setting of default display information for starting.**

| LED Character | Description |
|---|---|
| F 50.0 | Set frequency |
| H 0.0 | Output frequency |
| C 0.0 | Output current |
| U 311 | Bus voltage |
| n 0 | Rotational speed of motor |
| o 18.8 | IGBT Temperature |
| d 0 | Output voltage |
| P 0.0 | Output power |

| LED Character | Description |
|---|---|
| C. 0.00 | Percentage of output current |
| L 0 | Linear speed |
| A 0 | Count value |
| c 0.00 | PI Index value |
| P 0.0 | PI Feedback value |
| I ıııı | Input terminal status |
| O ıı | Output terminal status |
| Y 15 | Power |

| | | | |
|---|---|---|---|
| **P1-01** | Selection of display information | Count from 0 to 15<br>as given in P1-00 | 4 |

This determines the number of pages that will be displayed in the online display pages. The count ID relates to the field ID as shared in P1-00.

| | | | |
|---|---|---|---|
| **P1-02** | Display co-efficient of frequency | 0.1 – 10.0 | 1.0 |

This parameter determines the multiplier that will be applied to the output frequency parameter being displayed on the keypad. It will also affect the running frequency field accessed through external communication.

| | | | |
|---|---|---|---|
| **P1-03** | Display co-efficient of mechanical speed | 1.0 - 25.0 | 1.0 |

This parameter determines the multiplier that will be applied to the rotational speed field being displayed on the keypad and accessed through external communication.

| | | | |
|---|---|---|---|
| **P1-04** | Display co-efficient of linear speed | 0.1 - 25.0 | 1.0 |

This parameter determines the multiplier that will be applied to the rotational speed to calculate the linear speed being displayed on the keypad and accessed through external communication.

| | | | |
|---|---|---|---|
| **P1-05** | Jog/Rev function selection | 0: Jog<br>1: FWD/REV Switching | 0 |

This function determines the role of the JOG/REV key on the keypad.
0-The JOG/REV key will initiate jogging action. As mentioned earlier, the jogging operation is only valid for as long as the jogging signal is present. In this case, the jogging action will only be valid for as long as the key has been pressed.
1-The JOG/REV key will act as a direction reverser. For it to work properly, the anti-reversion setting (P0-07) needs to be disabled.
Pressing the key will alternate the direction of rotation of the motor from
FWD to REV and vice-versa.
This will be indicated to the user using the F/R LED on the keypad. Please note that the FWD direction will correspond to the default direction selected in the P0-06 setting.

| | | | |
|---|---|---|---|
| **P1-06** | Password | 0: Disable ; 1: Enable | 0 |
| **P1-07** | Set password | 1 - 9999 | 1 |

The password feature can be used to lock access to the programming parameters to prevent unauthorized changes to the same.

| | | | |
|---|---|---|---|
| **P1-08** | Frequency switch source | 0: Keypad UP / DOWN keys<br>1: Keypad encoder<br>2: AI1 (Pot input)<br>3: AI2 (Analog input)<br>4: Communication | 0 |

| | | | |
|---|---|---|---|
| **P1-09** | Reference frequency | Lower limit frequency to<br>Upper limit frequency | 0.0 Hz |

The user is given the option to switch between 2 frequency sources. This can be done by triggering the hand function by either using the HAND key on the HMI or the HAND function in the multifunction inputs. In case the value of P1-08 is stored as 0 or 1, the drive will switch to the frequency stored in P1-09.

## P2- Start and Stop parameters

| | | | |
|---|---|---|---|
| **P2-00** | Start mode | 0: Direct Start<br>1: DC Braking Start | 0 |

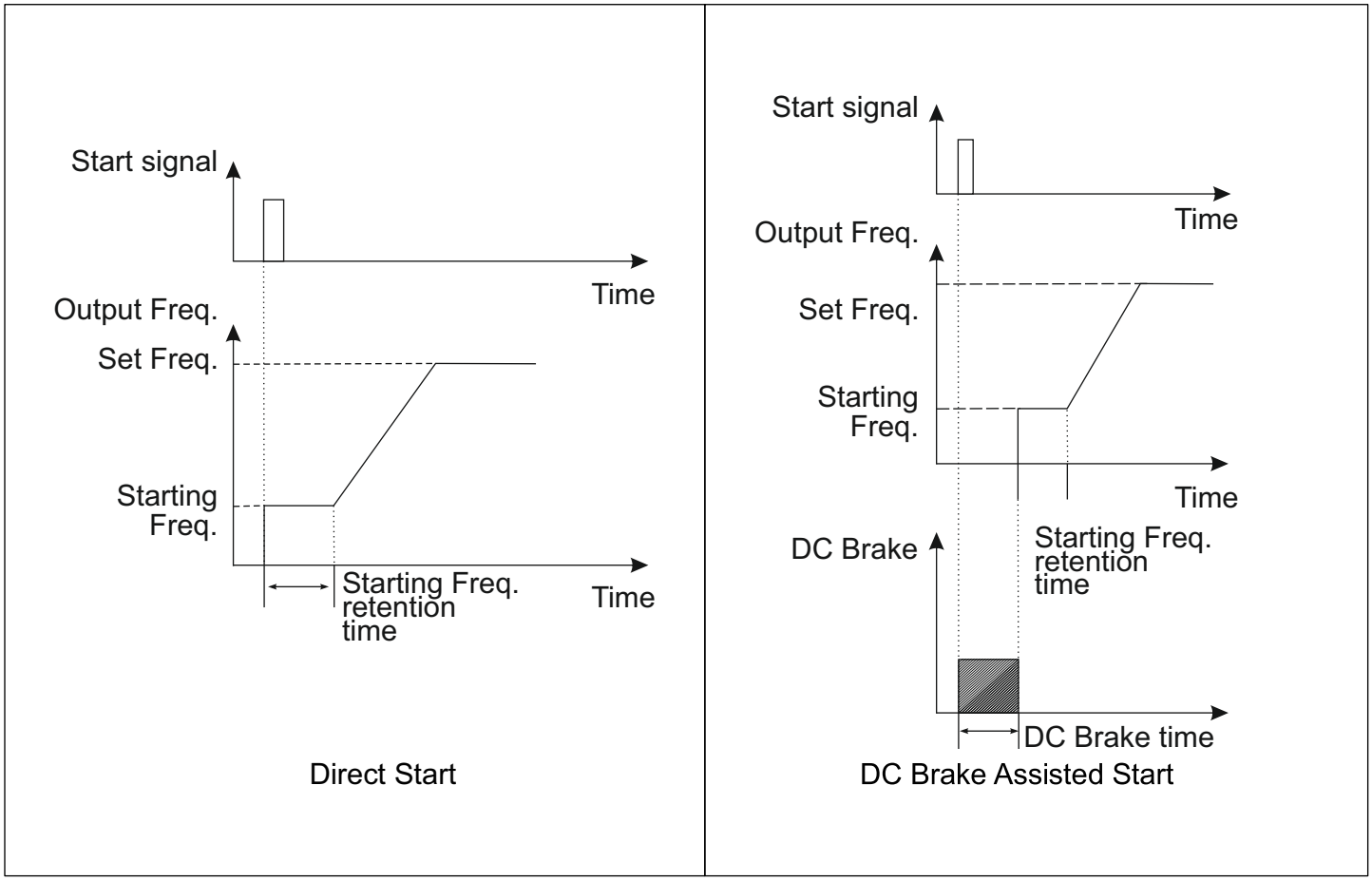



Fig.6.2 Direct Start and DC Brake Assisted Start

The start mode determines how the drive will initiate its operation when the RUN command is given through the selected control source.

0-In the direct start mode, the drive will start its operation towards the set frequency value directly.

1-In the DC Braking start mode, the drive will first inject a DC Current into the motor to hold it in place. This will be followed by the running operation towards set frequency. This technique is used in conditions where the load's inertia can cause the motor to operate in the reverse direction during startup.

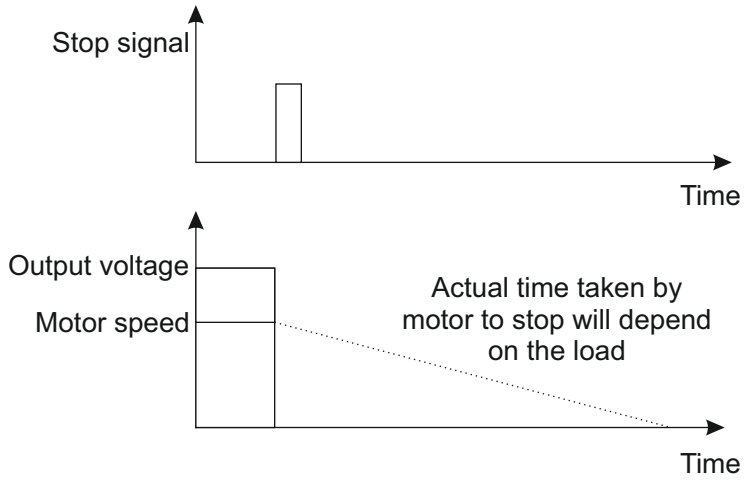
| | | | |
|---|---|---|---|
| **P2-01** | Starting frequency | Lower limiting frequency (P0-10)<br>– Upper limiting frequency (P0-09) | 0.5 Hz |
| **P2-02** | Retention time for starting | 0.0 – 50.0 s | 0 s |

Applicable starting frequency can ensure that there is enough torque for starting. Retention time for starting is needed for the formation of magnetic flow while the motor is on standby so that it can start accelerating after the start frequency is stabilized for a certain time.

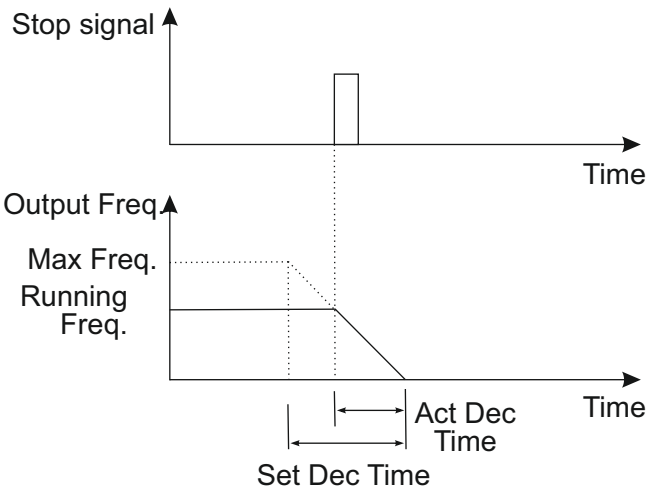
| | | | |
|---|---|---|---|
| **P2-03** | Braking current before starting | 0 – 150 % | 50 % |
| **P2-04** | Braking time before starting | 0.0 – 50.0 s | 0 s |

The braking current as a percentage of rated current determines the magnitude of the DC injection current being used during starting. The time in P2-04 determines the duration for which this current is applied.

| | | | |
|---|---|---|---|
| **P2-05** | Stop mode | 0: Coast to Stop<br>1: Ramp to Stop<br>2: DC Braking Stop | 1 |




Coast to Stop




Ramp to Stop

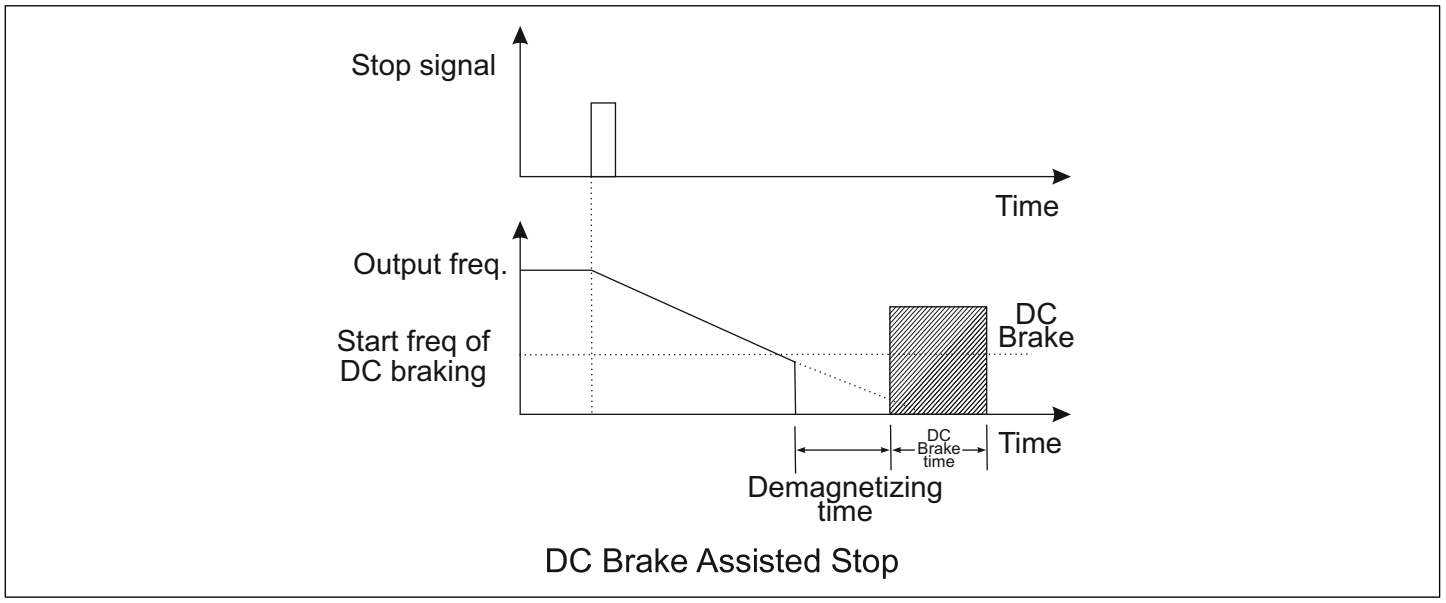



Fig.6.3 Different types of stop modes

This parameter determines how the drive executes the stopping operation

0: In coast to stop, the drive simply turns off all the output switches and the system comes to a halt purely based on the losses incurred due to friction.

1: In the ramp to stop mode, the drive decelerates the motor as per the selected deceleration time.

2: In DC Braking Stop, the drive first decelerates the motor to a preset frequency using the applicable deceleration time. This is followed by the injection of a settable DC current.

| | | | |
|---|---|---|---|
| **P2-06** | Start frequency of DC Braking | Lower Limiting Frequency (P0-10) – Upper Limiting Frequency (P0-09) | 2.0 Hz |

This parameter determines the frequency at which the ramp deceleration operation ends and DC braking operation starts.

| | | | |
|---|---|---|---|
| **P2-07** | Braking current for stopping | 0 - 150 % | 50 % |
| **P2-08** | Braking time for stopping | 0.0 – 50.0 s | 0.0 s |

Similar to starting operation, the braking current for stopping is a percentage of the motor rated current and determines the magnitude of the braking current that will be injected into the motor during stopping. The P2-08 parameter determines the duration for which this current is applied.

| | | | |
|---|---|---|---|
| **P2-09** | Demagnetizing time | 0.0 – 30.0 s | 0.1 s |

Before applying the braking current, in high inertia loads, it becomes important to allow the motor to demagnetize itself. This is done to protect the motor from drawing excessive amounts of current and damaging itself. The duration specified here is applicable post the drive has reached the P2-06 frequency and before the DC injection current is applied.

| | | | |
|---|---|---|---|
| **P2-10** | Deadtime between FWD/REV | 0.0 – 50.0 s | 0.2 s |

This parameter determines the transient time for which the drive will be at 0.0Hz when switching direction.

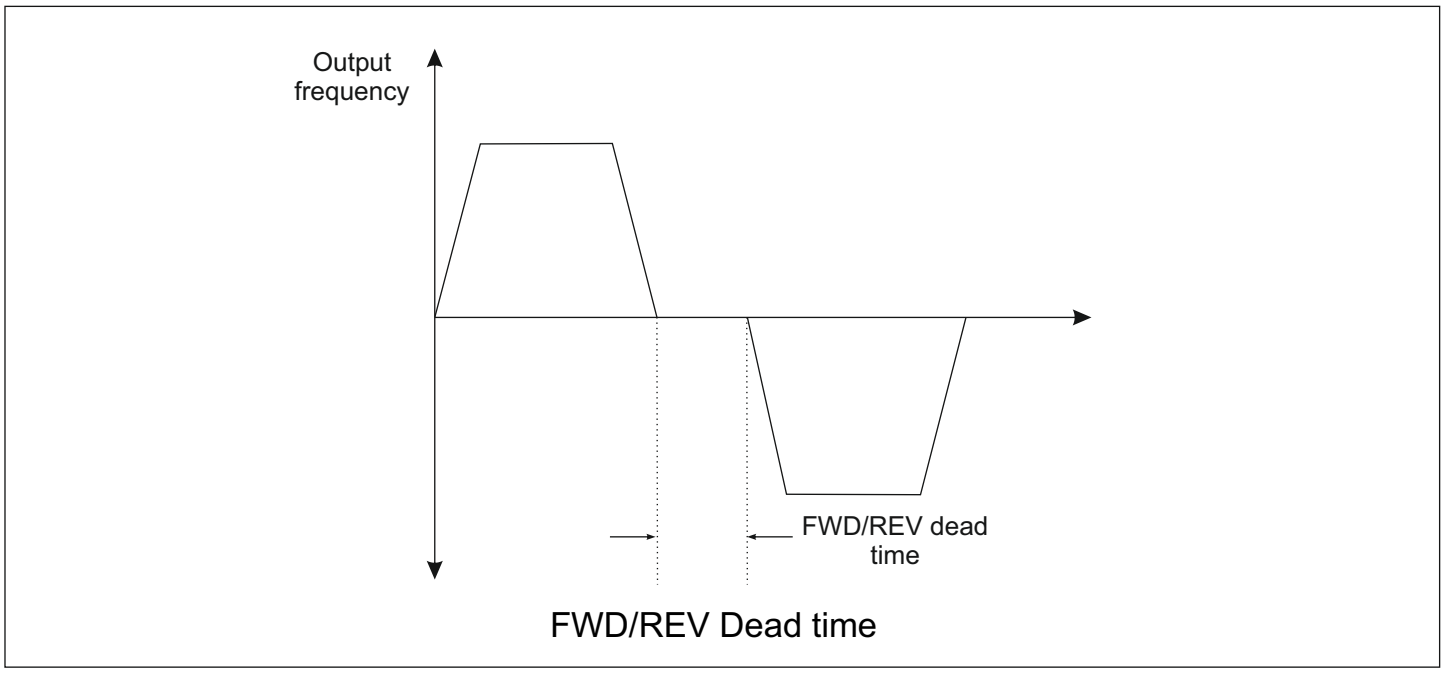



Fig.6.4 Dead Time

| | | | |
|---|---|---|---|
| **P2-11** | Lower frequency limit crossing action | 0: Running with low limit frequency<br>1: Stopping<br>2: Standby<br>3: Hibernation | 0 |
| **P2-12** | Hibernation restore delay time | Delay Time 0 – 50.0 s | 0.0 s |

This setting is used to determine the drive's operation in cases where the set frequency goes below the lower limiting frequency as set in P0-10.

0: The drive continues running with Lower Limiting frequency as the set frequency

1: The drive initiates stopping action

2: The drive enters standby mode. Here, the drive output remains in OFF condition till the set frequency goes above the lower limiting frequency

3: The drive enters hibernation mode. This is similar to standby mode as the drive turns all output switches OFF.

However, to get out of hibernation, the set frequency needs to be above the lower limiting frequency for a user settable duration as determined in the parameter P2-12.

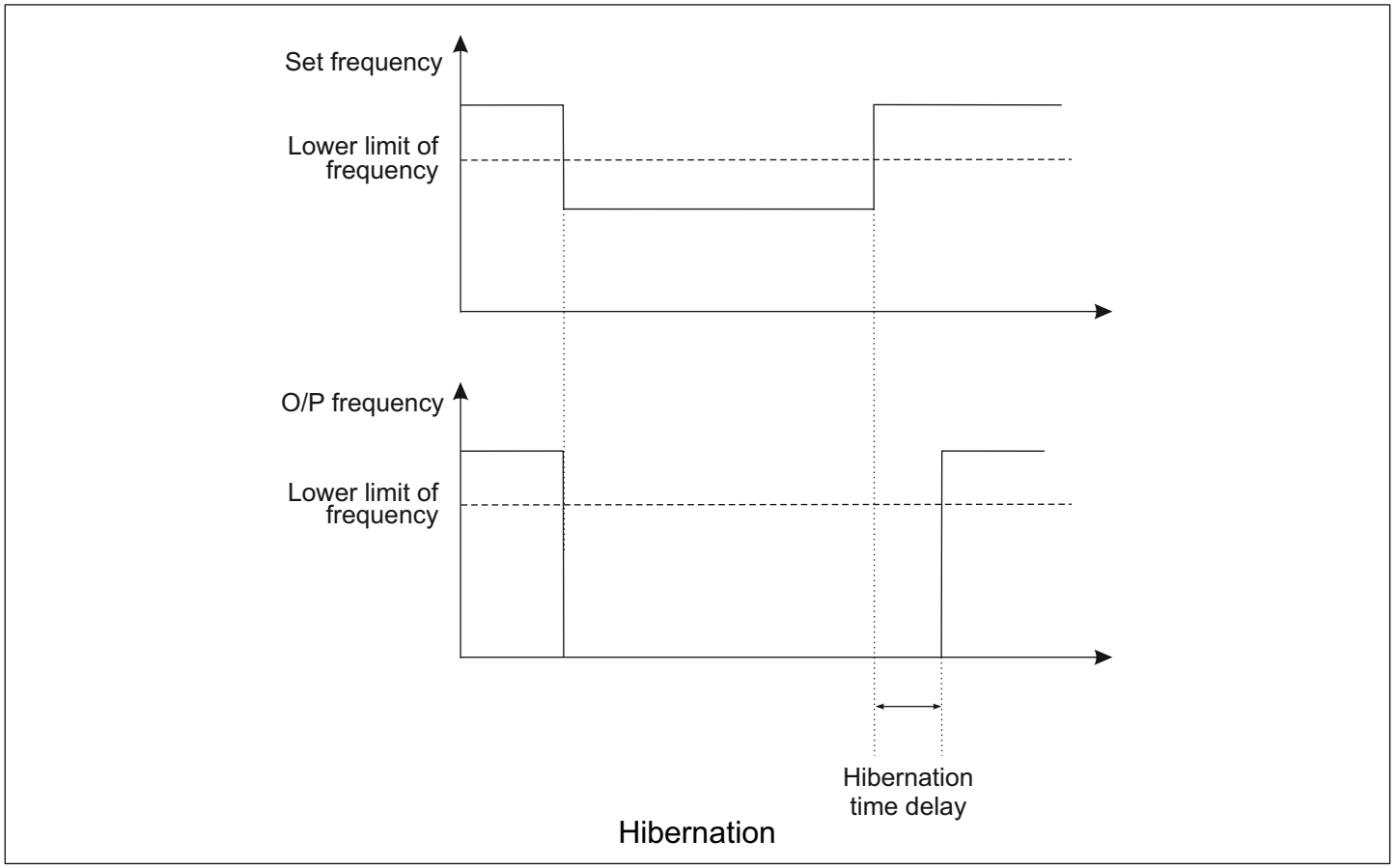



Fig.6.5 Hibernation

**P3- Motor parameters**

| | | | |
|---|---|---|---|
| **P3-00** | Rated frequency | F3 (P4-05) – 400.0 Hz | 50.0 Hz |
| **P3-01** | Rated voltage | Depends on model | Depends on model |
| **P3-02** | Rated current | Depends on model | Depends on model |
| **P3-03** | Rated power | Depends on model | Depends on model |
| **P3-04** | Rated speed | 1 – 36000 RPM | 1500 |
| **P3-05** | No of poles | 2 – 8 | 4 |
| **P3-06** | No load current | 0.1 – Rated current (P3-02) | Depends on model |
| **P3-07** | Stator resistance | Depends on model | Depends on model |
| **P3-08** | Magnetic inductance | Depends on model | Depends on model |

The motor parameters are used for all protection and control calculations. These must reflect the actual motor nameplate data for proper operation of the entire system. Incorrectness in this data can hamper the efficiency and safety of the system as a whole.

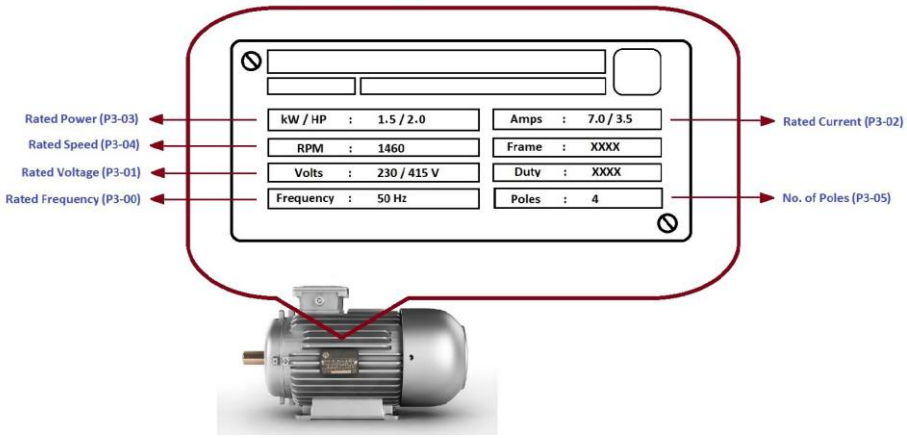



Fig.6.6 Motor Parameters

## P4- Scalar Control Parameters

| | | | |
|---|---|---|---|
| **P4-00** | V/f curve setting | 0: General V/f<br>1: 1.5 Power V/f<br>2: 1.7 Power V/f<br>3: 2 Power V/f<br>4: Multipoint V/f | 0 |

The V/f curve setting determines the profile of the V/f ratio that will be followed in the scalar operation of the drive.
In other words, it defines the nature of variation of the output voltage to the output frequency.

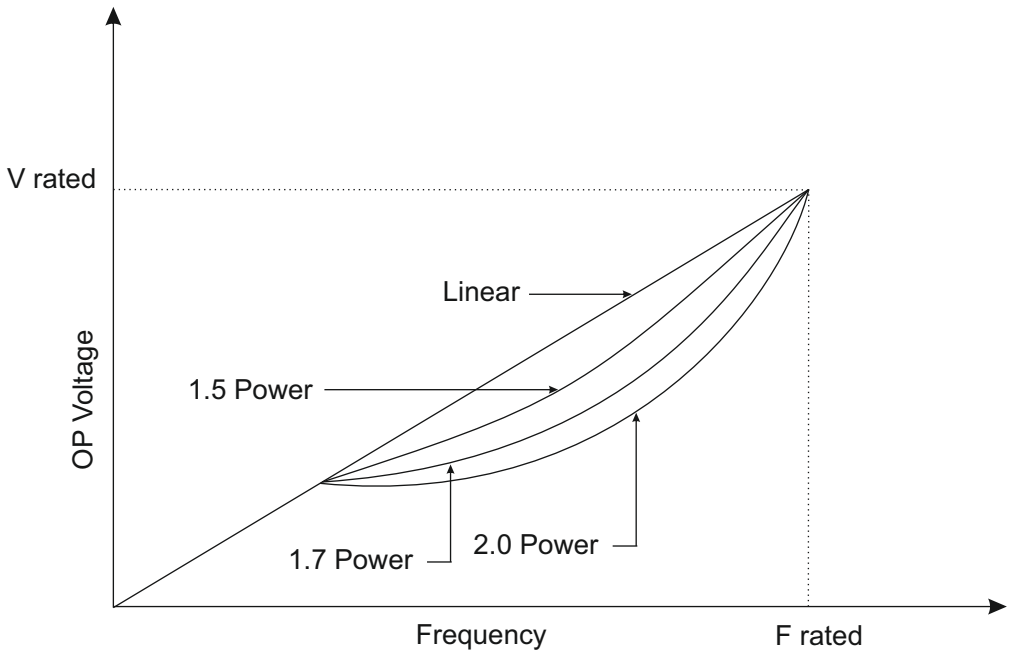



Fig.6.7 V/f Curve Settings

0: General V/f traces a linear relationship between the output voltage and frequency. It is used generally for constant load applications
1, 2, and 3: The Non-linear curves are usually used in pump and centrifugal applications and help in improving the energy efficiency of the system.
4: Multipoint V/f offers the user the option of entering a custom V/f curve using the rated Voltage and Frequency values and the user settable intermediate points in parameters P4-01 to P4-06.

| | | | |
|---|---|---|---|
| **P4-01** | V/f Intermediate frequency 1 (F1) | 0.0 Hz – F2 (P4-03) | 1.0 Hz |
| **P4-02** | V/f Intermediate voltage 1 | 0 - Rated voltage (P3-01) | 5 V |
| **P4-03** | V/f Intermediate frequency 2(F2) | F1 (P4-01) – F3 (P4-05) | 5.0 Hz |
| **P4-04** | V/f Intermediate voltage 2 | 0 - Rated voltage (P3-01) | 25 V |
| **P4-05** | V/F Intermediate frequency 3(F3) | F2 (P4-03) - Rated frequency (P3-00) | 25.0 Hz |
| **P4-06** | V/F Intermediate voltage 3 | 0 - Rated voltage (P3-01) | 115 V |

These parameters are used to provide the user with the option of a customizable V/f curve that will best suit their application. These parameters are used only when P4-00 is set to 4 i.e. Multipoint V/f.

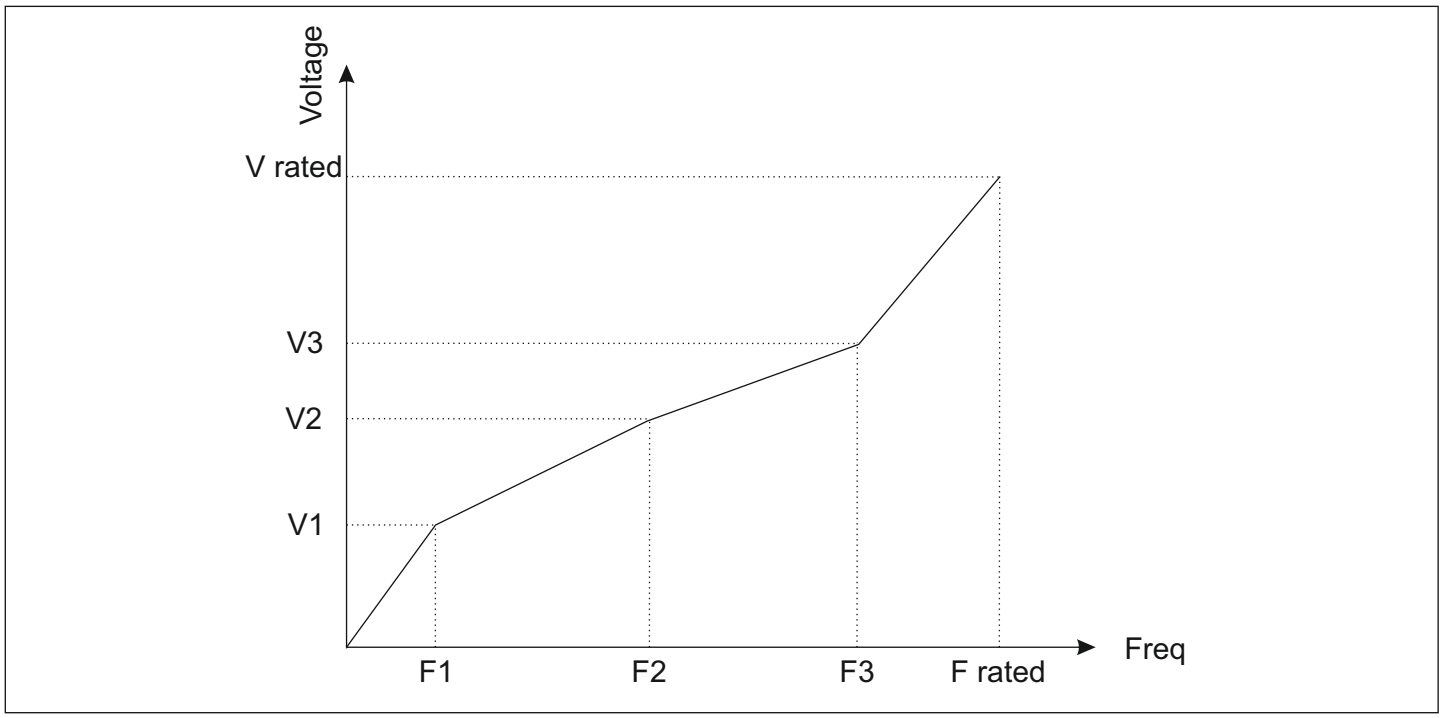



Fig.6.8 Multipoint V/f

| | | | |
|---|---|---|---|
| **P4-07** | Torque boost | 0-15.0 % | 1.00 % |

This parameter compensates for output voltage when the converter is running in the low-frequency region, to improve the low-frequency torque which is usually a drawback in scalar control schemes. However, if the setting of torque boost is too high, the motor could overheat or experience an overcurrent condition.
In general, the setting of torque upgrade must be no more than 10 %. This parameter should be increased whenever there is a heavy load; otherwise, please decrease this parameter.

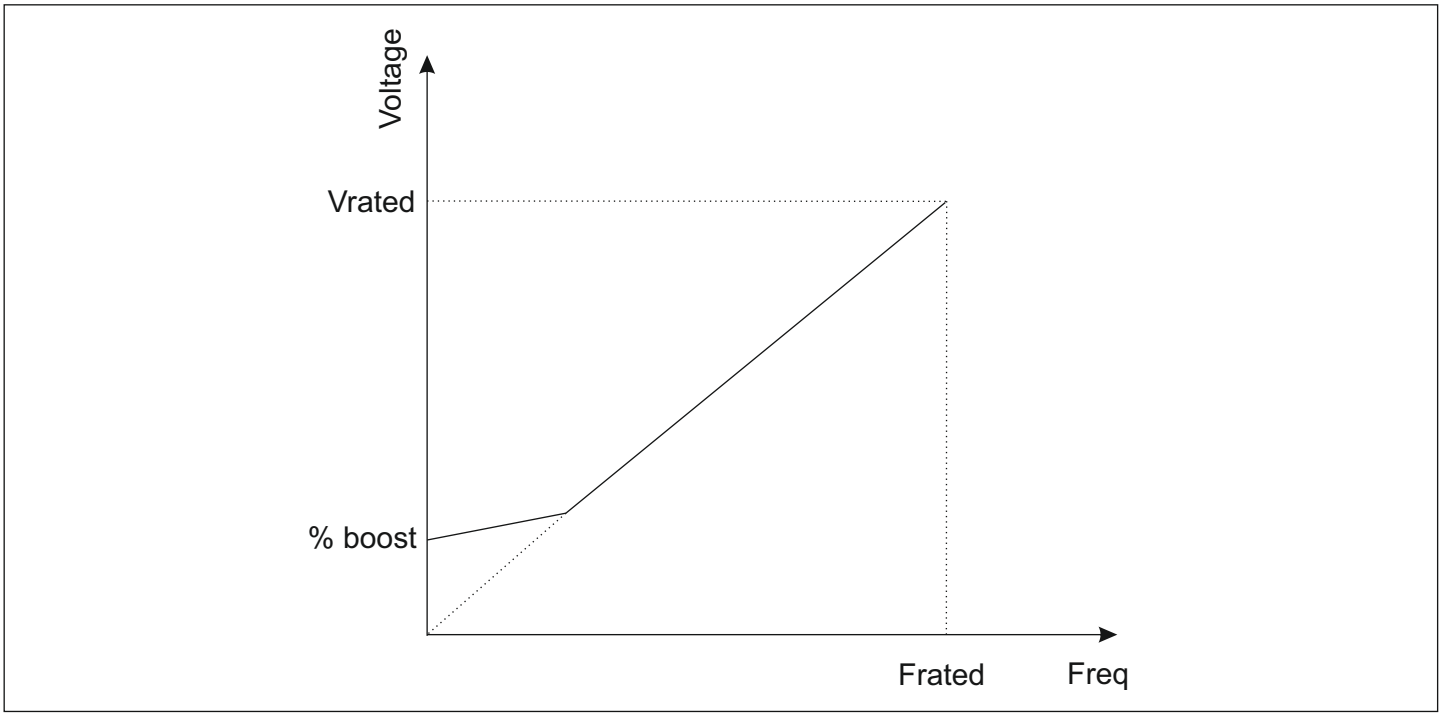



Fig.6.9 Torque Boost

| | | | |
|---|---|---|---|
| **P4-08** | AVR Function | 0 : Disabled<br>1 : Always enable<br>2 : Only enable during deceleration | 0 |

The AVR function ensures that the output voltage of the drive remains stable even in cases where the system might experience fluctuation in the grid voltage.

| | | | |
|---|---|---|---|
| **P4-09** | Energy - efficient running (EER) | 0: Disable<br>1: Enable | 0 |

In no-load and low-load conditions, the EER option helps in reducing the energy consumed by the motor by controlling the output voltage accordingly.

| | | | |
|---|---|---|---|
| **P4-10** | Braking Unit Enable | 0: Disable<br>300-400: Enable (1Ø);<br>600-700: Enable (3Ø) | 0 |

This parameter sets the DC Bus voltage reading value at which the internal braking unit is activated.

## P5- Input function parameters

| | | | |
|---|---|---|---|
| **P5-00** | Lower limit of AI1 | 0.0 – Upper limit of AI1(P5-02) | 0.5 % |
| **P5-01** | Corresponding setting of AI1 lower limit | 0.0 – Corresponding setting of AI1 Upper limit(P5-03) | 0.0 % |
| **P5-02** | Upper limit of AI1 | Lower limit of AI1(P5-00)– 100.0 % | 100.0 % |
| **P5-03** | Corresponding setting of AI1 upper limit | Corresponding setting of AI1 Lower limit(P5-01) -100% | 100.0 % |
| **P5-04** | AI1 Input filtering time | 0.0 s- 10.0 s | 0.1 s |
| **P5-05** | AI1 Signal loss threshold | 0.0 – Lower limit of AI1 (P5-00) | 0.5 % |

The functional codes above define the relationship between the analogue input signal and the corresponding variation in the set frequency value. These parameters relate specifically to the AI1 terminal i.e. the AI1 terminal. The P5-00 and P5-02 parameters define the percentage of the input signal that will be treated as the lower and upper limits for the signal received on the AI1 pin. The P5-01 and P5-03 parameters on the other hand are the corresponding limits for the set frequency values that will be mapped to the input signal. Note that P5-01 and P5-03 are defined as percentages of the Upper Limit Frequency as defined in P0-09. The relation between the AI signal and the corresponding signal has been explained in the graph below. The signal loss threshold denotes the level below which the system will consider the AI signal to be lost.

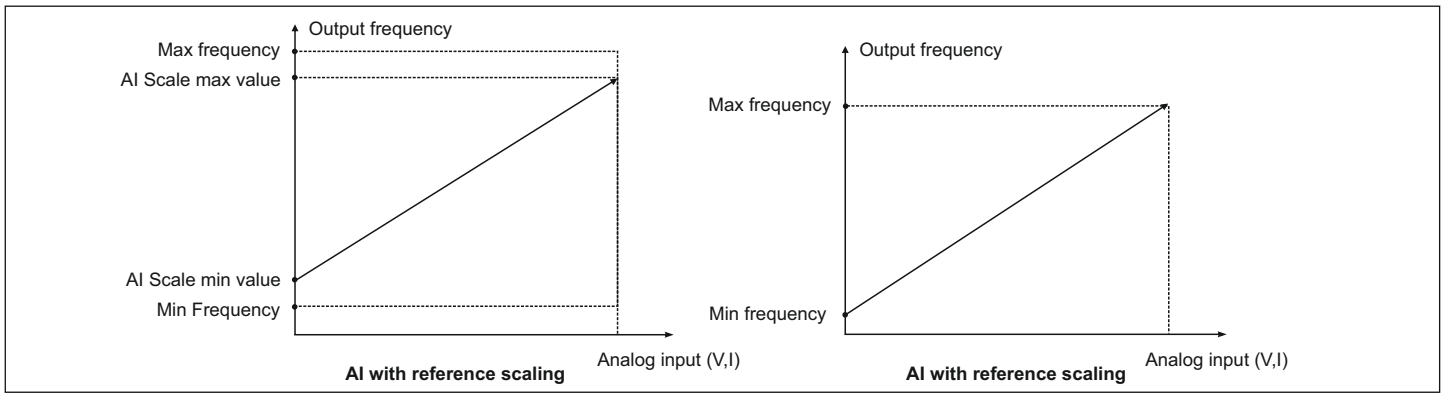
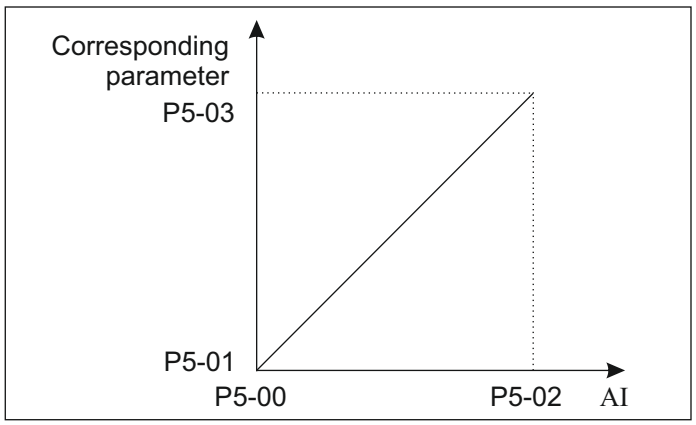



Fig.6.10 AI With and Without Scaling



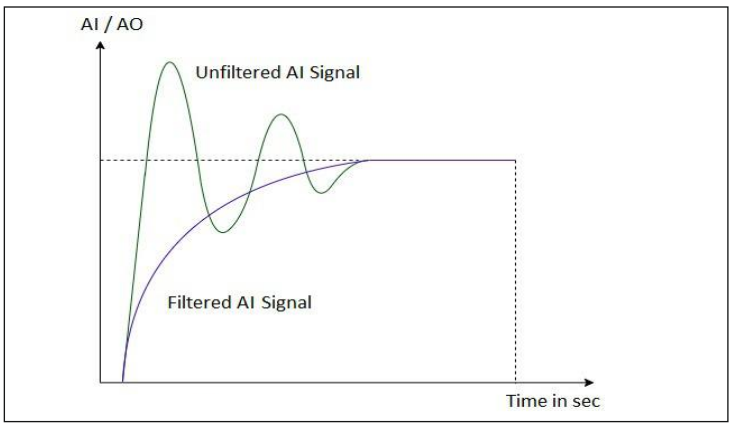




Fig.6.11 AI With and Without Filtering

| | | | |
|---|---|---|---|
| **P5-06** | Lower limit AI2 | 0.0 – Upper Limit of AI2 (P5-08) | 0.5 % |
| **P5-07** | Corresponding setting of AI2 lower limit | 0.0 – Corresponding setting of AI2 upper limit(P5-09) | 0.0 % |
| **P5-08** | Upper limit of AI2 | Lower limit of AI2 (P5-06) – 100 % | 100 % |
| **P5-09** | Corresponding Setting of AI2 Upper Limit | Corresponding setting of AI2 Lower limit (P5-07) – 100 % | 100.0 % |
| **P5-10** | AI2 Input filtering time | 0.0s- 10.0 s | 0.1 s |
| **P5-11** | AI2 Signal loss threshold | 0.0 – Lower limit of AI2 (P5-06) | 0.5 % |

Similar to the previous parameters, these parameters relate to the AI terminal. Note that this is a user-selected V/I terminal where the user has the option of selecting if they wish to give voltage or current signals by altering the position of the AI switch.

| | | | |
|---|---|---|---|
| **P5-12** | PNP/NPN Selection | 0 : NPN; 1 : PNP | 1 |

The P5-12 parameter is used to switch the polarity of the switches. Please refer to the standard wiring diagram for better clarity.

| | | | |
|---|---|---|---|
| **P5-13** | Multifunction input X1 | 0 : Disable<br>1 : Forward rotation<br>2 : Reverse rotation<br>3 : Three - wire control<br>4 : Multiphase reference velocity 1<br>5 : Multiphase reference velocity 2<br>6 : Multiphase reference velocity 3<br>7 : Multiphase reference velocity 4<br>8 : Forward JOG<br>9 : Reverse JOG<br>10 : Increasing frequency<br>11 : Decreasing frequency<br>12 : Acc- Dec time option 1<br>13 : Acc - Dec time option 2<br>14 : Stop of Acc - Dec<br>15 : External fault input<br>16 : Fault reset<br>17 : Regular stopping<br>18 : External count value input<br>19 : Count clear<br>20 : Program run<br>21 : Pause of program run<br>22 : DC Brake<br>23 : E - Stop<br>24 : Hand function | 1 |
| **P5-14** | Multifunction input X2 | | 2 |
| **P5-15** | Multifunction input X3 | | 8 |
| **P5-16** | Multifunction input X4 | | 15 |
| **P5-17** | Multifunction input X5 | | 16 |
| **P5-18** | Multifunction input X6 | | 9 |
| **P5-19** | Multifunction input X7 | | 23 |
| **P5-20** | Multifunction input X8 | | 24 |

These parameters allow the user to configure the functions for the multifunction inputs from X1 to X5. The functions are explained in the table below

<table>
<tr><th>Set value</th><th>Function</th><th>Description</th></tr>
<tr><td>0</td><td>Disabled</td><td>The input is assigned no function. Use this to check your wiring as the inputs will still be detected in the HMI page and communication address. It is advised that all unused pins are disabled to prevent any unwanted actions from taking place accidentally</td></tr>
<tr><td>1</td><td>Forward</td><td rowspan="3">Use these settings while setting up 2-wire and 3-wire control modes. These settings have been explained in depth in the explanation for parameter P5-15.</td></tr>
<tr><td>2</td><td>Reverse</td></tr>
<tr><td>3</td><td>Three Wire</td></tr>
<tr><td>4</td><td>Multiphase reference velocity 1 (S0)</td><td rowspan="3">16 levels of speed can be achieved using the multiphase reference velocity terminals.
<table>
<tr><th>S3</th><th>S2</th><th>S1</th><th>S0</th><th>Frequency</th><th>Parameter</th></tr>
<tr><td>0</td><td>0</td><td>0</td><td>0</td><td>Principal frequency</td><td>P0-03</td></tr>
<tr><td>0</td><td>0</td><td>0</td><td>1</td><td>Multiphase reference velocity 1</td><td>P8-01</td></tr>
<tr><td>0</td><td>0</td><td>1</td><td>0</td><td>Multiphase reference velocity 2</td><td>P8-02</td></tr>
<tr><td>0</td><td>0</td><td>1</td><td>1</td><td>Multiphase reference velocity 3</td><td>P8-03</td></tr>
<tr><td>0</td><td>1</td><td>0</td><td>0</td><td>Multiphase reference velocity 4</td><td>P8-04</td></tr>
<tr><td>0</td><td>1</td><td>0</td><td>1</td><td>Multiphase reference velocity 5</td><td>P8-05</td></tr>
<tr><td>0</td><td>1</td><td>1</td><td>0</td><td>Multiphase reference velocity 6</td><td>P8-06</td></tr>
<tr><td>0</td><td>1</td><td>1</td><td>1</td><td>Multiphase reference velocity 7</td><td>P8-07</td></tr>
</table></td></tr>
<tr><td>5</td><td>Multiphase reference velocity 2 (S1)</td></tr>
<tr><td>6</td><td>Multiphase reference velocity 3 (S2)</td></tr>
<tr><td>7</td><td>Multiphase reference velocity 3 (S2)</td><td>
<table>
<tr><td>1</td><td>0</td><td>0</td><td>0</td><td>Principal frequency</td><td>P8-08</td></tr>
<tr><td>1</td><td>0</td><td>0</td><td>1</td><td>Multiphase reference velocity 8</td><td>P8-09</td></tr>
<tr><td>1</td><td>0</td><td>1</td><td>0</td><td>Multiphase reference velocity 9</td><td>P8-10</td></tr>
<tr><td>1</td><td>0</td><td>1</td><td>1</td><td>Multiphase reference velocity 10</td><td>P8-11</td></tr>
<tr><td>1</td><td>1</td><td>0</td><td>0</td><td>Multiphase reference velocity 11</td><td>P8-12</td></tr>
<tr><td>1</td><td>1</td><td>0</td><td>1</td><td>Multiphase reference velocity 12</td><td>P8-13</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>0</td><td>Multiphase reference velocity 13</td><td>P8-14</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>1</td><td>Multiphase reference velocity 14</td><td>P8-15</td></tr>
</table></td></tr>
<tr><td>8</td><td>Forward Jog</td><td>Triggers forward jogging operation.</td></tr>
<tr><td>9</td><td>Reverse Jog</td><td>Triggers reverse jogging operation</td></tr>
<tr><td>10</td><td>Increase frequency</td><td rowspan="2">The input terminals are used to increase or decrease the set frequency value.<br>The step size is decided by parameter P5-17. The frequency source (P0-01) has to be set to either 5 or 6.</td></tr>
<tr><td>11</td><td>Decrease frequency</td></tr>
<tr><td>12</td><td>Acc - Dec time option 1 (A1)</td><td rowspan="2">The input terminals can be used to choose among 4 acceleration,deceleration time options as per the table below.
<table>
<tr><th>A2</th><th>A1</th><th>Acc - Dec time option selected</th><th>Parameters</th></tr>
<tr><td>0</td><td>0</td><td>Acc - Dec time 0</td><td>P0-04 and P0-05</td></tr>
<tr><td>0</td><td>1</td><td>Acc - Dec time 1</td><td>P12-00 and P12-01</td></tr>
<tr><td>1</td><td>0</td><td>Acc - Dec time 2</td><td>P12-02 and P12-03</td></tr>
<tr><td>1</td><td>1</td><td>Acc - Dec time 3</td><td>P12-04 and P12-05</td></tr>
</table></td></tr>
<tr><td>13</td><td>Acc - Dec time option 1 (A2)</td></tr>
</table>

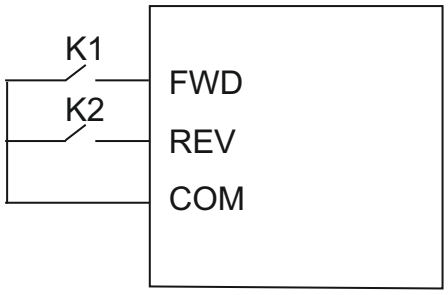
| Set Value | Function | Description |
|---|---|---|
| 14 | Stop of Acc-Dec | The terminal can be used to hold the drive at its current speed. |
| 15 | External fault input | The terminal can be used to trigger an external fault condition. |
| 16 | Fault reset | The terminal can be used to reset a fault condition.<br>The operation is similar to the RST key on the keypad. |
| 17 | Regular stopping | The input can be used to trigger a stopping action.<br>The drive will follow the stop mode as set in parameter P2-05. |
| 18 | External count value input | The input can be used to increment the internal counter. |
| 19 | Count clear | The input can be used to reset the internal counter to 0. |
| 20 | Program run | The input can be used to start the running of the Simple PLC feature. |
| 21 | Pause of program run | The input can be used to pause the running of the Simple PLC feature. |
| 22 | DC Braking | The input can be used to trigger a stopping action. In this case, irrespective of the setting in P2-05, the drive will follow the DC brake assisted stopping routine. |
| 23 | E Stop | The input can be used to trigger emergency stop |
| 24 | Hand function | The input can be used to trigger Hand operation and switch the frequency source. |

| | | | |
|---|---|---|---|
| **P5-21** | Terminal control mode | 0: Two - Wire control mode 1<br>1: Two - Wire control mode 2<br>2: Three - Wire control mode 1<br>3: Three - Wire control mode 2 | 0 |

This parameter decides the control technique that will be followed when the user selects P0-02 as 1 or 2.

0: Two - Wire control mode 1

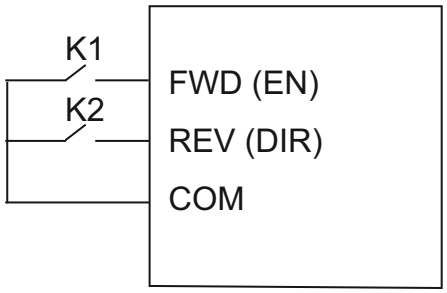
Two-wire control mode 1 is the most commonly used terminal control mode. One terminal acts to trigger FWD rotation while the other acts to trigger REV operation. The below diagram helps to illustrate this more easily -




| K1 | K2 | Command |
|---|---|---|
| 0 | 0 | Stop |
| 0 | 1 | Reverse Run |
| 1 | 0 | Forward Run |
| 1 | 1 | Continue state |

1: Two - Wire control mode 2

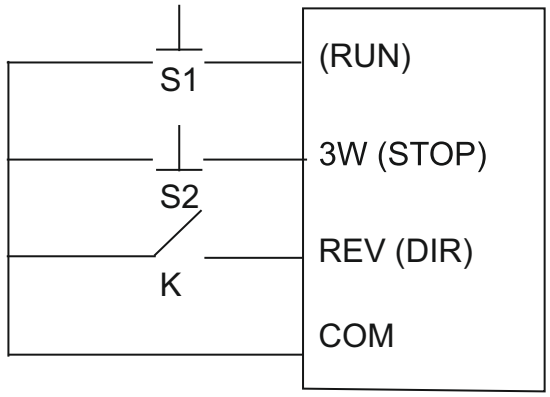
In Two - Wire mode 2, one terminal acts as an enable pin while the second terminal controls the direction. Refer to the illustration below to understand better-




| K1 | K2 | Command |
|---|---|---|
| 0 | 0 | Stop |
| 0 | 1 | Stop |
| 1 | 0 | Forward run |
| 1 | 1 | Reverse run |

2: Three - Wire control mode 1

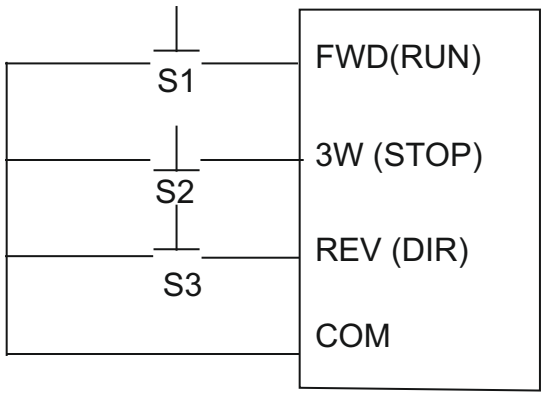
The three wire mode 1 combines a switch with 2 momentary push button. The switch is used for controlling the direction of rotation. of the 2 momentary buttons, 1 is NO and the other is NC. The NO switch is used for the RUN command while the NC switch is used for the STOP command. The illustration below explains this.




| | | |
|---|---|---|
| K | 0 | FWD |
| | 1 | REV |
| S1 | Run | |
| S2 | Stop | |

3: Three - Wire control mode 2

The three wire control mode 2 combines a switch with uses 3 momentary push button for its operation. Push button S3 is used to reverse the direction of motor. Momentary push button S1 (NO) is used for RUN command and S2 (NC) is used for the STOP command.




| | |
|---|---|
| S1 | Forward |
| S2 | Stop |
| S3 | Reverse |

| | | | |
|---|---|---|---|
| **P5-22** | Terminal filtering time | 2 ms- 100 ms | 10 ms |

This parameter allows the user to customize the debounce time being used for the multifunction input terminals. An increase in the filter time can protect the terminal from false activation in noisy environments. However, that will also adversely affect the sensitivity of the terminals.

| | | | |
|---|---|---|---|
| **P5-23** | Terminal frequency update step size | 0.0- Upper limit of frequency (P0-09) | 0.1 Hz |

This parameter defines the step size that will be used in cases where the set frequency is being updated using the multifunction input terminals.

### P6- Output function terminals

| | | | |
|---|---|---|---|
| **P6-00** | Y1 Output options | 0 : Disable<br>1 : Running<br>2 : Direction<br>3 : Fault output<br>4 : Pre - Alarm<br>5 : Standby<br>6 : Frequency arrived<br>7 : Frequency detected<br>8 : Upper limit frequency<br>9 : Lower limit frequency<br>10 : Setting count value received<br>11 : Specified count value received<br>12 : AI1 signal loss threshold reached<br>13 : AI2 Signal loss threshold reached | 1 |
| **P6-01** | Y2 Output options | | 2 |
| **P6-02** | Relay output options | | 3 |
| **P6-03** | Relay output options | | 0 |

The above parameters set the function of the transistor and relay output terminals. These functions are explained in the table below.

| Set value | Function | Description |
|---|---|---|
| 0 | Disable | The output terminal is not used for any task. |
| 1 | Running | The output terminal is used to denote that the drive is in running condition |
| 2 | Direction | The output terminal is used to denote the direction that the drive is operating in. A HIGH signal would indicate REV operation and a LOW signal would indicate FWD operation. |
| 3 | Fault output | The output terminal is used to denote the presence of a fault condition. |
| 4 | Pre - Alarm | The output terminal is used to indicate the presence of a prealarm condition |
| 5 | Standby | The output terminal is used to denote that the drive is in standby mode |

| Set value | Function | Description |
|---|---|---|
| 6 | Frequency arrived | The output terminal is used to denote the FAR condition. Refer parameter P12-14 |
| 7 | Frequency detected | The output terminal is used to denote the FDT condition. Refer parameters P12-12 and P12-13. |
| 8 | Upper limit frequency | The output terminal denotes that the drive has attained the upper limit of frequency (P0-09) |
| 9 | Lower Limit frequency | The output terminal denotes that the drive has attained the lower limit of frequency (P0-10) |
| 10 | Setting count value reached | The output terminal denotes that the internal counter has reached the setting count value (P12-15) |
| 11 | Specific count value reached | The output terminal denotes that the internal counter has reached the specific count value (P12-16) |
| 12 | AI1 Signal loss threshold reached | Denotes that the input signal at AI1 has gone below the user defined threshold value set in parameter P5-05 |
| 13 | AI2 Signal loss threshold reached | Denotes that the input signal at AI2 has gone below the user defined threshold value set in parameter P5-11 |

| | | | |
|---|---|---|---|
| **P6-04** | AO Options | 0 : Operating frequency, 1 : Output current<br>2 : Bus voltage, 3 : Output voltage | 0 |

The setting in P6-02 specifies which parameter will be used to scale the analogue output signal. The corresponding range of the individual parameters is as under-

| Set value | Function | Description |
|---|---|---|
| 0 | Operating frequency | 0 to Upper limit frequency (P0-09) |
| 1 | Output current | 0 to Twice the rated current (P3-02) |
| 2 | Bus voltage | 0 to 400 V (in case of 230 VAC units)<br>OR<br>0 to 700 V (in case of 415 VAC units) |
| 3 | Output voltage | 0 to rated voltage (P3-01) |

| | | | |
|---|---|---|---|
| **P6-05** | AO correction coefficient | 0.0 to 250.0 % | 100.0 % |

This parameter can be used to adjust the gain of the analogue output for field calibration. The actual analogue output will be calculated as

Analogue Output=Calculated Analogue value×P6−03

| | | | |
|---|---|---|---|
| **P6-06** | AO Current range selection | 0: 0~20 mA;<br>1: 4~20 mA | 0 |

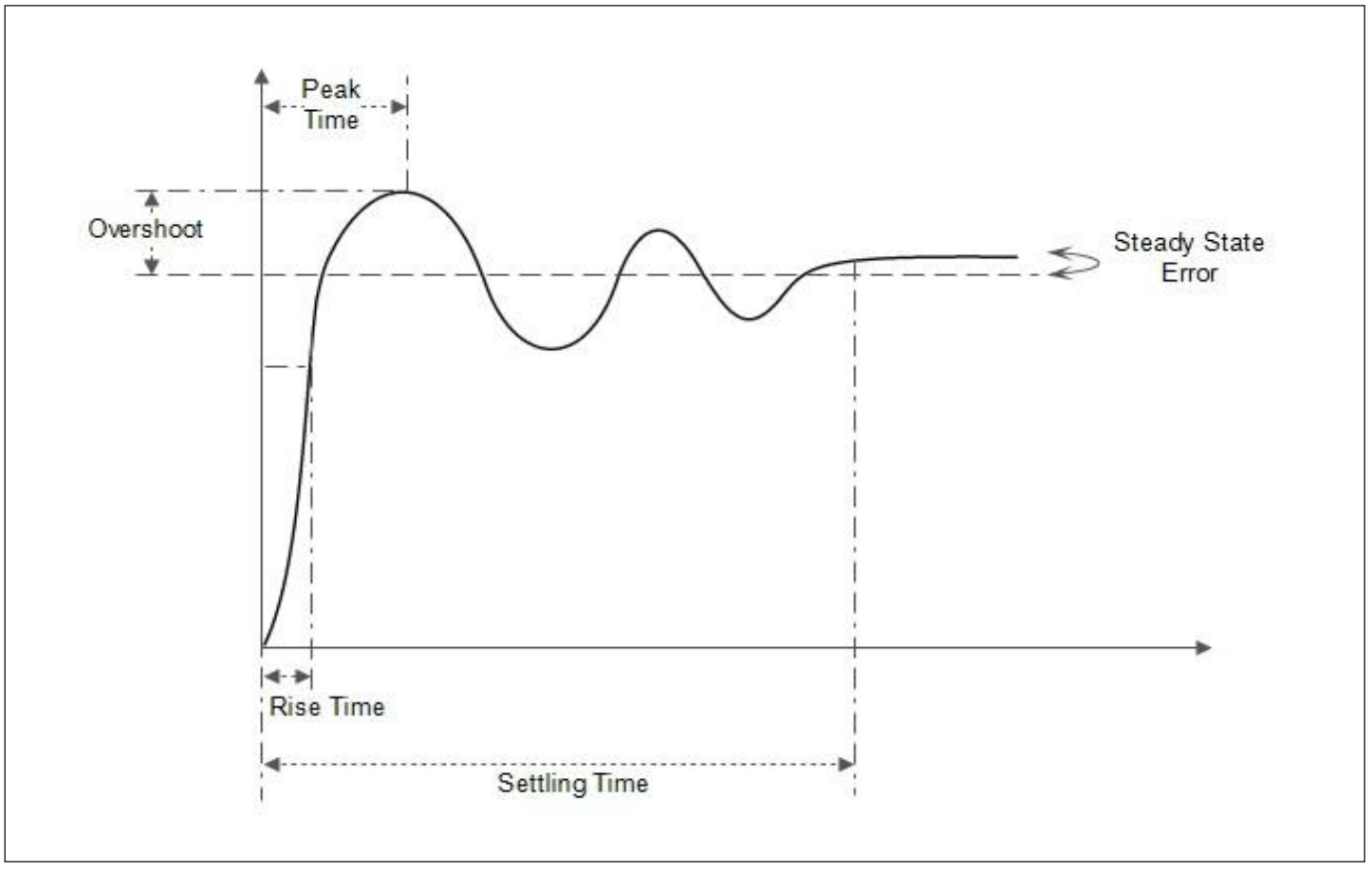
This parameter is used to change the range of the Analog output- current.

## P7 – PI Control Parameters

### Procedure to set PI values as per requirement:

The default set values for PI gain is 1.0 and for integral time is 1.0s. The first step is to start the VFD and operate on RUN mode. Check wheather the set point values are achieved within correct time intervals. If set points are not achieved within required time period, then user can reset the values of PI controller. While keeping the drive on RUN mode, slightly increase the PI gain untill the drive reaches stable operation. Once the stability is achieved, reduce the PI gain to minimize the oscillations. By increasing the value of gain, user can achieve fast response from the drive but, along with that the overshoot and settling time will also be increased. Hence it all depends on user to achieve fast responce or to achieve fast settling. The relation between PI gain and time is given in following table.

| Response | Rise time | Overshoot | Settling time | Steady state error |
|---|---|---|---|---|
| Increase gain | Decrease | Increase | No effect | Decrease |
| Increase time | No effect | Decrease | Decrease | No effect |



| | | | |
|---|---|---|---|
| **P7-00** | PI reference source | 0 : Keyboard<br>1 : Panel encoder<br>2 : AI1<br>3 : AI2 | 0 |

The PI Control parameters are used when PI control has been chosen as the frequency control source in P0-01.
Choose the source which will provide the reference value for the PI control loop.

| | | | |
|---|---|---|---|
| **P7-01** | PI reference value | 0.00 % to 100.00 % | 0.00 % |

Choose the set value for the PI control loop. This setting is used when the value in P7-00 is 0.

| | | | |
|---|---|---|---|
| **P7-02** | Feedback source | 0 : AI1 1 : AI2 | 0 |

Use this parameter to set the source of the feedback signal.

| | | | |
|---|---|---|---|
| **P7-03** | PI output characteristics options | 0 : Positive<br>1 : Negative | 0 |

Positive PI output characteristics: output frequency must be lowered to make it balance when the value of feedback signal is greater than PI set value, for example, PI control on winding tension.
Negative PI output characteristics: output frequency must be increased to make it balance when the value of feedback signal is greater than PI set value, for example, PI control on unwinding tension.

| | | | |
|---|---|---|---|
| **P7-04** | Proportional gain | 0.0 to 10.0 | 1.0 |
| **P7-05** | Integral time | 0.0 to 100.0 s | 1.0 s |

**Proportional gain (P)** determines the intensity of adjustment of PI regulator; the larger P-value is, the higher the intensity of adjustment will be.
**Integral time (I)** determines the speed of integral regulation on the difference between PI feedback quantity and given quantity. The less integral time is, the higher the intensity of adjustment will be.
PI is the most common control method for process control; the function of each part is different from the other.
Please refer to the following brief introduction of operating principles and regulation methods:
**Proportional gain (P) :** There will be a proportional adjustment between output and deviation if there is a difference between feedback value and set value; if the deviation is constant, regulating variable is also constant. Proportional control responses to the change of feedback quickly; however, error control can't be proceeded only by proportional control.

The greater the proportional gain is, the smaller the adjusting speed of the system will be. But the proportional gain is excessive, it may cause vibration. The adjustment method is to extend the integral time and make the system running only by proportional control; meanwhile, the set value should be changed to observe its stable deviation (static error) between the feedback signal and given quantity; if the static error is incompatible with the change of given quantity, proportional gain can be increased continuously, for example increasing given quantity, or feedback quantity is always less than given quantity after system is stable; otherwise, please reduce it. The instruction above should be implemented repeatedly until deviation is optimized/ minimized.

**Integral time (I) :** when there is difference between feedback value and set value, regulating variable of output should be accumulated continuously; if the deviation can't be eliminated, the regulating variable should be increased continuously until there is no deviation. Deviation can be eliminated effectively by integral controller. However, overshoot may be caused repeatedly if the adjustment of integral controller is too much, which makes system unstable and even causes vibration. If vibration is caused by excessive integral action, following characteristics can be observed oscillation of feedback signal on given quantity, expanding amplitude of oscillation, even vibration. The parameter of integral time should be adjusted generally from maximum value to minimum value so that the integral time can be changed gradually. Observation should be made on the effect on the system. Adjustment can't be stopped until the sable speed of system meets the requirements

| | | | |
|---|---|---|---|
| **P7-06** | Deviation limit | 0.0 to 20.0 | 2.0 |

Deviation limit of PI control defines the comparison between PI system output and maximum deviation value which is limited by closed-loop set value. As is shown in the graph, PI regulator is shut down while it's within deviation limit. The precision and stability of PI system can be improved by setting this function code properly.

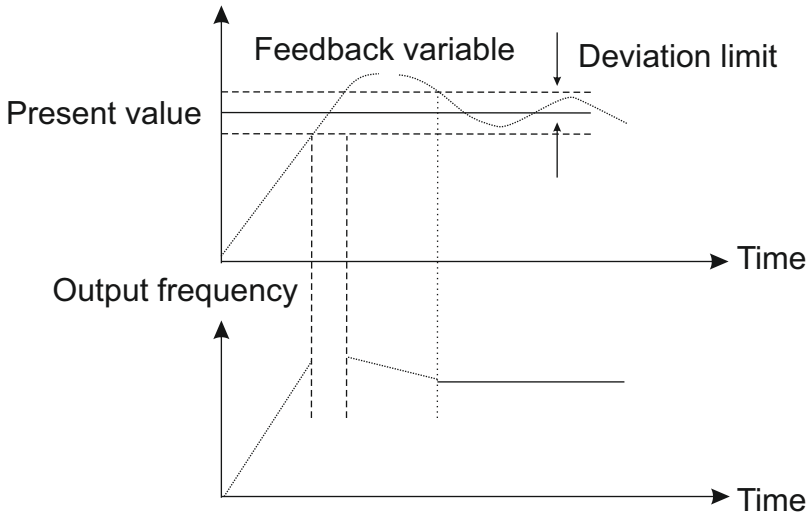



Fig.6.12 Deviation Limit

| | | | |
|---|---|---|---|
| **P7-07** | Sampling time | 0.1 to 100.0 s | 0.2 s |

Sampling period (T) means sampling period of feedback quantity; operation is performed by regulator once every one sampling period. The longer sampling period is, the slower response will be.

| | | | |
|---|---|---|---|
| **P7-08** | Feedback disconnection value | 0.1 % to 50.0 % | 0.1 % |
| **P7-09** | Feedback disconnection detection time | 0.1 to 100.0 s | 10.0 s |

The feedback variable of PI can be always detected by system; if feedback variable is less than the detected value of feedback dis-connection, system will consider feedback signal to be disconnected by default; if feedback variable is still less than the detected value of feedback disconnection while actual time is more than the time for detecting feedback disconnection, PIE can be detected and sent out by the system.

## P8 – Simple PLC and Multispeed parameters

| | | | |
|---|---|---|---|
| **P8-00** | Program run mode | 0: Disabled<br>1: Program stops after running for one cycle<br>2: Program runs for one cycle and then continues at last operating frequency<br>3: Circulatory running of the program | 0 |

This parameter selects how the Simple PLC program will run0: Simple PLC operation is disabled.
1: The program runs once and then the operation stops.
2: The program runs once and then continues operating at the last frequency in the sequence.
3: The program runs in a cyclic sequence continuously till deliberately stopped.

| | | | |
|---|---|---|---|
| **P8-01** | First phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 11.0 Hz |
| **P8-02** | Second phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 12.0 Hz |
| **P8-03** | Third phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 13.0 Hz |
| **P8-04** | Fourth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 14.0 Hz |
| **P8-05** | Fifth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 15.0 Hz |
| **P8-06** | Sixth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 16.0 Hz |
| **P8-07** | Seventh phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 17.0 Hz |

| | | | |
|---|---|---|---|
| **P8-08** | Eighth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 18.0 Hz |
| **P8-09** | Ninth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 19.0 Hz |
| **P8-10** | Seventh phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 20.0 Hz |
| **P8-11** | Eleventh phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 21.0 Hz |
| **P8-12** | Twelveth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 22.0 Hz |
| **P8-13** | Thirteenth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 23.0 Hz |
| **P8-14** | Seventh phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 24.0 Hz |
| **P8-15** | Fifteenth phase speed | Lower limiting frequency (P0-10)<br>Upper limiting frequency (P0-09) | 25.0 Hz |

The parameters above determine the 15 phase speeds in the simple PLC program. The principal frequency is set in parameter P0-03.

| | | | |
|---|---|---|---|
| **P8-16** | The runtime of principal frequency | 0.0-6400.0 | 0.0 |
| **P8-17** | First phase time | 0.0-6400.0 | 0.0 |
| **P8-18** | Second phase time | 0.0-6400.0 | 0.0 |
| **P8-19** | Third phase time | 0.0-6400.0 | 0.0 |
| **P8-20** | Fourth phase time | 0.0-6400.0 | 0.0 |
| **P8-21** | Fifth phase time | 0.0-6400.0 | 0.0 |
| **P8-22** | Sixth phase time | 0.0-6400.0 | 0.0 |
| **P8-23** | Seventh phase time | 0.0-6400.0 | 0.0 |
| **P8-24** | Eighth phase time | 0.0-6400.0 | 0.0 S |
| **P8-25** | Ninth phase time | 0.0-6400.0 | 0.0 S |
| **P8-26** | Tenth phase time | 0.0-6400.0 | 0.0 S |
| **P8-27** | Eleventh phase time | 0.0-6400.0 | 0.0 S |
| **P8-28** | Twelveth phase time | 0.0-6400.0 | 0.0 S |
| **P8-29** | Thirteenth phase time | 0.0-6400.0 | 0.0 S |
| **P8-30** | Fourteenth phase time | 0.0-6400.0 | 0.0 S |
| **P8-31** | Fifteenth phase time | 0.0-6400.0 | 0.0 S |

These parameters determine the time for which the frequencies set in P8-01 to P8-15 will be running. The operation is as shown in the timing diagram below.

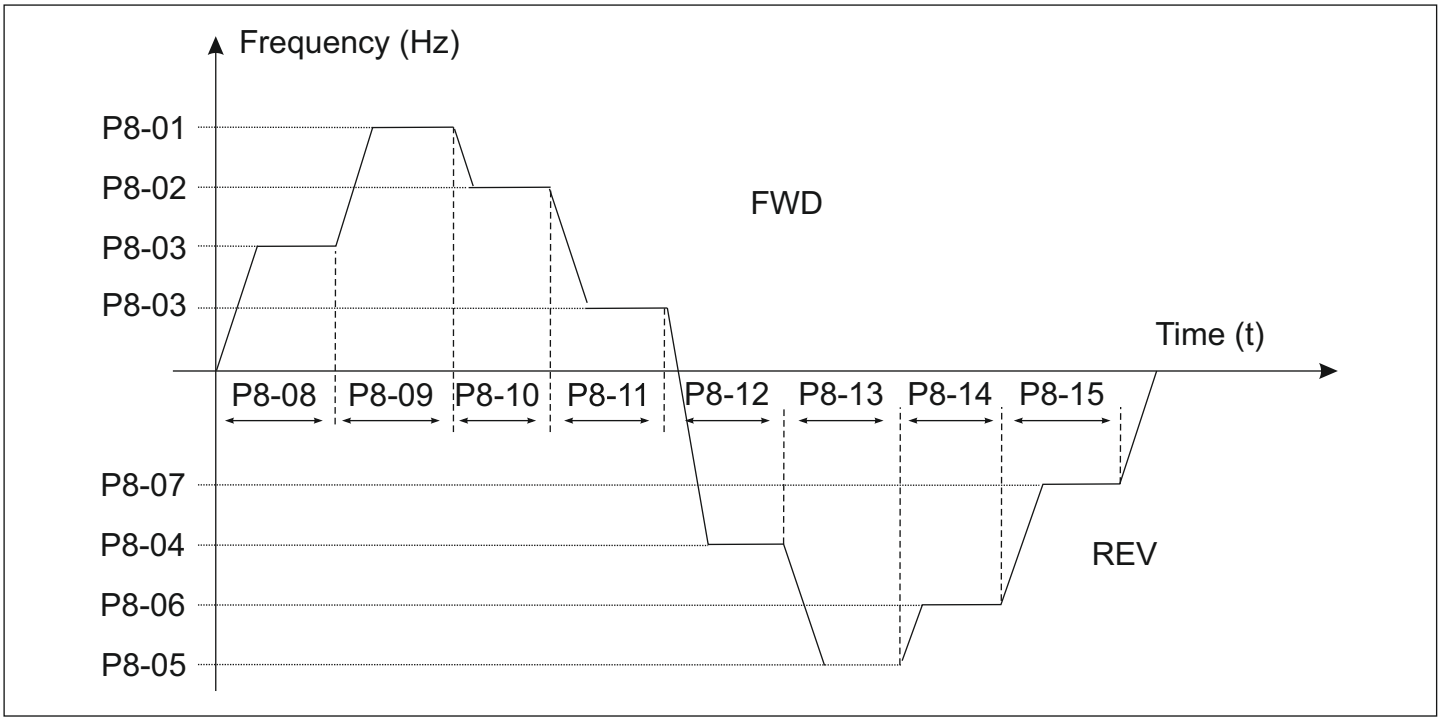



Fig.6.13 Multispeed Operation

| | | | |
|---|---|---|---|
| **P8-32** | Time unit of multi - velocity | 0: Seconds ; 1: Minutes<br>2: Hours | 0 |

The P8-32 parameter defines the time unit that will be used for the time settings in P8-17 to P8-31

| | | | |
|---|---|---|---|
| **P8-33** | Running direction of programs | 0-65535 BIT0-15 indicates directions for 0-15 (0:FWD 1:REV) | 0 |

The P8-33 parameter determines the direction that will be followed for the individual phases in the simple PLC program.

| **Weighted value** | $2^{15}$ | $2^{14}$ | $2^{13}$ | $2^{12}$ | $2^{11}$ | $2^{10}$ | $2^{9}$ | $2^{8}$ | $2^{7}$ | $2^{6}$ | $2^{5}$ | $2^{4}$ | $2^{3}$ | $2^{2}$ | $2^{1}$ | $2^{0}$ |
|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|
| **Direction (example)** | 0 | 0 | 0 | 0 | 0 | 0 | 0 | 0 | 1 | 1 | 0 | 1 | 0 | 0 | 1 | 0 |
| **Bit No.** | 15 | 14 | 13 | 12 | 11 | 10 | 9 | 8 | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 |
| **Phase No.** | 15 | 14 | 13 | 12 | 11 | 10 | 9 | 8 | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 |

Each bit in the byte corresponds to the corresponding phase in the simple PLC program as shown in the table above.
A value 0 in the bit corresponds to a FWD direction rotation while writing a value 1 to the bit will cause REV direction rotation.

In the above example, we have phases 0 (principal frequency), 2, 3, and 5 running in the forward direction while
phases 1, 4, 6, and 7 will run in the reverse direction. The parameter value comes out to be
$2^1+2^4+2^6+2^7$
i.e. 210.

| P8-34 | Acc-Dec time for each phase | 0-65535 BIT0-15 indicated acc/dec times for 0-7 | 0 |
|---|---|---|---|

| Weighted value | $2^{15}$ | $2^{14}$ | $2^{13}$ | $2^{12}$ | $2^{11}$ | $2^{10}$ | $2^{9}$ | $2^{8}$ | $2^{7}$ | $2^{6}$ | $2^{5}$ | $2^{4}$ | $2^{3}$ | $2^{2}$ | $2^{1}$ | $2^{0}$ |
|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|
| Time selection (example) | 0 | 0 | 0 | 0 | 0 | 0 | 0 | 0 | 1 | 1 | 1 | 0 | 0 | 1 | 0 | 1 |
| Bit No. | 15 | 14 | 13 | 12 | 11 | 10 | 9 | 8 | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 |
| Phase No. | 7 | | 6 | | 5 | | 4 | | 3 | | 2 | | 1 | | 0 | |

The P8-34 parameter determines the acceleration or deceleration times that will be followed for the individual phases in the simple PLC program. In the 16-bit word, every 2-bit data corresponds to the acc/dec time selection for the respective phase. The 2-bit data corresponds to 4 distinct Acc/Dec times as shown in the table below.

| MSB | LSB | Acc/Dec time selection | Parameter Code |
|---|---|---|---|
| 0 | 0 | 0 | P0-04 and P0-05 |
| 0 | 1 | 1 | P12-00 and P12-01 |
| 1 | 0 | 2 | P12-02 and P12-03 |
| 1 | 1 | 3 | P12-04 and P12-05 |

In the example given above, phases 4 through 7 will follow acc/dec times 0;phases 0 and 1 will follow acc/dec times 1; phase 2 will follow time combination 2; phase 3 will follow time 3. Converting the time selection word from binary to decimal, we get (0000000011100101)2 = (229)10, which is the value that needs to be stored in the parameter P8-34

| P8-35 | Acc-Dec time for each phase | 0-65535 BIT0-15 indicated acc/dec times for 8-15 | 0 |
|---|---|---|---|

| Weighted value | $2^{15}$ | $2^{14}$ | $2^{13}$ | $2^{12}$ | $2^{11}$ | $2^{10}$ | $2^{9}$ | $2^{8}$ | $2^{7}$ | $2^{6}$ | $2^{5}$ | $2^{4}$ | $2^{3}$ | $2^{2}$ | $2^{1}$ | $2^{0}$ |
|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|
| Time selection (example) | 0 | 0 | 0 | 0 | 0 | 0 | 0 | 0 | 1 | 1 | 1 | 0 | 0 | 1 | 0 | 1 |
| Bit No. | 15 | 14 | 13 | 12 | 11 | 10 | 9 | 8 | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 |
| Phase No. | 15 | | 14 | | 13 | | 12 | | 11 | | 10 | | 9 | | 8 | |

The P8-35 parameter determines the acceleration or deceleration times that will be followed for the individual phases in the simple PLC program. In the 16-bit word, every 2-bit data corresponds to the acc/dec time selection for the respective phase. The 2-bit data corresponds to 4 distinct Acc/Dec times as shown in the table below.

| MSB | LSB | Acc/Dec time selection | Parameter Code |
|---|---|---|---|
| 0 | 0 | 0 | P0-04 and P0-05 |
| 0 | 1 | 1 | P12-00 and P12-01 |
| 1 | 0 | 2 | P12-02 and P12-03 |
| 1 | 1 | 3 | P12-04 and P12-05 |

In the example given above, phase 12 through 15 will follow acc/dec times 0; phases 8 and 9 will follow acc/dec times 1; phase 10 will follow time combination 2; phase 11 will follow time 3. Converting the time selection word from binary to decimal, we get (0000000011100101)2 = (229)10, which is the value that needs to be stored in the parameter P8-35

## P9- Protection parameters

| | | | |
|---|---|---|---|
| **P9-00** | Overload protection enable | 0: Disable<br>1: Enable | 1 |
| **P9-01** | Critical value of overload protection | 50 – 200 % | 120 % |
| **P9-02** | Overload detection time | 0.1 to 3600.0 s | 10 s |
| **P9-03** | Overload pre-alarm enabled | 0: Disabled<br>1: Enabled | 0 |
| **P9-04** | Overload pre-alarm detection level | 50 % to Critical value of Overvoltage protection | 105 % |
| **P9-05** | Overload pre-alarm detection time | 0.1 to 3600.0 s | 0.1 s |

The Overload protection is used to provide a degree of thermal protection to the motor. The pre-alarm feature can be used to highlight that the system is approaching the critical trip state so that corrective actions can be taken accordingly. The percentage values specified in the parameters P9-01 and P9-04 correspond to the percentage of the rated power of the motor as specified in the parameter P3-03. The delay times act as ON-delay for the trip and prealarm conditions specifying that the drive will trigger the fault or pre-alarm actions after the time (P9-02 and P9-05 respectively) has elapsed.

| | | | |
|---|---|---|---|
| **P9-06** | Overvoltage protection enable | 0: Disabled<br>1: Enabled | 1 |
| **P9-07** | Critical value of OV protection | 415-475V | 460V |
| **P9-08** | Overvoltage Trip time | 0.1 to 3600.0 s | 0.1 s |
| **P9-09** | Overvoltage prealarm enable | 0: Disabled<br>1: Enabled | 0 |
| **P9-10** | Overvoltage pre-alarm detection level | 415-(P9-07) | 450V |
| **P9-11** | Overvoltage pre-alarm detection time | 0.1 to 3600.0 s | 0.1 s |

The overvoltage protection feature protects the drive from operating in ranges beyond the safe operating limits. The pre-alarm feature provides an early warning to the user for taking corrective actions before the drive executes the tripping action.

| | | | |
|---|---|---|---|
| **P9-12** | Undervoltage protection enable | 0: Disabled<br>1: Enabled | 1 |
| **P9-13** | Critical value of Under-voltage protection | 315-415V | 350V |
| **P9-14** | Undervoltage trip time | 0.1 to 3600.0 s | 1.0 s |
| **P9-15** | Undervoltage prealarm enable | 0: Disabled<br>1: Enabled | 0 |
| **P9-16** | Undervoltage pre-alarm detection level | (P9-13)-415V | 395V |
| **P9-17** | Undervoltage pre-alarm detection time | 0.1 to 3600.0 s | 0.1 s |

Undervoltage protection feature protects the drive from operating in ranges under the safe operating limits. The prealarm feature provides an early warning to the user for taking corrective actions before the drive executes the tripping action.

| | | | |
|---|---|---|---|
| **P9-18** | Overcurrent protection enable | 0: Disabled<br>1: Enabled | 1 |
| **P9-19** | Critical value of Overcurrent protection | 50-200 % | 120 % |
| **P9-20** | Overcurrent trip time | 0.1 to 3600.0 s | 5 s |
| **P9-21** | Overcurrent prealarm enable | 0: Disabled<br>1: Enabled | 0 |
| **P9-22** | Overcurrent pre-alarm detection level | 100% to (P9-19) | 105 % |
| **P9-23** | Overcurrent pre-alarm detection time | 0.1 to 3600.0 s | 0.1 s |

The overcurrent protection feature works by allowing the user to set the maximum current that the drive will source to the motor. This protects the motor windings from damage due to excessive current flow. The timings and prealarm functions operate just like other protection parameters.

| | | | |
|---|---|---|---|
| **P9-24** | Undercurrent protection enable | 0: Disabled<br>1: Enabled | 0 |
| **P9-25** | Critical value of Undercurrent protection | 20 to 90 % | 25 % |
| **P9-26** | Undercurrent trip time | 0.1 to 3600.0 s | 0.1 s |
| **P9-27** | Undercurrent prealarm enable | 0: Disabled<br>1: Enabled | 0 |
| **P9-28** | Undercurrent pre-alarm detection level | (P9-25) to 90 % | 50 % |
| **P9-29** | Undercurrent pre-alarm detection time | 0.1 to 3600.0 s | 0.1 s |

Undercurrent protection is usually used to prevent motor damage when operating certain pumps and similar applications. Please note that this feature is disabled by default.

| | | | |
|---|---|---|---|
| **P9-30** | Low power action | 0: Coast<br>1: Continue | 1 |

The low power actions can be used to continue drive operation even in cases where the supply power has degraded. It protects the system from complete shutdown but only allows limited operating speeds.

| | | | |
|---|---|---|---|
| **P9-31** | Automatic current limit | 0: Disabled<br>1: Enabled | 0 |
| **P9-32** | Automatic current limit level | 50 – 180 % | 150 % |

In cases where the motor acceleration has been set as too high, there is a possibility of the drive facing overcurrent faults. The automatic current limit feature helps mitigate those conditions by holding the speed of the motor till the current value becomes lesser than the threshold value. This feature is usually useful in cases where the starting load may not be constant and the user wants to extract the fastest acceleration.

## P10- Fault History

The fault history section helps in analysing the faults faced by the drive.

| | | | |
|---|---|---|---|
| **P10-00** | Previous fault code | 0-20 | 0 |
| **P10-01** | 2nd to previous fault code | 0-20 | 0 |
| **P10-02** | 3rd to previous fault code | 0-20 | 0 |

These addresses store the fault codes of the previous 3 faults faced by the drive. A summary of the fault codes can be found in Appendix A which deals with fault handling and troubleshooting.

| | | | |
|---|---|---|---|
| **P10-03** | Previous fault operating frequency | **-** | **-** |
| **P10-04** | Previous fault current | **-** | **-** |
| **P10-05** | Previous fault bus voltage | **-** | **-** |

These addresses store the operating frequency, current and bus voltage values for the previous fault.

| | | | |
|---|---|---|---|
| **P10-06** | Previous fault input state | **-** | **-** |
| **P10-07** | Previous fault output state | **-** | **-** |

These address store the status of the input and output terminals at the time of fault generation.

## P11- Communication parameters

| Fun. Code | Description | Settings and Range | Default Value |
|---|---|---|---|
| **P11-00** | Slave address | 1-127 | 1 |
| **P11-01** | Communication baud rate | 0: 1200 ; 1: 2400 ; 2: 4800 ;<br>3: 9600 ; 4: 19200 ; 5: 38400 ;<br>6: 57600 ; 7: 115200 | 3 |
| **P11-02** | Modbus data format | 0: 8-N-1; 1: 8-N-2; 2: 8-E-1<br>3: 8-E-2; 4: 8-O-1; 5: 8-O-2 | 0 |
| **P11-03** | Response delay | 0- 200 ms | 20 ms |
| **P11-04** | Serial timeout | 0: Disable ; 1: Time Setting | 0 |
| **P11-05** | Serial timeout time setting | 0.1- 60.0 s | 5 s |
| **P11-06** | Abnormal action selection | 0: Warn & Continue operation<br>1: Continue operation without warning<br>2: Alarm shutdown (Coast to stop)<br>3: Alarm shutdown (Ramp to stop) | 0 |

The above parameters deal with the external communication feature of the drive. The parameter P11-00 defines the slave ID that will be assigned to the VFD. Note that the drive always acts as a slave in the communication system. The parameter P11-01 defines the baud rate at which the communication system will operate. P11-02 defines the MODBUS data format that will be used. Note that these parameters need to be the same across all members of the communication system. The parameters P11-04, P11-05, and P11-06 deal with customizable timeout settings for the
user. In systems where input is expected from the master device in every set period, this feature can be used to generate a time-out action wherein one of the options from P11-06 will be performed. This action will be triggered if no data is received from the master device in the time specified in P11-05. This feature should be used only in cases where there is a continuous stream of data being transferred between the drive and the master device. Otherwise, it could trigger an unnecessary fault.

## P12 – Enhanced parameters

| | | | |
|---|---|---|---|
| **P12-00** | Acc. time 1 | 0.1 – 3600.0 s | 20.0 s |
| **P12-01** | Dec. time 1 | 0.1 – 3600.0 s | 20.0 s |
| **P12-02** | Acc. time 2 | 0.1 – 3600.0 s | 20.0 s |
| **P12-03** | Dec. time 2 | 0.1 – 3600.0 s | 20.0 s |
| **P12-04** | Acc. time 3 | 0.1 – 3600.0 s | 20.0 s |
| **P12-05** | Dec. time 3 | 0.1 – 3600.0 s | 20.0 s |

The acceleration-deceleration times 1 through 3 are defined similarly as Acceleration- Deceleration time 0 as defined in the P0 parameter family.

| | | | |
|---|---|---|---|
| **P12-06** | Jog Acc. Time | 0.1 – 3600.0 s | 5.0 s |
| **P12-07** | Jog Dec. Time | 0.1 – 3600.0 s | 5.0 s |

These 2 parameters define the acc/dec times for the jogging operation. Note that these times are also defined as the transition time between the Max Frequency as defined in (P0-08) to 0Hz.

| | | | |
|---|---|---|---|
| **P12-08** | Hopping frequency 1 lower limit | Lower limit frequency (P0-10) to hopping frequency 1 upper limit (P12-09) | 0.0 Hz |
| **P12-09** | Hopping frequency 1 upper limit | Hopping frequency 1 lower limit (P12-08) to upper limit frequency (P0-09) | 0.0 Hz |
| **P12-10** | Hopping frequency 2 lower limit | Lower limit frequency (PO-10) to hopping frequency 2 upper limit (P12-11) | 0.0 Hz |
| **P12-11** | Hopping frequency 2 upper limit | Hopping Frequency 2 Lower Limit (P12-10) to upper limit frequency (P0-09) | 0.0 Hz |

Hopping action is required in cases where the VFD could drive the motor through a frequency that matches the resonant frequency of the system that is being controlled. This matching could cause the entire system to vibrate which could prove to be harmful in the long run. The hopping feature allows the user to skip through such resonant frequency values. The below diagram will make this operation clearer. Note that in case of an overlap between the 2 hopping frequency ranges, band 1 will get a higher priority.

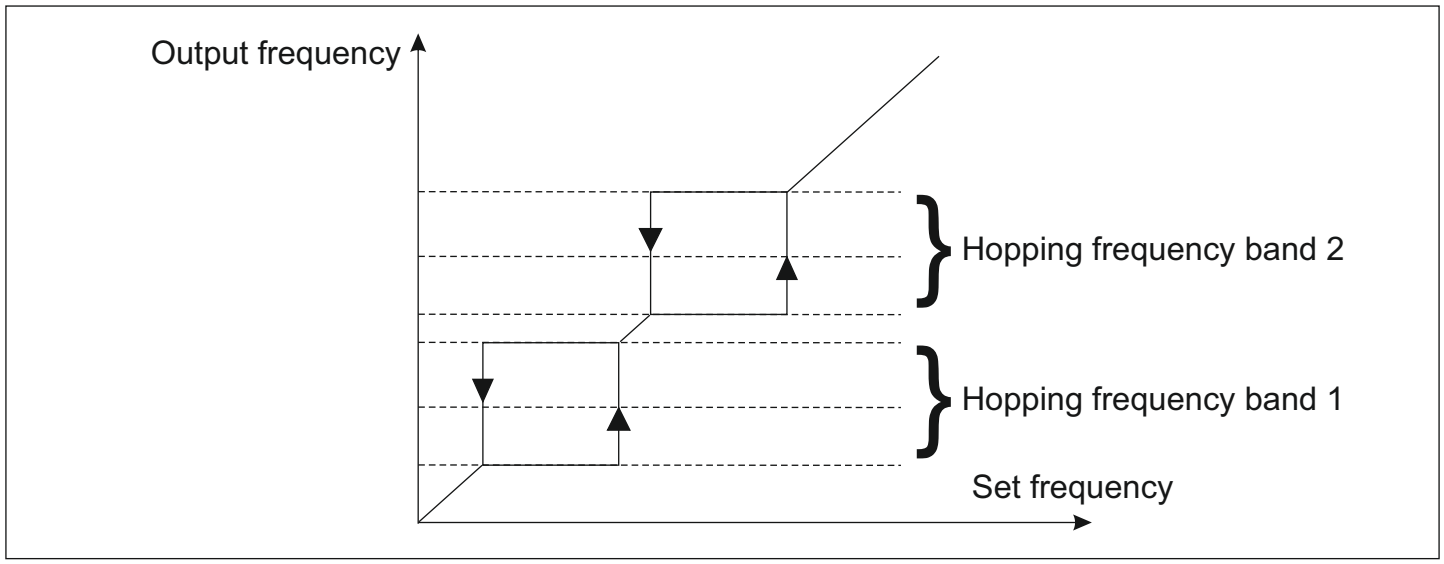



Fig.6.14 Frequency Hopping

| | | | |
|---|---|---|---|
| **P12-12** | FDT Level detection value | Lower limiting frequency (P0-10) – Upper limiting frequency (P0-09) | 0.0 Hz |
| **P12-13** | FDT Level lagged value | Lower limiting frequency (P0-10) – FDT Level detection value (P12-12) | 0.0 Hz |

These 2 parameters indicate that a particular frequency has been achieved. The operation is explained in the diagram below.

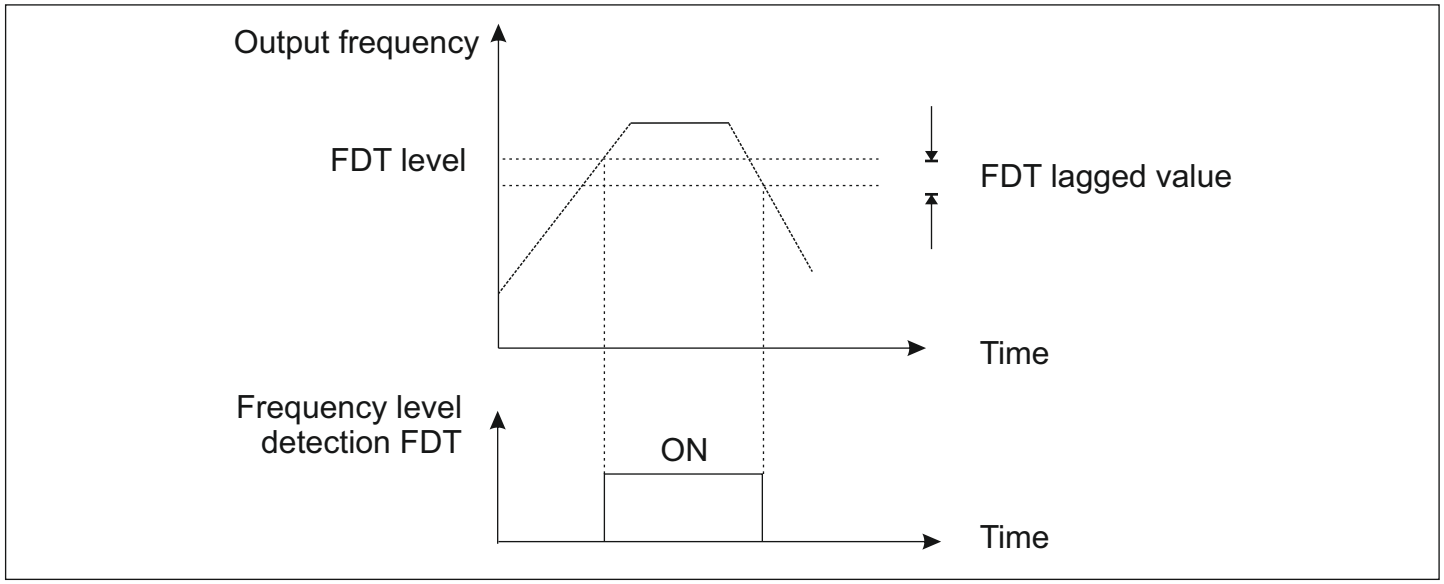



Fig.6.15 Frequency Detection Level

| | | | |
|---|---|---|---|
| **P12-14** | Amplitude of frequency arrival | Lower Limiting Frequency (P0-10) – Upper Limiting Frequency (P0-09) | 0.0 Hz |

This parameter indicates that the drive is approaching the set frequency value.

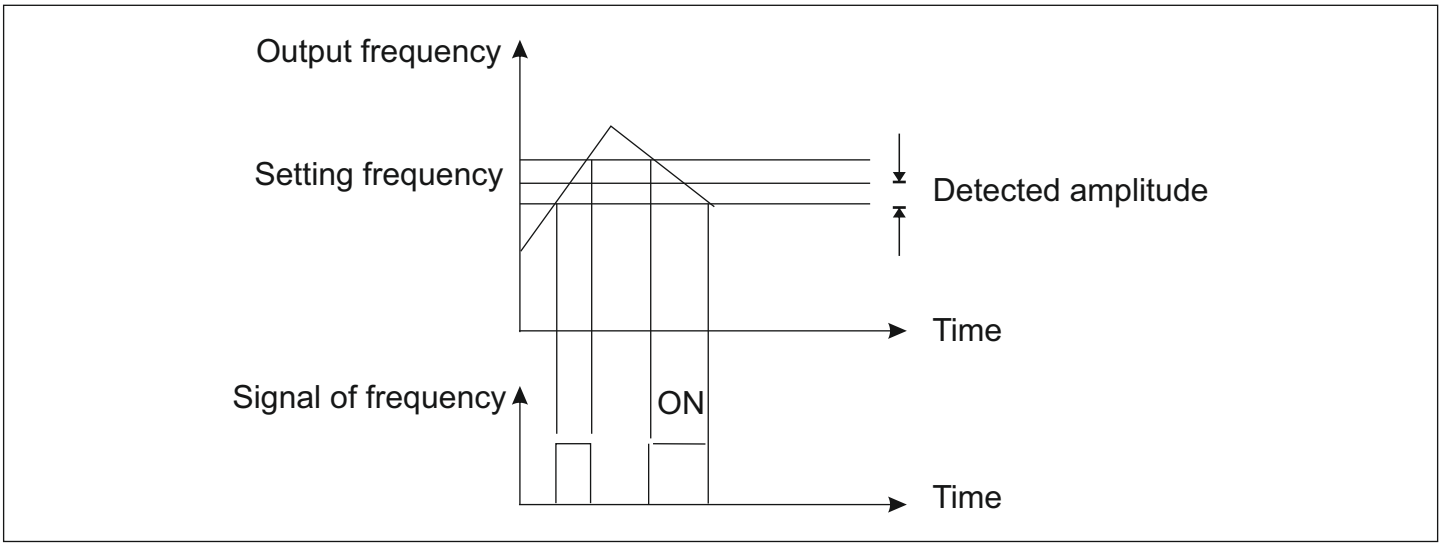



Fig.6.16 Amplitude of Frequency Arrival

| | | | |
|---|---|---|---|
| **P12-15** | Setting count | 1 – 65535 | 10 |
| **P12-16** | Specific count | 1 – Setting Count (P12-15) | 10 |

Counts of pulse or switching signal can be input by the counter through one of its multi-function DI terminals. When the count value reaches up to the setting count value, the drive will signal this using one of the DO terminals or output relays. When the count value reaches up to the specified count value, the drive will give a similar signal using one of its DO or RO terminals. The counter will not stop until it reaches up to the setting count value. Once reached though, the counter will stay there till reset.

| | | | |
|---|---|---|---|
| **P12-17** | DSP Code version | – | – |
| **P12-18** | IO Code version | – | – |
| **P12-19** | HMI Code version | – | – |

## 7. FAULT HANDLING AND TROUBLESHOOTING

### 7.1 Malfunction and solutions

| Fault code | Fault Indication | Fault description | Possible causes | Possible solutions |
|---|---|---|---|---|
| 1 | OV.t | Overvoltage fault | 1. Input voltage<br>2. Rapid deceleration<br>3. Load with heavy inertia | 1. Check input voltage is in permissible range<br>2. Increase deceleration time<br>3. Use dynamic braking resistor |
| 2 | UV.t | Under-voltage fault | 1. Input Voltage | 1. Check input voltage is in permissible range<br>2.Try changing Protection parameters (P9-12 to P9-17) |
| 3 | OC.t | Over-current fault | 1. Mismatch of capacity<br>2. Low supply voltage<br>3. Rapid acceleration/ deceleration<br>4. Heavy load fluctuations | 1. Select appropriately sized VFD<br>2. Check input voltage & wirings<br>3. Increase acceleration/ deceleration times<br>4. Detect and reduce |
| 4 | UC.t | Under-current fault | Pump operating in dry run mode | Check system operation |
| 5 | OL.t | Overload fault | 1. Similar to OC fault causes<br>2. Incorrect V/f settings<br>3. Excessive load on motor | 1. Refer to above solutions<br>2. Recheck and select appropriate settings for V/f control<br>3. Reduce load on motor |
| 6 | Ot | Overheat fault | 1. High ambient temperature<br>2. Obstruction to ventilation, fan malfunction, unclean heatsink<br>3.Excessive load on motor | 1. Lower ambient temperature<br>2. Check that the ventilation ducts are not blocked and the placement of the drive is as per instructions. Check that the fan is working. If not, contact for replacement. Check for dust/debris on heat sink and clean if dirty.<br>3. Reduce load on motor. Alternatively, reduce carrier frequency. |
| 7 | SC | Short-circuit | 1. Refer to the cases of OC fault.<br>2. Short circuit of power terminals<br>3. Damage to power module | 1. Refer to above solutions for OC fault<br>2. Check condition of wires coming to the power terminals<br>3. Seek technical support |
| 8 | nF | External Fault | 1. External fault signal received from input terminals | 1. Check input terminal settings to eliminate false alarms. In case a terminal has been set to trigger EF, check its status |

| Fault Code | Fault Indication | Fault description | Possible causes | Possible solutions |
|---|---|---|---|---|
| 9 | COn | External Communication failure | 1. Erronous communication settings<br>2. Damaged | 1. Crosscheck the communication settings across all devices communication wires connected to the network.<br>2. Check the status of the wires/ cable used for communications |
| 10 | SYS | System failure | 1. Critical damage to the system which could cause incorrect operation of the drive | 1. Ensure HMI is connected to the main drive correctly.<br>2. Contact technical support |
| 11 | PIE | PI fault | No detection of PI feedback signal for a certain time | Check on PI feedback signal and connection |

## 7.2. Common faults and processing schemes

**1. No Information display after power on:**

Please ensure that the input power supply is as per the standard rated supply required to the converter. Ensure that the three phase recitifier is in working condition. If the recitfier is damaged please seek for the technical support. Please check that the power indicator is on. If it is not, then this malfunction is caused due to abnormal rectifier and charging resisitor. If it is on but still no information is being displayed, then the fault is mainly causing by switching power supply. If the applications demand is to use the HMI externally, make sure the connectors used are properly fitted on bergs. Any loose connection between the HMI display and bergs can cause flickering or complete turn off.

**2. MCB / Switch of power supply trips when power is turned on**

Please make sure that the power supply is properly grounded or short circuited. Also make sure that the switch or MCB is in properly working condition. Solve it accordingly, if any issues persists, contact technical support

**3. Motor doesn't start running after the converter is started**

Please ensure that the three phase output supply of terminals U, V and W is symmetrical and proper. If the output supply is asymmetrical then the driver board or output model of the converter is damaged, in this case please contact to the technical support team. If the output is proper and symmetrical and even afterwards if the problem is appearing, then there are higher chances that the motor is damaged itself or some part or circuit of the motor is damaged, or other mechanical problems are causing the stalling of the motor. In this case please ispect the motor carefully and solve accordingly.

**4. MCB / Switch of power supply trips while running**

Please check that is there any short circuiting between the two phases in the power module. If it is short circuited, please contact to the technical support. Another reason of occurance of this fault is due to short circuiting between motor lines or lines being grounded. If this condition is there, solve accordingly. Always connect the motor to the drive via lugs, for the ideal lugs sizes refer to the appendix.

## 8. MAINTENANCE

Only the qualified engineer is allowed to conduct maintenance for converter; please pay attention to the following precautions:

- Maintenance must be conducted only by qualified engineers in specified way
- Wait for adequate time for the capacitors to discharge completely before taking on any kind of maintenance work. It is recommended that a time of at least 3 minutes (or as specified on the drive cover, whichever is higher) is given for the discharge operation.
- Do not touch the components on the PCB directly; otherwise, components can be damaged by static
- Make sure that all the screws are fastened after the maintenance.

### 8.1. General maintenance and upkeep

Affected by environmental conditions (e.g. temperature, humidity or smog) and aging of internal components, the drive may malfunction. Therefore, routine inspection and maintenance on converter. For the detailed information of daily inspection and maintenance, please refer to the following table:

| Items | Examination period | | Check points | Criteria and maintenace |
|---|---|---|---|---|
| | Non periodic | Periodic | | |
| Environ-mental | ✓ | | 1. Temperature & Humidity<br>2. Dust, abnormal gases | 1. Temperature in allowable range<br>2. Dust free environment.<br>No flammable/ explosive gases in vicinity |
| Cooling system | | ✓ | 1. Installation environment<br>2. Cooling fan<br>3. Heatsink | 1. Good ventilation. No obstruction to air flow from the cooling fan.<br>2. Normal operation.<br>No abnormal noise<br>3. No dust accumulation on the heatsink |
| Drive | ✓ | | 1. Vibrations, temperature<br>2. Noise<br>3.Leads and terminals | 1. Unit stable during operation. Temperature rise within control<br>2. No abnormal noise from unit<br>3. All terminals fastened correctly. No stray wires. |
| Motor | ✓ | | 1. Vibrations, temperature rise<br>2. Noise | 1. Stable operation and temperatures<br>2. No abnormal noise from the motor during operation |

### 8.2. Inspection and replacing damaged parts

As for some of internal components, abrasion or performance degradation may be caused during use. To ensure stable and reliable operation, preventive maintenance on converter must be conducted. If necessary, please replace them:
The fan must be replaced after more than 20,000 hours of running.
The electrolytic capacitors must be replaced after approx 15,000 hours of running.

### 8.3. Storage

This product can't be taken out from box until it's about to be installed. To ensure that it's still valid for warranty and available for maintenance in the future during the period of storage, please pay attention to the following points:

- Relative humidity must be within the range between 0% and 95%; no condensation is permitted;
- Ambient temperature must be within the range between -20°C and +60°C
- Converter must be stored in a dry place where there is no dust;
- It must be protected from caustic fluids;
- It must be packed properly and put on the shelf or desk.

### 8.4. Product warranty

- The warranty period for this product is 18 months but only 12 months for final buyer. During the period, any damage or fault without any wrong operation will be our responsibility to fix.
- Maintenance fee will be charged accordingly if warranty expires.
- Regarding the faults caused by the following points, extra fee will need to be charged as service fee:

1. Fault caused by faulty operation which is not in conformity with manual or specification
2. Fault caused by unauthorized maintenance modification;
3. Damage caused during the transportation or improper safekeeping;
4. Fault caused by misuse failure

## 9. EXTERNAL COMMUNICATION

The drive features external communication on the form of MODBUS RTU over RS485 interface, which is compliant with International Communication Standards. Centralized control can be implemented by PC/PLC as well as superior controller to adapt specific requirements for applications, including setting of control command, operating frequency, modification of parameters for relevant function code, monitoring of operating status or malfunction.

### 9.1. Protocol content

Modbus, also known as serial communication protocol, has defined its frames and format during the asynchronous transmission, including the format of polling to the host, broadcast frames and response fames to slave controller. The frames generated by the host included slave address/broadcast address, executive command, data & error correction; and the response of the slave controller has the similar frames as the host, including confirmation of instructions, data feedback and error correction. If any error happens when the slave controller receives the frames, or any instruction requested by the host can't be done, it will generate a malfunction frame and send feedback to the host.

#### 9.1.1. Application mode

The drive is compatible with control network equipped with RS485 bus which has single host & multiple slave controllers.

#### 9.1.2. Bus structure

1. Hardware Interface
   RS485 hardware interface

2. Transmission mode
   Serial, asynchronous, half-duplex communication

3. System with single host and multiple slave controllers
   The range of slave address should be 1~127; the number 0 stands for broadcast communication address. Every single slave address on the network is unique, which is the foundation of Modbus serial communication.

### 9.2. Protocol instructions

The protocol of VFD-S Series Converter is a kind of serial & asynchronous communication protocol with principal and subordinate Modbus; there is only one device (host) could set up protocol (named "query /command"), and the other devices (slave) can only response to the host's "query /command" by sending data, or issue commands/instructions according to the "query /command" from the host. The host herein mainly refers to personal computer, industrial control facility or Programmable Logic Controller (PLC); and the slave herein mainly refers to the drive or the other control facilities with similar/same communication protocol. The host can not only communicate with a certain slave controller independently but also send broadcast message to all the slave controllers. As to any independent access to the host's "query /command", message (called response) must be sent out from the slave controller; however, regarding the broadcast message issued by the host, it's not necessary for the slave controller to send feedback to the host.

### 9.3. Frame structure

In the RTU mode, the format of each byte is as follow: encoding system -8-bit binary system, there are two hexadecimal characters included in every 8-bit frame (hexadecimal characters include 0~9 & A-F). The transmissionof new frame will always be restarted with a interval of 3.5 bytes transmission time. When it's connected with the Internet of which transmission rate is calculated by Baud rate, 3.5-byte transmission time is easy to be controlled. The data fields of transmission will be sent in sequence as below: slave address - operating command code - data & CRC check word; and transmission byte of each field are hexadecimal (0~9, A~F). The networking devices will always monitor the operation of communication bus; when the first domain (address information) is received, it will be confirmed again by each networking device; when the transmission of last byte is done, there will be a interval of 3.5 bytes transmission time to identify the end of this frame. After that, transmission of new frame will be started again.

| Frame format of RTU data | | | | | |
|---|---|---|---|---|---|
| MODBUDS Message | | | | | |
| Initiate; an interval of at least 3.5 bytes | Slave address | Function code | Data | Verification | Terminate; an interval of at least 3.5 bytes |

A frame message must be transmitted in a consecutive data stream; if the interval is more than 1.5-byte transmission time before transmission of the whole frame is finished, those incomplete messages will be cleared by the receiver which will take the next byte as part of address field of new frame by mistake; likewise, if the interval is less than 3.5- byte transmission time, the receiver will identify it as the extension of last frame. Because of disorder of frames, CRC value will be incorrect, which may result in malfunction.

Standard Structure of RTU Frame :

| | |
|---|---|
| Frame header | T1-T2-T3-T4 (3.5-byte transmission time) |
| Slave address | Communication address: 0~147(decimal system) /<br>(Zero stands for broadcast communication address) |
| Function domain | 0x03: reading parameters of slave controller<br>0x06: programming parameters of slave controller |
| Data field | 2*N-byte data is not only the main content of communication<br>but also the core of data exchange during the communication. |
| Checksum | Estimated value: CRC value (16BIT) |
| Frame termination | T1-T2-T3-T4 (3.5-byte transmission time) |

### 9.4 Command code and data description

#### 9.4.1 Format of No.1 address for Setting as follows, setting frequency 50Hz (P0-03)

**Host command**

| | |
|---|---|
| Frame header | 3.5 byte interval |
| Slave address | 0x01 |
| Function code | 0x06 |
| Register address | 0x0003 |
| Register information | 0x01F4 |
| Checksum | 0x79DD |
| Frame termination | 3.5 byte interval |

**Slave Response**

| | |
|---|---|
| Frame header | 3.5 byte interval |
| Slave address | 0x01 |
| Function code | 0x06 |
| Register address | 0x0003 |
| Register information | 0x01F4 |
| Checksum | 0x79DD |
| Frame termination | 3.5 byte interval |

#### 9.4.2 Format of No.1 address for reading as follows, setting frequency (P0-03)

Note: register number must be one only when reading

**Host command**

| | |
|---|---|
| Frame header | 3.5 byte interval |
| Slave address | 0x01 |
| Function code | 0x03 |
| Register address | 0x0003 |
| Register information | 0x0001 |
| Checksum | 0x740A |
| Frame termination | 3.5 byte interval |

**Slave Response**

| | |
|---|---|
| Frame header | 3.5 byte interval |
| Slave address | 0x01 |
| Function code | 0x03 |
| Register address | 0x0002 |
| Register information | 0x01F4 |
| Checksum | 0xB853 |
| Frame termination | 3.5 byte interval |

#### 9.4.3 Frame format of response error as follows, setting frequency 60Hz (P0-03)

Type of error:
01H - Data address overrun
02H - Number of data overrun & read-in data content exceeding bounds (ceiling & floor)
03H - Operating, no read-in data are permitted

**Host command**

| | |
|---|---|
| Frame header | 3.5 byte interval |
| Slave address | 0x01 |
| Function code | 0x06 |
| Register address | 0x0003 |
| Register information | 0x0258 |
| Checksum | 0x7950 |
| Frame termination | 3.5 byte interval |

**Slave response**

| | |
|---|---|
| Frame header | 3.5 byte interval |
| Slave address | 0x01 |
| Function code | 0x86 |
| Error code | 0x0002 |
| Checksum | 0xC3A1 |
| Frame termination | 3.5 byte interval |

### 9.4.4 CRC Mode

RTU frame format is mainly applied to CRC (Cyclical Redundancy Check), error detecting field based on CRC is included in the message. CRC domain can detect all the information of message, which is two bytes with 16-bit binary value included. It will be added into the message after the calculation of transmission devices. The receiver will recalculate the CRC receiving the message, and compare it with the values in the CRC domain received by devices; if the CRC value is not equivalent to another one, it proves that there is error in the transmission

CRC will write 0xFFFF in superior host, and call a program to process the consecutive 8 bytes in the message as well as the values in the register. Only 8-bit data of each character is valid to CRC, the others are all invalid, including start bit, stop bit and parity check bit.

During the operation of CRC, each of 8-bit character is exclusive (XOR) with register content separately; result will be inclined to the least significant bit(LSB) while the most significant bit will be filled with Zero. LSB will be extracted from the data for checking; if LSB is one, register will be exclusive(XOR) with preset value separately; if LSB is zero,
calculation will not be conducted. This instruction of process will repeat for 8 times; when it comes to the last bit (8th bit), the next 8-bit bytes will be exclusive(XOR) with register value again. The final value in the register is the CRC value after the calculations of all the bytes in the message.

When CRC is added into the message, lower byte will be added first, then the high byte. The simple function of CRC is as follows:

```
unsigned int crc_chk_value（unsigned char *data_value,unsigned char length）
{
	unsigned int crc_value=0xFFFF;
	int I;
	while（length--）
	{
		crc_value ^= *data_value++;
		for（i=0;i<8;i++）
		{
			if（crc_value&0x0001）
			{
				crc_value=（crc_value>>1)^0xa001;
			}
			else
			{
				crc_value =（crc_value>>1);
			}
		}
	}
	return（crc_value）;
}
```

### 9.5 Read-write rules of parameter address for function code

#### 9.5.1 Monitoring parameters

| Address | Parameter |
|---|---|
| 30000 | Set frequency |
| 30001 | Output frequency |
| 30002 | Carrier frequency |
| 30003 | Output current |
| 30004 | Output voltage |
| 30005 | Bus voltage |
| 30006 | Motor's RPM |
| 30007 | %Full load current |
| 30008 | IGBT temperature |
| 30009 | %Output power |
| 30010 | Count value |
| 30018 | Fault code |
| 30019 | DC Current reading |

#### 9.5.2 Commanding the drive over communication

The control register address is 42000. The register values and actions are mentioned in the table below. Kindly note that the control mode for running (P0-02) should be set to “3: Control over Communication” for these settings to work.

| Value | Stored action |
|---|---|
| 1 | FWD Run |
| 2 | REV Run |
| 5 | FWD Jog |
| 6 | REV Jog |

| Value | Stored action |
|---|---|
| 8 | Coast to stop |
| 9 | Normal stop |
| 10 | E-Stop |
| 15 | Fault reset |

#### 9.5.3 Drive status

The address 30016 stores the current status of the drive.

| Value | Stored action |
|---|---|
| 1 | FWD Run |
| 2 | REV Run |
| 3 | Standby |
| 4 | Fault condition |

# 10. APPENDIX

## 10.1. Braking Resistor Calculations

If the controlled motor decelerates too fast, or load jittering of the motor is too fast while the converter is running, its electromotive force will charge the internal capacitors of the converter through the converter's reverse function, which will raise the voltage of the power module and damage converter. However, this will be restrained by the converter's internal control according to the condition of loading; an additional braking resistor needs to be installed externally to release the power in a time when braking performance doesn't meet Customer requirements. External braking resistor works by consuming energy which will be consumed completely by power braking resistor; therefore, power and resistance of braking resistor must be applicable and effective. According to the application at hand, an appropriately sized resistor can be used to aid the dissipation of energy from the DC bus. Due to the energy consumption of the braking resistor, a mass of heat may be generated if the braking is performed frequently. Adequate measures must be taken to ensure safety. Our recommended values are as under –

| PRODUCT CODE | RECOMMENDED VALUE | Braking Unit |
|---|---|---|
| VFD-SH-3-050-B-415V | 350W 150 Ω | Built In |
| VFD-SN-3-075-B-415V | 500W 90 Ω | Built In |
| VFD-SH-3-075-B-415V | 500W 90 Ω | Built In |
| VFD-SN-3-100-B-415V | 800W 60 Ω | Built In |
| VFD-SH-3-100-B-415V | 800W 60 Ω | Built In |
| VFD-SH-3-150-B-415V | 1000W 47 Ω | Built In |
| VFD-SN-3-200-B-415V | 1500W 36Ω | Built In |
| VFD-SH-3-200-B-415V | 1500W 36Ω | Built In |

## 10.2. Technical specifications

| | | |
|---|---|---|
| **Power supply** | Rated input voltage / frequency | Three Phase 415V 50/60 Hz |
| | Permissible voltage fluctuation | 415 V ±15 % for Three phase |
| | Permissible frequency fluctuation | ±5 % |
| **Control chara-cteristic** | Control mode | Space Vector PWM Based Scalar Control |
| | Frequency control range | 0.1 ~ 400 Hz |
| | Frequency accuracy | Digital setting 0.01 %, Analog instruction 0.1 % (Max frequency) |
| | Frequency resolution | Digital instruction 0.1 Hz, Analog instruction 0.1 Hz |
| | Acceleration / deceleration time | 0.1 ~ 3600 Sec. Four acceleration/deceleration time settings available |
| | Multi speed running | Built-in program using Simple PLC feature |
| | Built-in PI | Easy to set up a simple Automatic control system |
| | Built-in counter | Automatically Controlled Production line can be achieved |

| | | |
|---|---|---|
| **Control chara-cteristic** | Overload capacity | For ND : 120% up to 60 Sec, 150% up to 10s, 180% up to 1 Sec (every 10 mins)<br>For HD : 150% up to 60 Sec, 180% up to 10s, 200% up to 1 Sec (every 10 mins) |
| | V/F mode | 4 pre-set V/F mode and 1 User Defined V/F program |
| | Energy efficient running | Changes the V/F curve according to the load to reduce energy consumption |
| | Automatic current limit | Handles behaviour of drive during accelerating heavy inertia loads which in other cases would cause an overcurrent condition |
| | Reduce power mode | Continues operation even when the grid is below ideal voltage levels. |
| | Automatic voltage regulation | Regulates the voltage automatically whenever there is a change in grid voltage |
| **Operation function** | Operation commands | Keypad, External terminals, External communication using MODBUS |
| | Frequency setting | Keypad Up/Down keys, Keypad encoder, External potentiometer, Analog inputs (0-20 mA/4-20 mA/0-10 V), MODBUS communication |
| | Input signal | 8 User Selectable (PNP/NPN) Multifunction Inputs |
| | Output signal | 2 User Selectable Multifunction Relay Output (250V/5A Contact), 2 User Selectable Multifunction Open Collector Output, 2 Analog Input, 1 Analog Output |
| **Protection functions** | | Over Current, Over Voltage, Under Voltage, Over - Temperature, Overload, Under Current, System Error |
| **Display** | Display parameters | Parameters setting, Running status and Fault display |
| | Display type | Removable HMI with 8 keys, 1 switch enabled encoder, 5x 7segment LED display & 7 status LEDs |
| **External comm.** | Protocol | MODBUS RTU over RS485 with a maximum baud rate of 115200 |
| **Operating conditions** | Operating environment | Temperature: -10°C ~ +55°C, Humidity: < 90 %, No condensation, IP20 |
| | Operating area | Indoor, <1000 m altitude above sea level |
| | Storage temperature | -20°C ~ +60°C |
| | Vibration | <5.9 $m/s^2$ (0.6 g) |

## 10.3 Keypad dimension

Fig.10.1 Keypad Dimension

## Product dimensions

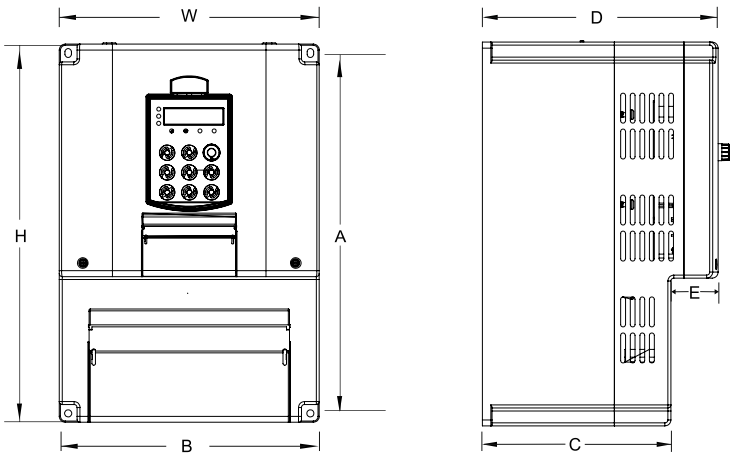



Fig.10.2 Add product Dimensions for higher variants

| Product code | Mounting dimension | | | Dimension | | | | Pore diameter | Weight |
|---|---|---|---|---|---|---|---|---|---|
| | A (mm) | B (mm) | C (mm) | H (mm) | W (mm) | D (mm) | E (mm) | (mm) | (kg) |
| H2 | 240 | 148 | 133.5 | 247 | 160 | 173 | 39.5 | 10 | 2.97 |
| | | | | | | | | | 3.08 |
| | | | | | | | | | 3.19 |
| H3 | 305 | 205 | 157 | 320 | 220 | 196.5 | | 10 | 6.30 |
| | | | | | | | | | 6.46 |
| | | | | | | | | | 6.62 |

## 10.4 Recommended choke value

The Variable Frequency Dirve (VFD) contains semiconductor devices which are sensitive to voltage and current surges and harmonics which are present in input power supply. If VFD is operated directly on line and such conditions occurs then the drive can malfunction, completely stop functioning or sometimes may get damage completely. To avoid such condition line reactors are used along with the drive. A line reactor (also refered as choke) are precisely calculated value inductors which is used as a protective device for the drive. Line reactors have ability to protect the drive from voltage and current surges and also provide protection from the harmonics to the drive. Following table contains the recommended values for the line reactors for diffrent variants of drives.

| Series: VFD-S-3 | | Selected values | |
|---|---|---|---|
| HP | Duty | Inductance (uH) | Current (A) |
| 5 | Heavy | 180 | 10 |
| 7.5 | Normal | 22 | 15 |
| | Heavy | 22 | 15 |
| 10 | Normal | 270 | 20 |
| | Heavy | 270 | 20 |
| 15 | Heavy | 750 | 30 |
| 20 | Normal | 27 | 40 |
| | Heavy | 27 | 40 |

## 10.5 Recommended lugs sizes

While operating the drive, all connections must be neat and tight. For this, it is recommended to connect the input and output wires to the drive along with the lugs. As per the terminals sizes the recommended lugs are as follows:

| Series: VFD-S-3 | | Selected values | | Current rating for Lugs & Wires |
|---|---|---|---|---|
| HP | Duty | A (mm) | B (mm) | (A) |
| 5 | Normal | 5.7 | 1.5 | 16 |
| | Heavy | 6.4 | 2.5 | 22 |
| 7.5 | Normal | 6.4 | 2.5 | 22 |
| | Heavy | 6.4 | 2.5 | 22 |
| 10 | Normal | 6.4 | 2.5 | 22 |
| | Heavy | 7.2 | 4 | 35 |
| 15 | Heavy | 7.2 | 4 | 35 |
| 20 | Normal | 7.2 | 4 | 35 |
| | Heavy | 7.2 | 4 | 35 |

## 10.6 – Recommended wire gauges

| Series: VFD-S-3 | | Selected values | |
|---|---|---|---|
| | | Wire gauge | Current rating for wires |
| HP | Duty | AWG | (A) |
| 5 | Normal | 14 | 16 |
| | Heavy | 10 | 22 |
| 7.5 | Normal | 10 | 22 |
| | Heavy | 8 | 22 |
| 10 | Normal | 10 | 22 |
| | Heavy | 8 | 35 |
| 15 | Heavy | 8 | 35 |
| 20 | Normal | 6 | 35 |
| | Heavy | 8 | 35 |

*AWG – American wire gauge