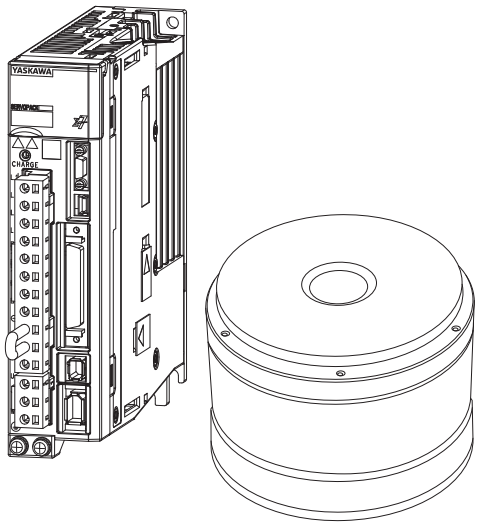
YASKAWA

Σ-7-Series AC Servo Drive

Σ-7S SERVOPACK with FT/EX Specification for Application with Special Motor, SGM7D Motor

Product Manual

Model: SGD7S-□□□□□□□A□□□F82□, -□□□□00A□□□F83□



Basic Information on SERVOPACKs 1

SERVOPACK Ratings and Specifications 2

Maintenance 3

Parameter Lists 4

MANUAL NO. SIEP S800001 91F

About this Manual

This manual describes the SGM7D motor drive application option for the Σ-7-Series AC Servo Drive Σ-7S SERVOPACKs for special motors.

Read and understand this manual to ensure correct usage of the Σ-7-Series AC Servo Drives.

Keep this manual in a safe place so that it can be referred to whenever necessary.

Outline of Manual

The contents of the chapters of this manual are described in the following table.

When you drive an SGM7D motor with a Σ-7-Series AC Servo Drive Σ-7S SERVOPACK for application with special motors, use this manual together with the relevant Σ-7-Series product manual.

◆ FT82 SERVOPACKs

Item		This Manual	Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)	Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)	Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)	Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
Basic Information on SERVOPACKs	The Σ-7 Series	–	1.1	1.1	1.1	1.1
	Product Introduction	1.1	–	–	–	–
	Interpreting the Nameplates	–	1.2	1.2	1.2	1.3
	Part Names	–	1.3	1.3	1.3	1.4
	Model Designations	1.2	–	–	–	–
	Combinations of SERVOPACKs and Servomotors	1.3	–	–	–	–
	Functions	–	1.6	1.6	1.6	1.8
	SigmaWin+	1.5	–	–	–	–
	Combining the SERVOPACKs with MP-Series Machine Controllers and the MPE720 Engineering Tool	1.6	–	–	–	–
Selecting a SERVOPACK	Ratings	2.1	–	–	–	–
	SERVOPACK Overload Protection Characteristics	–	2.1.2	2.1.2	2.1.2	2.1.2
	Specifications	2.3.1	–	–	–	–
	Block Diagrams	–	2.2	2.2	2.2	2.2
	External Dimensions	–	2.3	2.3	2.3	2.3
	Examples of Standard Connections between SERVOPACKs and Peripheral Devices	–	2.4	2.4	2.4	2.4
SERVOPACK Installation		–	Chapter 3	Chapter 3	Chapter 3	Chapter 3
Wiring and Connecting SERVOPACKs		–	Chapter 4	Chapter 4	Chapter 4	Chapter 4

Continued on next page.

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Item			This Manual	Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)	Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)	Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)	Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
Basic Functions That Require Setting before Operation			–	Chapter 5	Chapter 5	Chapter 5	Chapter 5
Application Functions			–	Chapter 6	Chapter 6	Chapter 6	Chapter 6
Trial Operation and Actual Operation			–	Chapter 7	Chapter 7	Chapter 7	Chapter 7
Tuning			–	Chapter 8	Chapter 8	Chapter 8	Chapter 8
Monitoring			–	Chapter 9	Chapter 9	Chapter 9	Chapter 9
Fully-Closed Loop Control			–	Chapter 10	Chapter 10	Chapter 10	Chapter 10
Safety Function			–	Chapter 11	Chapter 11	Chapter 11	Chapter 11
Settings for the INDEXER Module			–	–	–	–	Chapter 12
Operation with Digital I/O			–	–	–	–	Chapter 13
Operations with Serial Command Communications			–	–	–	–	Chapter 14
Maintenance	Inspections and Part Replacement		–	12.1	12.1	12.1	15.1
	Alarm Displays		3.1.1, 3.2.1, 3.3.1, 3.4.1	–	–	–	–
		List of Alarms	3.1.2, 3.2.2, 3.3.2, 3.4.2	–	–	–	–
		Troubleshooting Alarms	3.1.3, 3.2.3, 3.3.3, 3.4.3	–	–	–	–
		INDEXER Module Alarm Displays and Troubleshooting	3.4.4	–	–	–	–
		Resetting Alarms	–	12.2.3	12.2.3	12.2.3	15.2.4
		Displaying the Alarm History	–	12.2.4	12.2.4	12.2.4	15.2.5
		Clearing the Alarm History	–	12.2.5	12.2.5	12.2.5	15.2.6
		Resetting Alarms Detected in Option Modules	–	12.2.6	12.2.6	12.2.6	15.2.7
		Resetting Motor Type Alarms	–	12.2.7	12.2.7	12.2.7	15.2.8
	Warning Displays		3.1.4, 3.2.4, 3.3.4, 3.4.5	–	–	–	–
		List of Warnings	3.1.5, 3.2.5, 3.3.5, 3.4.6	–	–	–	–
		Troubleshooting Warnings	3.1.6, 3.2.6, 3.3.6, 3.4.7	–	–	–	–
		INDEXER Module Error Displays and Troubleshooting	3.4.8	–	–	–	–

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Item		This Manual	Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)	Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)	Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)	Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
Maintenance	Monitoring Communications Data during Alarms or Warnings	–	–	12.4	12.4	–
	Troubleshooting Based on the Operation and Conditions of the Servomotor	3.1.7, 3.2.7, 3.3.7, 3.4.9	–	–	–	–
Panel Displays and Panel Operator Procedures		–	Chapter 13	–	–	–
List of Parameters	Parameter Configuration	–	–	–	–	16.1
	Parameter Lists	4.1, 4.2, 4.3.1, 4.4	–	–	–	–
	List of MECHATROLINK-III Common Parameters	4.3.2	–	–	–	–
	Parameter Recording Table	–	14.2	13.2	13.3	16.3
Appendix		–	Chapter 15	Chapter 14	Chapter 14	Chapter 17

◆ FT83 SERVOPACKs

Item		This Manual	Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)	Σ-7S SERVOPACK with FT/EX Specification for Indexing Applications Product Manual (Manual No.: SIEP S800001 84)
Basic Information on SERVOPACKs	The Σ-7 Series	–	1.1	–
	Product Introduction	1.1	–	–
	Interpreting the Nameplates	–	1.2	–
	Part Names	–	1.3	–
	Model Designations	1.2	–	–
	Combinations of SERVOPACKs and Servomotors	1.3	–	–
	Functions	–	1.6	–
	SigmaWin+	1.5	–	–
	Combining the SERVOPACKs with MP-Series Machine Controllers and the MPE720 Engineering Tool	1.6	–	–
Selecting a SERVOPACK	Ratings	2.1	–	–
	SERVOPACK Overload Protection Characteristics	–	–	2.2
	Specifications	2.3.2	–	–
	Block Diagrams	–	2.2	–
	External Dimensions	–	2.3	–
	Examples of Standard Connections between SERVOPACKs and Peripheral Devices	–	2.4	–
SERVOPACK Installation		–	Chapter 3	–
Wiring and Connecting SERVOPACKs	Wiring Precautions	–	4.1	–
	Basic Wiring Diagrams	–	–	3.1
	Wiring the Power Supply to the SERVOPACK	–	4.3	–
	Wiring Servomotors	–	4.4	–
	I/O Signal Connections	–	–	3.2
	Connecting Safety Function Signals	–	4.6	–
	Connecting the Other Connectors	–	4.7	–
Basic Functions That Require Setting before Operation		–	Chapter 5	–
Application Functions		–	Chapter 6	–
Trial Operation and Actual Operation	Flow of Trial Operation	–	7.1	–
	Inspections and Confirmations before Trial Operation	–	7.2	–
	Trial Operation of Servomotor without a Load	–	7.3	–
	Trial Operation Example	–	–	4.1
	Trial Operation from the Host Controller for the Servomotor without a Load	–	7.4	–
	Trial Operation with the Servomotor Connected to the Machine	–	7.5	–
	Convenient Function to Use during Trial Operation	–	7.6	–
Tuning		–	Chapter 8	–
Monitoring	Monitoring Product Information	–	9.1	–
	Monitoring SERVOPACK Status	–	–	5.1
	Monitoring Machine Operation Status and Signal Waveforms	–	–	5.2
	Monitoring Product Life	–	9.4	–
Fully-Closed Loop Control		–	Chapter 10	–
Safety Function		–	Chapter 11	–

Continued on next page.

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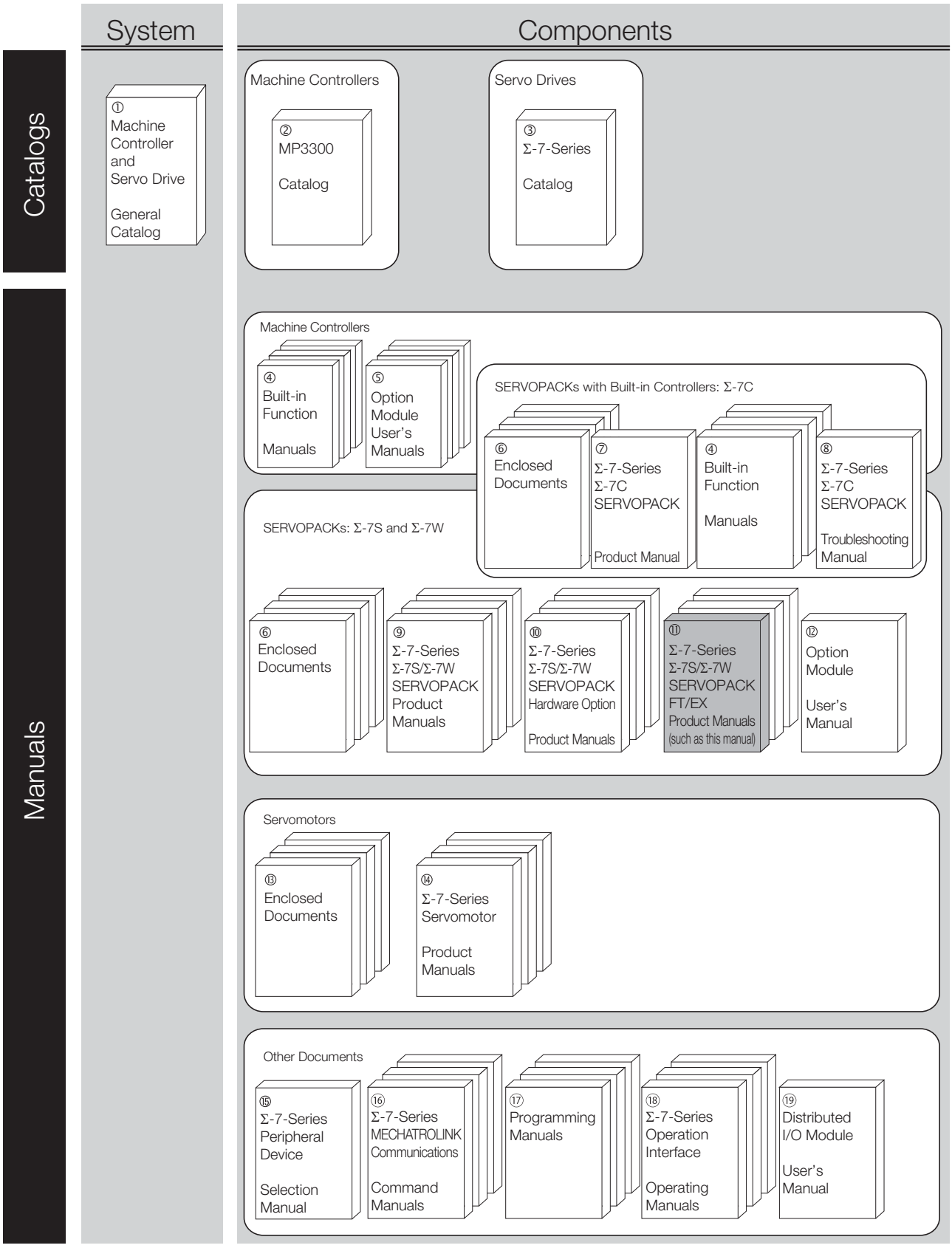
Item			This Manual	Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)	Σ-7S SERVOPACK with FT/EX Specification for Indexing Applications Product Manual (Manual No.: SIEP S800001 84)
Setting	Control Method Selection		–	–	6.1
	I/O Signal Allocations		–	–	6.2
	Moving Mode and Coordinate Settings		–	–	6.3
	Settings for References		–	–	6.4
	Origin Settings		–	–	6.5
Operation with Digital I/O	Operation Functions		–	–	7.1
	Origin Return		–	–	7.2
	Program Table Operation		–	–	7.3
	Jog Speed Table Operation		–	–	7.4
	ZONE Outputs		–	–	7.5
Maintenance	Inspections and Part Replacement		–	12.1	–
	Alarm Displays		3.5.1	–	–
		List of Alarms	3.5.2	–	–
		Troubleshooting Alarms	3.5.3	–	–
		INDEXER Module Alarm Displays and Troubleshooting	3.5.4	–	–
		Resetting Alarms	–	12.2.3	–
		Displaying the Alarm History	–	12.2.4	–
		Clearing the Alarm History	–	12.2.5	–
		Resetting Alarms Detected in Option Modules	–	12.2.6	–
		Resetting Motor Type Alarms	–	12.2.7	–
	Warning Displays		3.5.5	–	–
		List of Warnings	3.5.6	–	–
		Troubleshooting Warnings	3.5.7	–	–
		INDEXER Warning Displays and Troubleshooting	3.5.8	–	–
	Troubleshooting Based on the Operation and Conditions of the Servomotor		3.5.9	–	–
Panel Displays and Panel Operator Procedures			–	Chapter 13	–
List of Parameters	Parameter Configurations		–	–	9.1
	List of Parameters		4.5	–	–
	Parameter Recording Table		–	14.2	–
Appendix	Examples of Connections to Host Controllers		–	15.1	–
	Corresponding SERVOPACK and SigmaWin+ Function Names		–	–	10.1
	Operation of Digital Operator		–	–	10.2

Related Documents

The relationships between the documents that are related to the Servo Drives are shown in the following figure. The numbers in the figure correspond to the numbers in the table on the following pages. Refer to these documents as required.



Classification	Document Name	Document No.	Description
① Machine Controller and Servo Drive General Catalog	Machine Controller and AC Servo Drive Solutions Catalog	KAEP S800001 22	Describes the features and application examples for combinations of MP3000-Series Machine Controllers and Σ-7-Series AC Servo Drives.
② MP3300 Catalog	Machine Controller MP3300	KAEP C880725 03	Provides detailed information on MP3300 Machine Controllers, including features and specifications.
③ Σ-7-Series Catalog	AC Servo Drives Σ-7 Series	KAEP S800001 23	Provides detailed information on Σ-7-Series AC Servo Drives, including features and specifications.
④ Built-in Function Manuals	Σ-7-Series AC Servo Drive Σ-7C SERVOPACK Motion Control User's Manual	SIEP S800002 03	Provides detailed information on the specifications, system configuration, and application methods of the Motion Control Function Modules (SVD, SVC4, and SVR4) for Σ-7-Series Σ-7C SERVOPACKs.
	Machine Controller MP3000 Series Communications User's Manual	SIEP C880725 12	Provides detailed information on the specifications, system configuration, and communications connection methods for the Ethernet communications that are used with MP3000-Series Machine Controllers and Σ-7-Series Σ-7C SERVOPACKs.
⑤ Option Module User's Manuals	Machine Controller MP2000 Series Communication Module User's Manual	SIEP C880700 04	Provide detailed information on the specifications and communications methods for the Communications Modules that can be mounted to MP3000-Series Machine Controllers and Σ-7-Series Σ-7C SERVOPACKs.
	Machine Controller MP2000 Series 262IF-01 FL-net Communication Module User's Manual	SIEP C880700 36	
	Machine Controller MP2000 Series 263IF-01 EtherNet/IP Communication Module User's Manual	SIEP C880700 39	
	Machine Controller MP2000 Series I/O Module User's Manual	SIEP C880700 34	Provide detailed information on the specifications and communications methods for the I/O Modules that can be mounted to MP3000-Series Machine Controllers and Σ-7-Series Σ-7C SERVOPACKs.
	Machine Controller MP2000 Series Analog Input/Analog Output Module AI-01/AO-01 User's Manual	SIEP C880700 26	
	Machine Controller MP2000 Series Counter Module CNTR-01 User's Manual	SIEP C880700 27	

Continued on next page.

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Classification	Document Name	Document No.	Description
⑥ Enclosed Documents	Σ-7-Series AC Servo Drive Σ-7S and Σ-7W SERVOPACK Safety Precautions	TOMP C710828 00	Provides detailed information for the safe usage of Σ-7-Series SERVOPACKs.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Safety Precautions Option Module	TOBP C720829 00	Provides detailed information for the safe usage of Option Modules.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide Command Option Module	TOBP C720829 01	Provides detailed procedures for installing the Command Option Module in a SERVOPACK.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide Fully-closed Module	TOBP C720829 03	Provides detailed procedures for installing the Fully-closed Module in a SERVOPACK.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide Safety Module	TOBP C720829 06	Provides detailed procedures for installing the Safety Module in a SERVOPACK.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide INDEXER Module	TOBP C720829 02	Provides detailed procedures for installing the INDEXER Module in a SERVOPACK.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide DeviceNet Module	TOBP C720829 07	Provides detailed procedures for installing the DeviceNet Module in a SERVOPACK.
⑦ Σ-7-Series Σ-7C SERVOPACK Product Manual	Σ-7-Series AC Servo Drive Σ-7C SERVOPACK Product Manual	SIEP S800002 04	Provides detailed information on selecting Σ-7-Series Σ-7C SERVOPACKs; installing, connecting, setting, testing in trial operation, and tuning Servo Drives; writing, monitoring, and maintaining programs; and other information.
⑧ Σ-7-Series Σ-7C SERVOPACK Troubleshooting Manual	Σ-7-Series AC Servo Drive Σ-7C SERVOPACK Troubleshooting Manual	SIEP S800002 07	Provides detailed troubleshooting information for Σ-7-Series Σ-7C SERVOPACKs.

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Classification	Document Name	Document No.	Description
⑨ Σ-7-Series Σ-7S/Σ-7W SERVOPACK Product Manuals	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual	SIEP S800001 28	Provide detailed information on selecting Σ-7-Series SERVOPACKs and information on installing, connecting, setting, performing trial operation for, tuning, monitoring, and maintaining the Servo Drives.
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual	SIEP S800001 27	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual	SIEP S800001 26	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual	SIEP S800001 64	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK Command Option Attachable Type with DeviceNet Module Product Manual	SIEP S800001 70	
	Σ-7-Series AC Servo Drive Σ-7W SERVOPACK with MECHATROLINK-III Communications References Product Manual	SIEP S800001 29	
⑩ Σ-7-Series Σ-7S/Σ-7W SERVOPACK with Hardware Option Specifications Product Manuals	Σ-7-Series AC Servo Drive Σ-7S/Σ-7W SERVOPACK with Hardware Option Specifications Dynamic Brake Product Manual	SIEP S800001 73	Provide detailed information on Hardware Options for Σ-7-Series SERVOPACKs.
	Σ-7-Series AC Servo Drive Σ-7W/Σ-7C SERVOPACK with Hardware Option Specifications HWBB Function Product Manual	SIEP S800001 72	

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Classification	Document Name	Document No.	Description
⑪ Σ-7-Series Σ-7S/Σ-7W SERVOPACK FT/EX Product Manuals	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Indexing Application Product Manual	SIEP S800001 84	Provide detailed information on the FT/EX Option for Σ-7-Series SERVOPACKs.
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Tracking Application Product Manual	SIEP S800001 89	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Application with Special Motor, SGM7D Motor Product Manual	This manual (SIEP S800001 91)	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Press and Injection Molding Application Product Manual	SIEP S800001 94	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Transfer and Alignment Application Product Manual	SIEP S800001 95	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Torque/Force Assistance for Conveyance Application Product Manual	SIEP S800002 09	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Cutting Application Feed Shaft Motor Product Manual	SIEP S800002 10	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Three-Point Latching for Conveyance Application Product Manual	SIEP S800002 17	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with FT/EX Specification for Semi-/Fully-Closed Loop Control Online Switching for Conveyance Application	SIEP S800002 27	
	Σ-7-Series AC Servo Drive Σ-7W SERVOPACK with FT/EX Specification for Gantry Applications	SIEP S800002 29	
⑫ Option Module User's Manual	AC Servo Drives Σ-V Series/Σ-V Series for Large-Capacity Models/ Σ-7 Series User's Manual Safety Module	SIEP C720829 06	Provides details information required for the design and maintenance of a Safety Module.

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Classification	Document Name	Document No.	Description
⑬ Enclosed Documents	AC Servo Drive Rotary Servomotor Safety Precautions	TOBP C230260 00	Provides detailed information for the safe usage of Rotary Servomotors and Direct Drive Servomotors.
	AC Servomotor Linear Σ Series Safety Precautions	TOBP C230800 00	Provides detailed information for the safe usage of Linear Servomotors.
⑭ Σ-7-Series Servomotor Product Manuals	Σ-7-Series AC Servo Drive Rotary Servomotor Product Manual	SIEP S800001 36	Provide detailed information on selecting, installing, and connecting the Σ-7-Series Servomotors.
	Σ-7-Series AC Servo Drive Linear Servomotor Product Manual	SIEP S800001 37	
	Σ-7-Series AC Servo Drive Direct Drive Servomotor Product Manual	SIEP S800001 38	
⑮ Σ-7-Series Peripheral Device Selection Manual	Σ-7-Series AC Servo Drive Peripheral Device Selection Manual	SIEP S800001 32	Provides the following information in detail for Σ-7-Series Servo Systems. • Cables: Models, dimensions, wiring materials, connector models, and connection specifications • Peripheral devices: Models, specifications, diagrams, and selection (calculation) methods
⑯ Σ-7-Series MECHATROLINK Communications Command Manuals	Σ-7-Series AC Servo Drive MECHATROLINK-II Communications Command Manual	SIEP S800001 30	Provides detailed information on the MECHATROLINK-II communications commands that are used for a Σ-7-Series Servo System.
	Σ-7-Series AC Servo Drive MECHATROLINK-III Communications Standard Servo Profile Command Manual	SIEP S800001 31	Provides detailed information on the MECHATROLINK-III communications standard servo profile commands that are used for a Σ-7-Series Servo System.
⑰ Programming Manuals	Machine Controller MP3000 Series Ladder Programming Manual	SIEP C880725 13	Provides detailed information on the ladder programming specifications and instructions for MP3000-Series Machine Controllers and Σ-7-Series Σ-7C SERVOPACKs.
	Machine Controller MP3000 Series Motion Programming Manual	SIEP C880725 14	Provides detailed information on the motion programming and sequence programming specifications and instructions for MP3000-Series Machine Controllers and Σ-7-Series Σ-7C SERVOPACKs.

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Classification	Document Name	Document No.	Description
⑱ Σ-7-Series Operation Interface Operating Manuals	Machine Controller MP2000/MP3000 Series Engineering Tool MPE720 Version 7 User's Manual	SIEP C880761 03	Describes in detail how to operate MPE720 version 7.
	Σ-7-Series AC Servo Drive Digital Operator Operating Manual	SIEP S800001 33	Describes the operating procedures for a Digital Operator for a Σ-7-Series Servo System.
	AC Servo Drive Engineering Tool SigmaWin+ Operation Manual	SIET S800001 34	Provides detailed operating procedures for the SigmaWin+ Engineering Tool for a Σ-7-Series Servo System.
⑲ Distributed I/O Module User's Manual	MECHATROLINK-III Compatible I/O Module User's Manual	SIEP C880781 04	Describes the functions, specifications, operating methods, and MECHATROLINK-III communications for the Remote I/O Modules for MP2000/MP3000-Series Machine Controllers.

Using This Manual

◆ Technical Terms Used in This Manual

The following terms are used in this manual.

Term	Meaning
Servomotor	A Σ-7-Series Direct Drive Servomotor.
SERVOPACK	A Σ-7-Series Σ-7S SERVOPACK.
Servo Drive	The combination of a Servomotor and SERVOPACK.
Servo System	A servo control system that includes the combination of a Servo Drive with a host controller and peripheral devices.
servo ON	Supplying power to the motor.
servo OFF	Not supplying power to the motor.
base block (BB)	Shutting OFF the power supply to the motor by shutting OFF the base current to the power transistor in the SERVOPACK.
servo lock	A state in which the motor is stopped and is in a position loop with a position reference of 0.
Main Circuit Cable	One of the cables that connect to the main circuit terminals, including the Main Circuit Power Supply Cable, Control Power Supply Cable, and Servomotor Main Circuit Cable.
SigmaWin+	The Engineering Tool for setting up and tuning Servo Drives or a computer in which the Engineering Tool is installed.

◆ Notation Used in this Manual

■ Notation for Reverse Signals

The names of reverse signals (i.e., ones that are valid when low) are written with a forward slash (/) before the signal abbreviation.

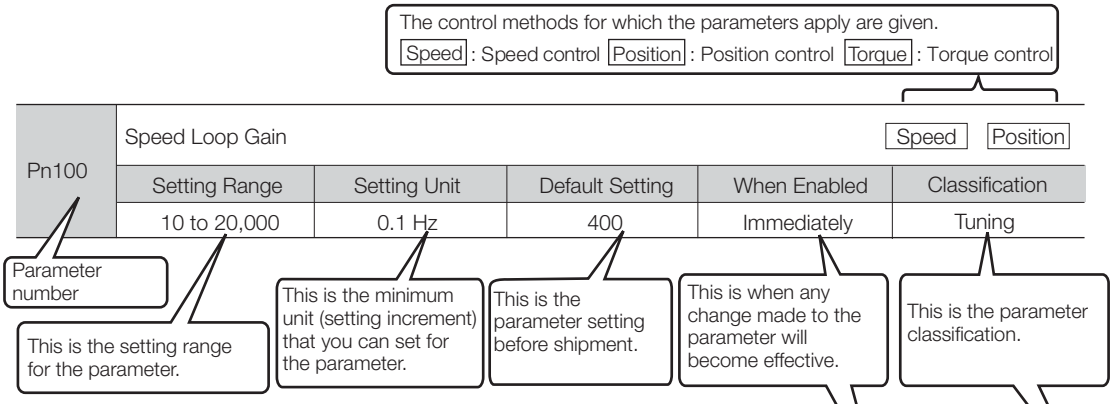
Notation Example

$\overline{BK}$ is written as /BK.

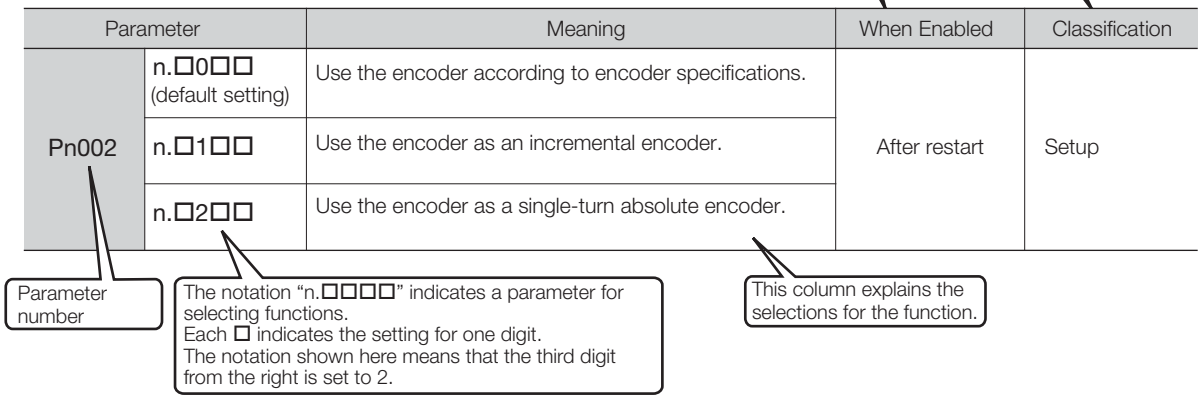
■ Notation for Parameters

The notation depends on whether the parameter requires a numeric setting (parameter for numeric setting) or requires the selection of a function (parameter for selecting functions).

- Parameters for Numeric Settings

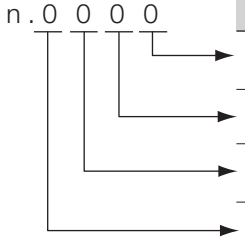


- Parameters for Selecting Functions



Notation Example

Notation Examples for Pn002



Digit Notation		Numeric Value Notation	
Notation	Meaning	Notation	Meaning
Pn002 = n.□□□X	Indicates the first digit from the right in Pn002.	Pn002 = n.□□□1	Indicates that the first digit from the right in Pn002 is set to 1.
Pn002 = n.□□X□	Indicates the second digit from the right in Pn002.	Pn002 = n.□□1□	Indicates that the second digit from the right in Pn002 is set to 1.
Pn002 = n.□X□□	Indicates the third digit from the right in Pn002.	Pn002 = n.□1□□	Indicates that the third digit from the right in Pn002 is set to 1.
Pn002 = n.X□□□	Indicates the fourth digit from the right in Pn002.	Pn002 = n.1□□□	Indicates that the fourth digit from the right in Pn002 is set to 1.

◆ Engineering Tools Used in This Manual

This manual uses the interfaces of the SigmaWin+ for descriptions.

◆ Trademarks

- QR code is a trademark of Denso Wave Inc.
- Other product names and company names are the trademarks or registered trademarks of the respective company. “TM” and the ® mark do not appear with product or company names in this manual.

◆ Visual Aids

The following aids are used to indicate certain types of information for easier reference.


Important

Indicates precautions or restrictions that must be observed.
Also indicates alarm displays and other precautions that will not result in machine damage.


Term

Indicates definitions of difficult terms or terms that have not been previously explained in this manual.

Example Indicates operating or setting examples.

Information Indicates supplemental information to deepen understanding or useful information.

Safety Precautions

◆ Safety Information

To prevent personal injury and equipment damage in advance, the following signal words are used to indicate safety precautions in this document. The signal words are used to classify the hazards and the degree of damage or injury that may occur if a product is used incorrectly. Information marked as shown below is important for safety. Always read this information and heed the precautions that are provided.

⚠ DANGER

- Indicates precautions that, if not heeded, are likely to result in loss of life, serious injury, or fire.

⚠ WARNING

- Indicates precautions that, if not heeded, could result in loss of life, serious injury, or fire.

⚠ CAUTION

- Indicates precautions that, if not heeded, could result in relatively serious or minor injury, or in fire.

NOTICE

- Indicates precautions that, if not heeded, could result in property damage.

◆ Safety Precautions That Must Always Be Observed

■ General Precautions

⚠ DANGER

- Read and understand this manual to ensure the safe usage of the product.
- Keep this manual in a safe, convenient place so that it can be referred to whenever necessary. Make sure that it is delivered to the final user of the product.
- Do not remove covers, cables, connectors, or optional devices while power is being supplied to the SERVOPACK.
  There is a risk of electric shock, operational failure of the product, or burning.

⚠ WARNING

- Use a power supply with specifications (number of phases, voltage, frequency, and AC/DC type) that are appropriate for the product.
  There is a risk of burning, electric shock, or fire.
- Connect the ground terminals on the SERVOPACK and Servomotor to ground poles according to local electrical codes (100 Ω or less for a SERVOPACK with a 100-VAC or 200-VAC power supply, and 10 Ω or less for a SERVOPACK with a 400-VAC power supply).
  There is a risk of electric shock or fire.
- Do not attempt to disassemble, repair, or modify the product.
  There is a risk of fire or failure.
  The warranty is void for the product if you disassemble, repair, or modify it.

⚠ CAUTION

- The SERVOPACK heat sinks, regenerative resistors, External Dynamic Brake Resistors, Servomotors, and other components can be very hot while power is ON or soon after the power is turned OFF. Implement safety measures, such as installing covers, so that hands and parts such as cables do not come into contact with hot components.
  There is a risk of burn injury.
- For a 24-VDC power supply, use a power supply device with double insulation or reinforced insulation.
  There is a risk of electric shock.
- Do not damage, pull on, apply excessive force to, place heavy objects on, or pinch cables.
  There is a risk of failure, damage, or electric shock.
- The person who designs the system that uses the hard wire base block safety function must have a complete knowledge of the related safety standards and a complete understanding of the instructions in this document.
  There is a risk of injury, product damage, or machine damage.
- Do not use the product in an environment that is subject to water, corrosive gases, or flammable gases, or near flammable materials.
  There is a risk of electric shock or fire.

NOTICE

- Do not attempt to use a SERVOPACK or Servomotor that is damaged or that has missing parts.
- Install external emergency stop circuits that shut OFF the power supply and stops operation immediately when an error occurs.
- In locations with poor power supply conditions, install the necessary protective devices (such as AC reactors) to ensure that the input power is supplied within the specified voltage range.
  There is a risk of damage to the SERVOPACK.
- Use a Noise Filter to minimize the effects of electromagnetic interference.
  Electronic devices used near the SERVOPACK may be affected by electromagnetic interference.
- Always use a Servomotor and SERVOPACK in one of the specified combinations.
- Do not touch a SERVOPACK or Servomotor with wet hands.
  There is a risk of product failure.

■ Storage Precautions

⚠ CAUTION

- Do not place an excessive load on the product during storage. (Follow all instructions on the packages.)
  There is a risk of injury or damage.

NOTICE

- Do not install or store the product in any of the following locations.
  - Locations that are subject to direct sunlight
  - Locations that are subject to ambient temperatures that exceed product specifications
  - Locations that are subject to relative humidities that exceed product specifications
  - Locations that are subject to condensation as the result of extreme changes in temperature
  - Locations that are subject to corrosive or flammable gases
  - Locations that are near flammable materials
  - Locations that are subject to dust, salts, or iron powder
  - Locations that are subject to water, oil, or chemicals
  - Locations that are subject to vibration or shock that exceeds product specifications
  - Locations that are subject to radiation

  If you store or install the product in any of the above locations, the product may fail or be damaged.

■ Transportation Precautions

⚠ CAUTION

- Transport the product in a way that is suitable to the mass of the product.
- Do not use the eyebolts on a SERVOPACK or Servomotor to move the machine.
  There is a risk of damage or injury.
- When you handle a SERVOPACK or Servomotor, be careful of sharp parts, such as the corners.
  There is a risk of injury.
- Do not place an excessive load on the product during transportation. (Follow all instructions on the packages.)
  There is a risk of injury or damage.

NOTICE

- Do not hold onto the front cover or connectors when you move a SERVOPACK.
  There is a risk of the SERVOPACK falling.
- A SERVOPACK or Servomotor is a precision device. Do not drop it or subject it to strong shock.
  There is a risk of failure or damage.
- Do not subject connectors to shock.
  There is a risk of faulty connections or damage.
- If disinfectants or insecticides must be used to treat packing materials such as wooden frames, plywood, or pallets, the packing materials must be treated before the product is packaged, and methods other than fumigation must be used.
  Example: Heat treatment, where materials are kiln-dried to a core temperature of 56°C for 30 minutes or more.
  If the electronic products, which include stand-alone products and products installed in machines, are packed with fumigated wooden materials, the electrical components may be greatly damaged by the gases or fumes resulting from the fumigation process. In particular, disinfectants containing halogen, which includes chlorine, fluorine, bromine, or iodine can contribute to the erosion of the capacitors.
- Do not overtighten the eyebolts on a SERVOPACK or Servomotor.
  If you use a tool to overtighten the eyebolts, the tapped holes may be damaged.

■ Installation Precautions

⚠ CAUTION

- Install the Servomotor or SERVOPACK in a way that will support the mass given in technical documents.
- Install SERVOPACKs, Servomotors, regenerative resistors, and External Dynamic Brake Resistors on nonflammable materials.
  Installation directly onto or near flammable materials may result in fire.
- Provide the specified clearances between the SERVOPACK and the control panel as well as with other devices.
  There is a risk of fire or failure.
- Install the SERVOPACK in the specified orientation.
  There is a risk of fire or failure.
- Do not step on or place a heavy object on the product.
  There is a risk of failure, damage, or injury.
- Do not allow any foreign matter to enter the SERVOPACK or Servomotor.
  There is a risk of failure or fire.

NOTICE

- Do not install or store the product in any of the following locations.
  - Locations that are subject to direct sunlight
  - Locations that are subject to ambient temperatures that exceed product specifications
  - Locations that are subject to relative humidities that exceed product specifications
  - Locations that are subject to condensation as the result of extreme changes in temperature
  - Locations that are subject to corrosive or flammable gases
  - Locations that are near flammable materials
  - Locations that are subject to dust, salts, or iron powder
  - Locations that are subject to water, oil, or chemicals
  - Locations that are subject to vibration or shock that exceeds product specifications
  - Locations that are subject to radiation

  If you store or install the product in any of the above locations, the product may fail or be damaged.
- Use the product in an environment that is appropriate for the product specifications.
  If you use the product in an environment that exceeds product specifications, the product may fail or be damaged.
- A SERVOPACK or Servomotor is a precision device. Do not drop it or subject it to strong shock.
  There is a risk of failure or damage.
- Always install a SERVOPACK in a control panel.
- Do not allow any foreign matter to enter a SERVOPACK or a Servomotor with a Cooling Fan and do not cover the outlet from the Servomotor's cooling fan.
  There is a risk of failure.

■ Wiring Precautions

⚠ DANGER

- Do not change any wiring while power is being supplied.
  There is a risk of electric shock or injury.

⚠ WARNING

- Wiring and inspections must be performed only by qualified engineers.
  There is a risk of electric shock or product failure.
- Check all wiring and power supplies carefully.
  Incorrect wiring or incorrect voltage application to the output circuits may cause short-circuit failures. If a short-circuit failure occurs as a result of any of these causes, the holding brake will not work. This could damage the machine or cause an accident that may result in death or injury.
- Connect the AC and DC power supplies to the specified SERVOPACK terminals.
  - Connect an AC power supply to the L1, L2, and L3 terminals and the L1C and L2C terminals on the SERVOPACK.
  - Connect a DC power supply to the B1/⊕ and ⊖2 terminals and the L1C and L2C terminals on the SERVOPACK.

  There is a risk of failure or fire.
- If you use a SERVOPACK that supports a Dynamic Brake Option, connect an External Dynamic Brake Resistor that is suitable for the machine and equipment specifications to the specified terminals.
  There is a risk of unexpected operation, machine damage, burning, or injury when an emergency stop is performed.

⚠ CAUTION

- Wait for six minutes after turning OFF the power supply and then make sure that the CHARGE indicator is not lit before starting wiring or inspection work. Do not touch the power supply terminals while the CHARGE lamp is lit after turning OFF the power supply because high voltage may still remain in the SERVOPACK.
  There is a risk of electric shock.
- Observe the precautions and instructions for wiring and trial operation precisely as described in this document.
  Failures caused by incorrect wiring or incorrect voltage application in the brake circuit may cause the SERVOPACK to fail, damage the equipment, or cause an accident resulting in death or injury.
- Check the wiring to be sure it has been performed correctly.
  Connectors and pin layouts are sometimes different for different models. Always confirm the pin layouts in technical documents for your model before operation.
  There is a risk of failure or malfunction.
- Connect wires to power supply terminals and motor connection terminals securely with the specified methods and tightening torque.
  Insufficient tightening may cause wires and terminal blocks to generate heat due to faulty contact, possibly resulting in fire.
- Use shielded twisted-pair cables or screened unshielded multi-twisted-pair cables for I/O Signal Cables and Encoder Cables.
- The maximum wiring length is 3 m for I/O Signal Cables, and 50 m for Encoder Cables or Servomotor Main Circuit Cables.
- Observe the following precautions when wiring the SERVOPACK's main circuit terminals.
  - Turn ON the power supply to the SERVOPACK only after all wiring, including the main circuit terminals, has been completed.
  - If a connector is used for the main circuit terminals, remove the main circuit connector from the SERVOPACK before you wire it.
  - Insert only one wire per insertion hole in the main circuit terminals.
  - When you insert a wire, make sure that the conductor wire (e.g., whiskers) does not come into contact with adjacent wires.
- Install molded-case circuit breakers and other safety measures to provide protection against short circuits in external wiring.
  There is a risk of fire or failure.

NOTICE

- Whenever possible, use the Cables specified by Yaskawa.
  If you use any other cables, confirm the rated current and application environment of your model and use the wiring materials specified by Yaskawa or equivalent materials.
- Securely tighten cable connector screws and lock mechanisms.
  Insufficient tightening may result in cable connectors falling off during operation.
- Do not bundle power lines (e.g., the Main Circuit Cable) and low-current lines (e.g., the I/O Signal Cables or Encoder Cables) together or run them through the same duct. If you do not place power lines and low-current lines in separate ducts, separate them by at least 30 cm.
  If the cables are too close to each other, malfunctions may occur due to noise affecting the low-current lines.
- Install a battery at either the host controller or on the Encoder Cable.
  If you install batteries both at the host controller and on the Encoder Cable at the same time, you will create a loop circuit between the batteries, resulting in a risk of damage or burning.
- When connecting a battery, connect the polarity correctly.
  There is a risk of battery rupture or encoder failure.

■ Operation Precautions

⚠ WARNING

- Before starting operation with a machine connected, change the settings of the switches and parameters to match the machine.
  Unexpected machine operation, failure, or personal injury may occur if operation is started before appropriate settings are made.
- Do not radically change the settings of the parameters.
  There is a risk of unstable operation, machine damage, or injury.
- Install limit switches or stoppers at the ends of the moving parts of the machine to prevent unexpected accidents.
  There is a risk of machine damage or injury.
- For trial operation, securely mount the Servomotor and disconnect it from the machine.
  There is a risk of injury.
- Forcing the motor to stop for overtravel is disabled when the Jog, Origin Search, or Easy FFT utility function is executed. Take necessary precautions.
  There is a risk of machine damage or injury.
- When an alarm occurs, the Servomotor will coast to a stop or stop with the dynamic brake according to the SERVOPACK Option specifications and settings. The coasting distance will change with the moment of inertia of the load and the resistance of the External Dynamic Brake Resistor. Check the coasting distance during trial operation and implement suitable safety measures on the machine.
- Do not enter the machine's range of motion during operation.
  There is a risk of injury.
- Do not touch the moving parts of the Servomotor or machine during operation.
  There is a risk of injury.

⚠ CAUTION

- Design the system to ensure safety even when problems, such as broken signal lines, occur. For example, the P-OT and N-OT signals are set in the default settings to operate on the safe side if a signal line breaks. Do not change the polarity of this type of signal.
- When overtravel occurs, the power supply to the motor is turned OFF and the brake is released. If you use the Servomotor to drive a vertical load, set the Servomotor to enter a zero-clamped state after the Servomotor stops. Also, install safety devices (such as an external brake or counterweight) to prevent the moving parts of the machine from falling.
- Always turn OFF the servo before you turn OFF the power supply. If you turn OFF the main circuit power supply or control power supply during operation before you turn OFF the servo, the Servomotor will stop as follows:
  - If you turn OFF the main circuit power supply during operation without turning OFF the servo, the Servomotor will stop abruptly with the dynamic brake.
  - If you turn OFF the control power supply without turning OFF the servo, the stopping method that is used by the Servomotor depends on the model of the SERVOPACK. For details, refer to the manual for the SERVOPACK.
  - If you use a SERVOPACK that supports a Dynamic Brake Option, the Servomotor stopping methods will be different from the stopping methods used without the Option or for other Hardware Option specifications. For details, refer to the *Σ-7-Series AC Servo Drive Σ-7S/Σ-7W SERVOPACK with Hardware Option Specifications Dynamic Brake Product Manual*.
- Do not use the dynamic brake for any application other than an emergency stop.
  There is a risk of failure due to rapid deterioration of elements in the SERVOPACK and the risk of unexpected operation, machine damage, burning, or injury.

NOTICE

- When you adjust the gain during system commissioning, use a measuring instrument to monitor the torque waveform and speed waveform and confirm that there is no vibration.
  If a high gain causes vibration, the Servomotor will be damaged quickly.
- Do not frequently turn the power supply ON and OFF. After you have started actual operation, allow at least one hour between turning the power supply ON and OFF (as a guideline).
  Do not use the product in applications that require the power supply to be turned ON and OFF frequently.
  The elements in the SERVOPACK will deteriorate quickly.
- An alarm or warning may occur if communications are performed with the host controller while the SigmaWin+ or Digital Operator is operating.
  If an alarm or warning occurs, it may interrupt the current process and stop the system.
- After you complete trial operation of the machine and facilities, use the SigmaWin+ to back up the settings of the SERVOPACK parameters. You can use them to reset the parameters after SERVOPACK replacement.
  If you do not copy backed up parameter settings, normal operation may not be possible after a faulty SERVOPACK is replaced, possibly resulting in machine or equipment damage.

■ Maintenance and Inspection Precautions

⚠ DANGER

- Do not change any wiring while power is being supplied.
  There is a risk of electric shock or injury.

⚠ WARNING

- Wiring and inspections must be performed only by qualified engineers.
  There is a risk of electric shock or product failure.

⚠ CAUTION

- Wait for six minutes after turning OFF the power supply and then make sure that the CHARGE indicator is not lit before starting wiring or inspection work. Do not touch the power supply terminals while the CHARGE lamp is lit after turning OFF the power supply because high voltage may still remain in the SERVOPACK.
  There is a risk of electric shock.
- Before you replace a SERVOPACK, back up the settings of the SERVOPACK parameters. Copy the backed up parameter settings to the new SERVOPACK and confirm that they were copied correctly.
  If you do not copy backed up parameter settings or if the copy operation is not completed normally, normal operation may not be possible, possibly resulting in machine or equipment damage.

NOTICE

- Discharge all static electricity from your body before you operate any of the buttons or switches inside the front cover of the SERVOPACK.
  There is a risk of equipment damage.

■ Troubleshooting Precautions

⚠ DANGER

- If the safety device (molded-case circuit breaker or fuse) installed in the power supply line operates, remove the cause before you supply power to the SERVOPACK again. If necessary, repair or replace the SERVOPACK, check the wiring, and remove the factor that caused the safety device to operate.
  There is a risk of fire, electric shock, or injury.

⚠ WARNING

- The product may suddenly start to operate when the power supply is recovered after a momentary power interruption. Design the machine to ensure human safety when operation restarts.
  There is a risk of injury.

⚠ CAUTION

- When an alarm occurs, remove the cause of the alarm and ensure safety. Then reset the alarm or turn the power supply OFF and ON again to restart operation.
  There is a risk of injury or machine damage.
- If the Servo ON signal is input to the SERVOPACK and an alarm is reset, the Servomotor may suddenly restart operation. Confirm that the servo is OFF and ensure safety before you reset an alarm.
  There is a risk of injury or machine damage.
- Always insert a magnetic contactor in the line between the main circuit power supply and the main circuit power supply terminals on the SERVOPACK so that the power supply can be shut OFF at the main circuit power supply.
  If a magnetic contactor is not connected when the SERVOPACK fails, a large current may flow, possibly resulting in fire.
- If an alarm occurs, shut OFF the main circuit power supply.
  There is a risk of fire due to a regenerative resistor overheating as the result of regenerative transistor failure.
- Install a ground fault detector against overloads and short-circuiting or install a molded-case circuit breaker combined with a ground fault detector.
  There is a risk of SERVOPACK failure or fire if a ground fault occurs.
- The holding brake on a Servomotor will not ensure safety if there is the possibility that an external force (including gravity) may move the current position and create a hazardous situation when power is interrupted or an error occurs. If an external force may cause movement, install an external braking mechanism that ensures safety.

■ Disposal Precautions

- When disposing of the product, treat it as ordinary industrial waste. However, local ordinances and national laws must be observed. Implement all labeling and warnings as a final product as required.

■ General Precautions

- Figures provided in this document are typical examples or conceptual representations. There may be differences between them and actual wiring, circuits, and products.
- The products shown in illustrations in this document are sometimes shown without covers or protective guards. Always replace all covers and protective guards before you use the product.
- If you need a new copy of this document because it has been lost or damaged, contact your nearest Yaskawa representative or one of the offices listed on the back of this document.
- This document is subject to change without notice for product improvements, specifications changes, and improvements to the manual itself.
  We will update the document number of the document and issue revisions when changes are made.
- Any and all quality guarantees provided by Yaskawa are null and void if the customer modifies the product in any way. Yaskawa disavows any responsibility for damages or losses that are caused by modified products.

Warranty

◆ Details of Warranty

■ Warranty Period

The warranty period for a product that was purchased (hereinafter called the “delivered product”) is one year from the time of delivery to the location specified by the customer or 18 months from the time of shipment from the Yaskawa factory, whichever is sooner.

■ Warranty Scope

Yaskawa shall replace or repair a defective product free of charge if a defect attributable to Yaskawa occurs during the above warranty period.
This warranty does not cover defects caused by the delivered product reaching the end of its service life and replacement of parts that require replacement or that have a limited service life.

This warranty does not cover failures that result from any of the following causes.

- Improper handling, abuse, or use in unsuitable conditions or in environments not described in product catalogs or manuals, or in any separately agreed-upon specifications
- Causes not attributable to the delivered product itself
- Modifications or repairs not performed by Yaskawa
- Use of the delivered product in a manner in which it was not originally intended
- Causes that were not foreseeable with the scientific and technological understanding at the time of shipment from Yaskawa
- Events for which Yaskawa is not responsible, such as natural or human-made disasters

◆ Limitations of Liability

- Yaskawa shall in no event be responsible for any damage or loss of opportunity to the customer that arises due to failure of the delivered product.
- Yaskawa shall not be responsible for any programs (including parameter settings) or the results of program execution of the programs provided by the user or by a third party for use with programmable Yaskawa products.
- The information described in product catalogs or manuals is provided for the purpose of the customer purchasing the appropriate product for the intended application. The use thereof does not guarantee that there are no infringements of intellectual property rights or other proprietary rights of Yaskawa or third parties, nor does it construe a license.
- Yaskawa shall not be responsible for any damage arising from infringements of intellectual property rights or other proprietary rights of third parties as a result of using the information described in catalogs or manuals.

◆ Suitability for Use

- It is the customer's responsibility to confirm conformity with any standards, codes, or regulations that apply if the Yaskawa product is used in combination with any other products.
- The customer must confirm that the Yaskawa product is suitable for the systems, machines, and equipment used by the customer.
- Consult with Yaskawa to determine whether use in the following applications is acceptable. If use in the application is acceptable, use the product with extra allowance in ratings and specifications, and provide safety measures to minimize hazards in the event of failure.
  - Outdoor use, use involving potential chemical contamination or electrical interference, or use in conditions or environments not described in product catalogs or manuals
  - Nuclear energy control systems, combustion systems, railroad systems, aviation systems, vehicle systems, medical equipment, amusement machines, and installations subject to separate industry or government regulations
  - Systems, machines, and equipment that may present a risk to life or property
  - Systems that require a high degree of reliability, such as systems that supply gas, water, or electricity, or systems that operate continuously 24 hours a day
  - Other systems that require a similar high degree of safety
- Never use the product for an application involving serious risk to life or property without first ensuring that the system is designed to secure the required level of safety with risk warnings and redundancy, and that the Yaskawa product is properly rated and installed.
- The circuit examples and other application examples described in product catalogs and manuals are for reference. Check the functionality and safety of the actual devices and equipment to be used before using the product.
- Read and understand all use prohibitions and precautions, and operate the Yaskawa product correctly to prevent accidental harm to third parties.

◆ Specifications Change

The names, specifications, appearance, and accessories of products in product catalogs and manuals may be changed at any time based on improvements and other reasons. The next editions of the revised catalogs or manuals will be published with updated code numbers. Consult with your Yaskawa representative to confirm the actual specifications before purchasing a product.

Compliance with UL Standards, EU Directives, and Other Safety Standards

Certification marks for the standards for which the product has been certified by certification bodies are shown on nameplate. Products that do not have the marks are not certified for the standards.

◆ North American Safety Standards (UL)

Product	Model	North American Safety Standards (UL File No.)
SERVOPACKs	SGD7S	UL 61800-5-1 (E147823), CSA C22.2 No.274

◆ European Directives

Product	Model	EU Directive	Harmonized Standards
SERVOPACKs	SGD7S	Machinery Directive 2006/42/EC	EN ISO13849-1: 2015
		EMC Directive 2014/30/EU	EN 55011 group 1, class A EN 61000-6-2 EN 61000-6-4 EN 61800-3 (Category C2, Second environment)
		Low Voltage Directive 2014/35/EU	EN 50178 EN 61800-5-1
		RoHS Directive 2011/65/EU	EN 50581
Direct Drive Servomotors	SGM7D	EMC Directive 2014/30/EU	EN 55011 group 1, class A EN 61000-6-2 EN 61000-6-4 EN 61800-3 (Category C2, Second environment)
		Low Voltage Directive 2014/35/EU	EN 60034-1 EN 60034-5
		RoHS Directive 2011/65/EU	EN 50581

Note: 1. We declared the CE Marking based on the harmonized standards in the above table.
2. These products are for industrial use. In home environments, these products may cause electromagnetic interference and additional noise reduction measures may be necessary.

◆ Safety Standards

Product	Model	Safety Standards	Standards
SERVOPACKs	SGD7S	Safety of Machinery	EN ISO13849-1:2015 IEC 60204-1
		Functional Safety	IEC 61508 series IEC 62061 IEC 61800-5-2
		EMC	IEC 61326-3-1

■ Safety Parameters

Item	Standards	Performance Level	
Safety Integrity Level	IEC 61508	SIL3	
	IEC 62061	SILCL3	
Mission Time	IEC 61508	10 years	20 years
Probability of Dangerous Failure per Hour	IEC 61508 IEC 62061	PFH = 4.04×10^{-9} [1/h] (4.04% of SIL3)	PFH = 4.05×10^{-9} [1/h] (4.05% of SIL3)
Performance Level	EN ISO 13849-1	PLe (Category 3)	
Mean Time to Dangerous Failure of Each Channel	EN ISO 13849-1	MTTFd: High	
Average Diagnostic Coverage	EN ISO 13849-1	DCavg: Medium	
Stop Category	IEC 60204-1	Stop category 0	
Safety Function	IEC 61800-5-2	STO	
Hardware Fault Tolerance	IEC 61508	HFT = 1	
Subsystem	IEC 61508	B	

Contents

About this Manual iii
Outline of Manual iii
Related Documents viii
Using This Manual xv
Safety Precautions xviii
Warranty xxviii
Compliance with UL Standards, EU Directives, and Other Safety Standards . . . xxx

1 Basic Information on SERVOPACKs

1.1 Product Introduction 1-2

1.2 Model Designations 1-3
1.2.1 Interpreting FT82 SERVOPACK Model Numbers 1-3
1.2.2 Interpreting FT83 SERVOPACK Model Numbers 1-4
1.2.3 Interpreting Direct Drive Servomotor Model Numbers 1-5

1.3 Combinations of SERVOPACKs and Servomotors 1-6

1.4 Functions 1-7
1.4.1 SERVOPACK Functions 1-7
1.4.2 Function Application Restrictions 1-10

1.5 SigmaWin+ 1-11

1.6 Combining the SERVOPACKs with MP-Series Machine Controllers and the MPE720 Engineering Tool . . 1-12

2 SERVOPACK Ratings and Specifications

2.1 Ratings 2-2
2.1.1 Three-Phase, 200 VAC 2-2
2.1.2 Single-Phase, 200 VAC 2-2
2.1.3 Single-Phase, 100 VAC 2-3

2.2 SERVOPACK Overload Protection Characteristics 2-4

2.3 Specifications 2-5
2.3.1 FT82 SERVOPACKs with Analog Voltage/Pulse Train References 2-5
2.3.2 FT82 SERVOPACK with MECHATROLINK-II Communications References 2-9
2.3.3 FT82 SERVOPACK with MECHATROLINK-III Communications References 2-12
2.3.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules 2-15
2.3.5 FT83 SERVOPACKs with Analog Voltage/Pulse Train References 2-19

3 Maintenance

3.1 FT82 SERVOPACKs with Analog Voltage/Pulse Train References . . 3-3
3.1.1 Alarm Displays . . . 3-3
3.1.2 List of Alarms . . . 3-3
3.1.3 Troubleshooting Alarms . . . 3-9
3.1.4 Warning Displays . . . 3-34
3.1.5 List of Warnings . . . 3-34
3.1.6 Troubleshooting Warnings . . . 3-35
3.1.7 Troubleshooting Based on the Operation and Conditions of the Servomotor . . . 3-41

3.2 FT82 SERVOPACK with MECHATROLINK-II Communications References . . 3-50
3.2.1 Alarm Displays . . . 3-50
3.2.2 List of Alarms . . . 3-50
3.2.3 Troubleshooting Alarms . . . 3-55
3.2.4 Warning Displays . . . 3-80
3.2.5 List of Warnings . . . 3-80
3.2.6 Troubleshooting Warnings . . . 3-82
3.2.7 Troubleshooting Based on the Operation and Conditions of the Servomotor . . . 3-89

3.3 FT82 SERVOPACK with MECHATROLINK-III Communications References . . 3-98
3.3.1 Alarm Displays . . . 3-98
3.3.2 List of Alarms . . . 3-98
3.3.3 Troubleshooting Alarms . . . 3-103
3.3.4 Warning Displays . . . 3-128
3.3.5 List of Warnings . . . 3-128
3.3.6 Troubleshooting Warnings . . . 3-130
3.3.7 Troubleshooting Based on the Operation and Conditions of the Servomotor . . . 3-137

3.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules . . 3-145
3.4.1 Alarm Displays . . . 3-145
3.4.2 List of Alarms . . . 3-146
3.4.3 Troubleshooting Alarms . . . 3-151
3.4.4 INDEXER Module Alarm Displays and Troubleshooting . . . 3-177
3.4.5 Warning Displays . . . 3-181
3.4.6 List of Warnings . . . 3-181
3.4.7 Troubleshooting Warnings . . . 3-183
3.4.8 INDEXER Module Error Displays and Troubleshooting . . . 3-189
3.4.9 Troubleshooting Based on the Operation and Conditions of the Servomotor . . . 3-197

3.5 FT83 SERVOPACKs with Analog Voltage/Pulse Train References . . 3-205
3.5.1 Alarm Displays . . . 3-205
3.5.2 List of Alarms . . . 3-205
3.5.3 Troubleshooting Alarms . . . 3-210
3.5.4 INDEXER Alarm Displays and Troubleshooting . . . 3-234
3.5.5 Warning Displays . . . 3-238
3.5.6 List of Warnings . . . 3-238
3.5.7 Troubleshooting Warnings . . . 3-240
3.5.8 INDEXER Warning Displays and Troubleshooting . . . 3-246
3.5.9 Troubleshooting Based on the Operation and Conditions of the Servomotor . . . 3-250

4 Parameter Lists

4.1 FT82 SERVOPACKs with Analog Voltage/Pulse Train References . . 4-2

4.2 FT82 SERVOPACK with MECHATROLINK-II Communications References . . 4-32

4.3 FT82 SERVOPACK with MECHATROLINK-III Communications References . . 4-67

4.3.1 List of Servo Parameters 4-67
4.3.2 List of MECHATROLINK-III Common Parameters 4-106

4.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules . . 4-114

4.5 FT83 SERVOPACKs with Analog Voltage/Pulse Train References . . 4-138

Index

Revision History

Basic Information on SERVOPACKs

1

This chapter provides basic information, including an introduction to the product, and describes how to interpret model numbers and combinations with Servomotors.

1.1 Product Introduction 1-2

1.2 Model Designations 1-3

1.2.1 Interpreting FT82 SERVOPACK Model Numbers . . 1-3
1.2.2 Interpreting FT83 SERVOPACK Model Numbers . . 1-4
1.2.3 Interpreting Direct Drive Servomotor Model Numbers 1-5

1.3 Combinations of SERVOPACKs and Servomotors 1-6

1.4 Functions 1-7

1.4.1 SERVOPACK Functions 1-7
1.4.2 Function Application Restrictions 1-10

1.5 SigmaWin+ 1-11

1.6 Combining the SERVOPACKs with MP-Series Machine Controllers and the MPE720 Engineering Tool . . 1-12

1.1 Product Introduction

The SERVOPACKs described in this manual were developed to drive SGM7D motors.

The SGM7D motors were designed for applications that require high torque, easy operation, and high precision. The SERVOPACK will make the most of machine performance in the shortest time possible, thus contributing to improving productivity.

1.2 Model Designations

1.2.1 Interpreting FT82 SERVOPACK Model Numbers

SGD7S - 2R8 A 00 A 001 F82 B

- SGD7S: Σ-7-Series Σ-7S SERVOPACKs
- 1st+2nd+3rd digits
- 4th digit
- 5th+6th digits
- 7th digit
- 8th+9th+10th digits
- 11th+12th+13th digits
- 14th digit

1st+2nd+3rd digits Maximum Applicable Motor Capacity

Voltage	Code	Specification
Three-Phase, 200 VAC	2R8*1	0.4 kW
	120*2	1.5 kW
Single-Phase, 100 VAC	2R8	0.4 kW

4th digit Voltage

Code	Specification
A	200 VAC
F	100 VAC

5th+6th digits Interface

Code	Specification
00	Analog voltage/pulse train reference
10	MECHATROLINK-II communications references
20	MECHATROLINK-III communications reference
E0	Command option attachable type*3

7th digit Design Revision Order

A

8th+9th+10th digits Hardware Options Specification

Code	Specification	Applicable Models
None	Without options	All models
000		
001	Rack-mounted	All models
002	Varnished	All models
008	Single-phase, 200-VAC power supply input	SGD7S-120A
020*4	No dynamic brake	SGD7S-2R8A and -2R8F
	External dynamic brake resistor	SGD7S-120A

11th+12th+13th digits FT/EX Specification

Code	Specification
F82	Application function option for special motors, SGM7D motor drive

14th digit BTO Specification*5

Code	Specification
None	None
B	BTO specification

*1. You can use these models with either a single-phase or three-phase input.

*2. A model with a single-phase, 200-VAC power supply input is available as a hardware option (model: SGD7S-120A00A008).

*3. This interface is supported only by an INDEXER Module. Refer to the following catalog for details.
AC Servo Drives Σ-7 Series (Manual No.: KAEP S800001 23)

*4. Refer to the following manual for details.
Σ-7-Series Σ-7S/Σ-7W SERVOPACK with Dynamic Brake Hardware Option Specifications Product Manual (Manual No.: SIEP S800001 73)

*5. The BTO specification indicates if the SEVOPACK is customized by using the MechatroCloud BTO service. You need a BTO number to order SERVOPACKs with customized specifications.
Refer to the following catalog for details on the BTO specification.
AC Servo Drives Σ-7 Series (Manual No.: KAEP S800001 23)

1.2.2 Interpreting FT83 SERVOPACK Model Numbers

SGD7S - 2R8 A 00 A 001 F83 B

- SGD7S: Σ-7-Series Σ-7S SERVOPACKs
- 2R8: 1st+2nd+3rd digits
- A: 4th digit
- 00: 5th+6th digits
- A: 7th digit
- 001: 8th+9th+10th digits
- F83: 11th+12th+13th digits
- B: 14th digit

1st+2nd+3rd digits Maximum Applicable Motor Capacity

Voltage	Code	Specification
Three-Phase, 200 VAC	2R8*1	0.4 kW
	120*2	1.5 kW
Single-Phase, 100 VAC	2R8	0.4 kW

4th digit Voltage

Code	Specification
A	200 VAC
F	100 VAC

5th+6th digits Interface

Code	Specification
00	Analog voltage/pulse train reference

7th digit Design Revision Order

A

8th+9th+10th digits Hardware Options Specification

Code	Specification	Applicable Models
None	Without options	All models
000		
001	Rack-mounted	All models
002	Varnished	All models
008	Single-phase, 200-VAC power supply input	SGD7S-120A
020*3	No dynamic brake	SGD7S-2R8A and -2R8F
	External dynamic brake resistor	SGD7S-120A

11th+12th+13th digits FT/EX Specification

Code	Specification
F83	Application function option for special motors, SGM7D motor drive, indexing

14th digit BTO Specification*4

Code	Specification
None	None
B	BTO specification

*1. You can use these models with either a single-phase or three-phase input.

*2. A model with a single-phase, 200-VAC power supply input is available as a hardware option (model: SGD7S-120A00A008).

*3. Refer to the following manual for details.
Σ-7-Series AC Servo Drive Σ-7S/Σ-7W SERVOPACK with Hardware Option Specifications Dynamic Brake Product Manual (Manual No.: SIEP S800001 73)

*4. The BTO specification indicates if the SEVOPACK is customized by using the MechatroCloud BTO service. You need a BTO number to order SERVOPACKs with customized specifications.
AC Servo Drives Σ-7 Series (Manual No.: KAEP S800001 23)

1.2.3 Interpreting Direct Drive Servomotor Model Numbers

SGM7D - 30 F 7 C 4 1

Direct Drive Servomotors: SGM7D

1st+2nd digits | 3rd digit | 4th digit | 5th digit | 6th digit | 7th digit

1st+2nd digits Rated Torque

Code	Specification	Code	Specification	Code	Specification
01	1.30 N·m	18	18.0 N·m	58	58.0 N·m
02	2.06 N·m	20	20.0 N·m	70	70.0 N·m
03	3.00 N·m	24	24.0 N·m	90	90.0 N·m
05	5.00 N·m	28	28.0 N·m	1Z	100 N·m
06	6.00 N·m	30	30.0 N·m	1A	110 N·m
08	8.00 N·m	34	34.0 N·m	1C	130 N·m
09	9.00 N·m	38	38.0 N·m	2B	220 N·m
12	12.0 N·m	45	45.0 N·m	2D	240 N·m

3rd digit Servomotor Outer Diameter

Code	Specification	Code	Specification
F	264-mm dia.	J	150-mm dia.
G	160-mm dia.	K	107-mm dia.
H	116-mm dia.	L	224 mm × 224 mm
I	264-mm dia.		

Note: 1. Direct Drive Servomotors are not available with holding brakes.
2. This information is provided to explain model numbers. It is not meant to imply that models are available for all combinations of codes.

4th digit Serial Encoder

Code	Specification
7	24-bit multiturn absolute encoder
F	24-bit incremental encoder

5th digit Design Revision Order

C

6th digit Flange

Code	Mounting		Servomotor Outer Diameter Code (3rd Digit)						
			F	G	H	I	J	K	L
4	Non-load side	With cable on side	✓	✓	✓	-	-	-	✓
5	Non-load side	With cable on bottom	✓	✓*	-	✓	✓	✓	-

✓: Applicable models.
* SGM7D-01G and -05G are not available with a cable extending from the bottom.

7th digit Options

Code	Specification
1	Standard mechanical precision
2	High mechanical precision*

* The SGM7D-01G, -05G, and -03H are available only with high mechanical precision.

◆ Manufactured Models

Rated Torque N·m	Servomotor Outer Diameter						
	F (264-mm dia.)	G (160-mm dia.)	H (116-mm dia.)	I (264-mm dia.)	J (150-mm dia.)	K (107-mm dia.)	L (224 mm × 224 mm)
1.30	–	SGM7D-01G	–	–	–	–	–
2.06	–	–	–	–	–	SGM7D-02K	–
3.00	–	–	SGM7D-03H	–	–	–	–
5.00	–	SGM7D-05G	–	–	–	–	–
6.00	–	–	–	–	SGM7D-06J	SGM7D-06K	SGM7D-06L
8.00	–	SGM7D-08G	–	–	–	SGM7D-08K	–
9.00	–	–	–	–	SGM7D-09J	–	–
12.0	–	–	–	–	–	–	SGM7D-12L
18.0	–	SGM7D-18G	–	–	SGM7D-18J	–	–
20.0	–	–	–	–	SGM7D-20J	–	–
24.0	–	SGM7D-24G	–	–	–	–	–
28.0	–	–	–	SGM7D-28I	–	–	–
30.0	SGM7D-30F	–	–	–	–	–	SGM7D-30L
34.0	–	SGM7D-34G	–	–	–	–	–
38.0	–	–	–	–	SGM7D-38J	–	–
45.0	–	SGM7D-45G	–	–	–	–	–
58.0	SGM7D-58F	–	–	–	–	–	–
70.0	–	–	–	SGM7D-70I	–	–	–
90.0	SGM7D-90F	–	–	–	–	–	–
100	–	–	–	SGM7D-1ZI	–	–	–
110	SGM7D-1AF	–	–	–	–	–	–
130	–	–	–	SGM7D-1CI	–	–	–
220	–	–	–	SGM7D-2BI	–	–	–
240	–	–	–	SGM7D-2DI	–	–	–

Note: The above table shows combinations of the rated torque and outer diameter. The fourth through seventh digits have been omitted.

1.3 Combinations of SERVOPACKs and Servomotors

Direct Drive Servomotor Model	Capacity	SERVOPACK Model
		SGD7S-
SGM7D-30F	188 W	120A
SGM7D-58F	364 W	
SGM7D-90F	565 W	
SGM7D-1AF	691 W	
SGM7D-01G	16 W	2R8A and 2R8F
SGM7D-05G	63 W	
SGM7D-08G	101 W	120A
SGM7D-18G	226 W	
SGM7D-24G	302 W	
SGM7D-34G	320 W	
SGM7D-45G	565 W	
SGM7D-03H	38 W	2R8A and 2R8F
SGM7D-28I	264 W	120A
SGM7D-70I	440 W	
SGM7D-1ZI	628 W	
SGM7D-1CI	817 W	
SGM7D-2BI	691 W	
SGM7D-2DI	754 W	
SGM7D-06J	75 W	
SGM7D-09J	113 W	
SGM7D-18J	226 W	
SGM7D-20J	251 W	
SGM7D-38J	358 W	
SGM7D-02K	52 W	2R8A and 2R8F
SGM7D-06K	151 W	
SGM7D-08K	201 W	
SGM7D-06L	113 W	
SGM7D-12L	226 W	
SGM7D-30L	565 W	120A

1.4 Functions

This section lists the functions provided by SERVOPACKs. Refer to the following manuals for details on the functions.

- FT82 SERVOPACKs
  - Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)
  - Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)
  - Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)
  - Σ-7-Series Σ-7S Command Option Attachable-type SERVOPACK with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
- FT83 SERVOPACKs
  - Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)
  - Σ-7-Series Σ-7S SERVOPACK with FT/EX Specification for Indexing Applications Product Manual (Manual No. SIEP S800001 84)

Functions in bold boxes in the functions tables are restricted if the above SERVOPACKs are used. Refer to the following section for details on restrictions to these functions.

☞ *1.4.2 Function Application Restrictions* on page 1-10

1.4.1 SERVOPACK Functions

- Functions Related to the Machine

Functions
Power Supply Type Settings for the Main Circuit and Control Circuit
Automatic Detection of Connected Motor
Motor Direction Setting
Setting the Linear Encoder Pitch
Writing Linear Servomotor Parameters
Selecting the Phase Sequence for a Linear Servomotor
Polarity Sensor Setting
Polarity Detection
Overtravel Function and Settings
Holding Brake
Motor Stopping Method for Servo OFF and Alarms
Resetting the Absolute Encoder
Setting the Origin of the Absolute Encoder
Setting the Regenerative Resistor Capacity
Operation for Momentary Power Interruptions
SEMI F47 Function
Motor Maximum Speed Setting
Software Limits and Settings*
Multiturn Limit Setting
Adjustment of Motor Current Detection Signal Offset
Forcing the Motor to Stop
Overheat Protection
Speed Ripple Compensation
Current Control Mode Selection
Current Gain Level Setting
Speed Detection Method Selection
Fully-closed Loop Control
Safety Function
External Latches*

* These functions can be used with SERVOPACKs with MECHATROLINK-II Communications References and SERVOPACKs with MECHATROLINK-III Communications References.

- Functions Related to the Host Controller

Functions
Electronic Gear Setting
I/O Signal Allocations
ALM (Servo Alarm) Signal
ALO1 to ALO3 (Alarm Code) Signals*
/WARN (Warning) Signal
/TGON (Rotation Detection) Signal
Servo Ready Output (/S-RDY) Signal
Speed Control*
Basic Settings for Speed Control*
Speed Reference Filter*
Zero Clamping*
/V-CMP (Speed Coincidence Detection) Signal
Position Control*
Reference Pulse Form*
CLR (Position Deviation Clear) Signal Function and Settings*
Reference Pulse Input Multiplication Switching*
/COIN (Positioning Completion) Signal
/NEAR (Near) Signal
Reference Pulse Inhibition Function and Settings*
Torque Control*
Basic Settings for Torque Control*
Torque Reference Filter Settings*
Speed Limit during Torque Control
/VLT (Speed Limit Detection) Signal
Encoder Divided Pulse Outputs
Selecting Torque Limits
Initializing the Vibration Detection Level
Resetting Alarms
Replacing the Battery
Setting the Position Deviation Overflow Alarm Level

* These functions can be used with SERVOPACKs with Analog Voltage/Pulse Train References.

• Functions to Achieve Optimum Motions

Functions
Speed Control*1
Soft Start Settings*1
Position Control*1
Smoothing Settings*1
Torque Control*1
Tuning-less Function
Autotuning without Host Reference
Autotuning with a Host Reference
Custom Tuning
Anti-resonance Control Adjustment
Vibration Suppression
Gain Selection
Friction Compensation
Gravity Compensation
Backlash Compensation*2
Model Following Control
Compatible Adjustment Functions
Mechanical Analysis
Easy FFT

*1. These functions can be used with SERVOPACKs with Analog Voltage/Pulse Train References.
*2. These functions can be used with SERVOPACKs with MECHATROLINK-II Communications References and SERVOPACKs with MECHATROLINK-III Communications References.

• Functions for Trial Operation during Setup

Functions
Software Reset
Trial Operation for the Servomotor without a Load
Program Jogging
Origin Searches
Test without a Motor
Monitoring Machine Operation Status and Signal Waveforms

• Functions for Inspection and Maintenance

Functions
Write Prohibition Setting for Parameters
Initializing Parameter Settings
Automatic Detection of Connected Motor
Monitoring Product Information
Monitoring Product Life
Displaying the Alarm History
Alarm Tracing

1.4.2 Function Application Restrictions

The following functional restrictions apply when you use the FT82/FT83 SERVOPACKs.

Function	Restriction
Setting the Linear Encoder Pitch	Cannot be used.
Writing Linear Servomotor Parameters	Cannot be used.
Selecting the Phase Sequence for a Linear Servomotor	Cannot be used.
Polarity Sensor Setting	Cannot be used.
Polarity Detection	Cannot be used.
Speed Ripple Compensation	Cannot be used. Do not change the following default setting: Pn423 = n.□□□0.
Tuning-less Function	Cannot be used if the load moment of inertia ratio is 10 or greater.

1.5 SigmaWin+

To use the SigmaWin+, a model information file for the SERVOPACK must be added to SigmaWin+ version 7.

- FT82 SERVOPACKs
  Add the FT82 model information file to SigmaWin+ to use the SigmaWin+.
- FT83 SERVOPACKs
  Add the FT83 model information file to SigmaWin+ to use the SigmaWin+.

1.6 Combining the SERVOPACKs with MP-Series Machine Controllers and the MPE720 Engineering Tool

If you combine the SERVOPACK with an MP-Series Machine Controller or the MPE720 Engineering Tool, it will be recognized as a SERVOPACK with standard specifications. To use the parameters that have been added or changed for the SERVOPACKs described in this manual, use the SigmaWin+.

SERVOPACK Ratings and Specifications

2

This chapter provides information required to select SERVOPACKs, such as specifications.

2.1 Ratings 2-2
2.1.1 Three-Phase, 200 VAC 2-2
2.1.2 Single-Phase, 200 VAC 2-2
2.1.3 Single-Phase, 100 VAC 2-3

2.2 SERVOPACK Overload Protection Characteristics . . 2-4

2.3 Specifications 2-5
2.3.1 FT82 SERVOPACKs with Analog Voltage/ Pulse Train References 2-5
2.3.2 FT82 SERVOPACK with MECHATROLINK-II Communications References 2-9
2.3.3 FT82 SERVOPACK with MECHATROLINK-III Communications References 2-12
2.3.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules 2-15
2.3.5 FT83 SERVOPACKs with Analog Voltage/ Pulse Train References 2-19

2.1 Ratings

The ratings of the FT82 and FT83 SERVOPACKs are the same. This section gives the ratings of SERVOPACKs.

2.1.1 Three-Phase, 200 VAC

Model SGD7S-			2R8A	120A
Maximum Applicable Motor Capacity [kW]			0.4	1.5
Continuous Output Current [Arms]			2.8	11.6
Instantaneous Maximum Output Current [Arms]			9.3	28
Main Circuit	Power Supply		200 VAC to 240 VAC, -15% to +10%, 50 Hz/60 Hz	
	Input Current [Arms]*		2.5	7.3
Control	Power Supply		200 VAC to 240 VAC, -15% to +10%, 50 Hz/60 Hz	
	Input Current [Arms]*		0.2	0.2
Power Supply Capacity [kVA]*			1.0	3.2
Power Loss*	Main Circuit Power Loss [W]		22.5	72.6
	Control Circuit Power Loss [W]		12	15
	Built-in Regenerative Resistor Power Loss [W]		–	12
	Total Power Loss [W]		34.5	97.6
Regenerative Resistor	Built-In Regenerative Resistor	Resistance [Ω]	–	20
		Capacity [W]	–	60
	Minimum Allowable External Resistance [Ω]		40	20
Overvoltage Category			III	

* This is the net value at the rated load.

2.1.2 Single-Phase, 200 VAC

Model SGD7S-			2R8A	120A
Maximum Applicable Motor Capacity [kW]			0.4	1.5
Continuous Output Current [Arms]			2.8	11.6
Instantaneous Maximum Output Current [Arms]			9.3	28
Main Circuit	Power Supply		200 VAC to 240 VAC, -15% to +10%, 50 Hz/60 Hz	
	Input Current [Arms]*		5.0	16
Control	Power Supply		200 VAC to 240 VAC, -15% to +10%, 50 Hz/60 Hz	
	Input Current [Arms]*		0.2	0.25
Power Supply Capacity [kVA]*			1.2	4.0
Power Loss*	Main Circuit Power Loss [W]		23.7	71.8
	Control Circuit Power Loss [W]		12	16
	Built-in Regenerative Resistor Power Loss [W]		–	12
	Total Power Loss [W]		35.7	103.8
Regenerative Resistor	Built-In Regenerative Resistor	Resistance [Ω]	–	12
		Capacity [W]	–	60
	Minimum Allowable External Resistance [Ω]		40	12
Overvoltage Category			III	

* This is the net value at the rated load.

2.1.3 Single-Phase, 100 VAC

SGD7S-		2R8F
Maximum Applicable Motor Capacity [kW]		0.4
Continuous Output Current [Arms]		2.8
Instantaneous Maximum Output Current [Arms]		9.3
Main Circuit	Power Supply	100 VAC to 120 VAC, -15% to +10%, 50 Hz/60 Hz
	Input Current [Arms]*	10
Control	Power Supply	100 VAC to 120 VAC, -15% to +10%, 50 Hz/60 Hz
	Input Current [Arms]*	0.38
Power Supply Capacity [kVA]*		1.4
Power Loss*	Main Circuit Power Loss [W]	26.2
	Control Circuit Power Loss [W]	12
	Total Power Loss [W]	38.2
Regenerative Resistor	Minimum Allowable Resistance [Ω]	40
Overvoltage Category		III

* This is the net value at the rated load.

2.2 SERVOPACK Overload Protection Characteristics

The overload protection characteristics of the FT82/FT83 SERVOPACKs are the same as the standard Σ-7-Series SERVOPACKs. Refer to the following manual for details.

- FT82 SERVOPACKs
  - 🕮 Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)
  - 🕮 Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)
  - 🕮 Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)
  - 🕮 Σ-7-Series Σ-7S Command Option Attachable-type SERVOPACK with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
- FT83 SERVOPACKs
  - 🕮 Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

2.3 Specifications

2.3.1 FT82 SERVOPACKs with Analog Voltage/Pulse Train References

<table>
<tr><th colspan="2">Item</th><th>Specification</th></tr>
<tr><td colspan="2">Control Method</td><td>IGBT-based PWM control, sine wave current drive</td></tr>
<tr><td colspan="2">Feedback</td><td>Serial encoder: 24 bits (incremental encoder/absolute encoder)</td></tr>
<tr><td rowspan="9">Environmental Conditions</td><td>Surrounding Air Temperature*1</td><td>-5°C to 55°C
(With derating, usage is possible between 55°C and 60°C.)
Refer to the following manual for derating specifications.
Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)</td></tr>
<tr><td>Storage Temperature</td><td>-20°C to 85°C</td></tr>
<tr><td>Surrounding Air Humidity</td><td>95% relative humidity max. (with no freezing or condensation)</td></tr>
<tr><td>Storage Humidity</td><td>95% relative humidity max. (with no freezing or condensation)</td></tr>
<tr><td>Vibration Resistance</td><td>4.9 m/s^2</td></tr>
<tr><td>Shock Resistance</td><td>19.6 m/s^2</td></tr>
<tr><td>Degree of Protection</td><td><table><tr><th>Degree</th><th>SERVOPACK Models</th></tr><tr><td>IP20</td><td>SGD7S-2R8A, -120A (three-phase, 200-VAC input), and -2R8F</td></tr><tr><td>IP10</td><td>SGD7S-120A00A008 (single-phase, 200-VAC input)</td></tr></table></td></tr>
<tr><td>Pollution Degree</td><td>2
• Must be no corrosive or flammable gases.
• Must be no exposure to water, oil, or chemicals.
• Must be no dust, salts, or iron dust.</td></tr>
<tr><td>Altitude*1</td><td>1,000 m max. (With derating, usage is possible between 1,000 m and 2,000 m.)
Refer to the following manual for derating specifications.
Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)</td></tr>
<tr><td>Others</td><td>Do not use the SERVOPACK in the following locations: Locations subject to static electricity noise, strong electromagnetic/magnetic fields, or radioactivity</td></tr>
<tr><td colspan="2">Applicable Standards</td><td>Refer to the following section for details.
☞ Compliance with UL Standards, EU Directives, and Other Safety Standards on page xxx</td></tr>
<tr><td colspan="2">Mounting</td><td>Base-mounted or rack-mounted</td></tr>
<tr><td rowspan="5">Performance</td><td>Speed Control Range</td><td>1:5000 (At the rated torque, the lower limit of the speed control range must not cause the Servomotor to stop.)</td></tr>
<tr><td rowspan="3">Coefficient of Speed Fluctuation*2</td><td>±0.01% of rated speed max. (for a load fluctuation of 0% to 100%)</td></tr>
<tr><td>0% of rated speed max. (for a load fluctuation of ±10%)</td></tr>
<tr><td>±0.1% of rated speed max. (for a temperature fluctuation of 25°C ±25°C)</td></tr>
<tr><td>Torque Control Precision (Repeatability)</td><td>±1%</td></tr>
<tr><td>Soft Start Time Setting</td><td>0 s to 10 s (Can be set separately for acceleration and deceleration.)</td></tr>
</table>

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Item			Specification
I/O Signals	Encoder Divided Pulse Output		Phase A, phase B, phase C: Line-driver output Number of divided output pulses: Any setting is allowed.
	Overheat Protection Input		Number of input points: 1 Input voltage range: 0 V to +5 V
	Sequence Input Signals	Fixed Input	Allowable voltage range: 5 VDC ±5% Number of input points: 1 SEN (Absolute Data Request) signal
		Input Signals That Can Be Allocated	Allowable voltage range: 24 VDC ±20% Number of input points: 7
			Input method: Sink inputs or source inputs Input Signals • /S-ON (Servo ON) signal • /P-CON (Proportional Control) signal • P-OT (Forward Drive Prohibit) and N-OT (Reverse Drive Prohibit) signals • /ALM-RST (Alarm Reset) signal • /P-CL (Forward External Torque Limit) and /N-CL (Reverse External Torque Limit) signals • /SPD-D (Motor Direction) signal • /SPD-A and /SPD-B (Internal Set Speed Selection) signals • /C-SEL (Control Selection) signal • /ZCLAMP (Zero Clamping) signal • /INHIBIT (Reference Pulse Inhibit) signal • /P-DET (Polarity Detection) signal • /G-SEL (Gain Selection) signal • /PSEL (Reference Pulse Input Multiplication Switch) signal • SEN (Absolute Data Request) signal A signal can be allocated and the positive and negative logic can be changed.
	Sequence Output Signals	Fixed Output	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 1 Output signal: ALM (Servo Alarm) signal
		Output Signals That Can Be Allocated	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 6 (A photocoupler output (isolated) is used for three of the outputs.) (An open-collector output (non-isolated) is used for the other three outputs.)
			Output signals • /COIN (Positioning Completion) signal • /V-CMP (Speed Coincidence Detection) signal • /TGON (Rotation Detection) signal • /S-RDY (Servo Ready) signal • /CLT (Torque Limit Detection) signal • /VLT (Speed Limit Detection) signal • /BK (Brake) signal • /WARN (Warning) signal • /NEAR (Near) signal • /PSELA (Reference Pulse Input Multiplication Switching Output) signal • ALO1, ALO2, and ALO3 (Alarm Code) signals A signal can be allocated and the positive and negative logic can be changed.

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Item			Specification
Communications	RS-422A Communications (CN3)	Interfaces	Digital Operator (JUSP-OP05A-1-E) and personal computer (with SigmaWin+)
		1:N Communications	Up to N = 15 stations possible for RS-422A port
		Axis Address Setting	Set with parameters.
	USB Communications (CN7)	Interface	Personal computer (with SigmaWin+)
		Communications Standard	Conforms to USB2.0 standard (12 Mbps).
Displays/Indicators			CHARGE indicator and five-digit seven-segment display
Panel Operator			Four push switches
Analog Monitor (CN5)			Number of points: 2 Output voltage range: ±10 VDC (effective linearity range: ±8 V) Resolution: 16 bits Accuracy: ±20 mV (Typ) Maximum output current: ±10 mA Settling time (±1%): 1.2 ms (Typ)
Dynamic Brake (DB)			Activated when a servo alarm or overtravel (OT) occurs, or when the power supply to the main circuit or servo is OFF.
Regenerative Processing			Built-in Refer to the following catalog for details. 📖 AC Servo Drives Σ-7 Series (Manual No.: KAEP S800001 23)
Overtravel (OT) Prevention			Stopping with dynamic brake, deceleration to a stop, or coasting to a stop for the P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal
Protective Functions			Overcurrent, overvoltage, low voltage, overload, regeneration error, etc.
Utility Functions			Gain adjustment, alarm history, jogging, origin search, etc.
Safety Functions	Inputs		/HWBB1 and /HWBB2: Base block signals for Power Modules
	Output		EDM1: Monitors the status of built-in safety circuit (fixed output).
	Applicable Standards*3		ISO13849-1 PLe (Category 3) and IEC61508 SIL3
Applicable Option Modules			Fully-closed Modules and Safety Modules Note: You cannot use a Fully-closed Module and a Safety Module together.

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Item					Specification
Controls	Speed Control	Soft Start Time Setting			0 s to 10 s (Can be set separately for acceleration and deceleration.)
		Input Signal		Reference Voltage	• Maximum input voltage: ±12 V (forward motor rotation for positive reference). • 6 VDC at rated speed (default setting). Input gain setting can be changed.
				Input Impedance	Approx. 14 kΩ
				Circuit Time Constant	30 μs
		Internal Set Speed Control		Rotation Direction Selection	With Proportional Control signal
				Speed Selection	With Forward/Reverse External Torque Limit signals (speed 1 to 3 selection). Servomotor stops or another control method is used when both signals are OFF.
	Position Control	Feedforward Compensation			0% to 100%
		Output Signal Positioning Completed Width Setting			0 to 1,073,741,824 reference units
		Input Signals	Reference pulses	Reference Pulse Form	One of the following is selected: Sign + pulse train, CW + CCW pulse trains, and two-phase pulse trains with 90° phase differential
				Input Form	Line driver or open collector
				Maximum Input Frequency	• Line Driver Sign + pulse train or CW + CCW pulse trains: 4 Mpps Two-phase pulse trains with 90° phase differential: 1 Mpps • Open Collector Sign + pulse train or CW + CCW pulse trains: 200 kpps Two-phase pulse trains with 90° phase differential: 200 kpps
				Input Multiplication Switching	1 to 100 times
			Clear Signal		Position deviation clear Line driver or open collector
	Torque Control	Input Signal		Reference Voltage	• Maximum input voltage: ±12 V (forward torque output for positive reference). • 3 VDC at rated torque (default setting). Input gain setting can be changed.
				Input Impedance	Approx. 14 kΩ
				Circuit Time Constant	16 μs

*1. If you combine a Σ-7-Series SERVOPACK with a Σ-V-Series Option Module, the following Σ-V-Series SERVOPACKs specifications must be used: a surrounding air temperature of 0°C to 55°C and an altitude of 1,000 m max. Also, the applicable surrounding range cannot be increased by derating.

*2. The coefficient of speed fluctuation for load fluctuation is defined as follows:

$$\text{Coefficient of speed fluctuation} = \frac{\text{No-load motor speed - Total-load motor speed}}{\text{Rated motor speed}} \times 100\%$$

*3. Always perform risk assessment for the system and confirm that the safety requirements are met.

2.3.2 FT82 SERVOPACK with MECHATROLINK-II Communications References

<table>
<tr><th colspan="2">Item</th><th>Specification</th></tr>
<tr><td colspan="2">Control Method</td><td>IGBT-based PWM control, sine wave current drive</td></tr>
<tr><td colspan="2">Feedback</td><td>Serial encoder: 24 bits (incremental encoder/absolute encoder)</td></tr>
<tr><td rowspan="8">Environmental Conditions</td><td>Surrounding Air Temperature*1</td><td>-5°C to 55°C
(With derating, usage is possible between 55°C and 60°C.)
Refer to the following manual for derating specifications.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)</td></tr>
<tr><td>Storage Temperature</td><td>-20°C to 85°C</td></tr>
<tr><td>Surrounding Air Humidity</td><td>95% relative humidity max. (with no freezing or condensation)</td></tr>
<tr><td>Storage Humidity</td><td>95% relative humidity max. (with no freezing or condensation)</td></tr>
<tr><td>Vibration Resistance</td><td>4.9 m/s^2</td></tr>
<tr><td>Shock Resistance</td><td>19.6 m/s^2</td></tr>
<tr><td>Degree of Protection</td><td><table><tr><th>Degree</th><th>SERVOPACK Models</th></tr><tr><td>IP20</td><td>SGD7S-2R8A, -120A (three-phase, 200-VAC input), and -2R8F</td></tr><tr><td>IP10</td><td>SGD7S-120A10A008 (single-phase, 200-VAC input)</td></tr></table></td></tr>
<tr><td>Pollution Degree</td><td>2
• Must be no corrosive or flammable gases.
• Must be no exposure to water, oil, or chemicals.
• Must be no dust, salts, or iron dust.</td></tr>
<tr><td>Altitude*1</td><td>1,000 m max. (With derating, usage is possible between 1,000 m and 2,000 m.)
Refer to the following manual for derating specifications.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)</td></tr>
<tr><td>Others</td><td>Do not use the SERVOPACK in the following locations: Locations subject to static electricity noise, strong electromagnetic/magnetic fields, or radioactivity</td></tr>
<tr><td colspan="2">Applicable Standards</td><td>Refer to the following section for details.
☞ Compliance with UL Standards, EU Directives, and Other Safety Standards on page xxx</td></tr>
<tr><td colspan="2">Mounting</td><td>Base-mounted or rack-mounted</td></tr>
<tr><td rowspan="5">Performance</td><td>Speed Control Range</td><td>1:5000 (At the rated torque, the lower limit of the speed control range must not cause the Servomotor to stop.)</td></tr>
<tr><td rowspan="3">Coefficient of Speed Fluctuation*2</td><td>±0.01% of rated speed max. (for a load fluctuation of 0% to 100%)</td></tr>
<tr><td>0% of rated speed max. (for a voltage fluctuation of ±10%)</td></tr>
<tr><td>±0.1% of rated speed max. (for a temperature fluctuation of 25°C ±25°C)</td></tr>
<tr><td>Torque Control Precision (Repeatability)</td><td>±1%</td></tr>
<tr><td>Soft Start Time Setting</td><td>0 s to 10 s (Can be set separately for acceleration and deceleration.)</td></tr>
</table>

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Item			Specification
I/O Signals	Encoder Divided Pulse Output		Phase A, phase B, phase C: Line-driver output Number of divided output pulses: Any setting is allowed.
	Overheat Protection Input		Number of input points: 1 Input voltage range: 0 V to +5 V
	Sequence Input Signals	Input Signals That Can Be Allocated	Allowable voltage range: 24 VDC ±20% Number of input points: 7
			Input method: Sink inputs or source inputs Input Signals • /DEC (Origin Return Deceleration Switch) signal • /EXT1 to /EXT3 (External Latch Input 1 to 3) signals • P-OT (Forward Drive Prohibit) and N-OT (Reverse Drive Prohibit) signals • /P-CL (Forward External Torque Limit) and /N-CL (Reverse External Torque Limit) signals • /P-DET (Polarity Detection) signal A signal can be allocated and the positive and negative logic can be changed.
	Sequence Output Signals	Fixed Output	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 1 Output signal: ALM (Servo Alarm) signal
		Output Signals That Can Be Allocated	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 3 (A photocoupler output (isolated) is used.)
			Output Signals • /COIN (Positioning Completion) signal • /V-CMP (Speed Coincidence Detection) signal • /TGON (Rotation Detection) signal • /S-RDY (Servo Ready) signal • /CLT (Torque Limit Detection) signal • /VLT (Speed Limit Detection) signal • /BK (Brake) signal • /WARN (Warning) signal • /NEAR (Near) signal A signal can be allocated and the positive and negative logic can be changed.
Communications	RS-422A Communications (CN3)	Interfaces	Digital Operator (JUSP-OP05A-1-E) and Personal computer (with SigmaWin+)
		1:N Communications	Up to N = 15 stations possible for RS-422A port
		Axis Address Setting	Set with parameters.
	USB Communications (CN7)	Interface	Personal computer (with SigmaWin+)
		Communications Standard	Conforms to USB2.0 standard (12 Mbps).
Displays/Indicators			CHARGE, PWR, and COM indicators, and one-digit seven-segment display

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Item		Specification
MECHATROLINK-II Communications	Communications Protocol	MECHATROLINK-II
	Station Address Settings	41h to 5Fh (maximum number of slaves: 30) Selected with the combination of a rotary switch (S2) and DIP switch (S3).
	Baud Rate	10 Mbps, 4 Mbps A DIP switch (S3) is used to select the baud rate.
	Transmission Cycle	250 μs or 0.5 ms to 4.0 ms (multiples of 0.5 ms)
	Number of Transmission Bytes	17 or 32 bytes/station A DIP switch (S3) is used to select the number of transmission bytes.
Reference Method	Performance	Position, speed, or torque control with MECHATROLINK-II communications
	Reference Input	MECHATROLINK-I or MECHATROLINK-II commands (sequence, motion, data setting, data access, monitoring, adjustment, etc.)
MECHATROLINK-II Communications Setting Switches		Rotary switch (S2) positions: 16
		Number of DIP switch (S3) pins: 4
Analog Monitor (CN5)		Number of points: 2 Output voltage range: ±10 VDC (effective linearity range: ±8 V) Resolution: 16 bits Accuracy: ±20 mV (Typ) Maximum output current: ±10 mA Settling time (±1%): 1.2 ms (Typ)
Dynamic Brake (DB)		Activated when a servo alarm or overtravel (OT) occurs, or when the power supply to the main circuit or servo is OFF.
Regenerative Processing		Built-in Refer to the following catalog for details. 📖 AC Servo Drives Σ-7 Series (Manual No.: KAEP S800001 23)
Overtravel (OT) Prevention		Stopping with dynamic brake, deceleration to a stop, or coasting to a stop for the P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal
Protective Functions		Overcurrent, overvoltage, low voltage, overload, regeneration error, etc.
Utility Functions		Gain adjustment, alarm history, jogging, origin search, etc.
Safety Functions	Inputs	/HWBB1 and /HWBB2: Base block signals for Power Modules
	Output	EDM1: Monitors the status of built-in safety circuit (fixed output).
	Applicable Standards*3	ISO13849-1 PLe (Category 3), IEC61508 SIL3
Applicable Option Modules		Fully-closed Modules and Safety Modules Note: You cannot use a Fully-closed Module and a Safety Module together.

*1. If you combine a Σ-7-Series SERVOPACK with a Σ-V-Series Option Module, the following Σ-V-Series SERVOPACKs specifications must be used: a surrounding air temperature of 0°C to 55°C and an altitude of 1,000 m max. Also, the applicable surrounding range cannot be increased by derating.

*2. The coefficient of speed fluctuation for load fluctuation is defined as follows:

$$\text{Coefficient of speed fluctuation} = \frac{\text{No-load motor speed - Total-load motor speed}}{\text{Rated motor speed}} \times 100\%$$

*3. Always perform risk assessment for the system and confirm that the safety requirements are met.

2.3.3 FT82 SERVOPACK with MECHATROLINK-III Communications References

<table>
<tr><th colspan="2">Item</th><th>Specification</th></tr>
<tr><td colspan="2">Drive Method</td><td>IGBT-based PWM control, sine wave current drive</td></tr>
<tr><td colspan="2">Feedback</td><td>Serial encoder: 24 bits (incremental encoder/absolute encoder)</td></tr>
<tr><td rowspan="8">Environmental Conditions</td><td>Surrounding Air Temperature*1</td><td>-5°C to 55°C
(With derating, usage is possible between 55°C and 60°C.)
Refer to the following manual for derating specifications.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)</td></tr>
<tr><td>Storage Temperature</td><td>-20°C to 85°C</td></tr>
<tr><td>Surrounding Air Humidity</td><td>95% relative humidity max. (with no freezing or condensation)</td></tr>
<tr><td>Storage Humidity</td><td>95% relative humidity max. (with no freezing or condensation)</td></tr>
<tr><td>Vibration Resistance</td><td>4.9 m/s^2</td></tr>
<tr><td>Shock Resistance</td><td>19.6 m/s^2</td></tr>
<tr><td>Degree of Protection</td><td><table><tr><th>Degree</th><th>SERVOPACK Models</th></tr><tr><td>IP20</td><td>SGD7S-2R8A, -120A (three-phase, 200-VAC input), and -2R8F</td></tr><tr><td>IP10</td><td>SGD7S-120A20A008 (single-phase, 200-VAC input)</td></tr></table></td></tr>
<tr><td>Pollution Degree</td><td>2
• Must be no corrosive or flammable gases.
• Must be no exposure to water, oil, or chemicals.
• Must be no dust, salts, or iron dust.</td></tr>
<tr><td>Altitude*1</td><td>1,000 m max. (With derating, usage is possible between 1,000 m and 2,000 m.)
Refer to the following manual for derating specifications.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)</td></tr>
<tr><td>Others</td><td>Do not use the SERVOPACK in the following locations: Locations subject to static electricity noise, strong electromagnetic/magnetic fields, or radioactivity</td></tr>
<tr><td colspan="2">Applicable Standards</td><td>Refer to the following section for details.
☞ Compliance with UL Standards, EU Directives, and Other Safety Standards on page xxx</td></tr>
<tr><td colspan="2">Mounting</td><td>Base-mounted or rack-mounted</td></tr>
<tr><td rowspan="5">Performance</td><td>Speed Control Range</td><td>1:5000 (At the rated torque, the lower limit of the speed control range must not cause the Servomotor to stop.)</td></tr>
<tr><td rowspan="3">Coefficient of Speed Fluctuation*2</td><td>±0.01% of rated speed max. (for a load fluctuation of 0% to 100%)</td></tr>
<tr><td>0% of rated speed max. (for a load fluctuation of ±10%)</td></tr>
<tr><td>±0.1% of rated speed max. (for a temperature fluctuation of 25°C ±25°C)</td></tr>
<tr><td>Torque Control Precision (Repeatability)</td><td>±1%</td></tr>
<tr><td>Soft Start Time Setting</td><td>0 s to 10 s (Can be set separately for acceleration and deceleration.)</td></tr>
</table>

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Item			Specification
I/O Signals	Encoder Divided Pulse Output		Phase A, phase B, phase C: Line-driver output Number of divided output pulses: Any setting is allowed.
	Overheat Protection Input		Number of input points: 1 Input voltage range: 0 V to +5 V
	Sequence Input Signals	Input Signals That Can Be Allocated	Allowable voltage range: 24 VDC ±20% Number of input points: 7
			Input method: Sink inputs or source inputs Input Signals • /DEC (Origin Return Deceleration Switch) signal • /EXT1 to /EXT3 (External Latch Input 1 to 3) signals • P-OT (Forward Drive Prohibit) and N-OT (Reverse Drive Prohibit) signals • /P-CL (Forward External Torque Limit) and /N-CL (Reverse External Torque Limit) signals • /P-DET (Polarity Detection) signal A signal can be allocated and the positive and negative logic can be changed.
	Sequence Output Signals	Fixed Output	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 1 Output signal: ALM (Servo Alarm) signal
		Output Signals That Can Be Allocated	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 3 (A photocoupler output (isolated) is used.)
			Output Signals • /COIN (Positioning Completion) signal • /V-CMP (Speed Coincidence Detection) signal • /TGON (Rotation Detection) signal • /S-RDY (Servo Ready) signal • /CLT (Torque Limit Detection) signal • /VLT (Speed Limit Detection) signal • /BK (Brake) signal • /WARN (Warning) signal • /NEAR (Near) signal A signal can be allocated and the positive and negative logic can be changed.
Communications	RS-422A Communications (CN3)	Interfaces	Digital Operator (JUSP-OP05A-1-E) and personal computer (with SigmaWin+)
		1:N Communications	Up to N = 15 stations possible for RS-422A port
		Axis Address Setting	Set with parameters.
	USB Communications (CN7)	Interface	Personal computer (with SigmaWin+)
		Communications Standard	Conforms to USB2.0 standard (12 Mbps).
Displays/Indicators			CHARGE, PWR, CN, L1, and L2 indicators, and one-digit seven-segment display

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Item		Specification
MECHATROLINK-III Communications	Communications Protocol	MECHATROLINK-III
	Station Address Settings	03h to EFh (maximum number of slaves: 62) The rotary switches (S1 and S2) are used to set the station address.
	Baud Rate	100 Mbps
	Transmission Cycle	125 μs, 250 μs, 500 μs, 750 μs, 1.0 ms to 4.0 ms (multiples of 0.5 ms)
	Number of Transmission Bytes	32 or 48 bytes/station A DIP switch (S3) is used to select the number of transmission bytes.
Reference Method	Performance	Position, speed, or torque control with MECHATROLINK-III communications
	Reference Input	MECHATROLINK-III commands (sequence, motion, data setting, data access, monitoring, adjustment, etc.)
	Profile	MECHATROLINK-III standard servo profile
MECHATROLINK-III Communications Setting Switches		Rotary switch (S1 and S2) positions: 16
		Number of DIP switch (S3) pins: 4
Analog Monitor (CN5)		Number of points: 2 Output voltage range: ±10 VDC (effective linearity range: ±8 V) Resolution: 16 bits Accuracy: ±20 mV (Typ) Maximum output current: ±10 mA Settling time (±1%): 1.2 ms (Typ)
Dynamic Brake (DB)		Activated when a servo alarm or overtravel (OT) occurs, or when the power supply to the main circuit or servo is OFF.
Regenerative Processing		Built-in Refer to the following catalog for details. 📖 AC Servo Drives Σ-7 Series (Manual No.: KAEP S800001 23)
Overtravel (OT) Prevention		Stopping with dynamic brake, deceleration to a stop, or coasting to a stop for the P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal
Protective Functions		Overcurrent, overvoltage, low voltage, overload, regeneration error, etc.
Utility Functions		Gain adjustment, alarm history, jogging, origin search, etc.
Safety Functions	Inputs	/HWBB1 and /HWBB2: Base block signals for Power Modules
	Output	EDM1: Monitors the status of built-in safety circuit (fixed output).
	Applicable Standards*3	ISO13849-1 PLe (Category 3), IEC61508 SIL3
Applicable Option Modules		Fully-closed Modules and Safety Modules Note: You cannot use a Fully-closed Module and a Safety Module together.

*1. If you combine a Σ-7-Series SERVOPACK with a Σ-V-Series Option Module, the following Σ-V-Series SERVOPACKs specifications must be used: a surrounding air temperature of 0°C to 55°C and an altitude of 1,000 m max. Also, the applicable surrounding range cannot be increased by derating.

*2. The coefficient of speed fluctuation for load fluctuation is defined as follows:

$$\text{Coefficient of speed fluctuation} = \frac{\text{No-load motor speed - Total-load motor speed}}{\text{Rated motor speed}} \times 100\%$$

*3. Always perform risk assessment for the system and confirm that the safety requirements are met.

2.3.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules

The specifications when the INDEXER Module is combined with a Command Option Attachable-type SERVOPACK are given in the following table.

Item		Specification
Control Method		IGBT-based PWM control, sine wave current drive
Feedback		Serial encoder: 24 bits (incremental encoder/absolute encoder)
Environmental Conditions	Surrounding Air Temperature	0°C to 55°C
	Storage Temperature	-20°C to 85°C
	Surrounding Air Humidity	90% relative humidity max. (with no freezing or condensation)
	Storage Humidity	90% relative humidity max. (with no freezing or condensation)
	Vibration Resistance	4.9 m/s^2
	Shock Resistance	19.6 m/s^2
	Degree of Protection	IP10
	Pollution Degree	2 • Must be no corrosive or flammable gases. • Must be no exposure to water, oil, or chemicals. • Must be no dust, salts, or iron dust.
	Altitude	1,000 m or less.
	Others	Do not use the SERVOPACK in the following locations: Locations subject to static electricity noise, strong electromagnetic/magnetic fields, or radioactivity
Applicable Standards		Refer to the following section for details. ☞ *Compliance with UL Standards, EU Directives, and Other Safety Standards* on page xxx
Mounting		Base-mounted or rack-mounted
Performance	Speed Control Range	1:5000 (At the rated torque, the lower limit of the speed control range must not cause the Servomotor to stop.)
	Coefficient of Speed Fluctuation*1	±0.01% of rated speed max. (for a load fluctuation of 0% to 100%)
		0% of rated speed max. (for a voltage fluctuation of ±10%)
		±0.1% of rated speed max. (for a temperature fluctuation of 25°C ±25°C)
	Torque Control Precision (Repeatability)	±1%
	Soft Start Time Setting	0 s to 10 s (Can be set separately for acceleration and deceleration.)

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<table>
<tr><th colspan="4">Item</th><th colspan="2">Specification</th></tr>
<tr><td rowspan="11">I/O Signals</td><td colspan="3">Encoder Divided Pulse Output</td><td colspan="2">Phase A, phase B, phase C: Line-driver output
Number of divided output pulses: Any setting is allowed.</td></tr>
<tr><td colspan="3">Overheat Protection Input</td><td colspan="2">Number of input points: 1
Input voltage range: 0 V to +5 V</td></tr>
<tr><td rowspan="9">Sequence Input Signals</td><td rowspan="2">SERVOPACK</td><td rowspan="9">Fixed Inputs</td><td colspan="2">Allowable voltage range: 24 VDC ±20%
Number of input points: 6</td></tr>
<tr><td colspan="2">Input method: Sink inputs or source inputs
Input signals:
• /ALM-RST (Alarm Reset) signal
• P-OT (Forward Drive Prohibit) signal
• N-OT (Reverse Drive Prohibit) signal
• /DEC (Origin Return Deceleration) switch
• /RGRT (Registration Input) signal
• /S-ON (Servo ON) signal
Positive or negative logic can be changed in the parameters.</td></tr>
<tr><td rowspan="7">INDEXER Module</td><td colspan="2">Allowable voltage range: 24 VDC ±10%
Number of input points: 11</td></tr>
<tr><td colspan="2">/MODE 0/1 (Mode Switch Input) signal</td></tr>
<tr><th>Mode 0</th><th>Mode 1</th></tr>
<tr><td>• /START-STOP (Program Table Operation Start-Stop Input) signal
• /PGMRES (Program Table Operation Reset Input) signal
• /SEL0 (Program Step Selection Input 0) signal
• /SEL1 (Program Step Selection Input 1) signal
• /SEL2 (Program Step Selection Input 2) signal
• /SEL3 (Program Step Selection Input 3) signal
• /SEL4 (Program Step Selection Input 4) signal
• /SEL5 (Program Step Selection Input 5) signal
• /SEL6 (Program Step Selection Input 6) signal
• /SEL7 (Program Step Selection Input 7) signal</td><td>• /HOME (Origin Return Input) signal
• /JOGP (Forward Jog Input) signal
• /JOGN (Reverse Jog Input) signal
• /JOG0 (Jog Speed Table Selection Input 0) signal
• /JOG1 (Jog Speed Table Selection Input 1) signal
• /JOG2 (Jog Speed Table Selection Input 2) signal
• /JOG3 (Jog Speed Table Selection Input 3) signal</td></tr>
</table>

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Item				Specification
I/O Signals	Sequence Output Signals	SERVOPACK	Fixed Outputs	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 1 Output signal: ALM (Servo Alarm Output) signal
			Output Signals for Which Allocations Can Be Changed	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 3 (A photocoupler output (isolated) is used.)
				Output signals: • /WARN (Warning Output) signal • /BK (Brake Output) signal • /S-RDY (Servo Ready Output) signal • ALO1, ALO2, and ALO3 (Alarm Code Output) signals Signal allocations and positive or negative logic can be changed in the parameters.
		INDEXER Module	Fixed Outputs	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 9 Output signals: • /INPOSITION (Positioning Completion Output) signal • /POUT0 (Programmable Output 0) signal • /POUT1 (Programmable Output 1) signal • /POUT2 (Programmable Output 2) signal • /POUT3 (Programmable Output 3) signal • /POUT4 (Programmable Output 4) signal • /POUT5 (Programmable Output 5) signal • /POUT6 (Programmable Output 6) signal • /POUT7 (Programmable Output 7) signal
Communications	RS-422A Communications (CN3)	Interfaces		Digital Operator (JUSP-OP05A-1-E) and Personal computer (with SigmaWin+)
		1:N Communications		Up to N = 15 stations possible for RS-422A port
		Axis Address Setting		Set with parameters.
	USB Communications (CN7)	Interface		Personal computer (with SigmaWin+)
		Communications Standard		Conforms to USB2.0 standard (12 Mbps).
Displays/ Indicators	SERVOPACK			CHARGE and PWR indicators, and one-digit seven-segment display
	INDEXER Module			Refer to the following manual for details. Σ-7-Series Σ-7S Command Option Attachable-type SERVOPACK with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)

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Item			Specification
Operating Methods	Program Table Method		• Program table positioning in which steps are executed sequentially by commands given through contact input or serial communications • Positioning in which station numbers are specified by commands given through contact input or serial communications
		Max. Number of Steps	256
		Max. Number of Tables	256
		Max. Number of Stations	256
	Serial Communications Method		Serial command by 1-channel ASCII code Communications specifications: RS-422/485 (50 m max.) Connection topology: Multi-drop connection (16 axes max.) Baud rate: 9600, 19200, 38400 bps
	Other Functions		Registration (positioning by external signals), origin return
Analog Monitor (CN5)			Number of points: 2 Output voltage range: ±10 VDC (effective linearity range: ±8 V) Resolution: 16 bits Accuracy: ±20 mV (Typ) Maximum output current: ±10 mA Settling time (±1%): 1.2 ms (Typ)
Dynamic Brake (DB)			Activated when a servo alarm or overtravel (OT) occurs, or when the power supply to the main circuit or servo is OFF.
Regenerative Processing			Built-in Refer to the following manual for details. 📖 Σ-7-Series Peripheral Device Selection Manual (Manual No.: SIEP S800001 32)
Overtravel (OT) Prevention			Stopping with dynamic brake, deceleration to a stop, or coasting to a stop for the P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal
Protective Functions			Overcurrent, overvoltage, low voltage, overload, regeneration error, etc.
Utility Functions			Gain adjustment, alarm history, jogging, origin search, etc.
Safety Functions	Inputs		/HWBB1 and /HWBB2: Base block signals for Power Modules
	Output		EDM1: Monitors the status of built-in safety circuit (fixed output).
	Applicable Standards*2		ISO13849-1 PLe (Category 3), IEC61508 SIL3
Applicable Option Modules			Fully-Closed Module Note: You cannot use a Safety Module if you are using an INDEXER Module.

*1. The coefficient of speed fluctuation for load fluctuation is defined as follows:

$$\text{Coefficient of speed fluctuation} = \frac{\text{No-load motor speed - Total-load motor speed}}{\text{Rated motor speed}} \times 100\%$$

*2. Always perform risk assessment for the system and confirm that the safety requirements are met.

2.3.5 FT83 SERVOPACKs with Analog Voltage/Pulse Train References

The product specifications are given below.

Item		Specification
Control Method		IGBT-based PWM control, sine wave current drive
Feedback		Serial encoder: 24 bits (incremental encoder/absolute encoder)
Environmental Conditions	Surrounding Air Temperature*1	0°C to 55°C
	Storage Temperature	-20°C to 85°C
	Surrounding Air Humidity	90% relative humidity max. (with no freezing or condensation)
	Storage Humidity	90% relative humidity max. (with no freezing or condensation)
	Vibration Resistance	4.9 m/s^2
	Shock Resistance	19.6 m/s^2
	Degree of Protection	IP10
	Pollution Degree	2 • Must be no corrosive or flammable gases. • Must be no exposure to water, oil, or chemicals. • Must be no dust, salts, or iron dust.
	Altitude*1	1,000 m max.
	Others	Do not use the SERVOPACK in the following locations: Locations subject to static electricity noise, strong electromagnetic/magnetic fields, or radioactivity
Applicable Standards		Refer to the following section for details. ☞ *Compliance with UL Standards, EU Directives, and Other Safety Standards* on page xxx
Mounting		Base-mounted or rack-mounted
Performance	Speed Control Range	1:5000 (At the rated torque, the lower limit of the speed control range must not cause the Servomotor to stop.)
	Coefficient of Speed Fluctuation*2	±0.01% of rated speed max. (for a load fluctuation of 0% to 100%)
		0% of rated speed max. (for a load fluctuation of ±10%)
		±0.1% of rated speed max. (for a temperature fluctuation of 25°C ±25°C)
	Torque Control Precision (Repeatability)	±1%
	Soft Start Time Setting	0 s to 10 s (Can be set separately for acceleration and deceleration.)
I/O Signals	Encoder Divided Pulse Output	Phase A, phase B, phase C: Line-driver output Number of divided output pulses: Any setting is allowed.
	Overheat Protection Input	Number of input points: 1 Input voltage range: 0 V to +5 V

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Item				Specification
I/O Signals	Sequence Input Signals	SERVO-PACKs	Fixed Input	Allowable voltage range: 5 VDC ±5% Number of input points: 1 SEN (Absolute Data Request) signal
			Input Signals for Which Allocations Can Be Changed	Number of input points: 1 Input method: Line driver or open collector Input Signals • /DEC (Origin Return Deceleration Switch) signal • /RGRT (Registration Input) signal • CLR (Clear) signal
				Allowable voltage range: 24 VDC ±20% Number of input points: 7 Input method: Sink inputs or source inputs Input Signals • /S-ON (Servo ON) signal • /P-CON (Proportional Control) Signal • P-OT (Forward Drive Prohibit) and N-OT (Reverse Drive Prohibit) signals • /ALM-RST (Alarm Reset) signal • /P-CL (Forward External Torque Limit) and /N-CL (Reverse External Torque Limit) signals • /SPD-D (Motor Direction) signal • /SPD-A and /SPD-B (Internal Set Speed Selection) signals • /C-SEL (Control Selection) signal • /ZCLAMP (Zero Clamping) signal • /INHIBIT (Reference Pulse Inhibit) signal • /P-DET (Polarity Detection) signal • /G-SEL (Gain Selection) signal • /PSEL (Reference Pulse Input Multiplication Switch) Signal • SEN (Absolute Data Request) signal • /DEC (Origin Return Deceleration Switch) signal • /MODE 0/1 (Mode Switch Input) signal • /START-STOP (Program Table Operation Start-Stop Input) signal • /JOGP (Forward Jog Input) signal • /JOGN (Reverse Jog Input) signal • /HOME (Origin Return Input) signal • /PGMRES (Program Table Operation Reset Input) signal • /SEL0 (Program Step Selection Input 0) signal • /SEL1 (Program Step Selection Input 1) signal • /SEL2 (Program Step Selection Input 2) signal • /SEL3 (Program Step Selection Input 3) signal • /SEL4 (Program Step Selection Input 4) signal • /JOG0 (Jog Speed Table Selection Input 0) signal • /JOG1 (Jog Speed Table Selection Input 1) signal • /JOG2 (Jog Speed Table Selection Input 2) signal A signal can be allocated and the positive and negative logic can be changed.

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Item				Specification
I/O Signals	Sequence Output Signals	SERVO-PACKs	Fixed Output	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 1 Output signal: ALM (Servo Alarm) signal
			Output Signals That Can Be Allocated	Allowable voltage range: 5 VDC to 30 VDC Number of output points: 6 (A photocoupler output (isolated) is used for three of the outputs.) (An open-collector output (non-isolated) is used for the other three outputs.) Output Signals • /COIN (Positioning Completion) Signal • /V-CMP (Speed Coincidence Detection) Signal • /TGON (Rotation Detection) Signal • /S-RDY (Servo Ready) signal • /CLT (Torque Limit Detection) Signal • /VLT (Speed Limit Detection) Signal • /BK (Brake) signal • /WARN (Warning) Signal • /NEAR (Near) signal • /PSELA (Reference Pulse Input Multiplication Switching Output) signal • ALO1, ALO2, and ALO3 (Alarm Code) signals • /POUT0 (Programmable Output 0) signal • /POUT1 (Programmable Output 1) signal • /POUT2 (Programmable Output 2) signal • /POUT3 (Programmable Output 3) signal • /POUT4 (Programmable Output 4) signal • /POSRDY (Origin Return Completed Output) signal • DEN (Position Reference Distribution Completed) signal A signal can be allocated and the positive and negative logic can be changed.
Communi-cations	Digital Operator Communi-cations (CN3)	Interfaces		Digital Operator (JUSP-OP05A-1-E)
		1:N Communications		Up to N = 15 stations possible for RS-422A port
		Axis Address Set-ting		Set with parameters.
	USB Communi-cations (CN7)	Interface		Personal computer (with SigmaWin+)
		Communications Standard		Conforms to USB2.0 standard (12 Mbps).
Displays/ Indicators	SERVOPACK			CHARGE indicator and five-digit seven-segment display
Panel Operator				Four push switches
Operating Methods	Program Table			• Program table positioning in which steps are executed in sequence with commands from contact inputs • Positioning by specifying station numbers with commands from contact inputs
		Maximum Number of Steps		256 steps (32 steps max. if input signals are used)
	Other Functions			Registration (positioning with external signals) and origin returns.
Analog Monitor (CN5)				Number of points: 2 Output voltage range: ±10 VDC (effective linearity range: ±8 V) Resolution: 16 bits Accuracy: ±20 mV (Typ) Maximum output current: ±10 mA Settling time (±1%): 1.2 ms (Typ)

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Item				Specification
Dynamic Brake (DB)				Activated when a servo alarm or overtravel (OT) occurs, or when the power supply to the main circuit or servo is OFF.
Regenerative Processing				Built-in (An external resistor must be connected to the SGD7S-470A to -780A.) Refer to the following catalog for details. 📖 Σ-7 Series AC Servo Drive Peripheral Device Selection Manual (Manual No.: SIEP S800001 32)
Overtravel (OT) Prevention				Stopping with dynamic brake, deceleration to a stop, or coasting to a stop for the P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal
Protective Functions				Overcurrent, overvoltage, low voltage, overload, regeneration error, etc.
Utility Functions				Gain adjustment, alarm history, jogging, origin search, etc.
Safety Functions		Inputs		/HWBB1 and /HWBB2: Base block signals for Power Modules
		Output		EDM1: Monitors the status of built-in safety circuit (fixed output).
		Applicable Standards*3		ISO13849-1 PLe (Category 3) and IEC61508 SIL3
Applicable Option Modules				Fully-closed Modules and Safety Modules Note: You cannot use a Fully-closed Module and a Safety Module together.
Controls	Speed Control	Soft Start Time Setting		0 s to 10 s (Can be set separately for acceleration and deceleration.)
		Input Signal	Reference Voltage	• Maximum input voltage: ±12 V (forward motor rotation for positive reference). • 6 VDC at rated speed (default setting). Input gain setting can be changed.
			Input Impedance	Approx. 14 kΩ
			Circuit Time Constant	30 μs
		Internal Set Speed Control	Rotation Direction Selection	With Proportional Control signal
			Speed Selection	With Forward/Reverse External Torque Limit signals (speed 1 to 3 selection). Servomotor stops or another control method is used when both signals are OFF.

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Item					Specification
Controls	Position Control	Feedforward Compensation			0% to 100%
		Output Signal Positioning Completed Width Setting			0 to 1,073,741,824 reference units
		Input Signals	Reference pulses	Reference Pulse Form	One of the following is selected: Sign + pulse train, CW + CCW pulse trains, and two-phase pulse trains with 90° phase differential
				Input Form	Line driver or open collector
				Maximum Input Frequency	• Line Driver Sign + pulse train or CW + CCW pulse trains: 4 Mpps Two-phase pulse trains with 90° phase differential: 1 Mpps • Open Collector Sign + pulse train or CW + CCW pulse trains: 200 kpps Two-phase pulse trains with 90° phase differential: 200 kpps
				Input Multiplication Switching	1 to 100 times
			Clear Signal		Position deviation clear Line driver or open collector
	Torque Control	Input Signal		Reference Voltage	• Maximum input voltage: ±12 V (forward torque output for positive reference). • 3 VDC at rated torque (default setting). Input gain setting can be changed.
				Input Impedance	Approx. 14 kΩ
				Circuit Time Constant	16 μs

*1. If you combine a Σ-7-Series SERVOPACK with a Σ-V-Series Option Module, the following Σ-V-Series SERVOPACKs specifications must be used: a surrounding air temperature of 0°C to 55°C and an altitude of 1,000 m max. Also, the applicable surrounding range cannot be increased by derating.

*2. The coefficient of speed fluctuation for load fluctuation is defined as follows:

$$\text{Coefficient of speed fluctuation} = \frac{\text{No-load motor speed - Total-load motor speed}}{\text{Rated motor speed}} \times 100\%$$

*3. Always perform risk assessment for the system and confirm that the safety requirements are met.

Maintenance

3

This chapter provides information on the meaning of, causes of, and corrections for alarms and warnings.

3.1 FT82 SERVOPACKs with Analog Voltage/Pulse Train References . . 3-3

3.1.1 Alarm Displays 3-3
3.1.2 List of Alarms 3-3
3.1.3 Troubleshooting Alarms 3-9
3.1.4 Warning Displays 3-34
3.1.5 List of Warnings 3-34
3.1.6 Troubleshooting Warnings 3-35
3.1.7 Troubleshooting Based on the Operation and Conditions of the Servomotor 3-41

3.2 FT82 SERVOPACK with MECHATROLINK-II Communications References . .3-50

3.2.1 Alarm Displays 3-50
3.2.2 List of Alarms 3-50
3.2.3 Troubleshooting Alarms 3-55
3.2.4 Warning Displays 3-80
3.2.5 List of Warnings 3-80
3.2.6 Troubleshooting Warnings 3-82
3.2.7 Troubleshooting Based on the Operation and Conditions of the Servomotor 3-89

3.3 FT82 SERVOPACK with MECHATROLINK-III Communications References . . 3-98

3.3.1 Alarm Displays 3-98
3.3.2 List of Alarms 3-98
3.3.3 Troubleshooting Alarms 3-103
3.3.4 Warning Displays 3-128
3.3.5 List of Warnings 3-128
3.3.6 Troubleshooting Warnings 3-130
3.3.7 Troubleshooting Based on the Operation and Conditions of the Servomotor 3-137

3.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules . . 3-145

3.4.1 Alarm Displays 3-145
3.4.2 List of Alarms 3-146
3.4.3 Troubleshooting Alarms 3-151
3.4.4 INDEXER Module Alarm Displays and Troubleshooting 3-177
3.4.5 Warning Displays 3-181
3.4.6 List of Warnings 3-181
3.4.7 Troubleshooting Warnings 3-183
3.4.8 INDEXER Module Error Displays and Troubleshooting 3-189
3.4.9 Troubleshooting Based on the Operation and Conditions of the Servomotor 3-197

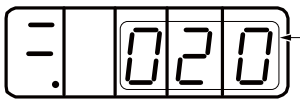
3.5 FT83 SERVOPACKs with Analog Voltage/Pulse Train References . . 3-205

3.5.1 Alarm Displays 3-205
3.5.2 List of Alarms 3-205
3.5.3 Troubleshooting Alarms 3-210
3.5.4 INDEXER Alarm Displays and Troubleshooting 3-234
3.5.5 Warning Displays 3-238
3.5.6 List of Warnings 3-238
3.5.7 Troubleshooting Warnings 3-240
3.5.8 INDEXER Warning Displays and Troubleshooting 3-246
3.5.9 Troubleshooting Based on the Operation and Conditions of the Servomotor 3-250

3.1 FT82 SERVOPACKs with Analog Voltage/Pulse Train References

3.1.1 Alarm Displays

If an error occurs in the SERVOPACK, an alarm number will be displayed on the panel display. However, if □□-□□ appears on the panel display, the display will indicate a SERVOPACK system error. Replace the SERVOPACK.



Example: If an A.020 alarm occurs, "020" will flash on the display.

3.1.2 List of Alarms

The list of alarms gives the alarm name, alarm meaning, alarm stopping method, alarm reset possibility, and alarm code output in order of the alarm numbers.

Servomotor Stopping Method for Alarms

Refer to the following manual for information on the stopping method for alarms.

Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

Alarm Reset Possibility

Yes: You can use an alarm reset to clear the alarm. However, this assumes that the cause of the alarm has been removed.
No: You cannot clear the alarm.

List of Alarms

Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					ALO1	ALO2	ALO3
A.020	Parameter Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No	H	H	H
A.021	Parameter Format Error	There is an error in the parameter data format in the SERVOPACK.	Gr.1	No	H	H	H
A.022	System Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No	H	H	H
A.024	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.025	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.030	Main Circuit Detector Error	There is an error in the detection data for the main circuit.	Gr.1	Yes	H	H	H

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					ALO1	ALO2	ALO3
A.040	Parameter Setting Error	A parameter setting is outside of the setting range.	Gr.1	No	H	H	H
A.041	Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Gr.1	No	H	H	H
A.042	Parameter Combination Error	The combination of some parameters exceeds the setting range.	Gr.1	No	H	H	H
A.044	Semi-Closed/Fully-Closed Loop Control Parameter Setting Error	The settings of the Option Module and Pn002 = n.X□□□ (External Encoder Usage) do not match.	Gr.1	No	H	H	H
A.050	Combination Error	The capacities of the SERVOPACK and Servomotor do not match.	Gr.1	Yes	H	H	H
A.051	Unsupported Device Alarm	An unsupported device was connected.	Gr.1	No	H	H	H
A.0b0	Invalid Servo ON Command Alarm	The /S-ON (Servo ON) signal was input from the host controller after a utility function that turns ON the Servomotor was executed.	Gr.1	Yes	H	H	H
A.100	Overcurrent Detected	An overcurrent flowed through the power transformer or the heat sink overheated.	Gr.1	No	L	H	H
A.101	Motor Overcurrent Detected	The current to the motor exceeded the allowable current.	Gr.1	No	L	H	H
A.300	Regeneration Error	There is an error related to regeneration.	Gr.1	Yes	L	L	H
A.320	Regenerative Overload	A regenerative overload occurred.	Gr.2	Yes	L	L	H
A.330	Main Circuit Power Supply Wiring Error	• The AC power supply input setting or DC power supply input setting is not correct. • The power supply wiring is not correct.	Gr.1	Yes	L	L	H
A.400	Overvoltage	The main circuit DC voltage is too high.	Gr.1	Yes	H	H	L
A.410	Undervoltage	The main circuit DC voltage is too low.	Gr.2	Yes	H	H	L
A.510	Overspeed	The motor exceeded the maximum speed.	Gr.1	Yes	L	H	L
A.511	Encoder Output Pulse Overspeed	The pulse output speed for the setting of Pn212 (Encoder Output Pulses) was exceeded.	Gr.1	Yes	L	H	L
A.520	Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Gr.1	Yes	L	H	L
A.521	Autotuning Alarm	Vibration was detected during autotuning for the tuning-less function.	Gr.1	Yes	L	H	L

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					ALO1	ALO2	ALO3
A.550	Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum motor speed.	Gr.1	Yes	L	H	L
A.710	Instantaneous Overload	The Servomotor was operating for several seconds to several tens of seconds under a torque that largely exceeded the rating.	Gr.2	Yes	L	L	L
A.720	Continuous Overload	The Servomotor was operating continuously under a torque that exceeded the rating.	Gr.1	Yes	L	L	L
A.730	Dynamic Brake Overload	When the dynamic brake was applied, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Gr.1	Yes	L	L	L
A.731							
A.740	Inrush Current Limiting Resistor Overload	The main circuit power supply was frequently turned ON and OFF.	Gr.1	Yes	L	L	L
A.7A1	Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	Gr.2	Yes	L	L	L
A.7A2	Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.	Gr.2	Yes	L	L	L
A.7A3	Internal Temperature Sensor Error	An error occurred in the temperature sensor circuit.	Gr.2	No	L	L	L
A.7Ab	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Gr.1	Yes	L	L	L
A.810	Encoder Backup Alarm	The power supplies to the encoder all failed and the position data was lost.	Gr.1	No	H	H	H
A.820	Encoder Checksum Alarm	There is an error in the checksum results for encoder memory.	Gr.1	No	H	H	H
A.830	Encoder Battery Alarm	The battery voltage was lower than the specified level after the control power supply was turned ON.	Gr.1	Yes	H	H	H
A.840	Encoder Data Alarm	There is an internal data error in the encoder.	Gr.1	No	H	H	H
A.850	Encoder Overspeed	The encoder was operating at high speed when the power was turned ON.	Gr.1	No	H	H	H
A.860	Encoder Overheated	The internal temperature of the rotary encoder or linear encoder is too high.	Gr.1	No	H	H	H
A.861	Motor Overheated	The internal temperature of motor is too high.	Gr.1	No	H	H	H

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					ALO1	ALO2	ALO3
A.862	Overheat Alarm	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61B (Overheat Alarm Level).	Gr.1	Yes	H	H	H
A.8A0	External Encoder Error	An error occurred in the external encoder.	Gr.1	Yes	H	H	H
A.8A1	External Encoder Module Error	An error occurred in the Serial Converter Unit.	Gr.1	Yes	H	H	H
A.8A2	External Incremental Encoder Sensor Error	An error occurred in the external encoder.	Gr.1	Yes	H	H	H
A.8A3	External Absolute Encoder Position Error	An error occurred in the position data of the external encoder.	Gr.1	Yes	H	H	H
A.8A5	External Encoder Overspeed	An overspeed error occurred in the external encoder.	Gr.1	Yes	H	H	H
A.8A6	External Encoder Overheated	An overheating error occurred in the external encoder.	Gr.1	Yes	H	H	H
A.b10	Speed Reference A/D Error	An error occurred in the A/D converter for the speed reference input.	Gr.2	Yes	H	H	H
A.b11	Speed Reference A/D Data Error	An error occurred in the A/D conversion data for the speed reference.	Gr.2	Yes	H	H	H
A.b20	Torque Reference A/D Error	An error occurred in the A/D converter for the torque reference input.	Gr.2	Yes	H	H	H
A.b33	Current Detection Error 3	An error occurred in the current detection circuit.	Gr.1	No	H	H	H
A.bF0	System Alarm 0	Internal program error 0 occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.bF1	System Alarm 1	Internal program error 1 occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.bF2	System Alarm 2	Internal program error 2 occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.bF3	System Alarm 3	Internal program error 3 occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.bF4	System Alarm 4	Internal program error 4 occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.bF5	System Alarm 5	Internal program error 5 occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.bF6	System Alarm 6	Internal program error 6 occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.bF7	System Alarm 7	Internal program error 7 occurred in the SERVOPACK.	Gr.1	No	H	H	H

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					ALO1	ALO2	ALO3
A.bF8	System Alarm 8	Internal program error 8 occurred in the SERVOPACK.	Gr.1	No	H	H	H
A.C10	Servomotor Out of Control	The Servomotor ran out of control.	Gr.1	Yes	L	H	L
A.C80	Encoder Clear Error or Multiturn Limit Setting Error	The multiturn data for the absolute encoder was not correctly cleared or set.	Gr.1	No	L	H	L
A.C90	Encoder Communications Error	Communications between the encoder and SERVOPACK is not possible.	Gr.1	No	L	H	L
A.C91	Encoder Communications Position Data Acceleration Rate Error	An error occurred in calculating the position data of the encoder.	Gr.1	No	L	H	L
A.C92	Encoder Communications Timer Error	An error occurred in the communications timer between the encoder and SERVOPACK.	Gr.1	No	L	H	L
A.CA0	Encoder Parameter Error	The parameters in the encoder are corrupted.	Gr.1	No	L	H	L
A.Cb0	Encoder Echoback Error	The contents of communications with the encoder are incorrect.	Gr.1	No	L	H	L
A.CC0	Multiturn Limit Disagreement	Different multiturn limits have been set in the encoder and the SERVOPACK.	Gr.1	No	L	H	L
A.CF1	Reception Failed Error in Feedback Option Module Communications	Receiving data from the Feedback Option Module failed.	Gr.1	No	L	H	L
A.CF2	Timer Stopped Error in Feedback Option Module Communications	An error occurred in the timer for communications with the Feedback Option Module.	Gr.1	No	L	H	L
A.d00	Position Deviation Overflow	The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.	Gr.1	Yes	L	L	H
A.d01	Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Gr.1	Yes	L	L	H
A.d02	Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if reference pulses are input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded before the limit is cleared.	Gr.2	Yes	L	L	H

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					ALO1	ALO2	ALO3
A.d10	Motor-Load Position Deviation Overflow	There was too much position deviation between the motor and load during fully-closed loop control.	Gr.2	Yes	L	L	H
A.d30	Position Data Overflow	The position feedback data exceeded ±1,879,048,192.	Gr.1	No	L	L	H
A.E71	Safety Option Module Detection Failure	Detection of the Safety Option Module failed.	Gr.1	No	H	L	L
A.E72	Feedback Option Module Detection Failure	Detection of the Feedback Option Module failed.	Gr.1	No	H	L	L
A.E74	Unsupported Safety Option Module	An unsupported Safety Option Module was connected.	Gr.1	No	H	L	L
A.Eb1	Safety Function Signal Input Timing Error	An error occurred in the input timing of the safety function signal.	Gr.1	No	H	L	L
A.EC8	Gate Drive Error 1	An error occurred in the gate drive circuit.	Gr.1	No	H	L	L
A.EC9	Gate Drive Error 2	An error occurred in the gate drive circuit.	Gr.1	No	H	L	L
A.F10	Power Supply Line Open Phase	The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.	Gr.2	Yes	H	L	H
FL-1*	System Alarm	An internal program error occurred in the SERVOPACK.	–	No	Undefined.		
FL-2*							
FL-3*							
FL-4*							
FL-5*							
FL-6*							
CPF00	Digital Operator Communications Error 1	Communications were not possible between the Digital Operator (model: JUSP-OP05A-1-E) and the SERVOPACK (e.g., a CPU error occurred).	–	No	Undefined.		
CPF01	Digital Operator Communications Error 2						

* These alarms are not stored in the alarm history. They are only displayed on the panel display.

Note: The A.Eb0, A.Eb2 to A.Eb9, and A.EC0 to A.EC2 alarms can occur when a Safety Module is connected. Refer to the following manual for details.
Σ-V-Series/Σ-V-Series for Large-Capacity Models/Σ-7-Series User's Manual Safety Module (Manual No.: SIEP C720829 06)

3.1.3 Troubleshooting Alarms

The causes of and corrections for the alarms are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.020: Parameter Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	Set the power supply voltage within the specified range, and initialize the parameter settings.	*1
	The power supply was shut OFF while writing parameter settings.	Check the timing of shutting OFF the power supply.	Initialize the parameter settings and then set the parameters again.	
	The number of times that parameters were written exceeded the limit.	Check to see if the parameters were frequently changed from the host controller.	The SERVOPACK may be faulty. Replace the SERVOPACK. Reconsider the method for writing the parameters.	–
	A malfunction was caused by noise from the AC power supply, ground, static electricity, or other source.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, noise may be the cause.	Implement countermeasures against noise.	*1
	Gas, water drops, or cutting oil entered the SERVOPACK and caused failure of the internal components.	Check the installation conditions.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.021: Parameter Format Error (There is an error in the parameter data format in the SERVOPACK.)	The software version of the SERVOPACK that caused the alarm is older than the software version of the parameters specified to write.	Read the product information to see if the software versions are the same. If they are different, it could be the cause of the alarm.	Write the parameters from another SERVOPACK with the same model and the same software version, and then turn the power OFF and ON again.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.022: System Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The power supply was shut OFF while setting a utility function.	Check the timing of shutting OFF the power supply.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.024: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.025: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.030: Main Circuit Detector Error	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.040: Parameter Setting Error (A parameter setting is outside of the setting range.)	The SERVOPACK and Servomotor capacities do not match each other.	Check the combination of the SERVOPACK and Servomotor capacities.	Select a proper combination of SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A parameter setting is outside of the setting range.	Check the setting ranges of the parameters that have been changed.	Set the parameters to values within the setting ranges.	–
	The electronic gear ratio is outside of the setting range.	Check the electronic gear ratio. The ratio must be within the following range: 0.001 < (Pn20E/Pn210) < 64,000.	Set the electronic gear ratio in the following range: 0.001 < (Pn20E/Pn210) < 64,000.	*1
A.041: Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Check the setting of Pn212 or Pn281.	Set Pn212 or Pn281 to an appropriate value.	*1
A.042: Parameter Combination Error	The speed of program jogging went below the setting range when the electronic gear ratio (Pn20E/Pn210) or the Servomotor was changed.	Check to see if the detection conditions*2 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1
	The speed of program jogging went below the setting range when Pn533 or Pn585 (Program Jogging Speed) was changed.	Check to see if the detection conditions*2 are satisfied.	Increase the setting of Pn533 or Pn585.	*1
	The movement speed of advanced autotuning went below the setting range when the electronic gear ratio (Pn20E/ Pn210) or the Servomotor was changed.	Check to see if the detection conditions*3 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.044: Semi-Closed/ Fully-Closed Loop Control Parameter Setting Error	The setting of the Fully-Closed Module does not match the setting of Pn002 = n.X□□□ (External Encoder Usage).	Check the setting of Pn002 = n.X□□□.	Make sure that the setting of the Fully-closed Module agrees with the setting of Pn002 = n.X□□□.	*1
A.050: Combination Error (The capacities of the SERVOPACK and Servomotor do not match.)	The SERVOPACK and Servomotor capacities do not match each other.	Confirm that the following condition is met: 1/4 ≤ (Servomotor capacity/SERVOPACK capacity) ≤ 4	Select a proper combination of the SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the encoder.	Replace the encoder and check to see if the alarm still occurs.	Replace the Servomotor or encoder.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.051: Unsupported Device Alarm	An unsupported Serial Converter Unit or encoder (e.g., an external encoder) is connected to the SERVOPACK.	Check the product combination specifications.	Change to a correct combination of models.	–
A.0b0: Invalid Servo ON Command Alarm	The /S-ON (Servo ON) signal was input from the host controller after a utility function that turns ON the Servomotor was executed.	–	Turn the power supply to the SERVOPACK OFF and ON again. Or, execute a software reset.	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	The regenerative resistor is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	The dynamic brake (DB, emergency stop executed from the SERVOPACK) was frequently activated, or a DB overload alarm occurred.	Check the power consumed by the DB resistor to see how frequently the DB is being used. Or, check the alarm display to see if a DB overload alarm (A.730 or A.731) has occurred.	Change the SERVOPACK model, operating methods, or the mechanisms so that the dynamic brake does not need to be used so frequently.	–
	The regenerative processing capacity was exceeded.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Recheck the operating conditions and load.	*4
	The SERVOPACK regenerative resistance is too small.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Change the regenerative resistance to a value larger than the SERVOPACK minimum allowable resistance.	

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.101: Motor Overcurrent Detected (The current to the motor exceeded the allowable current.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across cable phases U, V, and W, or between the ground and cable phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
A.101: Motor Overcurrent Detected (The current to the motor exceeded the allowable current.)	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.300: Regeneration Error	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to one of the following SERVOPACKs: SGD7S-2R8A or -2R8F.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or set Pn600 (Regenerative Resistor Capacity) to 0 (setting unit: ×10 W) if no Regenerative Resistor is required.	*1
	The jumper between the regenerative resistor terminals (B2 and B3) was removed from one of the following SERVOPACKs: SGD7S-120A.	Check to see if the jumper is connected between power supply terminals B2 and B3. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correctly connect a jumper.	*1
	The External Regenerative Resistor or Regenerative Resistor Unit is not wired correctly, or was removed or disconnected.	Check the wiring of the External Regenerative Resistor or Regenerative Resistor Unit. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correct the wiring of the External Regenerative Resistor or Regenerative Resistor Unit.	
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.320: Regenerative Overload	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The external regenerative resistance value or regenerative resistor capacity is too small, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or other means.	Change the regenerative resistance value or capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	*4
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
	The setting of Pn600 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check it see if a Regenerative Resistor is connected and check the setting of Pn600.	Correct the setting of Pn600.	*1
	The setting of Pn603 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check to see if a Regenerative Resistor is connected and check the setting of Pn603.	Correct the setting of Pn603.	*1
	The external regenerative resistance is too high.	Check the regenerative resistance.	Change the regenerative resistance to a correct value or use an External Regenerative Resistor of an appropriate capacity.	*4
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.330: Main Circuit Power Supply Wiring Error (Detected when the main circuit power supply is turned ON.)	The regenerative resistor was disconnected when the SERVOPACK power supply voltage was high.	Measure the resistance of the regenerative resistor using a measuring instrument.	If you are using the regenerative resistor built into the SERVOPACK, replace the SERVOPACK. If you are using an External Regenerative Resistor, replace the External Regenerative Resistor.	–
	DC power was supplied when an AC power supply input was specified in the settings.	Check the power supply to see if it is a DC power supply.	Correct the power supply setting to match the actual power supply.	*1
	AC power was supplied when a DC power supply input was specified in the settings.	Check the power supply to see if it is an AC power supply.	Correct the power supply setting to match the actual power supply.	
	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to an SGD7S-2R8A SERVOPACKs.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or if an External Regenerative Resistor is not required, set Pn600 to 0.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.400: Overvoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the AC/DC power supply voltage within the specified range.	–
	The power supply is not stable or was influenced by a lightning surge.	Measure the power supply voltage.	Improve the power supply conditions, install a surge absorber, and then turn the power supply OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The voltage for AC power supply was too high during acceleration or deceleration.	Check the power supply voltage and the speed and torque during operation.	Set the AC power supply voltage within the specified range.	–
	The external regenerative resistance is too high for the operating conditions.	Check the operating conditions and the regenerative resistance.	Select a regenerative resistance value that is appropriate for the operating conditions and load.	*4
	The moment of inertia ratio or mass ratio exceeded the allowable value.	Check to see if the moment of inertia ratio or mass ratio is within the allowable range.	Increase the deceleration time, or reduce the load.	–
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.410: Undervoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage went below the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*1
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor to the DC reactor terminals (⊖1 and ⊖2) on the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.510: Overspeed (The motor exceeded the maximum speed.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the wiring of the Servomotor.	Make sure that the Servomotor is correctly wired.	–
	A reference value that exceeded the overspeed detection level was input.	Check the input reference.	Reduce the reference value. Or, adjust the gain.	*1
	The motor exceeded the maximum speed.	Check the waveform of the motor speed.	Reduce the speed reference input gain and adjust the servo gain. Or, reconsider the operating conditions.	
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.511: Encoder Output Pulse Overspeed	The encoder output pulse frequency exceeded the limit.	Check the encoder output pulse setting.	Decrease the setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution).	*1
	The encoder output pulse frequency exceeded the limit because the motor speed was too high.	Check the encoder output pulse setting and the motor speed.	Reduce the motor speed.	–
A.520: Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the setting of Pn100 (Speed Loop Gain).	*1
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*1
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.521: Autotuning Alarm (Vibration was detected while executing the custom tuning, Easy FFT, or the tuning-less function.)	The Servomotor vibrated considerably while performing the tuning-less function.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio is within the allowable value. Or increase the load level or reduce the rigidity level in the tuning-less level settings.	*1
	The Servomotor vibrated considerably while performing custom tuning or Easy FFT.	Check the waveform of the motor speed.	Check the operating procedure of corresponding function and implement corrections.	*1
A.550: Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum speed.	Check the setting of Pn385, and the upper limits of the maximum motor speed setting and the encoder output resolution setting.	Set Pn385 to a value that does not exceed the maximum motor speed.	*1
A.710: Instantaneous Overload A.720: Continuous Overload	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	*1
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven due to mechanical problems.	Check the operation reference and motor speed.	Correct the mechanical problem.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.730 and A.731: Dynamic Brake Overload (An excessive power consumption by the dynamic brake was detected.)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia ratio or mass ratio. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.740: Inrush Current Limiting Resistor Overload (The main circuit power supply was frequently turned ON and OFF.)	The allowable frequency of the inrush current limiting resistor was exceeded when the main circuit power supply was turned ON and OFF.	–	Reduce the frequency of turning the main circuit power supply ON and OFF.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7A1: Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A2: Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A3: Internal Temperature Sensor Error (An error occurred in the temperature sensor circuit.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7Ab: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.810: Encoder Backup Alarm (Detected at the encoder, but only when an absolute encoder is used.)	The power to the absolute encoder was turned ON for the first time.	Check to see if the power supply was turned ON for the first time.	Set up the encoder.	*1
	The Encoder Cable was disconnected and then connected again.	Check to see if the power supply was turned ON for the first time.	Check the encoder connection and set up the encoder.	
	Power is not being supplied both from the control power supply (+5 V) from the SERVOPACK and from the battery power supply.	Check the encoder connector battery and the connector status.	Replace the battery or implement similar measures to supply power to the encoder, and set up the encoder.	
	A failure occurred in the absolute encoder.	–	If the alarm still occurs after setting up the encoder again, replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.820: Encoder Checksum Alarm (Detected at the encoder.)	A failure occurred in the encoder.	–	■ When Using an Absolute Encoder Set up the encoder again. If the alarm still occurs, the Servomotor may be faulty. Replace the Servomotor. ■ When Using a Single-turn Absolute Encoder or Incremental Encoder The Servomotor may be faulty. Replace the Servomotor.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.830: Encoder Battery Alarm (The absolute encoder battery voltage was lower than the specified level.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*1
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.840: Encoder Data Alarm (Detected at the encoder.)	The encoder malfunctioned.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor or linear encoder may be faulty. Replace the Servomotor or linear encoder.	–
	The encoder malfunctioned due to noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	–
A.850: Encoder Overspeed (Detected at the encoder when the control power supply is turned ON.)	The Servomotor speed was 200 min^{-1} or higher when the control power supply was turned ON.	Check the motor speed when the power supply is turned ON.	Reduce the Servomotor speed to a value less than 200 min^{-1}, and turn ON the control power supply.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.860: Encoder Overheated (Detected at the encoder.)	The surrounding air temperature around the Servomotor is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40°C or less.	–
	The Servomotor load is greater than the rated load.	Use the accumulated load ratio to check the load.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.861: Motor Overheated	The surrounding temperature around the Servomotor is too high.	Measure the surrounding temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40° or less.	–
	The motor load is greater than the rated load.	Check the load with the accumulated load ratio on the Motion Monitor Tab Page on the SigmaWin+.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the Serial Converter Unit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Serial Converter Unit may be faulty. Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.862: Overheat Alarm	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	The overheat protection input signal line is disconnected or short-circuited.	Check the input voltage with the overheat protection input information on the Motion Monitor Tab Page on the SigmaWin+.	Repair the line for the overheat protection input signal.	–
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.8A0: External Encoder Error	Setting the origin of the absolute linear encoder failed because the motor moved.	Before you set the origin, use the fully-closed feedback pulse counter to confirm that the motor is not moving.	The motor must be stopped while setting the origin position.	*1
	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A1: External Encoder Module Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.8A2: External Incremental Encoder Sensor Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A3: External Absolute Encoder Position Error	A failure occurred in the external absolute encoder.	–	The external absolute encoder may be faulty. Refer to the encoder manufacturer's instruction manual for corrections.	–
A.8A5: External Encoder Overspeed	An overspeed error was detected in the external encoder.	Check the maximum speed of the external encoder.	Keep the external encoder below its maximum speed.	–
A.8A6: External Encoder Overheated	An overheating error was detected in the external encoder.	–	Replace the external encoder.	–
A.b10: Speed Reference A/D Error (Detected when the servo is turned ON.)	A malfunction occurred in the speed reference input section.	–	Reset the alarm and restart operation.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.b11: Speed Reference A/D Data Error	A malfunction occurred in the speed reference input section.	–	Reset the alarm and restart operation.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.b20: Torque Reference A/D Error (Detected when the servo is turned ON.)	A malfunction occurred in the reading section for the torque reference input.	–	Reset the alarm and restart operation.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.b33: Current Detection Error 3	A failure occurred in the current detection circuit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF0: System Alarm 0	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.bF1: System Alarm 1	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF2: System Alarm 2	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF3: System Alarm 3	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF4: System Alarm 4	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF5: System Alarm 5	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF6: System Alarm 6	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF7: System Alarm 7	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF8: System Alarm 8	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C10: Servomotor Out of Control (Detected when the servo is turned ON.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the Servomotor wiring.	Make sure that the Servomotor is correctly wired.	–
	A failure occurred in the encoder.	–	If the motor wiring is correct and an alarm still occurs after turning the power supply OFF and ON again, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C80: Encoder Clear Error or Multiturn Limit Setting Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C90: Encoder Communications Error	There is a faulty contact in the connector or the connector is not wired correctly for the encoder.	Check the condition of the encoder connector.	Reconnect the encoder connector and check the encoder wiring.	*1
	There is a cable disconnection or short-circuit in the encoder. Or, the cable impedance is outside the specified values.	Check the condition of the Encoder Cable.	Use the Encoder Cable within the specified specifications.	–
	One of the following has occurred: corrosion caused by improper temperature, humidity, or gas, a short-circuit caused by entry of water drops or cutting oil, or faulty contact in connector caused by vibration.	Check the operating environment.	Improve the operating environmental, and replace the cable. If the alarm still occurs, replace the SERVOPACK.	*1
	A malfunction was caused by noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	*1
	A failure occurred in the SERVOPACK.	–	Connect the Servomotor to another SERVOPACK, and turn ON the control power supply. If no alarm occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C91: Encoder Communications Position Data Acceleration Rate Error	Noise entered on the signal lines because the Encoder Cable is bent or the sheath is damaged.	Check the condition of the Encoder Cable and connectors.	Check the Encoder Cable to see if it is installed correctly.	*1
	The Encoder Cable is bundled with a high-current line or installed near a high-current line.	Check the installation condition of the Encoder Cable.	Confirm that there is no surge voltage on the Encoder Cable.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the installation condition of the Encoder Cable.	Properly ground the machine to separate it from the FG of the encoder.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C92: Encoder Communications Timer Error	Noise entered on the signal line from the encoder.	–	Implement countermeasures against noise for the encoder wiring.	*1
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CA0: Encoder Parameter Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.Cb0: Encoder Echoback Error	The encoder is wired incorrectly or there is faulty contact.	Check the wiring of the encoder.	Make sure that the encoder is correctly wired.	*1
	The specifications of the Encoder Cable are not correct and noise entered on it.	–	Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	–
	The Encoder Cable is too long and noise entered on it.	–	The encoder cable wiring distance must be 50 m max.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the condition of the Encoder Cable and connectors.	Properly ground the machine to separate it from the FG of the encoder.	–
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CC0: Multiturn Limit Disagreement	When using a Direct Drive Servomotor, the setting of Pn205 (Multiturn Limit Setting) does not agree with the encoder.	Check the setting of Pn205.	Correct the setting of Pn205 (0 to 65,535).	*1
	The multiturn limit of the encoder is different from that of the SERVOPACK. Or, the multiturn limit of the SERVOPACK has been changed.	Check the setting of Pn205 in the SERVOPACK.	Change the setting if the alarm occurs.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.CF1: Reception Failed Error in Feedback Option Module Communications	The cable between the Serial Converter Unit and SERVOPACK is not wired correctly or there is a faulty contact.	Check the wiring of the external encoder.	Correctly wire the cable between the Serial Converter Unit and SERVOPACK.	*1
	A specified cable is not being used between Serial Converter Unit and SERVOPACK.	Check the wiring specifications of the external encoder.	Use a specified cable.	–
	The cable between the Serial Converter Unit and SERVOPACK is too long.	Measure the length of the cable that connects the Serial Converter Unit.	The length of the cable between the Serial Converter Unit and SERVOPACK must be 20 m or less.	–
	The sheath on cable between the Serial Converter Unit and SERVOPACK is broken.	Check the cable that connects the Serial Converter Unit.	Replace the cable between the Serial Converter Unit and SERVOPACK.	–
A.CF2: Timer Stopped Error in Feedback Option Module Communications	Noise entered the cable between the Serial Converter Unit and SERVOPACK.	–	Correct the wiring around the Serial Converter Unit, e.g., separate I/O signal lines from the Main Circuit Cables or ground.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.d00: Position Deviation Overflow (The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.)	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty contacts in the wiring for the Servomotor and encoder.	–
	The frequency of the position reference pulse is too high.	Reduce the reference pulse frequency and try operating the SERVOPACK.	Reduce the position reference pulse frequency or the reference acceleration rate, or reconsider the electronic gear ratio.	*1
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Apply smoothing, i.e., by using Pn216 (Position Reference Acceleration/ Deceleration Time Constant).	*1
	The setting of Pn520 (Excessive Position Deviation Alarm Level) is too low for the operating conditions.	Check Pn520 (Excessive Position Deviation Alarm Level) to see if it is set to an appropriate value.	Optimize the setting of Pn520.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.d01: Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Check the position deviation while the servo is OFF.	Set the position deviation to be cleared while the servo is OFF. Optimize the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON).	*1
A.d02: Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if reference pulses are input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded.	–	Set the position deviation to be cleared while the servo is OFF. Optimize the setting of Pn520 (Excessive Position Deviation Alarm Level). Or, adjust the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON).	
A.d10: Motor-Load Position Deviation Overflow	The motor direction and external encoder installation orientation are backward.	Check the motor direction and the external encoder installation orientation.	Install the external encoder in the opposite direction, or change the setting of Pn002 = n.X□□□ (External Encoder Usage) to reverse the direction.	*1
	There is an error in the connection between the load (e.g., stage) and external encoder coupling.	Check the coupling of the external encoder.	Check the mechanical coupling.	–
A.d30: Position Data Overflow	The position data exceeded ±1,879,048,192.	Check the input reference pulse counter.	Reconsider the operating specifications.	–
A.E71: Safety Option Module Detection Failure	There is a faulty connection between the SERVOPACK and the Safety Option Module.	Check the connection between the SERVOPACK and the Safety Option Module.	Correctly connect the Safety Option Module.	–
	The Safety Option Module was disconnected.	–	Execute Fn014 (Reset Option Module Configuration Error) from the Digital Operator or SigmaWin+ and then turn the power supply to the SERVOPACK OFF and ON again.	*1
	A failure occurred in the Safety Option Module.	–	Replace the Safety Option Module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.E72: Feedback Option Module Detection Failure	There is a faulty connection between the SERVOPACK and the Feedback Option Module.	Check the connection between the SERVOPACK and the Feedback Option Module.	Correctly connect the Feedback Option Module.	–
	The Feedback Option Module was disconnected.	–	Reset the Option Module configuration error and turn the power supply to the SERVOPACK OFF and ON again.	*1
	A failure occurred in the Feedback Option Module.	–	Replace the Feedback Option Module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.E74: Unsupported Safety Option Module	A failure occurred in the Safety Option Module.	–	Replace the Safety Option Module.	–
	An unsupported Safety Option Module was connected.	Refer to the catalog of the connected Safety Option Module.	Connect a compatible Safety Option Module.	–
A.Eb1: Safety Function Signal Input Timing Error	The delay between activation of the /HWBB1 and /HWBB2 input signals for the HWBB was ten second or longer.	Measure the time delay between the /HWBB1 and /HWBB2 signals.	The output signal circuits or devices for /HWBB1 and /HWBB2 or the SERVOPACK input signal circuits may be faulty. Alternatively, the input signal cables may be disconnected. Check to see if any of these items are faulty or have been disconnected.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.EC8: Gate Drive Error 1 (An error occurred in the gate drive circuit.)	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.EC9: Gate Drive Error 2 (An error occurred in the gate drive circuit.)				

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.F10: Power Supply Line Open Phase (The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.)	The three-phase power supply wiring is not correct.	Check the power supply wiring.	Make sure that the power supply is correctly wired.	*1
	The three-phase power supply is unbalanced.	Measure the voltage for each phase of the three-phase power supply.	Balance the power supply by changing phases.	–
	A single-phase power supply was input without specifying a signal-phase AC power supply input (Pn00B = n.□1□□).	Check the power supply and the parameter setting.	Match the parameter setting to the power supply.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
FL-1*5: System Alarm FL-2*5: System Alarm FL-3*5: System Alarm FL-4*5: System Alarm FL-5*5: System Alarm FL-6*5: System Alarm	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
CPF00: Digital Operator Communications Error 1	There is a faulty contact between the Digital Operator and the SERVOPACK.	Check the connector contact.	Disconnect the connector and insert it again. Or, replace the cable.	–
	A malfunction was caused by noise.	–	Keep the Digital Operator or the cable away from sources of noise.	–
CPF01: Digital Operator Communications Error 2	A failure occurred in the Digital Operator.	–	Disconnect the Digital Operator and then connect it again. If an alarm still occurs, the Digital Operator may be faulty. Replace the Digital Operator.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

*2. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Pn533 [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{6 \times 10^5} \leq \dfrac{\text{Pn20E}}{\text{Pn210}}$

- $\text{Maximum motor speed [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \dfrac{\text{Pn20E}}{\text{Pn210}}$

*3. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Rated motor speed [min}^{-1}\text{]} \times 1/3 \times \dfrac{\text{Encoder resolution}}{6 \times 10^5} \leq \dfrac{\text{Pn20E}}{\text{Pn210}}$

- $\text{Maximum motor speed [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \dfrac{\text{Pn20E}}{\text{Pn210}}$

*4. Refer to the following manual for details.
Σ-7-Series Peripheral Device Selection Manual (Manual No.: SIEP S800001 32)

*5. These alarms are not stored in the alarm history. They are only displayed on the panel display.

3.1.4 Warning Displays

If a warning occurs in the SERVOPACK, a warning number will be displayed on the panel display. Warnings are displayed to warn you before an alarm occurs.

3.1.5 List of Warnings

The list of warnings gives the warning name, warning meaning, and warning code output in order of the warning numbers.

Warning Number	Warning Name	Meaning	Warning Code Output		
			ALO1	ALO2	ALO3
A.900	Position Deviation Overflow	The position deviation exceeded the percentage set with the following formula: (Pn520 × Pn51E/100)	H	H	H
A.901	Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)	H	H	H
A.910	Overload	This warning occurs before an overload alarm (A.710 or A.720) occurs. If the warning is ignored and operation is continued, an alarm may occur.	L	H	H
A.911	Vibration	Abnormal vibration was detected during motor operation. The detection level is the same as A.520. Set whether to output an alarm or a warning by setting Pn310 (Vibration Detection Switch).	L	H	H
A.912	Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	H	L	H
A.913	Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.	H	L	H
A.920	Regenerative Overload	This warning occurs before an A.320 alarm (Regenerative Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.	H	L	H
A.921	Dynamic Brake Overload	This warning occurs before an A.731 alarm (Dynamic Brake Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.	H	L	H
A.923	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	H	L	H
A.930	Absolute Encoder Battery Error	This warning occurs when the voltage of absolute encoder's battery is low.	L	L	H
A.93B	Overheat Warning	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61C (Overheat Warning Level).	L	L	H
A.941	Change of Parameters Requires Restart	Parameters have been changed that require the power supply to be turned OFF and ON again.	H	H	L
A.942	Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	H	H	L
A.971	Undervoltage	This warning occurs before an A.410 alarm (Undervoltage) occurs. If the warning is ignored and operation is continued, an alarm may occur.	L	L	L
A.9A0	Overtravel	Overtravel was detected while the servo was ON.	H	L	L

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Warning Number	Warning Name	Meaning	Warning Code Output		
			ALO1	ALO2	ALO3
A.9b0	Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	H	L	H

Note: 1. A warning code is not output unless you set Pn001 to n.1□□□ (Output both alarm codes and warning codes).
2. Use Pn008 = n.□X□□ (Warning Detection Selection) to control warning detection.
However, the following warnings are not affected by the setting of Pn008 = n.□X□□ and other parameter settings are required in addition to Pn008 = n.□X□□.

Warning	Parameters That Must Be Set to Select Warning Detection
A.911	Pn310 = n.□□□X (Vibration Detection Setting)
A.923	– (Not affected by the setting of Pn008 = n.□X□□.)
A.930	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection)
A.942	Pn423 = n.□□X□ (Speed Ripple Compensation Information Disagreement Warning Detection Selection)
A.971	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection) (Not affected by the setting of Pn008 = n.□X□□.)
A.9A0	Pn00D = n.X□□□ (Overtravel Warning Detection Selection) (Not affected by the setting of Pn008 = n.□X□□.)
A.9b0	Pn00F = n.□□□X (Preventative Maintenance Selection)

3.1.6 Troubleshooting Warnings

The causes of and corrections for the warnings are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.900: Position Deviation Overflow	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty connections in the wiring for the Servomotor and encoder.	–
	A SERVOPACK gain is too low.	Check the SERVOPACK gains.	Increase the servo gain, e.g., by using autotuning without a host reference.	*
	The frequency of the position reference pulse is too high.	Reduce the reference pulse frequency and try operating the SERVOPACK.	Reduce the position reference pulse frequency or the reference acceleration rate, or reconsider the electronic gear ratio.	*
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Apply smoothing, i.e., by using Pn216 (Position Reference Acceleration/ Deceleration Time Constant).	*
	The excessive position deviation alarm level (Pn520 × Pn51E/100) is too low for the operating conditions.	Check excessive position deviation alarm level (Pn520 × Pn51E/100) to see if it is set to an appropriate value.	Optimize the settings of Pn520 and Pn51E.	*
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.901: Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)	–	Set the position deviation to be cleared while the servo is OFF. Optimize the setting of Pn528 (Excessive Position Error Warning Level at Servo ON).	*
A.910: Overload (warning before an A.710 or A.720 alarm occurs)	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	–
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven because of mechanical problems.	Check the operation reference and motor speed.	Remove the mechanical problem.	–
	The overload warning level (Pn52B) is not suitable.	Check that the overload warning level (Pn52B) is suitable.	Set a suitable overload warning level (Pn52B).	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.911: Vibration	Abnormal vibration was detected during motor operation.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the servo gain with custom tuning.	*
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.912: Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.913: Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.920: Regenerative Overload (warning before an A.320 alarm occurs)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	There is insufficient external regenerative resistance, regenerative resistor capacity, or SERVOPACK capacity, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or another means.	Change the regenerative resistance value, regenerative resistance capacity, or SERVOPACK capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	–
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
A.921: Dynamic Brake Overload (warning before an A.731 alarm occurs)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia or mass. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.923: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.930: Absolute Encoder Battery Error (The absolute encoder battery voltage was lower than the specified level.) (Detected only when an absolute encoder is connected.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.93B: Overheat Warning	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.941: Change of Parameters Requires Restart	Parameters have been changed that require the power supply to be turned OFF and ON again.	–	Turn the power supply to the SERVOPACK OFF and ON again.	–
A.942: Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	–	Reset the speed ripple compensation value on the SigmaWin+.	*
		–	Set Pn423 to n.□□1□ (Do not detect A.942 alarms). However, changing the setting may increase the speed ripple.	*
		–	Set Pn423 to n.□□□0 (Disable torque ripple compensation). However, changing the setting may increase the speed ripple.	*
A.971: Undervoltage	For a 200-V SERVOPACK, the AC power supply voltage dropped below 140 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	For a 100-V SERVOPACK, the AC power supply voltage dropped below 60 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.9A0: Overtravel (Overtravel status was detected.)	Overtravel was detected while the servo was ON.	Check the status of the overtravel signals on the input signal monitor.	Even if an overtravel signal is not shown by the input signal monitor, momentary overtravel may have been detected. Take the following precautions. • Do not specify movements that would cause overtravel from the host controller. • Check the wiring of the overtravel signals. • Implement countermeasures against noise.	*
A.9b0: Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	–	Replace the part. Contact your Yaskawa representative for replacement.	*

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

3.1.7 Troubleshooting Based on the Operation and Conditions of the Servomotor

This section provides troubleshooting based on the operation and conditions of the Servomotor, including causes and corrections.

Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The control power supply is not turned ON.	Measure the voltage between control power supply terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the control power supply is turned ON.	–
	The main circuit power supply is not turned ON.	Measure the voltage between the main circuit power input terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the main circuit power supply is turned ON.	–
	The I/O signal connector (CN1) pins are not wired correctly or are disconnected.	Turn OFF the power supply to the servo system. Check the wiring condition of the I/O signal connector (CN1) pins.	Correct the wiring of the I/O signal connector (CN1) pins.	*
	The wiring for the Servomotor Main Circuit Cables or Encoder Cable is disconnected.	Check the wiring conditions.	Turn OFF the power supply to the servo system. Wire the cable correctly.	–
	There is an overload on the Servomotor.	Operate the Servomotor with no load and check the load status.	Turn OFF the power supply to the servo system. Reduce the load or replace the Servomotor with a Servomotor with a larger capacity.	–
	The type of encoder that is being used does not agree with the setting of Pn002 = n.□X□□ (Encoder Usage).	Check the type of the encoder that is being used and the setting of Pn002 = n.□X□□.	Set Pn002 = n.□X□□ according to the type of the encoder that is being used.	*
	No speed or position reference is input.	Turn OFF the power supply to the servo system. Check the allocation status of the input signals.	Allocate an input signal so that the speed and position references are input correctly.	*
	There is a mistake in the input signal allocations (Pn50A to Pn50D, Pn515, and Pn516).	Check the input signal allocations (Pn50A to Pn50D, Pn515, and Pn516).	Correctly allocate the input signals (Pn50A to Pn50D, Pn515, and Pn516).	*
	The /S-ON (Servo ON) signal is OFF.	Check the settings of Pn50A = n.□□□X (Input Signal Allocation Mode) and Pn50A =n.□□X□ (Servo ON (/S-ON) Signal Mapping).	Set Pn50A = n.□□XX correctly and turn ON the /S-ON signal.	*
	The function setting of the /P-CON (Proportional Control) signal is not correct.	Check the setting of Pn000 = n.□□X□ (Control Method Selection).	Set the parameter to match the application.	*
	The SEN input is OFF.	Check the ON/OFF status of the SEN input.	If you are using an absolute encoder, turn ON the SEN signal.	*

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Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The reference pulse mode selection is not correct.	Check the setting of Pn200 =n.□□□X (Reference Pulse Form) and the reference pulse form.	Set Pn200 =n.□□□X so that is agrees with the reference pulse form.	*
	Speed control: The speed reference input is not appropriate.	Check between the speed reference input (V-REF) and signal ground (SG) to see if the control method and the input agree.	Correctly set the control method and input method.	*
	Torque control: The torque reference input is not appropriate.	Check between the torque reference input (T-REF) and signal ground (SG) to see if the control method and the input agree.	Correctly set the control method and input method.	*
	Position control: The reference pulse input is not appropriate.	Check the setting of Pn200 =n.□□□X (Reference Pulse Form) and the sign and pulse signals.	Correctly set the control method and input method.	*
	The /CLR (Position Deviation Clear) input signal has not been turned OFF.	Check the /CLR signal (CN1-14 and CN1-15).	Turn OFF the /CLR signal.	*
	The P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal is still OFF.	Check the P-OT and N-OT signals.	Turn ON the P-OT and N-OT signals.	*
	The safety input signals (/HWBB1 or /HWBB2) were not turned ON.	Check the /HWBB1 and /HWBB2 input signals.	Turn ON the /HWBB1 and /HWBB2 input signals. If you are not using the safety function, connect the Safety Jumper Connector (provided as an accessory) to CN8.	*
	The FSTP (Forced Stop Input) signal is still OFF.	Check the FSTP signal.	• Turn ON the FSTP signal. • If you will not use the function to force the motor to stop, set Pn516 = n.□□□X (FSTP (Forced Stop Input) Signal Allocation) to disable the signal.	*
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Servomotor Moves Instantaneously, and Then Stops	There is a mistake in the Servomotor wiring.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Servomotor correctly.	–
	There is a mistake in the wiring of the encoder or Serial Converter Unit.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Serial Converter Unit correctly.	–
Servomotor Speed Is Unstable	There is a faulty connection in the Servomotor wiring.	Turn OFF the power supply to the servo system. The connector connections for the power line (U, V, and W phases) and the encoder or Serial Converter Unit may be unstable. Check the wiring.	Tighten any loose terminals or connectors and correct the wiring.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Moves without a Reference Input	Speed control: The speed reference input is not appropriate.	Check between the speed reference input (V-REF) and signal ground (SG) to see if the control method and the input agree.	Correctly set the control method and input method.	*
	Torque control: The torque reference input is not appropriate.	Check between the torque reference input (T-REF) and signal ground (SG) to see if the control method and the input agree.	Correctly set the control method and input method.	*
	The speed reference offset is not correct.	The SERVOPACK offset is adjusted incorrectly.	Adjust the SERVOPACK offset.	*
	Position control: The reference pulse input is not appropriate.	Check the setting of Pn200 =n.□□□X (Reference Pulse Form) and the sign and pulse signals.	Correctly set the control method and input method.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Dynamic Brake Does Not Operate	The setting of Pn001 = n.□□□X (Servo OFF or Alarm Group 1 Stopping Method) is not suitable.	Check the setting of Pn001 = n.□□□X.	Set Pn001 = n.□□□X correctly.	–
	The dynamic brake resistor is disconnected.	Check the moment of inertia, motor speed, and dynamic brake frequency of use. If the moment of inertia, motor speed, or dynamic brake frequency of use is excessive, the dynamic brake resistance may be disconnected.	Turn OFF the power supply to the servo system. Replace the SERVOPACK. To prevent disconnection, reduce the load.	–
	There was a failure in the dynamic brake drive circuit.	–	Turn OFF the power supply to the servo system. There is a defective component in the dynamic brake circuit. Replace the SERVOPACK.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	The Servomotor vibrated considerably while performing the tuning-less function with the default settings.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio or mass ratio is within the allowable value, or increase the load level or reduce the rigidity level in the tuning-less level settings.	*
	The machine mounting is not secure.	Turn OFF the power supply to the servo system. Check to see if there are any loose mounting screws.	Tighten the mounting screws.	–
	The machine mounting is not secure.	Turn OFF the power supply to the servo system. Check to see if there is misalignment in the coupling.	Align the coupling.	–
		Turn OFF the power supply to the servo system. Check to see if the coupling is balanced.	Balance the coupling.	–
	The bearings are defective.	Turn OFF the power supply to the servo system. Check for noise and vibration around the bearings.	Replace the Servomotor.	–
	There is a vibration source at the driven machine.	Turn OFF the power supply to the servo system. Check for any foreign matter, damage, or deformation in the machine's moving parts.	Consult with the machine manufacturer.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use shielded twisted-pair wire cables or screened twisted-pair cables with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Make sure that the rotary or Linear Encoder Cable satisfies the specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with a conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Check to see if there is noise interference on the signal line from the encoder.	Turn OFF the power supply to the servo system. Implement countermeasures against noise for the encoder wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
Servomotor Vibrates at Frequency of Approx. 200 to 400 Hz.	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	*
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Large Motor Speed Overshoot on Starting and Stopping	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	*
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–
	The torque reference is saturated.	Check the waveform of the torque reference.	Use the mode switch.	–
	The force limits (Pn483 and Pn484) are set to the default values.	The default values of the force limits and Pn483 = 30% and Pn484 = 30%.	Set Pn483 and Pn484 to appropriate values.	*
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	Replace the Encoder Cable and correct the cable installation environment.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder or Serial Converter Unit wiring.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
	Host Controller Multiturn Data or Absolute Encoder Position Data Reading Error	Check the error detection section of the host controller.	Correct the error detection section of the host controller.	–
		Check to see if the host controller is executing data parity checks.	Perform parity checks for the multiturn data or absolute encoder position data.	–
		Check for noise interference in the cable between the SERVOPACK and the host controller.	Implement countermeasures against noise and then perform parity checks again for the multiturn data or absolute encoder position data.	–
Overtravel Occurred	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal was input.	Check the external power supply (+24 V) voltage for the input signals.	Correct the external power supply (+24 V) voltage for the input signals.	–
		Check the operating condition of the overtravel limit switches.	Make sure that the overtravel limit switches operate correctly.	–
		Check the wiring of the overtravel limit switches.	Correct the wiring of the overtravel limit switches.	*
		Check the settings of the overtravel input signal allocations (Pn50A/Pn50B).	Set the parameters to correct values.	*
	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal malfunctioned.	Check for fluctuation in the external power supply (+24 V) voltage for the input signals.	Eliminate fluctuation from the external power supply (+24 V) voltage for the input signals.	–
		Check to see if the operation of the overtravel limit switches is unstable.	Stabilize the operating condition of the overtravel limit switches.	–
		Check the wiring of the overtravel limit switches (e.g., check for cable damage and loose screws).	Correct the wiring of the overtravel limit switches.	–
	There is a mistake in the allocation of the P-OT or N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal in Pn50A = n.X□□□ or Pn50B = n.□□□X.	Check to see if the P-OT signal is allocated in Pn50A = n.X□□□.	If another signal is allocated in Pn50A =n.X□□□, allocate the P-OT signal instead.	*
		Check to see if the N-OT signal is allocated in Pn50B = n.□□□X.	If another signal is allocated in Pn50B =n.□□□X, allocate the N-OT signal instead.	

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Problem	Possible Cause	Confirmation	Correction	Reference
Overtravel Occurred	The selection of the Servomotor stopping method is not correct.	Check the servo OFF stopping method set in Pn001 = n.□□□X or Pn001 = n.□□X□.	Select a Servomotor stopping method other than coasting to a stop.	*
		Check the torque control stopping method set in Pn001 = n.□□□X or Pn001 = n.□□X□.	Select a Servomotor stopping method other than coasting to a stop.	
Improper Stop Position for Overtravel (OT) Signal	The limit switch position and dog length are not appropriate.	–	Install the limit switch at the appropriate position.	–
	The overtravel limit switch position is too close for the coasting distance.	–	Install the overtravel limit switch at the appropriate position.	–
Position Deviation (without Alarm)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder wiring or Serial Converter Unit wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	The coupling between the machine and Servomotor is not suitable.	Turn OFF the power supply to the servo system. Check to see if position offset occurs at the coupling between machine and Servomotor.	Correctly secure the coupling between the machine and Servomotor.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Position Deviation (without Alarm)	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	If reference pulse input multiplication switching is being used, noise may be causing the I/O signals used for this function (/PSEL and /PSELA) to be falsely detected.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	An encoder fault occurred. (The pulse count does not change.)	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Servomotor Overheated	The surrounding air temperature is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature to 40°C or less.	–
	The surface of the Servomotor is dirty.	Turn OFF the power supply to the servo system. Visually check the surface for dirt.	Clean dirt, dust, and oil from the surface.	–
	There is an overload on the Servomotor.	Check the load status with a monitor.	If the Servomotor is overloaded, reduce the load or replace the Servo Drive with a SERVOPACK and Servomotor with larger capacities.	–
	Polarity detection was not performed correctly.	Check to see if electrical angle 2 (electrical angle from polarity origin) at any position is between ±10°.	Correct the settings for the polarity detection-related parameters.	–
Estimating the moment of inertia failed.	The acceleration rate is low and travel distance is short.	Check the Condition Setting Dialog Box used to perform moment of inertia estimation.	Increase the acceleration rate and travel distance.	–

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

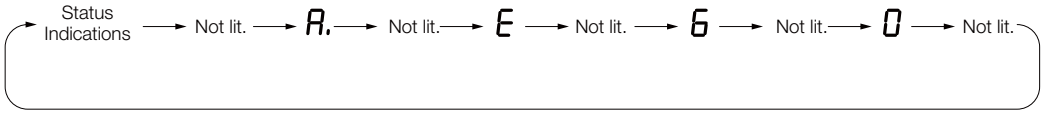
3.2 FT82 SERVOPACK with MECHATROLINK-II Communications References

3.2.1 Alarm Displays

If an error occurs in the SERVOPACK, an alarm number will be displayed on the panel display. However, if □□-□□ appears on the panel display, the display will indicate a SERVOPACK system error. Replace the SERVOPACK.

If there is an alarm, the display will change in the following order.

Example: Alarm A.E60



3.2.2 List of Alarms

The list of alarms gives the alarm name, alarm meaning, alarm stopping method, and alarm reset possibility in order of the alarm numbers.

Servomotor Stopping Method for Alarms

Refer to the following manual for information on the stopping method for alarms.

📖 Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)

Alarm Reset Possibility

Yes: You can use an alarm reset to clear the alarm. However, this assumes that the cause of the alarm has been removed.
No: You cannot clear the alarm.

List of Alarms

Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.020	Parameter Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No
A.021	Parameter Format Error	There is an error in the parameter data format in the SERVOPACK.	Gr.1	No
A.022	System Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No
A.024	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No
A.025	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No
A.030	Main Circuit Detector Error	There is an error in the detection data for the main circuit.	Gr.1	Yes
A.040	Parameter Setting Error	A parameter setting is outside of the setting range.	Gr.1	No

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.041	Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Gr.1	No
A.042	Parameter Combination Error	The combination of some parameters exceeds the setting range.	Gr.1	No
A.044	Semi-Closed/Fully-Closed Loop Control Parameter Setting Error	The settings of the Option Module and Pn002 = n.X□□□ (External Encoder Usage) do not match.	Gr.1	No
A.04A	Parameter Setting Error 2	There is an error in the bank members or bank data settings.	Gr.1	No
A.050	Combination Error	The capacities of the SERVOPACK and Servomotor do not match.	Gr.1	Yes
A.051	Unsupported Device Alarm	An unsupported device was connected.	Gr.1	No
A.0b0	Invalid Servo ON Command Alarm	The SV_ON (Servo ON) command was sent from the host controller after a utility function that turns ON the Servomotor was executed.	Gr.1	Yes
A.100	Overcurrent Detected	An overcurrent flowed through the power transformer or the heat sink overheated.	Gr.1	No
A.101	Motor Overcurrent Detected	The current to the motor exceeded the allowable current.	Gr.1	No
A.300	Regeneration Error	There is an error related to regeneration.	Gr.1	Yes
A.320	Regenerative Overload	A regenerative overload occurred.	Gr.2	Yes
A.330	Main Circuit Power Supply Wiring Error	• The AC power supply input setting or DC power supply input setting is not correct. • The power supply wiring is not correct.	Gr.1	Yes
A.400	Overvoltage	The main circuit DC voltage is too high.	Gr.1	Yes
A.410	Undervoltage	The main circuit DC voltage is too low.	Gr.2	Yes
A.510	Overspeed	The motor exceeded the maximum speed.	Gr.1	Yes
A.511	Encoder Output Pulse Overspeed	The pulse output speed for the setting of Pn212 (Encoder Output Pulses) was exceeded.	Gr.1	Yes
A.520	Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Gr.1	Yes
A.521	Autotuning Alarm	Vibration was detected during autotuning for the tuning-less function.	Gr.1	Yes
A.550	Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum motor speed.	Gr.1	Yes
A.710	Instantaneous Overload	The Servomotor was operating for several seconds to several tens of seconds under a torque that largely exceeded the rating.	Gr.2	Yes
A.720	Continuous Overload	The Servomotor was operating continuously under a torque that exceeded the rating.	Gr.1	Yes
A.730	Dynamic Brake Overload	When the dynamic brake was applied, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Gr.1	Yes
A.731				
A.740	Inrush Current Limiting Resistor Overload	The main circuit power supply was frequently turned ON and OFF.	Gr.1	Yes
A.7A1	Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	Gr.2	Yes

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.7A2	Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.	Gr.2	Yes
A.7A3	Internal Temperature Sensor Error	An error occurred in the temperature sensor circuit.	Gr.2	No
A.7Ab	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Gr.1	Yes
A.810	Encoder Backup Alarm	The power supplies to the encoder all failed and the position data was lost.	Gr.1	No
A.820	Encoder Checksum Alarm	There is an error in the checksum results for encoder memory.	Gr.1	No
A.830	Encoder Battery Alarm	The battery voltage was lower than the specified level after the control power supply was turned ON.	Gr.1	Yes
A.840	Encoder Data Alarm	There is an internal data error in the encoder.	Gr.1	No
A.850	Encoder Overspeed	The encoder was operating at high speed when the power was turned ON.	Gr.1	No
A.860	Encoder Overheated	The internal temperature of encoder is too high.	Gr.1	No
A.861	Motor Overheated	The internal temperature of motor is too high.	Gr.1	No
A.862	Overheat Alarm	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61B (Overheat Alarm Level).	Gr.1	Yes
A.8A0	External Encoder Error	An error occurred in the external encoder.	Gr.1	Yes
A.8A1	External Encoder Module Error	An error occurred in the Serial Converter Unit.	Gr.1	Yes
A.8A2	External Incremental Encoder Sensor Error	An error occurred in the external encoder.	Gr.1	Yes
A.8A3	External Absolute Encoder Position Error	An error occurred in the position data of the external encoder.	Gr.1	Yes
A.8A5	External Encoder Overspeed	An overspeed error occurred in the external encoder.	Gr.1	Yes
A.8A6	External Encoder Overheated	An overheating error occurred in the external encoder.	Gr.1	Yes
A.b33	Current Detection Error 3	An error occurred in the current detection circuit.	Gr.1	No
A.b6A	MECHATROLINK Communications ASIC Error 1	ASIC error 1 occurred in MECHATROLINK communications.	Gr.1	No
A.b6b	MECHATROLINK Communications ASIC Error 2	ASIC error 2 occurred in MECHATROLINK communications.	Gr.2	No
A.bF0	System Alarm 0	Internal program error 0 occurred in the SERVOPACK.	Gr.1	No
A.bF1	System Alarm 1	Internal program error 1 occurred in the SERVOPACK.	Gr.1	No
A.bF2	System Alarm 2	Internal program error 2 occurred in the SERVOPACK.	Gr.1	No
A.bF3	System Alarm 3	Internal program error 3 occurred in the SERVOPACK.	Gr.1	No
A.bF4	System Alarm 4	Internal program error 4 occurred in the SERVOPACK.	Gr.1	No
A.bF5	System Alarm 5	Internal program error 5 occurred in the SERVOPACK.	Gr.1	No
A.bF6	System Alarm 6	Internal program error 6 occurred in the SERVOPACK.	Gr.1	No

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.bF7	System Alarm 7	Internal program error 7 occurred in the SERVOPACK.	Gr.1	No
A.bF8	System Alarm 8	Internal program error 8 occurred in the SERVOPACK.	Gr.1	No
A.C10	Servomotor Out of Control	The Servomotor ran out of control.	Gr.1	Yes
A.C80	Encoder Clear Error or Multiturn Limit Setting Error	The multiturn data for the absolute encoder was not correctly cleared or set.	Gr.1	No
A.C90	Encoder Communications Error	Communications between the encoder and SERVOPACK is not possible.	Gr.1	No
A.C91	Encoder Communications Position Data Acceleration Rate Error	An error occurred in calculating the position data of the encoder.	Gr.1	No
A.C92	Encoder Communications Timer Error	An error occurred in the communications timer between the encoder and SERVOPACK.	Gr.1	No
A.CA0	Encoder Parameter Error	The parameters in the encoder are corrupted.	Gr.1	No
A.Cb0	Encoder Echoback Error	The contents of communications with the encoder are incorrect.	Gr.1	No
A.CC0	Multiturn Limit Disagreement	Different multiturn limits have been set in the encoder and the SERVOPACK.	Gr.1	No
A.CF1	Reception Failed Error in Feedback Option Module Communications	Receiving data from the Feedback Option Module failed.	Gr.1	No
A.CF2	Timer Stopped Error in Feedback Option Module Communications	An error occurred in the timer for communications with the Feedback Option Module.	Gr.1	No
A.d00	Position Deviation Overflow	The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.	Gr.1	Yes
A.d01	Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Gr.1	Yes
A.d02	Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if a position reference is input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded before the limit is cleared.	Gr.2	Yes
A.d10	Motor-Load Position Deviation Overflow	There was too much position deviation between the motor and load during fully-closed loop control.	Gr.2	Yes
A.d30	Position Data Overflow	The position feedback data exceeded ±1,879,048,192.	Gr.1	No
A.E02	MECHATROLINK Internal Synchronization Error 1	A synchronization error occurred during MECHATROLINK communications with the SERVOPACK.	Gr.1	Yes
A.E40	MECHATROLINK Transmission Cycle Setting Error	The setting of the MECHATROLINK communications transmission cycle is not correct.	Gr.2	Yes
A.E50*	MECHATROLINK Synchronization Error	A synchronization error occurred during MECHATROLINK communications.	Gr.2	Yes

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.E51	MECHATROLINK Synchronization Failed	Synchronization failed during MECHATROLINK communications.	Gr.2	Yes
A.E60*	Reception Error in MECHATROLINK Communications	Communications errors occurred continuously during MECHATROLINK communications.	Gr.2	Yes
A.E61	Synchronization Interval Error in MECHATROLINK Transmission Cycle	An error occurred in the transmission cycle during MECHATROLINK communications.	Gr.2	Yes
A.E71	Safety Option Module Detection Failure	Detection of the Safety Option Module failed.	Gr.1	No
A.E72	Feedback Option Module Detection Failure	Detection of the Feedback Option Module failed.	Gr.1	No
A.E74	Unsupported Safety Option Module	An unsupported Safety Option Module was connected.	Gr.1	No
A.Eb1	Safety Function Signal Input Timing Error	An error occurred in the input timing of the safety function signal.	Gr.1	No
A.EC8	Gate Drive Error 1	An error occurred in the gate drive circuit.	Gr.1	No
A.EC9	Gate Drive Error 2	An error occurred in the gate drive circuit.	Gr.1	No
A.Ed1	Command Execution Timeout	A timeout error occurred for a MECHATROLINK command.	Gr.2	Yes
A.F10	Power Supply Line Open Phase	The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.	Gr.2	Yes
FL-1*	System Alarm	An internal program error occurred in the SERVOPACK.	–	No
FL-2*				
FL-3*				
FL-4*				
FL-5*				
FL-6*				
CPF00	Digital Operator Communications Error 1	Communications were not possible between the Digital Operator (model: JUSP-OP05A-1-E) and the SERVOPACK (e.g., a CPU error occurred).	–	No
CPF01	Digital Operator Communications Error 2			

* These alarms are not stored in the alarm history. They are only displayed on the panel display.

Note: The A.Eb0, A.Eb2 to A.Eb9, and A.EC0 to A.EC2 alarms can occur when a Safety Module is connected.
Refer to the following manual for details.
AC Servo Drive Σ-V-Series/Σ-V-Series for Large-Capacity Models/Σ-7-Series User's Manual Safety Module (Manual No.: SIEP C720829 06)

3.2.3 Troubleshooting Alarms

The causes of and corrections for the alarms are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.020: Parameter Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	Set the power supply voltage within the specified range, and initialize the parameter settings.	*1
	The power supply was shut OFF while writing parameter settings.	Check the timing of shutting OFF the power supply.	Initialize the parameter settings and then set the parameters again.	
	The number of times that parameters were written exceeded the limit.	Check to see if the parameters were frequently changed from the host controller.	The SERVOPACK may be faulty. Replace the SERVOPACK. Reconsider the method for writing the parameters.	–
	A malfunction was caused by noise from the AC power supply, ground, static electricity, or other source.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, noise may be the cause.	Implement countermeasures against noise.	*1
	Gas, water drops, or cutting oil entered the SERVOPACK and caused failure of the internal components.	Check the installation conditions.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.021: Parameter Format Error (There is an error in the parameter data format in the SERVOPACK.)	The software version of the SERVOPACK that caused the alarm is older than the software version of the parameters specified to write.	Read the product information to see if the software versions are the same. If they are different, it could be the cause of the alarm.	Write the parameters from another SERVOPACK with the same model and the same software version, and then turn the power OFF and ON again.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.022: System Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The power supply was shut OFF while setting a utility function.	Check the timing of shutting OFF the power supply.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.024: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.025: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.030: Main Circuit Detector Error	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.040: Parameter Setting Error (A parameter setting is outside of the setting range.)	The SERVOPACK and Servomotor capacities do not match each other.	Check the combination of the SERVOPACK and Servomotor capacities.	Select a proper combination of SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A parameter setting is outside of the setting range.	Check the setting ranges of the parameters that have been changed.	Set the parameters to values within the setting ranges.	–
	The electronic gear ratio is outside of the setting range.	Check the electronic gear ratio. The ratio must be within the following range: 0.001 < (Pn20E/Pn210) < 64,000.	Set the electronic gear ratio in the following range: 0.001 < (Pn20E/Pn210) < 64,000.	*1
A.041: Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Check the setting of Pn212 or Pn281.	Set Pn212 or Pn281 to an appropriate value.	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.042: Parameter Combination Error	The speed of program jogging went below the setting range when the electronic gear ratio (Pn20E/ Pn210) or the Servomotor was changed.	Check to see if the detection conditions*2 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1
	The speed of program jogging went below the setting range when Pn533 or Pn585 (Program Jogging Speed) was changed.	Check to see if the detection conditions*2 are satisfied.	Increase the setting of Pn533 or Pn585.	*1
	The movement speed of advanced autotuning went below the setting range when the electronic gear ratio (Pn20E/ Pn210) or the Servomotor was changed.	Check to see if the detection conditions*3 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1
A.044: Semi-Closed/ Fully-Closed Loop Control Parameter Setting Error	The setting of the Fully-Closed Module does not match the setting of Pn002 = n.X□□□ (External Encoder Usage).	Check the setting of Pn002 = n.X□□□.	Make sure that the setting of the Fully-closed Module agrees with the setting of Pn002 = n.X□□□.	*1
A.04A: Parameter Setting Error 2	For 4-byte parameter bank members, there are two consecutive members with nothing registered.	–	Change the number of bytes for bank members to an appropriate value.	–
	The total amount of bank data exceeds 64 (Pn900 × Pn901 > 64).	–	Reduce the total amount of bank data to 64 or less.	–
A.050: Combination Error (The capacities of the SERVOPACK and Servomotor do not match.)	The SERVOPACK and Servomotor capacities do not match each other.	Confirm that the following condition is met: 1/4 ≤ (Servomotor capacity/SERVOPACK capacity) ≤ 4	Select a proper combination of the SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the encoder.	Replace the encoder and check to see if the alarm still occurs.	Replace the Servomotor or encoder.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.051: Unsupported Device Alarm	An unsupported Serial Converter Unit or encoder (e.g., an external encoder) is connected to the SERVOPACK.	Check the product combination specifications.	Change to a correct combination of models.	–
A.0b0: Invalid Servo ON Command Alarm	The SV_ON (Servo ON) command was sent from the host controller after a utility function that turns ON the Servomotor was executed.	–	Turn the power supply to the SERVOPACK OFF and ON again. Or, execute a software reset.	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	The regenerative resistor is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	The dynamic brake (DB, emergency stop executed from the SERVOPACK) was frequently activated, or a DB overload alarm occurred.	Check the power consumed by the DB resistor to see how frequently the DB is being used. Or, check the alarm display to see if a DB overload alarm (A.730 or A.731) has occurred.	Change the SERVOPACK model, operating methods, or the mechanisms so that the dynamic brake does not need to be used so frequently.	–
	The regenerative processing capacity was exceeded.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Recheck the operating conditions and load.	*4
	The SERVOPACK regenerative resistance is too small.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Change the regenerative resistance to a value larger than the SERVOPACK minimum allowable resistance.	

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.101: Motor Overcurrent Detected (The current to the motor exceeded the allowable current.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across cable phases U, V, and W, or between the ground and cable phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.300: Regeneration Error	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to one of the following SERVOPACKs: SGD7S-2R8A or -2R8F.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or set Pn600 (Regenerative Resistor Capacity) to 0 (setting unit: ×10 W) if no Regenerative Resistor is required.	*1
	The jumper between the regenerative resistor terminals (B2 and B3) was removed from one of the following SERVOPACKs: SGD7S-120A.	Check to see if the jumper is connected between power supply terminals B2 and B3. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correctly connect a jumper.	*1
	The External Regenerative Resistor or Regenerative Resistor Unit is not wired correctly, or was removed or disconnected.	Check the wiring of the External Regenerative Resistor or Regenerative Resistor Unit. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correct the wiring of the External Regenerative Resistor or Regenerative Resistor Unit.	
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.320: Regenerative Overload	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The external regenerative resistance value or regenerative resistor capacity is too small, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or other means.	Change the regenerative resistance value or capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	*4
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
	The setting of Pn600 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check it see if a Regenerative Resistor is connected and check the setting of Pn600.	Correct the setting of Pn600.	*1
	The setting of Pn603 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check to see if a Regenerative Resistor is connected and check the setting of Pn603.	Correct the setting of Pn603.	*1
	The external regenerative resistance is too high.	Check the regenerative resistance.	Change the regenerative resistance to a correct value or use an External Regenerative Resistor of an appropriate capacity.	*4
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.330: Main Circuit Power Supply Wiring Error (Detected when the main circuit power supply is turned ON.)	The regenerative resistor was disconnected when the SERVOPACK power supply voltage was high.	Measure the resistance of the regenerative resistor using a measuring instrument.	If you are using the regenerative resistor built into the SERVOPACK, replace the SERVOPACK. If you are using an External Regenerative Resistor, replace the External Regenerative Resistor.	–
	DC power was supplied when an AC power supply input was specified in the settings.	Check the power supply to see if it is a DC power supply.	Correct the power supply setting to match the actual power supply.	*1
	AC power was supplied when a DC power supply input was specified in the settings.	Check the power supply to see if it is an AC power supply.	Correct the power supply setting to match the actual power supply.	
	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to an SGD7S-2R8A SERVOPACKs.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or if an External Regenerative Resistor is not required, set Pn600 to 0.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.400: Overvoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the AC/DC power supply voltage within the specified range.	–
	The power supply is not stable or was influenced by a lightning surge.	Measure the power supply voltage.	Improve the power supply conditions, install a surge absorber, and then turn the power supply OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The voltage for AC power supply was too high during acceleration or deceleration.	Check the power supply voltage and the speed and torque during operation.	Set the AC power supply voltage within the specified range.	–
	The external regenerative resistance is too high for the operating conditions.	Check the operating conditions and the regenerative resistance.	Select a regenerative resistance value that is appropriate for the operating conditions and load.	*4
	The moment of inertia ratio or mass ratio exceeded the allowable value.	Check to see if the moment of inertia ratio or mass ratio is within the allowable range.	Increase the deceleration time, or reduce the load.	–
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.410: Undervoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage went below the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*1
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor to the DC reactor terminals (⊖1 and ⊖2) on the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.510: Overspeed (The motor exceeded the maximum speed.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the wiring of the Servomotor.	Make sure that the Servomotor is correctly wired.	–
	A reference value that exceeded the overspeed detection level was input.	Check the input reference.	Reduce the reference value. Or, adjust the gain.	–
	The motor exceeded the maximum speed.	Check the waveform of the motor speed.	Reduce the speed reference input gain and adjust the servo gain. Or, reconsider the operating conditions.	
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.511: Encoder Output Pulse Overspeed	The encoder output pulse frequency exceeded the limit.	Check the encoder output pulse setting.	Decrease the setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution).	*1
	The encoder output pulse frequency exceeded the limit because the motor speed was too high.	Check the encoder output pulse setting and the motor speed.	Reduce the motor speed.	–
A.520: Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the setting of Pn100 (Speed Loop Gain).	*1
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*1
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.521: Autotuning Alarm (Vibration was detected while executing the custom tuning, Easy FFT, or the tuning-less function.)	The Servomotor vibrated considerably while performing the tuning-less function.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio is within the allowable value. Or increase the load level or reduce the rigidity level in the tuning-less level settings.	*1
	The Servomotor vibrated considerably while performing custom tuning or Easy FFT.	Check the waveform of the motor speed.	Check the operating procedure of corresponding function and implement corrections.	*1
A.550: Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum speed.	Check the setting of Pn385, and the upper limits of the maximum motor speed setting and the encoder output resolution setting.	Set Pn385 to a value that does not exceed the maximum motor speed.	*1
A.710: Instantaneous Overload A.720: Continuous Overload	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	*1
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven due to mechanical problems.	Check the operation reference and motor speed.	Correct the mechanical problem.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.730 and A.731: Dynamic Brake Overload (An excessive power consumption by the dynamic brake was detected.)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia ratio or mass ratio. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.740: Inrush Current Limiting Resistor Overload (The main circuit power supply was frequently turned ON and OFF.)	The allowable frequency of the inrush current limiting resistor was exceeded when the main circuit power supply was turned ON and OFF.	–	Reduce the frequency of turning the main circuit power supply ON and OFF.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7A1: Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A2: Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A3: Internal Temperature Sensor Error (An error occurred in the temperature sensor circuit.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7Ab: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.810: Encoder Backup Alarm (Detected at the encoder, but only when an absolute encoder is used.)	The power to the absolute encoder was turned ON for the first time.	Check to see if the power supply was turned ON for the first time.	Set up the encoder.	*1
	The Encoder Cable was disconnected and then connected again.	Check to see if the power supply was turned ON for the first time.	Check the encoder connection and set up the encoder.	
	Power is not being supplied both from the control power supply (+5 V) from the SERVOPACK and from the battery power supply.	Check the encoder connector battery and the connector status.	Replace the battery or implement similar measures to supply power to the encoder, and set up the encoder.	
	A failure occurred in the absolute encoder.	–	If the alarm still occurs after setting up the encoder again, replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.820: Encoder Checksum Alarm (Detected at the encoder.)	A failure occurred in the encoder.	–	■ When Using an Absolute Encoder Set up the encoder again. If the alarm still occurs, the Servomotor may be faulty. Replace the Servomotor. ■ When Using a Single-turn Absolute Encoder or Incremental Encoder The Servomotor may be faulty. Replace the Servomotor.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.830: Encoder Battery Alarm (The absolute encoder battery voltage was lower than the specified level.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*1
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.840: Encoder Data Alarm (Detected at the encoder.)	The encoder malfunctioned.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	The encoder malfunctioned due to noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	–
A.850: Encoder Overspeed (Detected at the encoder when the control power supply is turned ON.)	The Servomotor speed was 200 min^{-1} or higher when the control power supply was turned ON.	Check the motor speed when the power supply is turned ON.	Reduce the Servomotor speed to a value less than 200 min^{-1}, and turn ON the control power supply.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.860: Encoder Overheated (Detected at the encoder.)	The surrounding air temperature around the Servomotor is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40°C or less.	–
	The Servomotor load is greater than the rated load.	Use the accumulated load ratio to check the load.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.861: Motor Overheated	The surrounding temperature around the Servomotor is too high.	Measure the surrounding temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40° or less.	–
	The motor load is greater than the rated load.	Check the load with the accumulated load ratio on the Motion Monitor Tab Page on the SigmaWin+.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the Serial Converter Unit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Serial Converter Unit may be faulty. Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.862: Overheat Alarm	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	The overheat protection input signal line is disconnected or short-circuited.	Check the input voltage with the overheat protection input information on the Motion Monitor Tab Page on the SigmaWin+.	Repair the line for the overheat protection input signal.	–
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.8A0: External Encoder Error	Setting the origin of the absolute linear encoder failed because the motor moved.	Before you set the origin, use the fully-closed feedback pulse counter to confirm that the motor is not moving.	The motor must be stopped while setting the origin position.	*1
	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A1: External Encoder Module Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.8A2: External Incremental Encoder Sensor Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A3: External Absolute Encoder Position Error	A failure occurred in the external absolute encoder.	–	The external absolute encoder may be faulty. Refer to the encoder manufacturer's instruction manual for corrections.	–
A.8A5: External Encoder Overspeed	An overspeed error was detected in the external encoder.	Check the maximum speed of the external encoder.	Keep the external encoder below its maximum speed.	–
A.8A6: External Encoder Overheated	An overheating error was detected in the external encoder.	–	Replace the external encoder.	–
A.b33: Current Detection Error 3	A failure occurred in the current detection circuit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.b6A: MECHATROLINK Communications ASIC Error 1	There is a fault in the SERVOPACK MECHATROLINK communications section.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.b6b: MECHATROLINK Communications ASIC Error 2	A malfunction occurred in the MECHATROLINK communications section due to noise.	–	Implement the following countermeasures against noise. • Check the MECHATROLINK Communications Cable and FG wiring. • Attach a ferrite core to the MECHATROLINK Communications Cable.	–
	There is a fault in the SERVOPACK MECHATROLINK communications section.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF0: System Alarm 0	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF1: System Alarm 1	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF2: System Alarm 2	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.bF3: System Alarm 3	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF4: System Alarm 4	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF5: System Alarm 5	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF6: System Alarm 6	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF7: System Alarm 7	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF8: System Alarm 8	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C10: Servomotor Out of Control (Detected when the servo is turned ON.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the Servomotor wiring.	Make sure that the Servomotor is correctly wired.	–
	A failure occurred in the encoder.	–	If the motor wiring is correct and an alarm still occurs after turning the power supply OFF and ON again, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C54: Polarity Detection Failure 2	An external force was applied to the Servomotor.	–	Increase the setting of Pn495 (Polarity Detection Confirmation Force Reference). Increase the setting of Pn498 (Polarity Detection Allowable Error Range). Increasing the allowable error will also increase the motor temperature.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C80: Encoder Clear Error or Multiturn Limit Setting Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C90: Encoder Communications Error	There is a faulty contact in the connector or the connector is not wired correctly for the encoder.	Check the condition of the encoder connector.	Reconnect the encoder connector and check the encoder wiring.	*1
	There is a cable disconnection or short-circuit in the encoder. Or, the cable impedance is outside the specified values.	Check the condition of the Encoder Cable.	Use the Encoder Cable within the specified specifications.	–
	One of the following has occurred: corrosion caused by improper temperature, humidity, or gas, a short-circuit caused by entry of water drops or cutting oil, or faulty contact in connector caused by vibration.	Check the operating environment.	Improve the operating environmental, and replace the cable. If the alarm still occurs, replace the SERVOPACK.	*1
	A malfunction was caused by noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	*1
	A failure occurred in the SERVOPACK.	–	Connect the Servomotor to another SERVOPACK, and turn ON the control power supply. If no alarm occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C91: Encoder Communications Position Data Acceleration Rate Error	Noise entered on the signal lines because the Encoder Cable is bent or the sheath is damaged.	Check the condition of the Encoder Cable and connectors.	Check the Encoder Cable to see if it is installed correctly.	*1
	The Encoder Cable is bundled with a high-current line or installed near a high-current line.	Check the installation condition of the Encoder Cable.	Confirm that there is no surge voltage on the Encoder Cable.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the installation condition of the Encoder Cable.	Properly ground the machine to separate it from the FG of the encoder.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C92: Encoder Communications Timer Error	Noise entered on the signal line from the encoder.	–	Implement countermeasures against noise for the encoder wiring.	*1
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CA0: Encoder Parameter Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.Cb0: Encoder Echoback Error	The encoder is wired incorrectly or there is faulty contact.	Check the wiring of the encoder.	Make sure that the encoder is correctly wired.	*1
	The specifications of the Encoder Cable are not correct and noise entered on it.	–	Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	–
	The Encoder Cable is too long and noise entered on it.	–	Rotary Servomotors: The Encoder Cable wiring distance must be 50 m max.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the condition of the Encoder Cable and connectors.	Properly ground the machine to separate it from the FG of the encoder.	–
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CC0: Multiturn Limit Disagreement	When using a Direct Drive Servomotor, the setting of Pn205 (Multiturn Limit Setting) does not agree with the encoder.	Check the setting of Pn205.	Correct the setting of Pn205 (0 to 65,535).	*1
	The multiturn limit of the encoder is different from that of the SERVOPACK. Or, the multiturn limit of the SERVOPACK has been changed.	Check the setting of Pn205 in the SERVOPACK.	Change the setting if the alarm occurs.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.CF1: Reception Failed Error in Feedback Option Module Communications	The cable between the Serial Converter Unit and SERVOPACK is not wired correctly or there is a faulty contact.	Check the wiring of the external encoder.	Correctly wire the cable between the Serial Converter Unit and SERVOPACK.	*1
	A specified cable is not being used between Serial Converter Unit and SERVOPACK.	Check the wiring specifications of the external encoder.	Use a specified cable.	–
	The cable between the Serial Converter Unit and SERVOPACK is too long.	Measure the length of the cable that connects the Serial Converter Unit.	The length of the cable between the Serial Converter Unit and SERVOPACK must be 20 m or less.	–
	The sheath on cable between the Serial Converter Unit and SERVOPACK is broken.	Check the cable that connects the Serial Converter Unit.	Replace the cable between the Serial Converter Unit and SERVOPACK.	–
A.CF2: Timer Stopped Error in Feedback Option Module Communications	Noise entered the cable between the Serial Converter Unit and SERVOPACK.	–	Correct the wiring around the Serial Converter Unit, e.g., separate I/O signal lines from the Main Circuit Cables or ground.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.d00: Position Deviation Overflow (The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.)	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty contacts in the wiring for the Servomotor and encoder.	–
	The position command speed is too fast.	Reduce the position command speed and try operating the SERVOPACK.	Reduce the position reference speed or the reference acceleration rate, or reconsider the electronic gear ratio.	*1
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Reduce the acceleration of the position reference using a MECHATROLINK command. Or, smooth the position reference acceleration by selecting the position reference filter (ACCFIL) using a MECHATROLINK command.	–
	The setting of Pn520 (Excessive Position Deviation Alarm Level) is too low for the operating conditions.	Check Pn520 (Excessive Position Deviation Alarm Level) to see if it is set to an appropriate value.	Optimize the setting of Pn520.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.d01: Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Check the position deviation while the servo is OFF.	Optimize the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON).	
A.d02: Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if a position reference is input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded.	–	Optimize the setting of Pn520 (Excessive Position Deviation Alarm Level). Or, adjust the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON).	*1
A.d10: Motor-Load Position Deviation Overflow	The motor direction and external encoder installation orientation are backward.	Check the motor direction and the external encoder installation orientation.	Install the external encoder in the opposite direction, or change the setting of Pn002 = n.X□□□ (External Encoder Usage) to reverse the direction.	*1
	There is an error in the connection between the load (e.g., stage) and external encoder coupling.	Check the coupling of the external encoder.	Check the mechanical coupling.	–
A.d30: Position Data Overflow	The position data exceeded ±1,879,048,192.	Check the input reference pulse counter.	Reconsider the operating specifications.	–
A.E02: MECHATROLINK Internal Synchronization Error 1	The MECHATROLINK transmission cycle fluctuated.	–	Remove the cause of transmission cycle fluctuation at the host controller.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E40: MECHATROLINK Transmission Cycle Setting Error	The setting of MECHATROLINK transmission cycle is outside of the specified range.	Check the setting of the MECHATROLINK transmission cycle.	Set the MECHATROLINK transmission cycle to an appropriate value.	–
A.E50*5: MECHATROLINK Synchronization Error	The WDT data in the host controller was not updated normally.	Check to see if the WDT data is being updated at the host controller.	Correctly update the WDT data at the host controller.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.E51: MECHATROLINK Synchronization Failed	The WDT data at the host controller was not updated correctly at the start of synchronous communications, so synchronous communications could not be started.	Check to see if the WDT data is being updated in the host controller.	Correctly update the WDT data at the host controller.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E60*5: Reception Error in MECHATROLINK Communications	MECHATROLINK wiring is not correct.	Check the MECHATROLINK wiring.	Correct the MECHATROLINK Communications Cable wiring. Correctly connect the terminator.	–
	A MECHATROLINK data reception error occurred due to noise.	–	Implement countermeasures against noise. (Check the MECHATROLINK Communications Cable and FG wiring, and implement measures such as attaching a ferrite core to the MECHATROLINK Communications Cable.)	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E61: Synchronization Interval Error in MECHATROLINK Transmission Cycle	The MECHATROLINK transmission cycle fluctuated.	Check the setting of the MECHATROLINK transmission cycle.	Remove the cause of transmission cycle fluctuation at the host controller.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E71: Safety Option Module Detection Failure	There is a faulty connection between the SERVOPACK and the Safety Option Module.	Check the connection between the SERVOPACK and the Safety Option Module.	Correctly connect the Safety Option Module.	–
	The Safety Option Module was disconnected.	–	Execute Fn014 (Reset Option Module Configuration Error) from the Digital Operator or SigmaWin+ and then turn the power supply to the SERVOPACK OFF and ON again.	*1
	A failure occurred in the Safety Option Module.	–	Replace the Safety Option Module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.E72: Feedback Option Module Detection Failure	There is a faulty connection between the SERVOPACK and the Feedback Option Module.	Check the connection between the SERVOPACK and the Feedback Option Module.	Correctly connect the Feedback Option Module.	–
	The Feedback Option Module was disconnected.	–	Reset the Option Module configuration error and turn the power supply to the SERVOPACK OFF and ON again.	*1
	A failure occurred in the Feedback Option Module.	–	Replace the Feedback Option Module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.E74: Unsupported Safety Option Module	A failure occurred in the Safety Option Module.	–	Replace the Safety Option Module.	–
	An unsupported Safety Option Module was connected.	Refer to the catalog of the connected Safety Option Module.	Connect a compatible Safety Option Module.	–
A.Eb1: Safety Function Signal Input Timing Error	The delay between activation of the /HWBB1 and /HWBB2 input signals for the HWBB was ten second or longer.	Measure the time delay between the /HWBB1 and /HWBB2 signals.	The output signal circuits or devices for /HWBB1 and /HWBB2 or the SERVOPACK input signal circuits may be faulty. Alternatively, the input signal cables may be disconnected. Check to see if any of these items are faulty or have been disconnected.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.EC8: Gate Drive Error 1 (An error occurred in the gate drive circuit.)	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.EC9: Gate Drive Error 2 (An error occurred in the gate drive circuit.)				
A.Ed1: Command Execution Timeout	A timeout error occurred for a MECHATROLINK command.	Check the motor status when the command is executed.	Execute the SV_ON or SENS_ON command only when the motor is not operating.	–
		For fully-closed loop control, check the status of the external encoder when the command is executed.	Execute the SENS_ON command only when an external encoder is connected.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.F10: Power Supply Line Open Phase (The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.)	The three-phase power supply wiring is not correct.	Check the power supply wiring.	Make sure that the power supply is correctly wired.	*1
	The three-phase power supply is unbalanced.	Measure the voltage for each phase of the three-phase power supply.	Balance the power supply by changing phases.	–
	A single-phase power supply was input without specifying a signal-phase AC power supply input (Pn00B = n.□1□□).	Check the power supply and the parameter setting.	Match the parameter setting to the power supply.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
FL-1*5: System Alarm FL-2*5: System Alarm FL-3*5: System Alarm FL-4*5: System Alarm FL-5*5: System Alarm FL-6*5: System Alarm	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
CPF00: Digital Operator Communications Error 1	There is a faulty contact between the Digital Operator and the SERVOPACK.	Check the connector contact.	Disconnect the connector and insert it again. Or, replace the cable.	–
	A malfunction was caused by noise.	–	Keep the Digital Operator or the cable away from sources of noise.	–
CPF01: Digital Operator Communications Error 2	A failure occurred in the Digital Operator.	–	Disconnect the Digital Operator and then connect it again. If an alarm still occurs, the Digital Operator may be faulty. Replace the Digital Operator.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)

*2. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Pn533 [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{6 \times 10^5} \leq \dfrac{\text{Pn20E}}{\text{Pn210}}$

- $\text{Maximum motor speed [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \dfrac{\text{Pn20E}}{\text{Pn210}}$

*3. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Rated motor speed [min}^{-1}\text{]} \times 1/3 \times \dfrac{\text{Encoder resolution}}{6 \times 10^5} \leq \dfrac{\text{Pn20E}}{\text{Pn210}}$

- $\text{Maximum motor speed [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \dfrac{\text{Pn20E}}{\text{Pn210}}$

*4. Refer to the following manual for details.
Σ-7-Series Peripheral Device Selection Manual (Manual No.: SIEP S800001 32)

*5. These alarms are not stored in the alarm history. They are only displayed on the panel display.

3.2.4 Warning Displays

If a warning occurs in the SERVOPACK, a warning number will be displayed on the panel display. Warnings are displayed to warn you before an alarm occurs.

3.2.5 List of Warnings

The list of warnings gives the warning name and warning meaning in order of the warning numbers.

Warning Number	Warning Name	Meaning
A.900	Position Deviation Overflow	The position deviation exceeded the percentage set with the following formula: (Pn520 × Pn51E/100)
A.901	Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)
A.910	Overload	This warning occurs before an overload alarm (A.710 or A.720) occurs. If the warning is ignored and operation is continued, an alarm may occur.
A.911	Vibration	Abnormal vibration was detected during motor operation. The detection level is the same as A.520. Set whether to output an alarm or a warning by setting Pn310 (Vibration Detection Switch).
A.912	Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.
A.913	Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.
A.920	Regenerative Overload	This warning occurs before an A.320 alarm (Regenerative Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.
A.921	Dynamic Brake Overload	This warning occurs before an A.731 alarm (Dynamic Brake Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.
A.923	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.
A.930	Absolute Encoder Battery Error	This warning occurs when the voltage of absolute encoder's battery is low.
A.93B	Overheat Warning	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61C (Overheat Warning Level).
A.942	Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.
A.94A	Data Setting Warning 1 (Parameter Number Error)	There is an error in the parameter number for a Data Setting Warning 1 (Parameter Number) command.
A.94b	Data Setting Warning 2 (Out of Range)	The command data is out of range.
A.94C	Data Setting Warning 3 (Calculation Error)	A calculation error was detected.
A.94d	Data Setting Warning 4 (Parameter Size)	The data sizes do not match.
A.94E	Data Setting Warning 5 (Latch Mode Error)	A latch mode error was detected.

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Warning Number	Warning Name	Meaning
A.95A	Command Warning 1 (Unsatisfied Command Conditions)	A command was sent when the conditions for sending a command were not satisfied.
A.95b	Command Warning 2 (Unsupported Command)	An unsupported command was sent.
A.95d	Command Warning 4 (Command Interference)	There was command interference, particularly latch command interference.
A.95E	Command Warning 5 (Subcommand Not Possible)	The subcommand and main command interfere with each other.
A.95F	Command Warning 6 (Undefined Command)	An undefined command was sent.
A.960	MECHATROLINK Communications Warning	A communications error occurred during MECHATROLINK communications.
A.971	Undervoltage	This warning occurs before an A.410 alarm (Undervoltage) occurs. If the warning is ignored and operation is continued, an alarm may occur.
A.9A0	Overtravel	Overtravel was detected while the servo was ON.
A.9b0	Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.

Note: 1. A warning code is not output unless you set Pn001 to n.1□□□ (Output both alarm codes and warning codes).

2. Use Pn008 = n.□X□□ (Warning Detection Selection) to control warning detection.
However, the following warnings are not affected by the setting of Pn008 = n.□X□□ and other parameter settings are required in addition to Pn008 = n.□X□□.

Warning	Parameters That Must Be Set to Select Warning Detection
A.911	Pn310 = n.□□□X (Vibration Detection Setting)
A.923	– (Not affected by the setting of Pn008 = n.□X□□.)
A.930	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection)
A.942	Pn423 = n.□□X□ (Speed Ripple Compensation Information Disagreement Warning Detection Selection)
A.94A to A.960	Pn800=n.□□X□ (Warning Check Masks)
A.971	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection) (Not affected by the setting of Pn008 = n.□X□□.)
A.9A0	Pn00D = n.X□□□ (Overtravel Warning Detection Selection) (Not affected by the setting of Pn008 = n.□X□□.)
A.9b0	Pn00F = n.□□□X (Preventative Maintenance Selection)

3.2.6 Troubleshooting Warnings

The causes of and corrections for the warnings are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.900: Position Deviation Overflow	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty connections in the wiring for the Servomotor and encoder.	–
	A SERVOPACK gain is too low.	Check the SERVOPACK gains.	Increase the servo gain, e.g., by using autotuning without a host reference.	*
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Reduce the acceleration of the position reference using a MECHATROLINK command. Or, smooth the position reference acceleration by selecting the position reference filter (ACCFIL) using a MECHATROLINK command.	–
	The excessive position deviation alarm level (Pn520 × Pn51E/100) is too low for the operating conditions.	Check excessive position deviation alarm level (Pn520 × Pn51E/100) to see if it is set to an appropriate value.	Optimize the settings of Pn520 and Pn51E.	*
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.901: Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)	–	Optimize the setting of Pn528 (Excessive Position Error Warning Level at Servo ON).	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.910: Overload (warning before an A.710 or A.720 alarm occurs)	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	–
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven because of mechanical problems.	Check the operation reference and motor speed.	Remove the mechanical problem.	–
	The overload warning level (Pn52B) is not suitable.	Check that the overload warning level (Pn52B) is suitable.	Set a suitable overload warning level (Pn52B).	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.911: Vibration	Abnormal vibration was detected during motor operation.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the servo gain with custom tuning.	*
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.912: Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.913: Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.920: Regenerative Overload (warning before an A.320 alarm occurs)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	There is insufficient external regenerative resistance, regenerative resistor capacity, or SERVOPACK capacity, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or another means.	Change the regenerative resistance value, regenerative resistance capacity, or SERVOPACK capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	–
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
A.921: Dynamic Brake Overload (warning before an A.731 alarm occurs)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia or mass. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.923: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.930: Absolute Encoder Battery Error (The absolute encoder battery voltage was lower than the specified level.) (Detected only when an absolute encoder is connected.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.93B: Overheat Warning	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.942: Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	–	Reset the speed ripple compensation value on the SigmaWin+.	*
		–	Set Pn423 to n.□□1□ (Do not detect A.942 alarms). However, changing the setting may increase the speed ripple.	*
		–	Set Pn423 to n.□□□0 (Disable torque ripple compensation). However, changing the setting may increase the speed ripple.	*
A.94A: Data Setting Warning 1 (Parameter Number Error)	An invalid parameter number was used.	Check the command that caused the warning.	Use the correct parameter number.	*
A.94b: Data Setting Warning 2 (Out of Range)	The set command data was clamped to the minimum or maximum value of the setting range.	Check the command that caused the warning.	Set the parameter within the setting range.	*
A.94C: Data Setting Warning 3 (Calculation Error)	The calculation result of the setting is not correct.	Check the command that caused the warning.	Set the parameter within the setting range.	*
A.94d: Data Setting Warning 4 (Parameter Size)	The parameter size set in the command is not correct.	Check the command that caused the warning.	Set the correct parameter size.	*
A.94E: Data Setting Warning 5 (Latch Mode Error)	A latch mode error was detected.	Check the command that caused the warning.	Change the setting of Pn850 or the LT_MOD data for the LTMOD_ON command sent by the host controller to an appropriate value.	*
A.95A: Command Warning 1 (Unsatisfied Command Conditions)	The command conditions are not satisfied.	Check the command that caused the warning.	Send the command after the command conditions are satisfied.	*
A.95b: Command Warning 2 (Unsupported Command)	An unsupported command was received.	Check the command that caused the warning.	Do not send unsupported commands.	*

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.95d: Command Warning 4 (Command Interference)	The command sending conditions for latch-related commands was not satisfied.	Check the command that caused the warning.	Send the command after the command conditions are satisfied.	*
A.95E: Command Warning 5 (Subcommand Not Possible)	The command sending conditions for subcommands was not satisfied.	Check the command that caused the warning.	Send the command after the conditions are satisfied.	*
A.95F: Command Warning 6 (Undefined Command)	An undefined command was sent.	Check the command that caused the warning.	Do not send undefined commands.	*
A.960: MECHATROLINK Communications Warning	The MECHATROLINK Communications Cable is not wired correctly.	Check the wiring conditions.	Correct the MECHATROLINK communications cable wiring. Or, connect a terminator to the final station.	*
	A MECHATROLINK data reception error occurred due to noise.	Confirm the installation conditions.	Implement the following countermeasures against noise. • Check the MECHATROLINK Communications Cable and FG wiring and implement countermeasures to prevent noise from entering. • Attach a ferrite core to the MECHATROLINK Communications Cable.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.971: Undervoltage	For a 200-V SERVOPACK, the AC power supply voltage dropped below 140 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	For a 100-V SERVOPACK, the AC power supply voltage dropped below 60 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.9A0: Overtravel (Overtravel status was detected.)	Overtravel was detected while the servo was ON.	Check the status of the overtravel signals on the input signal monitor.	Even if an overtravel signal is not shown by the input signal monitor, momentary overtravel may have been detected. Take the following precautions. • Do not specify movements that would cause overtravel from the host controller. • Check the wiring of the overtravel signals. • Implement countermeasures against noise.	*
A.9b0: Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	–	Replace the part. Contact your Yaskawa representative for replacement.	*

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)

3.2.7 Troubleshooting Based on the Operation and Conditions of the Servomotor

This section provides troubleshooting based on the operation and conditions of the Servomotor, including causes and corrections.

Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The control power supply is not turned ON.	Measure the voltage between control power supply terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the control power supply is turned ON.	–
	The main circuit power supply is not turned ON.	Measure the voltage across the main circuit power input terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the main circuit power supply is turned ON.	–
	The I/O signal connector (CN1) pins are not wired correctly or are disconnected.	Turn OFF the power supply to the servo system. Check the wiring condition of the I/O signal connector (CN1) pins.	Correct the wiring of the I/O signal connector (CN1) pins.	*
	The wiring for the Servomotor Main Circuit Cables or Encoder Cable is disconnected.	Check the wiring conditions.	Turn OFF the power supply to the servo system. Wire the cable correctly.	–
	There is an overload on the Servomotor.	Operate the Servomotor with no load and check the load status.	Turn OFF the power supply to the servo system. Reduce the load or replace the Servomotor with a Servomotor with a larger capacity.	–
	The type of encoder that is being used does not agree with the setting of Pn002 = n.□X□□ (Encoder Usage).	Check the type of the encoder that is being used and the setting of Pn002 = n.□X□□.	Set Pn002 = n.□X□□ according to the type of the encoder that is being used.	*
	There is a mistake in the input signal allocations (Pn50A, Pn50B, Pn511, and Pn516).	Check the input signal allocations (Pn50A, Pn50B, Pn511, and Pn516).	Correctly allocate the input signals (Pn50A, Pn50B, Pn511, and Pn516).	*
	The SV_ON command was not sent.	Check the commands sent from the host controller.	Send the SV_ON command from the host controller.	–
	The SENS_ON (Turn ON Sensor) command was not sent.	Check the commands sent from the host controller.	Send the commands to the SERVOPACK in the correct sequence.	–
	The P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal is still OFF.	Check the P-OT and N-OT signals.	Turn ON the P-OT and N-OT signals.	*
	The safety input signals (/HWBB1 or /HWBB2) were not turned ON.	Check the /HWBB1 and /HWBB2 input signals.	Turn ON the /HWBB1 and /HWBB2 input signals. If you are not using the safety function, connect the Safety Jumper Connector (provided as an accessory) to CN8.	*

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Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The FSTP (Forced Stop Input) signal is still OFF.	Check the FSTP signal.	• Turn ON the FSTP signal. • If you will not use the function to force the motor to stop, set Pn516 = n.□□□X (FSTP (Forced Stop Input) Signal Allocation) to disable the signal.	*
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Servomotor Moves Instantaneously, and Then Stops	There is a mistake in the Servomotor wiring.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Servomotor correctly.	–
	There is a mistake in the wiring of the encoder or Serial Converter Unit.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Serial Converter Unit correctly.	–
Servomotor Speed Is Unstable	There is a faulty connection in the Servomotor wiring.	Turn OFF the power supply to the servo system. The connector connections for the power line (U, V, and W phases) and the encoder or Serial Converter Unit may be unstable. Check the wiring.	Tighten any loose terminals or connectors and correct the wiring.	–
Servomotor Moves without a Reference Input	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Dynamic Brake Does Not Operate	The setting of Pn001 = n.□□□X (Servo OFF or Alarm Group 1 Stopping Method) is not suitable.	Check the setting of Pn001 = n.□□□X.	Set Pn001 = n.□□□X correctly.	–
	The dynamic brake resistor is disconnected.	Check the moment of inertia, motor speed, and dynamic brake frequency of use. If the moment of inertia, motor speed, or dynamic brake frequency of use is excessive, the dynamic brake resistance may be disconnected.	Turn OFF the power supply to the servo system. Replace the SERVOPACK. To prevent disconnection, reduce the load.	–
	There was a failure in the dynamic brake drive circuit.	–	Turn OFF the power supply to the servo system. There is a defective component in the dynamic brake circuit. Replace the SERVOPACK.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	The Servomotor vibrated considerably while performing the tuning-less function with the default settings.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio or mass ratio is within the allowable value, or increase the load level or reduce the rigidity level in the tuning-less level settings.	*
	The machine mounting is not secure.	Turn OFF the power supply to the servo system. Check to see if there are any loose mounting screws.	Tighten the mounting screws.	–
	The machine mounting is not secure.	Turn OFF the power supply to the servo system. Check to see if there is misalignment in the coupling.	Align the coupling.	–
		Turn OFF the power supply to the servo system. Check to see if the coupling is balanced.	Balance the coupling.	–
	The bearings are defective.	Turn OFF the power supply to the servo system. Check for noise and vibration around the bearings.	Replace the Servomotor.	–
	There is a vibration source at the driven machine.	Turn OFF the power supply to the servo system. Check for any foreign matter, damage, or deformation in the machine's moving parts.	Consult with the machine manufacturer.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use shielded twisted-pair wire cables or screened twisted-pair cables with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Make sure that the rotary or Linear Encoder Cable satisfies the specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with a conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Check to see if there is noise interference on the signal line from the encoder.	Turn OFF the power supply to the servo system. Implement countermeasures against noise for the encoder wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
Servomotor Vibrates at Frequency of Approx. 200 to 400 Hz.	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	*
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Large Motor Speed Overshoot on Starting and Stopping	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	*
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–
	The torque reference is saturated.	Check the waveform of the torque reference.	Use the mode switch.	–
	The force limits (Pn483 and Pn484) are set to the default values.	The default values of the force limits and Pn483 = 30% and Pn484 = 30%.	Set Pn483 and Pn484 to appropriate values.	*
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	Replace the Encoder Cable and correct the cable installation environment.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder or Serial Converter Unit wiring.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
	Host Controller Multiturn Data or Absolute Encoder Position Data Reading Error	Check the error detection section of the host controller.	Correct the error detection section of the host controller.	–
		Check to see if the host controller is executing data parity checks.	Perform parity checks for the multiturn data or absolute encoder position data.	–
		Check for noise interference in the cable between the SERVOPACK and the host controller.	Implement countermeasures against noise and then perform parity checks again for the multiturn data or absolute encoder position data.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Overtravel Occurred	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal was input.	Check the external power supply (+24 V) voltage for the input signals.	Correct the external power supply (+24 V) voltage for the input signals.	–
		Check the operating condition of the overtravel limit switches.	Make sure that the overtravel limit switches operate correctly.	–
		Check the wiring of the overtravel limit switches.	Correct the wiring of the overtravel limit switches.	*
		Check the settings of the overtravel input signal allocations (Pn50A/ Pn50B).	Set the parameters to correct values.	*
	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal malfunctioned.	Check for fluctuation in the external power supply (+24 V) voltage for the input signals.	Eliminate fluctuation from the external power supply (+24 V) voltage for the input signals.	–
		Check to see if the operation of the overtravel limit switches is unstable.	Stabilize the operating condition of the overtravel limit switches.	–
		Check the wiring of the overtravel limit switches (e.g., check for cable damage and loose screws).	Correct the wiring of the overtravel limit switches.	–
	There is a mistake in the allocation of the P-OT or N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal in Pn50A = n.X□□□ or Pn50B = n.□□□X.	Check to see if the P-OT signal is allocated in Pn50A = n.X□□□.	If another signal is allocated in Pn50A =n.X□□□, allocate the P-OT signal instead.	*
		Check to see if the N-OT signal is allocated in Pn50B = n.□□□X.	If another signal is allocated in Pn50B =n.□□□X, allocate the N-OT signal instead.	
	The selection of the Servomotor stopping method is not correct.	Check the servo OFF stopping method set in Pn001 = n.□□□X or Pn001 = n.□□X□.	Select a Servomotor stopping method other than coasting to a stop.	*
		Check the torque control stopping method set in Pn001 = n.□□□X or Pn001 = n.□□X□.	Select a Servomotor stopping method other than coasting to a stop.	
Improper Stop Position for Overtravel (OT) Signal	The limit switch position and dog length are not appropriate.	–	Install the limit switch at the appropriate position.	–
	The overtravel limit switch position is too close for the coasting distance.	–	Install the overtravel limit switch at the appropriate position.	–
Position Deviation (without Alarm)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Position Deviation (without Alarm)	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder wiring or Serial Converter Unit wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	The coupling between the machine and Servomotor is not suitable.	Turn OFF the power supply to the servo system. Check to see if position offset occurs at the coupling between machine and Servomotor.	Correctly secure the coupling between the machine and Servomotor.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	An encoder fault occurred. (The pulse count does not change.)	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Overheated	The surrounding air temperature is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature to 40°C or less.	–
	The surface of the Servomotor is dirty.	Turn OFF the power supply to the servo system. Visually check the surface for dirt.	Clean dirt, dust, and oil from the surface.	–
	There is an overload on the Servomotor.	Check the load status with a monitor.	If the Servomotor is overloaded, reduce the load or replace the Servo Drive with a SERVOPACK and Servomotor with larger capacities.	–
	Polarity detection was not performed correctly.	Check to see if electrical angle 2 (electrical angle from polarity origin) at any position is between ±10°.	Correct the settings for the polarity detection-related parameters.	–
Estimating the moment of inertia failed.	The acceleration rate is low and travel distance is short.	Check the Condition Setting Dialog Box used to perform moment of inertia estimation.	Increase the acceleration rate and travel distance.	–

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)

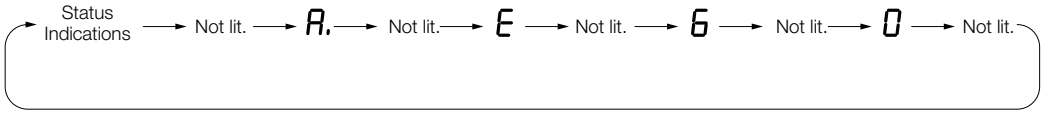
3.3 FT82 SERVOPACK with MECHATROLINK-III Communications References

3.3.1 Alarm Displays

If an error occurs in the SERVOPACK, an alarm number will be displayed on the panel display. However, if □□-□□ appears on the panel display, the display will indicate a SERVOPACK system error. Replace the SERVOPACK.

If there is an alarm, the display will change in the following order.

Example: Alarm A.E60



3.3.2 List of Alarms

The list of alarms gives the alarm name, alarm meaning, alarm stopping method, and alarm reset possibility in order of the alarm numbers.

Servomotor Stopping Method for Alarms

Refer to the following manual for information on the stopping method for alarms.

Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)

Alarm Reset Possibility

Yes: You can use an alarm reset to clear the alarm. However, this assumes that the cause of the alarm has been removed.
No: You cannot clear the alarm.

List of Alarms

Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.020	Parameter Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No
A.021	Parameter Format Error	There is an error in the parameter data format in the SERVOPACK.	Gr.1	No
A.022	System Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No
A.024	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No
A.025	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No
A.030	Main Circuit Detector Error	There is an error in the detection data for the main circuit.	Gr.1	Yes
A.040	Parameter Setting Error	A parameter setting is outside of the setting range.	Gr.1	No

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.041	Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Gr.1	No
A.042	Parameter Combination Error	The combination of some parameters exceeds the setting range.	Gr.1	No
A.044	Semi-Closed/Fully-Closed Loop Control Parameter Setting Error	The settings of the Option Module and Pn002 = n.X□□□ (External Encoder Usage) do not match.	Gr.1	No
A.04A	Parameter Setting Error 2	There is an error in the bank members or bank data settings.	Gr.1	No
A.050	Combination Error	The capacities of the SERVOPACK and Servomotor do not match.	Gr.1	Yes
A.051	Unsupported Device Alarm	An unsupported device was connected.	Gr.1	No
A.0b0	Invalid Servo ON Command Alarm	The SV_ON (Servo ON) command was sent from the host controller after a utility function that turns ON the Servomotor was executed.	Gr.1	Yes
A.100	Overcurrent Detected	An overcurrent flowed through the power transformer or the heat sink overheated.	Gr.1	No
A.101	Motor Overcurrent Detected	The current to the motor exceeded the allowable current.	Gr.1	No
A.300	Regeneration Error	There is an error related to regeneration.	Gr.1	Yes
A.320	Regenerative Overload	A regenerative overload occurred.	Gr.2	Yes
A.330	Main Circuit Power Supply Wiring Error	• The AC power supply input setting or DC power supply input setting is not correct. • The power supply wiring is not correct.	Gr.1	Yes
A.400	Overvoltage	The main circuit DC voltage is too high.	Gr.1	Yes
A.410	Undervoltage	The main circuit DC voltage is too low.	Gr.2	Yes
A.510	Overspeed	The motor exceeded the maximum speed.	Gr.1	Yes
A.511	Encoder Output Pulse Overspeed	The pulse output speed for the setting of Pn212 (Encoder Output Pulses) was exceeded.	Gr.1	Yes
A.520	Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Gr.1	Yes
A.521	Autotuning Alarm	Vibration was detected during autotuning for the tuning-less function.	Gr.1	Yes
A.550	Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum motor speed.	Gr.1	Yes
A.710	Instantaneous Overload	The Servomotor was operating for several seconds to several tens of seconds under a torque that largely exceeded the rating.	Gr.2	Yes
A.720	Continuous Overload	The Servomotor was operating continuously under a torque that exceeded the rating.	Gr.1	Yes
A.730	Dynamic Brake Overload	When the dynamic brake was applied, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Gr.1	Yes
A.731				
A.740	Inrush Current Limiting Resistor Overload	The main circuit power supply was frequently turned ON and OFF.	Gr.1	Yes
A.7A1	Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	Gr.2	Yes

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.7A2	Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.	Gr.2	Yes
A.7A3	Internal Temperature Sensor Error	An error occurred in the temperature sensor circuit.	Gr.2	No
A.7Ab	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Gr.1	Yes
A.810	Encoder Backup Alarm	The power supplies to the encoder all failed and the position data was lost.	Gr.1	No
A.820	Encoder Checksum Alarm	There is an error in the checksum results for encoder memory.	Gr.1	No
A.830	Encoder Battery Alarm	The battery voltage was lower than the specified level after the control power supply was turned ON.	Gr.1	Yes
A.840	Encoder Data Alarm	There is an internal data error in the encoder.	Gr.1	No
A.850	Encoder Overspeed	The encoder was operating at high speed when the power was turned ON.	Gr.1	No
A.860	Encoder Overheated	The internal temperature of encoder is too high.	Gr.1	No
A.861	Motor Overheated	The internal temperature of motor is too high.	Gr.1	No
A.862	Overheat Alarm	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61B (Overheat Alarm Level).	Gr.1	Yes
A.8A0	External Encoder Error	An error occurred in the external encoder.	Gr.1	Yes
A.8A1	External Encoder Module Error	An error occurred in the Serial Converter Unit.	Gr.1	Yes
A.8A2	External Incremental Encoder Sensor Error	An error occurred in the external encoder.	Gr.1	Yes
A.8A3	External Absolute Encoder Position Error	An error occurred in the position data of the external encoder.	Gr.1	Yes
A.8A5	External Encoder Overspeed	An overspeed error occurred in the external encoder.	Gr.1	Yes
A.8A6	External Encoder Overheated	An overheating error occurred in the external encoder.	Gr.1	Yes
A.b33	Current Detection Error 3	An error occurred in the current detection circuit.	Gr.1	No
A.b6A	MECHATROLINK Communications ASIC Error 1	ASIC error 1 occurred in MECHATROLINK communications.	Gr.1	No
A.b6b	MECHATROLINK Communications ASIC Error 2	ASIC error 2 occurred in MECHATROLINK communications.	Gr.2	No
A.bF0	System Alarm 0	Internal program error 0 occurred in the SERVOPACK.	Gr.1	No
A.bF1	System Alarm 1	Internal program error 1 occurred in the SERVOPACK.	Gr.1	No
A.bF2	System Alarm 2	Internal program error 2 occurred in the SERVOPACK.	Gr.1	No
A.bF3	System Alarm 3	Internal program error 3 occurred in the SERVOPACK.	Gr.1	No
A.bF4	System Alarm 4	Internal program error 4 occurred in the SERVOPACK.	Gr.1	No
A.bF5	System Alarm 5	Internal program error 5 occurred in the SERVOPACK.	Gr.1	No
A.bF6	System Alarm 6	Internal program error 6 occurred in the SERVOPACK.	Gr.1	No

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.bF7	System Alarm 7	Internal program error 7 occurred in the SERVOPACK.	Gr.1	No
A.bF8	System Alarm 8	Internal program error 8 occurred in the SERVOPACK.	Gr.1	No
A.C10	Servomotor Out of Control	The Servomotor ran out of control.	Gr.1	Yes
A.C80	Encoder Clear Error or Multiturn Limit Setting Error	The multiturn data for the absolute encoder was not correctly cleared or set.	Gr.1	No
A.C90	Encoder Communications Error	Communications between the encoder and SERVOPACK is not possible.	Gr.1	No
A.C91	Encoder Communications Position Data Acceleration Rate Error	An error occurred in calculating the position data of the encoder.	Gr.1	No
A.C92	Encoder Communications Timer Error	An error occurred in the communications timer between the encoder and SERVOPACK.	Gr.1	No
A.CA0	Encoder Parameter Error	The parameters in the encoder are corrupted.	Gr.1	No
A.Cb0	Encoder Echoback Error	The contents of communications with the encoder are incorrect.	Gr.1	No
A.CC0	Multiturn Limit Disagreement	Different multiturn limits have been set in the encoder and the SERVOPACK.	Gr.1	No
A.CF1	Reception Failed Error in Feedback Option Module Communications	Receiving data from the Feedback Option Module failed.	Gr.1	No
A.CF2	Timer Stopped Error in Feedback Option Module Communications	An error occurred in the timer for communications with the Feedback Option Module.	Gr.1	No
A.d00	Position Deviation Overflow	The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.	Gr.1	Yes
A.d01	Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Gr.1	Yes
A.d02	Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if a position reference is input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded before the limit is cleared.	Gr.2	Yes
A.d10	Motor-Load Position Deviation Overflow	There was too much position deviation between the motor and load during fully-closed loop control.	Gr.2	Yes
A.d30	Position Data Overflow	The position feedback data exceeded ±1,879,048,192.	Gr.1	No
A.E02	MECHATROLINK Internal Synchronization Error 1	A synchronization error occurred during MECHATROLINK communications with the SERVOPACK.	Gr.1	Yes
A.E40	MECHATROLINK Transmission Cycle Setting Error	The setting of the MECHATROLINK communications transmission cycle is not correct.	Gr.2	Yes
A.E41	MECHATROLINK Communications Data Size Setting Error	The setting of the MECHATROLINK communications data size is not correct.	Gr.2	Yes

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?
A.E42	MECHATROLINK Station Address Setting Error	The setting of the MECHATROLINK station address is not correct.	Gr.2	No
A.E50*	MECHATROLINK Synchronization Error	A synchronization error occurred during MECHATROLINK communications.	Gr.2	Yes
A.E51	MECHATROLINK Synchronization Failed	Synchronization failed during MECHATROLINK communications.	Gr.2	Yes
A.E60*	Reception Error in MECHATROLINK Communications	Communications errors occurred continuously during MECHATROLINK communications.	Gr.2	Yes
A.E61	Synchronization Interval Error in MECHATROLINK Transmission Cycle	An error occurred in the transmission cycle during MECHATROLINK communications.	Gr.2	Yes
A.E63	MECHATROLINK Synchronization Frame Not Received	Synchronization frames were continuously not received during MECHATROLINK communications.	Gr.2	Yes
A.E71	Safety Option Module Detection Failure	Detection of the Safety Option Module failed.	Gr.1	No
A.E72	Feedback Option Module Detection Failure	Detection of the Feedback Option Module failed.	Gr.1	No
A.E74	Unsupported Safety Option Module	An unsupported Safety Option Module was connected.	Gr.1	No
A.Eb1	Safety Function Signal Input Timing Error	An error occurred in the input timing of the safety function signal.	Gr.1	No
A.EC8	Gate Drive Error 1	An error occurred in the gate drive circuit.	Gr.1	No
A.EC9	Gate Drive Error 2	An error occurred in the gate drive circuit.	Gr.1	No
A.Ed1	Command Execution Timeout	A timeout error occurred for a MECHATROLINK command.	Gr.2	Yes
A.F10	Power Supply Line Open Phase	The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.	Gr.2	Yes
FL-1*	System Alarm	An internal program error occurred in the SERVOPACK.	–	No
FL-2*				
FL-3*				
FL-4*				
FL-5*				
FL-6*				
CPF00	Digital Operator Communications Error 1	Communications were not possible between the Digital Operator (model: JUSP-OP05A-1-E) and the SERVOPACK (e.g., a CPU error occurred).	–	No
CPF01	Digital Operator Communications Error 2			

* These alarms are not stored in the alarm history. They are only displayed on the panel display.

Note: The A.Eb0, A.Eb2 to A.Eb9, and A.EC0 to A.EC2 alarms can occur when a Safety Module is connected.
Refer to the following manual for details.
AC Servo Drive Σ-V-Series/Σ-V-Series for Large-Capacity Models/Σ-7-Series User's Manual Safety Module (Manual No.: SIEP C720829 06)

3.3.3 Troubleshooting Alarms

The causes of and corrections for the alarms are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.020: Parameter Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	Set the power supply voltage within the specified range, and initialize the parameter settings.	*1
	The power supply was shut OFF while writing parameter settings.	Check the timing of shutting OFF the power supply.	Initialize the parameter settings and then set the parameters again.	
	The number of times that parameters were written exceeded the limit.	Check to see if the parameters were frequently changed from the host controller.	The SERVOPACK may be faulty. Replace the SERVOPACK. Reconsider the method for writing the parameters.	–
	A malfunction was caused by noise from the AC power supply, ground, static electricity, or other source.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, noise may be the cause.	Implement countermeasures against noise.	*1
	Gas, water drops, or cutting oil entered the SERVOPACK and caused failure of the internal components.	Check the installation conditions.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.021: Parameter Format Error (There is an error in the parameter data format in the SERVOPACK.)	The software version of the SERVOPACK that caused the alarm is older than the software version of the parameters specified to write.	Read the product information to see if the software versions are the same. If they are different, it could be the cause of the alarm.	Write the parameters from another SERVOPACK with the same model and the same software version, and then turn the power OFF and ON again.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.022: System Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The power supply was shut OFF while setting a utility function.	Check the timing of shutting OFF the power supply.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.024: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.025: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.030: Main Circuit Detector Error	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.040: Parameter Setting Error (A parameter setting is outside of the setting range.)	The SERVOPACK and Servomotor capacities do not match each other.	Check the combination of the SERVOPACK and Servomotor capacities.	Select a proper combination of SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A parameter setting is outside of the setting range.	Check the setting ranges of the parameters that have been changed.	Set the parameters to values within the setting ranges.	–
	The electronic gear ratio is outside of the setting range.	Check the electronic gear ratio. The ratio must be within the following range: 0.001 < (Pn20E/Pn210) < 64,000.	Set the electronic gear ratio in the following range: 0.001 < (Pn20E/Pn210) < 64,000.	*1
A.041: Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Check the setting of Pn212 or Pn281.	Set Pn212 or Pn281 to an appropriate value.	*1
A.042: Parameter Combination Error	The speed of program jogging went below the setting range when the electronic gear ratio (Pn20E/Pn210) or the Servomotor was changed.	Check to see if the detection conditions*2 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1
	The speed of program jogging went below the setting range when Pn533 or Pn585 (Program Jogging Speed) was changed.	Check to see if the detection conditions*2 are satisfied.	Increase the setting of Pn533 or Pn585.	*1
	The movement speed of advanced autotuning went below the setting range when the electronic gear ratio (Pn20E/ Pn210) or the Servomotor was changed.	Check to see if the detection conditions*3 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.044: Semi-Closed/ Fully-Closed Loop Control Parameter Setting Error	The setting of the Fully-Closed Module does not match the setting of Pn002 = n.X□□□ (External Encoder Usage).	Check the setting of Pn002 = n.X□□□.	Make sure that the setting of the Fully-closed Module agrees with the setting of Pn002 = n.X□□□.	*1
A.04A: Parameter Setting Error 2	For 4-byte parameter bank members, there are two consecutive members with nothing registered.	–	Change the number of bytes for bank members to an appropriate value.	–
	The total amount of bank data exceeds 64 (Pn900 × Pn901 > 64).	–	Reduce the total amount of bank data to 64 or less.	–
A.050: Combination Error (The capacities of the SERVOPACK and Servomotor do not match.)	The SERVOPACK and Servomotor capacities do not match each other.	Confirm that the following condition is met: 1/4 ≤ (Servomotor capacity/SERVOPACK capacity) ≤ 4	Select a proper combination of the SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the encoder.	Replace the encoder and check to see if the alarm still occurs.	Replace the Servomotor or encoder.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.051: Unsupported Device Alarm	An unsupported Serial Converter Unit or encoder (e.g., an external encoder) is connected to the SERVOPACK.	Check the product combination specifications.	Change to a correct combination of models.	–
A.0b0: Invalid Servo ON Command Alarm	The SV_ON (Servo ON) command was sent from the host controller after a utility function that turns ON the Servomotor was executed.	–	Turn the power supply to the SERVOPACK OFF and ON again. Or, execute a software reset.	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	The regenerative resistor is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	The dynamic brake (DB, emergency stop executed from the SERVOPACK) was frequently activated, or a DB overload alarm occurred.	Check the power consumed by the DB resistor to see how frequently the DB is being used. Or, check the alarm display to see if a DB overload alarm (A.730 or A.731) has occurred.	Change the SERVOPACK model, operating methods, or the mechanisms so that the dynamic brake does not need to be used so frequently.	–
	The regenerative processing capacity was exceeded.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Recheck the operating conditions and load.	*4
	The SERVOPACK regenerative resistance is too small.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Change the regenerative resistance to a value larger than the SERVOPACK minimum allowable resistance.	

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.101: Motor Overcurrent Detected (The current to the motor exceeded the allowable current.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across cable phases U, V, and W, or between the ground and cable phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.300: Regeneration Error	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to one of the following SERVOPACKs: SGD7S-2R8A or -2R8F.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or set Pn600 (Regenerative Resistor Capacity) to 0 (setting unit: ×10 W) if no Regenerative Resistor is required.	*1
	The jumper between the regenerative resistor terminals (B2 and B3) was removed from one of the following SERVOPACKs: SGD7S-120A.	Check to see if the jumper is connected between power supply terminals B2 and B3. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correctly connect a jumper.	*1
	The External Regenerative Resistor or Regenerative Resistor Unit is not wired correctly, or was removed or disconnected.	Check the wiring of the External Regenerative Resistor or Regenerative Resistor Unit. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correct the wiring of the External Regenerative Resistor or Regenerative Resistor Unit.	
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.320: Regenerative Overload	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The external regenerative resistance value or regenerative resistor capacity is too small, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or other means.	Change the regenerative resistance value or capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	*4
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
	The setting of Pn600 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check it see if a Regenerative Resistor is connected and check the setting of Pn600.	Correct the setting of Pn600.	*1
	The setting of Pn603 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check to see if a Regenerative Resistor is connected and check the setting of Pn603.	Correct the setting of Pn603.	*1
	The external regenerative resistance is too high.	Check the regenerative resistance.	Change the regenerative resistance to a correct value or use an External Regenerative Resistor of an appropriate capacity.	*4
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.330: Main Circuit Power Supply Wiring Error (Detected when the main circuit power supply is turned ON.)	The regenerative resistor was disconnected when the SERVOPACK power supply voltage was high.	Measure the resistance of the regenerative resistor using a measuring instrument.	If you are using the regenerative resistor built into the SERVOPACK, replace the SERVOPACK. If you are using an External Regenerative Resistor, replace the External Regenerative Resistor.	–
	DC power was supplied when an AC power supply input was specified in the settings.	Check the power supply to see if it is a DC power supply.	Correct the power supply setting to match the actual power supply.	*1
	AC power was supplied when a DC power supply input was specified in the settings.	Check the power supply to see if it is an AC power supply.	Correct the power supply setting to match the actual power supply.	
	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to an SGD7S-2R8A SERVOPACKs.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or if an External Regenerative Resistor is not required, set Pn600 to 0.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.400: Overvoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the AC/DC power supply voltage within the specified range.	–
	The power supply is not stable or was influenced by a lightning surge.	Measure the power supply voltage.	Improve the power supply conditions, install a surge absorber, and then turn the power supply OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The voltage for AC power supply was too high during acceleration or deceleration.	Check the power supply voltage and the speed and torque during operation.	Set the AC power supply voltage within the specified range.	–
	The external regenerative resistance is too high for the operating conditions.	Check the operating conditions and the regenerative resistance.	Select a regenerative resistance value that is appropriate for the operating conditions and load.	*4
	The moment of inertia ratio or mass ratio exceeded the allowable value.	Check to see if the moment of inertia ratio or mass ratio is within the allowable range.	Increase the deceleration time, or reduce the load.	–
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.410: Undervoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage went below the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*1
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor to the DC reactor terminals (⊖1 and ⊖2) on the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.510: Overspeed (The motor exceeded the maximum speed.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the wiring of the Servomotor.	Make sure that the Servomotor is correctly wired.	–
	A reference value that exceeded the overspeed detection level was input.	Check the input reference.	Reduce the reference value. Or, adjust the gain.	–
	The motor exceeded the maximum speed.	Check the waveform of the motor speed.	Reduce the speed reference input gain and adjust the servo gain. Or, reconsider the operating conditions.	
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.511: Encoder Output Pulse Overspeed	The encoder output pulse frequency exceeded the limit.	Check the encoder output pulse setting.	Decrease the setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution).	*1
	The encoder output pulse frequency exceeded the limit because the motor speed was too high.	Check the encoder output pulse setting and the motor speed.	Reduce the motor speed.	–
A.520: Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the setting of Pn100 (Speed Loop Gain).	*1
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*1
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.521: Autotuning Alarm (Vibration was detected while executing the custom tuning, Easy FFT, or the tuning-less function.)	The Servomotor vibrated considerably while performing the tuning-less function.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio is within the allowable value. Or increase the load level or reduce the rigidity level in the tuning-less level settings.	*1
	The Servomotor vibrated considerably while performing custom tuning or Easy FFT.	Check the waveform of the motor speed.	Check the operating procedure of corresponding function and implement corrections.	*1
A.550: Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum speed.	Check the setting of Pn385, and the upper limits of the maximum motor speed setting and the encoder output resolution setting.	Set Pn385 to a value that does not exceed the maximum motor speed.	*1
A.710: Instantaneous Overload A.720: Continuous Overload	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	*1
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven due to mechanical problems.	Check the operation reference and motor speed.	Correct the mechanical problem.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.730 and A.731: Dynamic Brake Overload (An excessive power consumption by the dynamic brake was detected.)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia ratio or mass ratio. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.740: Inrush Current Limiting Resistor Overload (The main circuit power supply was frequently turned ON and OFF.)	The allowable frequency of the inrush current limiting resistor was exceeded when the main circuit power supply was turned ON and OFF.	–	Reduce the frequency of turning the main circuit power supply ON and OFF.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7A1: Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A2: Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A3: Internal Temperature Sensor Error (An error occurred in the temperature sensor circuit.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7Ab: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.810: Encoder Backup Alarm (Detected at the encoder, but only when an absolute encoder is used.)	The power to the absolute encoder was turned ON for the first time.	Check to see if the power supply was turned ON for the first time.	Set up the encoder.	*1
	The Encoder Cable was disconnected and then connected again.	Check to see if the power supply was turned ON for the first time.	Check the encoder connection and set up the encoder.	
	Power is not being supplied both from the control power supply (+5 V) from the SERVOPACK and from the battery power supply.	Check the encoder connector battery and the connector status.	Replace the battery or implement similar measures to supply power to the encoder, and set up the encoder.	
	A failure occurred in the absolute encoder.	–	If the alarm still occurs after setting up the encoder again, replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.820: Encoder Checksum Alarm (Detected at the encoder.)	A failure occurred in the encoder.	–	■ When Using an Absolute Encoder Set up the encoder again. If the alarm still occurs, the Servomotor may be faulty. Replace the Servomotor. ■ When Using a Single-turn Absolute Encoder or Incremental Encoder The Servomotor may be faulty. Replace the Servomotor.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.830: Encoder Battery Alarm (The absolute encoder battery voltage was lower than the specified level.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*1
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.840: Encoder Data Alarm (Detected at the encoder.)	The encoder malfunctioned.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	The encoder malfunctioned due to noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	–
A.850: Encoder Overspeed (Detected at the encoder when the control power supply is turned ON.)	The Servomotor speed was 200 min^{-1} or higher when the control power supply was turned ON.	Check the motor speed when the power supply is turned ON.	Reduce the Servomotor speed to a value less than 200 min^{-1}, and turn ON the control power supply.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.860: Encoder Overheated (Detected at the encoder.)	The surrounding air temperature around the Servomotor is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40°C or less.	–
	The Servomotor load is greater than the rated load.	Use the accumulated load ratio to check the load.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.861: Motor Overheated	The surrounding temperature around the Servomotor is too high.	Measure the surrounding temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40° or less.	–
	The motor load is greater than the rated load.	Check the load with the accumulated load ratio on the Motion Monitor Tab Page on the SigmaWin+.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the Serial Converter Unit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Serial Converter Unit may be faulty. Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.862: Overheat Alarm	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	The overheat protection input signal line is disconnected or short-circuited.	Check the input voltage with the overheat protection input information on the Motion Monitor Tab Page on the SigmaWin+.	Repair the line for the overheat protection input signal.	–
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.8A0: External Encoder Error	Setting the origin of the absolute linear encoder failed because the motor moved.	Before you set the origin, use the fully-closed feedback pulse counter to confirm that the motor is not moving.	The motor must be stopped while setting the origin position.	*1
	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A1: External Encoder Module Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.8A2: External Incremental Encoder Sensor Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A3: External Absolute Encoder Position Error	A failure occurred in the external absolute encoder.	–	The external absolute encoder may be faulty. Refer to the encoder manufacturer's instruction manual for corrections.	–
A.8A5: External Encoder Overspeed	An overspeed error was detected in the external encoder.	Check the maximum speed of the external encoder.	Keep the external encoder below its maximum speed.	–
A.8A6: External Encoder Overheated	An overheating error was detected in the external encoder.	–	Replace the external encoder.	–
A.b33: Current Detection Error 3	A failure occurred in the current detection circuit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.b6A: MECHATROLINK Communications ASIC Error 1	There is a fault in the SERVOPACK MECHATROLINK communications section.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.b6b: MECHATROLINK Communications ASIC Error 2	A malfunction occurred in the MECHATROLINK communications section due to noise.	–	Implement the following countermeasures against noise. • Check the MECHATROLINK Communications Cable and FG wiring. • Attach a ferrite core to the MECHATROLINK Communications Cable.	–
	There is a fault in the SERVOPACK MECHATROLINK communications section.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF0: System Alarm 0	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF1: System Alarm 1	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF2: System Alarm 2	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.bF3: System Alarm 3	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF4: System Alarm 4	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF5: System Alarm 5	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF6: System Alarm 6	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF7: System Alarm 7	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF8: System Alarm 8	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C10: Servomotor Out of Control (Detected when the servo is turned ON.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the Servomotor wiring.	Make sure that the Servomotor is correctly wired.	–
	A failure occurred in the encoder.	–	If the motor wiring is correct and an alarm still occurs after turning the power supply OFF and ON again, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C54: Polarity Detection Failure 2	An external force was applied to the Servomotor.	–	Increase the setting of Pn495 (Polarity Detection Confirmation Force Reference). Increase the setting of Pn498 (Polarity Detection Allowable Error Range). Increasing the allowable error will also increase the motor temperature.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C80: Encoder Clear Error or Multiturn Limit Setting Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C90: Encoder Communications Error	There is a faulty contact in the connector or the connector is not wired correctly for the encoder.	Check the condition of the encoder connector.	Reconnect the encoder connector and check the encoder wiring.	*1
	There is a cable disconnection or short-circuit in the encoder. Or, the cable impedance is outside the specified values.	Check the condition of the Encoder Cable.	Use the Encoder Cable within the specified specifications.	–
	One of the following has occurred: corrosion caused by improper temperature, humidity, or gas, a short-circuit caused by entry of water drops or cutting oil, or faulty contact in connector caused by vibration.	Check the operating environment.	Improve the operating environmental, and replace the cable. If the alarm still occurs, replace the SERVOPACK.	*1
	A malfunction was caused by noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	*1
	A failure occurred in the SERVOPACK.	–	Connect the Servomotor to another SERVOPACK, and turn ON the control power supply. If no alarm occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C91: Encoder Communications Position Data Acceleration Rate Error	Noise entered on the signal lines because the Encoder Cable is bent or the sheath is damaged.	Check the condition of the Encoder Cable and connectors.	Check the Encoder Cable to see if it is installed correctly.	*1
	The Encoder Cable is bundled with a high-current line or installed near a high-current line.	Check the installation condition of the Encoder Cable.	Confirm that there is no surge voltage on the Encoder Cable.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the installation condition of the Encoder Cable.	Properly ground the machine to separate it from the FG of the encoder.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C92: Encoder Communications Timer Error	Noise entered on the signal line from the encoder.	–	Implement countermeasures against noise for the encoder wiring.	*1
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CA0: Encoder Parameter Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.Cb0: Encoder Echoback Error	The encoder is wired incorrectly or there is faulty contact.	Check the wiring of the encoder.	Make sure that the encoder is correctly wired.	*1
	The specifications of the Encoder Cable are not correct and noise entered on it.	–	Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	–
	The Encoder Cable is too long and noise entered on it.	–	Rotary Servomotors: The Encoder Cable wiring distance must be 50 m max.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the condition of the Encoder Cable and connectors.	Properly ground the machine to separate it from the FG of the encoder.	–
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CC0: Multiturn Limit Disagreement	When using a Direct Drive Servomotor, the setting of Pn205 (Multiturn Limit Setting) does not agree with the encoder.	Check the setting of Pn205.	Correct the setting of Pn205 (0 to 65,535).	*1
	The multiturn limit of the encoder is different from that of the SERVOPACK. Or, the multiturn limit of the SERVOPACK has been changed.	Check the setting of Pn205 in the SERVOPACK.	Change the setting if the alarm occurs.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.CF1: Reception Failed Error in Feedback Option Module Communications	The cable between the Serial Converter Unit and SERVOPACK is not wired correctly or there is a faulty contact.	Check the wiring of the external encoder.	Correctly wire the cable between the Serial Converter Unit and SERVOPACK.	*1
	A specified cable is not being used between Serial Converter Unit and SERVOPACK.	Check the wiring specifications of the external encoder.	Use a specified cable.	–
	The cable between the Serial Converter Unit and SERVOPACK is too long.	Measure the length of the cable that connects the Serial Converter Unit.	The length of the cable between the Serial Converter Unit and SERVOPACK must be 20 m or less.	–
	The sheath on cable between the Serial Converter Unit and SERVOPACK is broken.	Check the cable that connects the Serial Converter Unit.	Replace the cable between the Serial Converter Unit and SERVOPACK.	–
A.CF2: Timer Stopped Error in Feedback Option Module Communications	Noise entered the cable between the Serial Converter Unit and SERVOPACK.	–	Correct the wiring around the Serial Converter Unit, e.g., separate I/O signal lines from the Main Circuit Cables or ground.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.d00: Position Deviation Overflow (The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.)	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty contacts in the wiring for the Servomotor and encoder.	–
	The position command speed is too fast.	Reduce the position command speed and try operating the SERVOPACK.	Reduce the position reference speed or the reference acceleration rate, or reconsider the electronic gear ratio.	*1
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Reduce the acceleration of the position reference using a MECHATROLINK command. Or, smooth the position reference acceleration by selecting the position reference filter (ACCFIL) using a MECHATROLINK command.	–
	The setting of Pn520 (Excessive Position Deviation Alarm Level) is too low for the operating conditions.	Check Pn520 (Excessive Position Deviation Alarm Level) to see if it is set to an appropriate value.	Optimize the setting of Pn520.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.d01: Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Check the position deviation while the servo is OFF.	Optimize the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON).	
A.d02: Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if a position reference is input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded.	–	Optimize the setting of Pn520 (Excessive Position Deviation Alarm Level). Or, adjust the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON).	*1
A.d10: Motor-Load Position Deviation Overflow	The motor direction and external encoder installation orientation are backward.	Check the motor direction and the external encoder installation orientation.	Install the external encoder in the opposite direction, or change the setting of Pn002 = n.X□□□ (External Encoder Usage) to reverse the direction.	*1
	There is an error in the connection between the load (e.g., stage) and external encoder coupling.	Check the coupling of the external encoder.	Check the mechanical coupling.	–
A.d30: Position Data Overflow	The position data exceeded ±1,879,048,192.	Check the input reference pulse counter.	Reconsider the operating specifications.	–
A.E02: MECHATROLINK Internal Synchronization Error 1	The MECHATROLINK transmission cycle fluctuated.	–	Remove the cause of transmission cycle fluctuation at the host controller.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E40: MECHATROLINK Transmission Cycle Setting Error	The setting of MECHATROLINK transmission cycle is outside of the specified range.	Check the setting of the MECHATROLINK transmission cycle.	Set the MECHATROLINK transmission cycle to an appropriate value.	–
A.E41: MECHATROLINK Communications Data Size Setting Error	The number of transmission bytes set on DIP switch S3 is not correct.	Check the MECHATROLINK communications data size of the host controller.	Reset DIP switch S3 to change the number of transmission bytes to an appropriate value.	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.E42: MECHATROLINK Station Address Setting Error	The station address is outside of the setting range.	Check rotary switches S1 and S2 to see if the station address is between 03 and EF.	Check the setting of the station address of the host controller, and reset rotary switches S1 and S2 to change the address to an appropriate value between 03 and EF.	*1
	Two or more stations on the communications network have the same address.	Check to see if two or more stations on the communications network have the same address.	Check the setting of the station address of the host controller, and reset rotary switches S1 and S2 to change the address to an appropriate value between 03 and EF.	
A.E50*5: MECHATROLINK Synchronization Error	The WDT data in the host controller was not updated normally.	Check to see if the WDT data is being updated at the host controller.	Correctly update the WDT data at the host controller.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E51: MECHATROLINK Synchronization Failed	The WDT data at the host controller was not updated correctly at the start of synchronous communications, so synchronous communications could not be started.	Check to see if the WDT data is being updated in the host controller.	Correctly update the WDT data at the host controller.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E60*5: Reception Error in MECHATROLINK Communications	MECHATROLINK wiring is not correct.	Check the MECHATROLINK wiring.	Correct the MECHATROLINK Communications Cable wiring. Correctly connect the terminator.	–
	A MECHATROLINK data reception error occurred due to noise.	–	Implement countermeasures against noise. (Check the MECHATROLINK Communications Cable and FG wiring, and implement measures such as attaching a ferrite core to the MECHATROLINK Communications Cable.)	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.E61: Synchronization Interval Error in MECHATROLINK Transmission Cycle	The MECHATROLINK transmission cycle fluctuated.	Check the setting of the MECHATROLINK transmission cycle.	Remove the cause of transmission cycle fluctuation at the host controller.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E63: MECHATROLINK Synchronization Frame Not Received	MECHATROLINK wiring is not correct.	Check the Servomotor wiring.	Correct the MECHATROLINK Communications Cable wiring.	–
	A MECHATROLINK data reception error occurred due to noise.	–	Implement countermeasures against noise. (Check the MECHATROLINK Communications Cable and FG wiring, and implement measures such as attaching a ferrite core to the MECHATROLINK Communications Cable.)	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.E71: Safety Option Module Detection Failure	There is a faulty connection between the SERVOPACK and the Safety Option Module.	Check the connection between the SERVOPACK and the Safety Option Module.	Correctly connect the Safety Option Module.	–
	The Safety Option Module was disconnected.	–	Execute Fn014 (Reset Option Module Configuration Error) from the Digital Operator or SigmaWin+ and then turn the power supply to the SERVOPACK OFF and ON again.	*1
	A failure occurred in the Safety Option Module.	–	Replace the Safety Option Module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.E72: Feedback Option Module Detection Failure	There is a faulty connection between the SERVOPACK and the Feedback Option Module.	Check the connection between the SERVOPACK and the Feedback Option Module.	Correctly connect the Feedback Option Module.	–
	The Feedback Option Module was disconnected.	–	Reset the Option Module configuration error and turn the power supply to the SERVOPACK OFF and ON again.	*1
	A failure occurred in the Feedback Option Module.	–	Replace the Feedback Option Module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.E74: Unsupported Safety Option Module	A failure occurred in the Safety Option Module.	–	Replace the Safety Option Module.	–
	An unsupported Safety Option Module was connected.	Refer to the catalog of the connected Safety Option Module.	Connect a compatible Safety Option Module.	–
A.Eb1: Safety Function Signal Input Timing Error	The delay between activation of the /HWBB1 and /HWBB2 input signals for the HWBB was ten second or longer.	Measure the time delay between the /HWBB1 and /HWBB2 signals.	The output signal circuits or devices for /HWBB1 and /HWBB2 or the SERVOPACK input signal circuits may be faulty. Alternatively, the input signal cables may be disconnected. Check to see if any of these items are faulty or have been disconnected.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.EC8: Gate Drive Error 1 (An error occurred in the gate drive circuit.) A.EC9: Gate Drive Error 2 (An error occurred in the gate drive circuit.)	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.Ed1: Command Execution Timeout	A timeout error occurred for a MECHATROLINK command.	Check the motor status when the command is executed.	Execute the SV_ON or SENS_ON command only when the motor is not operating.	–
		For fully-closed loop control, check the status of the external encoder when the command is executed.	Execute the SENS_ON command only when an external encoder is connected.	–
A.F10: Power Supply Line Open Phase (The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.)	The three-phase power supply wiring is not correct.	Check the power supply wiring.	Make sure that the power supply is correctly wired.	*1
	The three-phase power supply is unbalanced.	Measure the voltage for each phase of the three-phase power supply.	Balance the power supply by changing phases.	–
	A single-phase power supply was input without specifying a signal-phase AC power supply input (Pn00B = n.□1□□).	Check the power supply and the parameter setting.	Match the parameter setting to the power supply.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
FL-1*5: System Alarm	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
FL-2*5: System Alarm				
FL-3*5: System Alarm				
FL-4*5: System Alarm				
FL-5*5: System Alarm				
FL-6*5: System Alarm				
CPF00: Digital Operator Communications Error 1	There is a faulty contact between the Digital Operator and the SERVOPACK.	Check the connector contact.	Disconnect the connector and insert it again. Or, replace the cable.	–
	A malfunction was caused by noise.	–	Keep the Digital Operator or the cable away from sources of noise.	–
CPF01: Digital Operator Communications Error 2	A failure occurred in the Digital Operator.	–	Disconnect the Digital Operator and then connect it again. If an alarm still occurs, the Digital Operator may be faulty. Replace the Digital Operator.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)

*2. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Pn533 [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{6 \times 10^5} \leq \dfrac{\text{Pn20E}}{\text{Pn210}}$
- $\text{Maximum motor speed [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \dfrac{\text{Pn20E}}{\text{Pn210}}$

*3. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Rated motor speed [min}^{-1}\text{]} \times 1/3 \times \dfrac{\text{Encoder resolution}}{6 \times 10^5} \leq \dfrac{\text{Pn20E}}{\text{Pn210}}$
- $\text{Maximum motor speed [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \dfrac{\text{Pn20E}}{\text{Pn210}}$

*4. Refer to the following manual for details.
Σ-7-Series Peripheral Device Selection Manual (Manual No.: SIEP S800001 32)

*5. These alarms are not stored in the alarm history. They are only displayed on the panel display.

3.3.4 Warning Displays

If a warning occurs in the SERVOPACK, a warning number will be displayed on the panel display. Warnings are displayed to warn you before an alarm occurs.

3.3.5 List of Warnings

The list of warnings gives the warning name and warning meaning in order of the warning numbers.

Warning Number	Warning Name	Meaning	Resetting
A.900	Position Deviation Overflow	The position deviation exceeded the percentage set with the following formula: (Pn520 × Pn51E/100)	Required.
A.901	Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)	Required.
A.910	Overload	This warning occurs before an overload alarm (A.710 or A.720) occurs. If the warning is ignored and operation is continued, an alarm may occur.	Required.
A.911	Vibration	Abnormal vibration was detected during motor operation. The detection level is the same as A.520. Set whether to output an alarm or a warning by setting Pn310 (Vibration Detection Switch).	Required.
A.912	Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	Required.
A.913	Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.	Required.
A.920	Regenerative Overload	This warning occurs before an A.320 alarm (Regenerative Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.	Required.
A.921	Dynamic Brake Overload	This warning occurs before an A.731 alarm (Dynamic Brake Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.	Required.
A.923	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Required.
A.930	Absolute Encoder Battery Error	This warning occurs when the voltage of absolute encoder's battery is low.	Required.
A.93B	Overheat Warning	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61C (Overheat Warning Level).	Required.
A.942	Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	Required.
A.94A	Data Setting Warning 1 (Parameter Number Error)	There is an error in the parameter number for a Data Setting Warning 1 (Parameter Number) command.	Automatically reset.*
A.94b	Data Setting Warning 2 (Out of Range)	The command data is out of range.	Automatically reset.*
A.94C	Data Setting Warning 3 (Calculation Error)	A calculation error was detected.	Automatically reset.*

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Warning Number	Warning Name	Meaning	Resetting
A.94d	Data Setting Warning 4 (Parameter Size)	The data sizes do not match.	Automatically reset.*
A.94E	Data Setting Warning 5 (Latch Mode Error)	A latch mode error was detected.	Required.
A.95A	Command Warning 1 (Unsatisfied Command Conditions)	A command was sent when the conditions for sending a command were not satisfied.	Automatically reset.*
A.95b	Command Warning 2 (Unsupported Command)	An unsupported command was sent.	Automatically reset.*
A.95d	Command Warning 4 (Command Interference)	There was command interference, particularly latch command interference.	Automatically reset.*
A.95E	Command Warning 5 (Subcommand Not Possible)	The subcommand and main command interfere with each other.	Automatically reset.*
A.95F	Command Warning 6 (Undefined Command)	An undefined command was sent.	Automatically reset.*
A.960	MECHATROLINK Communications Warning	A communications error occurred during MECHATROLINK communications.	Required.
A.971	Undervoltage	This warning occurs before an A.410 alarm (Undervoltage) occurs. If the warning is ignored and operation is continued, an alarm may occur.	Required.
A.97A	Command Warning 7 (Phase Error)	A command that cannot be executed in the current phase was sent.	Automatically reset.*
A.97b	Data Clamp Out of Range	The set command data was clamped to the minimum or maximum value of the allowable setting range.	Automatically reset.*
A.9A0	Overtravel	Overtravel was detected while the servo was ON.	Required.
A.9b0	Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	Required.

* If using the commands for the MECHATROLINK-III standard servo profile, the warning will automatically be cleared after the correct command is received. If you use MECHATROLINK-II-compatible profile commands, send an ALM_CLR (Clear Warning or Alarm) command to clear the warning.

Note: 1. A warning code is not output unless you set Pn001 to n.1□□□ (Output both alarm codes and warning codes).

2. Use Pn008 = n.□X□□ (Warning Detection Selection) to control warning detection.
However, the following warnings are not affected by the setting of Pn008 = n.□X□□ and other parameter settings are required in addition to Pn008 = n.□X□□.

Warning	Parameters That Must Be Set to Select Warning Detection
A.911	Pn310 = n.□□□X (Vibration Detection Setting)
A.923	– (Not affected by the setting of Pn008 = n.□X□□.)
A.930	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection)
A.942	Pn423 = n.□□X□ (Speed Ripple Compensation Information Disagreement Warning Detection Selection)
A.94A to A.960 and A.97A to A.97b	Pn800=n.□□X□ (Warning Check Masks)
A.971	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection) (Not affected by the setting of Pn008 = n.□X□□.)
A.9A0	Pn00D = n.X□□□ (Overtravel Warning Detection Selection) (Not affected by the setting of Pn008 = n.□X□□.)
A.9b0	Pn00F = n.□□□X (Preventative Maintenance Selection)

3.3.6 Troubleshooting Warnings

The causes of and corrections for the warnings are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.900: Position Deviation Overflow	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty connections in the wiring for the Servomotor and encoder.	–
	A SERVOPACK gain is too low.	Check the SERVOPACK gains.	Increase the servo gain, e.g., by using autotuning without a host reference.	*
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Reduce the acceleration of the position reference using a MECHATROLINK command. Or, smooth the position reference acceleration by selecting the position reference filter (ACCFIL) using a MECHATROLINK command.	–
	The excessive position deviation alarm level (Pn520 × Pn51E/100) is too low for the operating conditions.	Check excessive position deviation alarm level (Pn520 × Pn51E/100) to see if it is set to an appropriate value.	Optimize the settings of Pn520 and Pn51E.	*
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.901: Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)	–	Optimize the setting of Pn528 (Excessive Position Error Warning Level at Servo ON).	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.910: Overload (warning before an A.710 or A.720 alarm occurs)	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	–
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven because of mechanical problems.	Check the operation reference and motor speed.	Remove the mechanical problem.	–
	The overload warning level (Pn52B) is not suitable.	Check that the overload warning level (Pn52B) is suitable.	Set a suitable overload warning level (Pn52B).	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.911: Vibration	Abnormal vibration was detected during motor operation.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the servo gain with custom tuning.	*
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.912: Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.913: Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.920: Regenerative Overload (warning before an A.320 alarm occurs)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	There is insufficient external regenerative resistance, regenerative resistor capacity, or SERVOPACK capacity, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or another means.	Change the regenerative resistance value, regenerative resistance capacity, or SERVOPACK capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	–
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
A.921: Dynamic Brake Overload (warning before an A.731 alarm occurs)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia or mass. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.923: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.930: Absolute Encoder Battery Error (The absolute encoder battery voltage was lower than the specified level.) (Detected only when an absolute encoder is connected.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.93B: Overheat Warning	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.942: Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	–	Reset the speed ripple compensation value on the SigmaWin+.	*
		–	Set Pn423 to n.□□1□ (Do not detect A.942 alarms). However, changing the setting may increase the speed ripple.	*
		–	Set Pn423 to n.□□□0 (Disable torque ripple compensation). However, changing the setting may increase the speed ripple.	*
A.94A: Data Setting Warning 1 (Parameter Number Error)	An invalid parameter number was used.	Check the command that caused the warning.	Use the correct parameter number.	*
A.94b: Data Setting Warning 2 (Out of Range)	The set command data was clamped to the minimum or maximum value of the setting range.	Check the command that caused the warning.	Set the parameter within the setting range.	*
A.94C: Data Setting Warning 3 (Calculation Error)	The calculation result of the setting is not correct.	Check the command that caused the warning.	Set the parameter within the setting range.	*
A.94d: Data Setting Warning 4 (Parameter Size)	The parameter size set in the command is not correct.	Check the command that caused the warning.	Set the correct parameter size.	*
A.94E: Data Setting Warning 5 (Latch Mode Error)	A latch mode error was detected.	Check the command that caused the warning.	Change the setting of Pn850 or the LT_MOD data for the LTMOD_ON command sent by the host controller to an appropriate value. (The applies when using the MECHATROLINK-II-compatible profile.)	*
A.95A: Command Warning 1 (Unsatisfied Command Conditions)	The command conditions are not satisfied.	Check the command that caused the warning.	Send the command after the command conditions are satisfied.	*

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.95b: Command Warning 2 (Unsupported Command)	An unsupported command was received.	Check the command that caused the warning.	Do not send unsupported commands.	*
A.95d: Command Warning 4 (Command Interference)	The command sending conditions for latch-related commands was not satisfied.	Check the command that caused the warning.	Send the command after the command conditions are satisfied.	*
A.95E: Command Warning 5 (Subcommand Not Possible)	The command sending conditions for subcommands was not satisfied.	Check the command that caused the warning.	Send the command after the conditions are satisfied.	*
A.95F: Command Warning 6 (Undefined Command)	An undefined command was sent.	Check the command that caused the warning.	Do not send undefined commands.	*
A.960: MECHATROLINK Communications Warning	The MECHATROLINK Communications Cable is not wired correctly.	Check the wiring conditions.	Correct the MECHATROLINK communications cable wiring.	*
	A MECHATROLINK data reception error occurred due to noise.	Confirm the installation conditions.	Implement the following countermeasures against noise. • Check the MECHATROLINK Communications Cable and FG wiring and implement countermeasures to prevent noise from entering. • Attach a ferrite core to the MECHATROLINK Communications Cable.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.971: Undervoltage	For a 200-V SERVOPACK, the AC power supply voltage dropped below 140 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	For a 100-V SERVOPACK, the AC power supply voltage dropped below 60 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.97A: Command Warning 7 (Phase Error)	A command that cannot be executed in the current phase was sent.	–	Send the command after the command conditions are satisfied.	–
A.97b: Data Clamp Out of Range	The set command data was clamped to the minimum or maximum value of the setting range.	–	Set the command data within the setting ranges.	–
A.9A0: Overtravel (Overtravel status was detected.)	Overtravel was detected while the servo was ON.	Check the status of the overtravel signals on the input signal monitor.	Even if an overtravel signal is not shown by the input signal monitor, momentary overtravel may have been detected. Take the following precautions. • Do not specify movements that would cause overtravel from the host controller. • Check the wiring of the overtravel signals. • Implement countermeasures against noise.	*
A.9b0: Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	–	Replace the part. Contact your Yaskawa representative for replacement.	*

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)

3.3.7 Troubleshooting Based on the Operation and Conditions of the Servomotor

This section provides troubleshooting based on the operation and conditions of the Servomotor, including causes and corrections.

Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The control power supply is not turned ON.	Measure the voltage between control power supply terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the control power supply is turned ON.	–
	The main circuit power supply is not turned ON.	Measure the voltage across the main circuit power input terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the main circuit power supply is turned ON.	–
	The I/O signal connector (CN1) pins are not wired correctly or are disconnected.	Turn OFF the power supply to the servo system. Check the wiring condition of the I/O signal connector (CN1) pins.	Correct the wiring of the I/O signal connector (CN1) pins.	*
	The wiring for the Servomotor Main Circuit Cables or Encoder Cable is disconnected.	Check the wiring conditions.	Turn OFF the power supply to the servo system. Wire the cable correctly.	–
	There is an overload on the Servomotor.	Operate the Servomotor with no load and check the load status.	Turn OFF the power supply to the servo system. Reduce the load or replace the Servomotor with a Servomotor with a larger capacity.	–
	The type of encoder that is being used does not agree with the setting of Pn002 = n.□X□□ (Encoder Usage).	Check the type of the encoder that is being used and the setting of Pn002 = n.□X□□.	Set Pn002 = n.□X□□ according to the type of the encoder that is being used.	*
	There is a mistake in the input signal allocations (Pn50A, Pn50B, Pn511, and Pn516).	Check the input signal allocations (Pn50A, Pn50B, Pn511, and Pn516).	Correctly allocate the input signals (Pn50A, Pn50B, Pn511, and Pn516).	*
	The SV_ON command was not sent.	Check the commands sent from the host controller.	Send the SV_ON command from the host controller.	–
	The SENS_ON (Turn ON Sensor) command was not sent.	Check the commands sent from the host controller.	Send the commands to the SERVOPACK in the correct sequence.	–
	The P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal is still OFF.	Check the P-OT and N-OT signals.	Turn ON the P-OT and N-OT signals.	*
	The safety input signals (/HWBB1 or /HWBB2) were not turned ON.	Check the /HWBB1 and /HWBB2 input signals.	Turn ON the /HWBB1 and /HWBB2 input signals. If you are not using the safety function, connect the Safety Jumper Connector (provided as an accessory) to CN8.	*

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Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The FSTP (Forced Stop Input) signal is still OFF.	Check the FSTP signal.	• Turn ON the FSTP signal. • If you will not use the function to force the motor to stop, set Pn516 = n.□□□X (FSTP (Forced Stop Input) Signal Allocation) to disable the signal.	*
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Servomotor Moves Instantaneously, and Then Stops	There is a mistake in the Servomotor wiring.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Servomotor correctly.	–
	There is a mistake in the wiring of the encoder or Serial Converter Unit.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Serial Converter Unit correctly.	–
Servomotor Speed Is Unstable	There is a faulty connection in the Servomotor wiring.	Turn OFF the power supply to the servo system. The connector connections for the power line (U, V, and W phases) and the encoder or Serial Converter Unit may be unstable. Check the wiring.	Tighten any loose terminals or connectors and correct the wiring.	–
Servomotor Moves without a Reference Input	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Dynamic Brake Does Not Operate	The setting of Pn001 = n.□□□X (Servo OFF or Alarm Group 1 Stopping Method) is not suitable.	Check the setting of Pn001 = n.□□□X.	Set Pn001 = n.□□□X correctly.	–
	The dynamic brake resistor is disconnected.	Check the moment of inertia, motor speed, and dynamic brake frequency of use. If the moment of inertia, motor speed, or dynamic brake frequency of use is excessive, the dynamic brake resistance may be disconnected.	Turn OFF the power supply to the servo system. Replace the SERVOPACK. To prevent disconnection, reduce the load.	–
	There was a failure in the dynamic brake drive circuit.	–	Turn OFF the power supply to the servo system. There is a defective component in the dynamic brake circuit. Replace the SERVOPACK.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	The Servomotor vibrated considerably while performing the tuning-less function with the default settings.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio or mass ratio is within the allowable value, or increase the load level or reduce the rigidity level in the tuning-less level settings.	*
	The machine mounting is not secure.	Turn OFF the power supply to the servo system. Check to see if there are any loose mounting screws.	Tighten the mounting screws.	–
	The machine mounting is not secure.	Turn OFF the power supply to the servo system. Check to see if there is misalignment in the coupling.	Align the coupling.	–
		Turn OFF the power supply to the servo system. Check to see if the coupling is balanced.	Balance the coupling.	–
	The bearings are defective.	Turn OFF the power supply to the servo system. Check for noise and vibration around the bearings.	Replace the Servomotor.	–
	There is a vibration source at the driven machine.	Turn OFF the power supply to the servo system. Check for any foreign matter, damage, or deformation in the machine's moving parts.	Consult with the machine manufacturer.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use shielded twisted-pair wire cables or screened twisted-pair cables with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Make sure that the rotary or Linear Encoder Cable satisfies the specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with a conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Check to see if there is noise interference on the signal line from the encoder.	Turn OFF the power supply to the servo system. Implement countermeasures against noise for the encoder wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
Servomotor Vibrates at Frequency of Approx. 200 to 400 Hz.	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	*
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Large Motor Speed Overshoot on Starting and Stopping	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	*
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–
	The torque reference is saturated.	Check the waveform of the torque reference.	Use the mode switch.	–
	The force limits (Pn483 and Pn484) are set to the default values.	The default values of the force limits and Pn483 = 30% and Pn484 = 30%.	Set Pn483 and Pn484 to appropriate values.	*
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	Replace the Encoder Cable and correct the cable installation environment.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder or Serial Converter Unit wiring.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
	Host Controller Multiturn Data or Absolute Encoder Position Data Reading Error	Check the error detection section of the host controller.	Correct the error detection section of the host controller.	–
		Check to see if the host controller is executing data parity checks.	Perform parity checks for the multiturn data or absolute encoder position data.	–
		Check for noise interference in the cable between the SERVOPACK and the host controller.	Implement countermeasures against noise and then perform parity checks again for the multiturn data or absolute encoder position data.	–
Overtravel Occurred	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal was input.	Check the external power supply (+24 V) voltage for the input signals.	Correct the external power supply (+24 V) voltage for the input signals.	–
		Check the operating condition of the overtravel limit switches.	Make sure that the overtravel limit switches operate correctly.	–
		Check the wiring of the overtravel limit switches.	Correct the wiring of the overtravel limit switches.	*
		Check the settings of the overtravel input signal allocations (Pn50A/ Pn50B).	Set the parameters to correct values.	*
	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal malfunctioned.	Check for fluctuation in the external power supply (+24 V) voltage for the input signals.	Eliminate fluctuation from the external power supply (+24 V) voltage for the input signals.	–
		Check to see if the operation of the overtravel limit switches is unstable.	Stabilize the operating condition of the overtravel limit switches.	–
		Check the wiring of the overtravel limit switches (e.g., check for cable damage and loose screws).	Correct the wiring of the overtravel limit switches.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Overtravel Occurred	There is a mistake in the allocation of the P-OT or N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal in Pn50A = n.X□□□ or Pn50B = n.□□□X.	Check to see if the P-OT signal is allocated in Pn50A = n.X□□□.	If another signal is allocated in Pn50A =n.X□□□, allocate the P-OT signal instead.	*
		Check to see if the N-OT signal is allocated in Pn50B = n.□□□X.	If another signal is allocated in Pn50B =n.□□□X, allocate the N-OT signal instead.	
	The selection of the Servomotor stopping method is not correct.	Check the servo OFF stopping method set in Pn001 = n.□□□X or Pn001 = n.□□X□.	Select a Servomotor stopping method other than coasting to a stop.	*
		Check the torque control stopping method set in Pn001 = n.□□□X or Pn001 = n.□□X□.	Select a Servomotor stopping method other than coasting to a stop.	
Improper Stop Position for Overtravel (OT) Signal	The limit switch position and dog length are not appropriate.	–	Install the limit switch at the appropriate position.	–
	The overtravel limit switch position is too close for the coasting distance.	–	Install the overtravel limit switch at the appropriate position.	–
Position Deviation (without Alarm)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder wiring or Serial Converter Unit wiring.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Position Deviation (without Alarm)	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	The coupling between the machine and Servomotor is not suitable.	Turn OFF the power supply to the servo system. Check to see if position offset occurs at the coupling between machine and Servomotor.	Correctly secure the coupling between the machine and Servomotor.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	An encoder fault occurred. (The pulse count does not change.)	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Servomotor Overheated	The surrounding air temperature is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature to 40°C or less.	–
	The surface of the Servomotor is dirty.	Turn OFF the power supply to the servo system. Visually check the surface for dirt.	Clean dirt, dust, and oil from the surface.	–
	There is an overload on the Servomotor.	Check the load status with a monitor.	If the Servomotor is overloaded, reduce the load or replace the Servo Drive with a SERVOPACK and Servomotor with larger capacities.	–
	Polarity detection was not performed correctly.	Check to see if electrical angle 2 (electrical angle from polarity origin) at any position is between ±10°.	Correct the settings for the polarity detection-related parameters.	–
Estimating the moment of inertia failed.	The acceleration rate is low and travel distance is short.	Check the Condition Setting Dialog Box used to perform moment of inertia estimation.	Increase the acceleration rate and travel distance.	–

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)

3.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules

3.4.1 Alarm Displays

If an error occurs in the SERVOPACK, the status is displayed as described below.

◆ Status Display

SERVOPACK Panel Display	The alarm number will be displayed. Refer to the following section for details. 📖 Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
Indicators	Green indicator: Remains unlit Red indicator: Remains lit Refer to the following section for details. 📖 Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
Digital Operator	The alarm code is displayed at the top left of the screen.
Response to the Alarm or Warning Read Command (ALM)	Alarm code
Response to the Most Recent Error Read Command (ERR)	No change
ALM Signal	The alarm signal turns ON. (The photocoupler turns OFF.)
/WARN Signal	No change

3.4.2 List of Alarms

The alarms when the INDEXER Module is combined with a Command Option Attachable-type SERVOPACK are given in the following table.

Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.020	Parameter Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No	H	H	H
A.021	Parameter Format Error	There is an error in the parameter data format in the SERVOPACK.	Gr.1	No			
A.022	System Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No			
A.024	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No			
A.025	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No			
A.030	Main Circuit Detector Error	There is an error in the detection data for the main circuit.	Gr.1	Yes			
A.040	Parameter Setting Error	A parameter setting is outside of the setting range.	Gr.1	No			
A.041	Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Gr.1	No			
A.042	Parameter Combination Error	The combination of some parameters exceeds the setting range.	Gr.1	No			
A.044	Semi-Closed/Fully-Closed Loop Control Parameter Setting Error	The settings of the Option Module and Pn002 = n.X□□□ (External Encoder Usage) do not match.	Gr.1	No	H	H	H
A.04A	Parameter Setting Error 2	There is an error in setting of parameters reserved by the system.	Gr.1	No			
A.050	Combination Error	The capacities of the SERVOPACK and Servomotor do not match.	Gr.1	Yes			
A.051	Unsupported Device Alarm	An unsupported device was connected.	Gr.1	No			
A.0b0	Invalid Servo ON Command Alarm	The /S-ON (Servo ON) signal was input from the host controller after a utility function that turns ON the Servomotor was executed.	Gr.1	Yes			
A.100	Overcurrent Detected	An overcurrent flowed through the power transformer or the heat sink overheated.	Gr.1	No	L	H	H
A.101	Motor Overcurrent Detected	The current to the motor exceeded the allowable current.	Gr.1	No			
A.300	Regeneration Error	There is an error related to regeneration.	Gr.1	Yes	L	L	H
A.320	Regenerative Overload	A regenerative overload occurred.	Gr.2	Yes			
A.330	Main Circuit Power Supply Wiring Error	• The AC power supply input setting or DC power supply input setting is not correct. • The power supply wiring is not correct.	Gr.1	Yes			
A.400	Overvoltage	The main circuit DC voltage is too high.	Gr.1	Yes	H	H	L
A.410	Undervoltage	The main circuit DC voltage is too low.	Gr.2	Yes			

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.510	Overspeed	The motor exceeded the maximum speed.	Gr.1	Yes	L	H	L
A.511	Encoder Output Pulse Overspeed	The pulse output speed for the setting of Pn212 (Encoder Output Pulses) was exceeded.	Gr.1	Yes			
A.520	Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Gr.1	Yes			
A.521	Autotuning Alarm	Vibration was detected during autotuning for the tuning-less function.	Gr.1	Yes			
A.550	Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum motor speed.	Gr.1	Yes			
A.710	Instantaneous Overload	The Servomotor was operating for several seconds to several tens of seconds under a torque that largely exceeded the rating.	Gr.2	Yes	L	L	L
A.720	Continuous Overload	The Servomotor was operating continuously under a torque that exceeded the rating.	Gr.1	Yes			
A.730	Dynamic Brake Overload	When the dynamic brake was applied, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Gr.1	Yes			
A.731							
A.740	Inrush Current Limiting Resistor Overload	The main circuit power supply was frequently turned ON and OFF.	Gr.1	Yes			
A.7A1	Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	Gr.2	Yes			
A.7A2	Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.	Gr.2	Yes			
A.7A3	Internal Temperature Sensor Error	An error occurred in the temperature sensor circuit.	Gr.2	No			
A.7Ab	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Gr.1	Yes			
A.810	Encoder Backup Alarm	The power supplies to the encoder all failed and the position data was lost.	Gr.1	No	H	H	H
A.820	Encoder Checksum Alarm	There is an error in the checksum results for encoder memory.	Gr.1	No			
A.830	Encoder Battery Alarm	The battery voltage was lower than the specified level after the control power supply was turned ON.	Gr.1	Yes			
A.840	Encoder Data Alarm	There is an internal data error in the encoder.	Gr.1	No			
A.850	Encoder Overspeed	The encoder was operating at high speed when the power was turned ON.	Gr.1	No			
A.860	Encoder Overheated	The internal temperature of encoder is too high.	Gr.1	No			
A.861	Motor Overheated	The internal temperature of motor is too high.	Gr.1	No			
A.862	Overheat Alarm	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61B (Overheat Alarm Level).	Gr.1	Yes			

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.8A0	External Encoder Error	An error occurred in the external encoder.	Gr.1	Yes	H	H	H
A.8A1	External Encoder Module Error	An error occurred in the Serial Converter Unit.	Gr.1	Yes			
A.8A2	External Incremental Encoder Sensor Error	An error occurred in the external encoder.	Gr.1	Yes			
A.8A3	External Absolute Encoder Position Error	An error occurred in the position data of the external encoder.	Gr.1	Yes			
A.8A5	External Encoder Overspeed	An overspeed error occurred in the external encoder.	Gr.1	Yes			
A.8A6	External Encoder Overheated	An overheating error occurred in the external encoder.	Gr.1	Yes			
A.AEF	INDEXER Module Alarm	Some kind of alarm has occurred at the INDEXER Module.	Gr.1	Depends on module alarm.*1	H	L	L
A.b33	Current Detection Error 3	An error occurred in the current detection circuit.	Gr.1	No	H	H	H
A.bF0	System Alarm 0	Internal program error 0 occurred in the SERVOPACK.	Gr.1	No			
A.bF1	System Alarm 1	Internal program error 1 occurred in the SERVOPACK.	Gr.1	No			
A.bF2	System Alarm 2	Internal program error 2 occurred in the SERVOPACK.	Gr.1	No			
A.bF3	System Alarm 3	Internal program error 3 occurred in the SERVOPACK.	Gr.1	No			
A.bF4	System Alarm 4	Internal program error 4 occurred in the SERVOPACK.	Gr.1	No			
A.bF5	System Alarm 5	Internal program error 5 occurred in the SERVOPACK.	Gr.1	No			
A.bF6	System Alarm 6	Internal program error 6 occurred in the SERVOPACK.	Gr.1	No			
A.bF7	System Alarm 7	Internal program error 7 occurred in the SERVOPACK.	Gr.1	No			
A.bF8	System Alarm 8	Internal program error 8 occurred in the SERVOPACK.	Gr.1	No			
A.C10	Servomotor Out of Control	The Servomotor ran out of control.	Gr.1	Yes	L	H	L
A.C80	Encoder Clear Error or Multiturn Limit Setting Error	The multiturn data for the absolute encoder was not correctly cleared or set.	Gr.1	No			
A.C90	Encoder Communications Error	Communications between the encoder and SERVOPACK is not possible.	Gr.1	No			

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.C91	Encoder Communications Position Data Acceleration Rate Error	An error occurred in calculating the position data of the encoder.	Gr.1	No	L	H	L
A.C92	Encoder Communications Timer Error	An error occurred in the communications timer between the encoder and SERVOPACK.	Gr.1	No			
A.CA0	Encoder Parameter Error	The parameters in the encoder are corrupted.	Gr.1	No			
A.Cb0	Encoder Echoback Error	The contents of communications with the encoder are incorrect.	Gr.1	No			
A.CC0	Multiturn Limit Disagreement	Different multiturn limits have been set in the encoder and the SERVOPACK.	Gr.1	No			
A.CF1	Reception Failed Error in Feedback Option Module Communications	Receiving data from the Feedback Option Module failed.	Gr.1	No			
A.CF2	Timer Stopped Error in Feedback Option Module Communications	An error occurred in the timer for communications with the Feedback Option Module.	Gr.1	No			
A.d00	Position Deviation Overflow	The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.	Gr.1	Yes	L	L	H
A.d01	Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Gr.1	Yes			
A.d02	Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if a position reference is input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded before the limit is cleared.	Gr.2	Yes			
A.d10	Motor-Load Position Deviation Overflow	There was too much position deviation between the motor and load during fully-closed loop control.	Gr.2	Yes			
A.d30	Position Data Overflow	The position feedback data exceeded ±1,879,048,192.	Gr.1	No			
A.E00	Command Option Module IF Initialization Timeout Error	Communications initialization failed between the SERVOPACK and the Command Option Module.	Gr.2	Yes	H	L	L
A.E02	Command Option Module IF Synchronization Error 1	An synchronization error occurred between the SERVOPACK and the Command Option Module.	Gr.1	Yes			
A.E03	Command Option Module IF Communications Data Error	An error occurred in the data of communications between the SERVOPACK and the Command Option Module.	Gr.1	Yes			
A.E70	Command Option Module Detection Failure	Detection of the Command Option Module failed.	Gr.1	No			

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Alarm Number	Alarm Name	Alarm Meaning	Servo-motor Stop-ping Method	Alarm Reset Possi-ble?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.E71	Safety Option Module Detection Failure	Detection of the safety option module failed.	Gr.1	No	H	L	L
A.E72	Feedback Option Module Detection Failure	Detection of the Feedback Option Module failed.	Gr.1	No			
A.E73	Unsupported Command Option Module	An unsupported command option module was connected.	Gr.1	No			
A.E74	Unsupported Safety Option Module	An unsupported safety option module was connected.	Gr.1	No			
A.E75	Unsupported Feedback Option Module	An unsupported feedback option module was connected.	Gr.1	No			
A.E80	Command Option Module Unmatched Error	The command option module was replaced with a different model.	Gr.1	No			
A.EA2	Alarm in Current Communications between the INDEXER Module and SERVOPACK 1	An error occurred in communications between the INDEXER Module and SERVOPACK during operation.	Gr.1	Yes			
A.EA3	Alarm in Current Communications between the INDEXER Module and SERVOPACK 2	An error occurred in communications between the INDEXER Module and SERVOPACK during operation.	Gr.1	Yes			
A.Eb1	Safety Function Signal Input Timing Error	An error occurred in the input timing of the safety function signal.	Gr.1	No			
A.EC8	Gate Drive Error 1	An error occurred in the gate drive circuit.	Gr.1	No			
A.EC9	Gate Drive Error 2	An error occurred in the gate drive circuit.	Gr.1	No			
A.Ed1	Command Option Module IF Command Timeout Error	Processing of command from the command option module was not completed.	Gr.2	Yes			
A.F10	Power Supply Line Open Phase	The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.	Gr.2	Yes	H	L	H
FL-1*2	System Alarm	An internal program error occurred in the SERVOPACK.	–	No	Undefined.		
FL-2*2							
FL-3*2							
FL-4*2							
FL-5*2							
FL-6*2							
CPF00	Digital Operator Communications Error 1	Communications were not possible between the Digital Operator (model: JUSP-OP05A-1-E) and the SERVOPACK (e.g., a CPU error occurred).	–	No			
CPF01	Digital Operator Communications Error 2						

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)

*2. These alarms are not stored in the alarm history. They are only displayed on the panel display.

3.4.3 Troubleshooting Alarms

The causes of and corrections for the alarms are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.020: Parameter Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	Set the power supply voltage within the specified range, and initialize the parameter settings.	*1
	The power supply was shut OFF while writing parameter settings.	Check the timing of shutting OFF the power supply.	Initialize the parameter settings and then set the parameters again.	
	The number of times that parameters were written exceeded the limit.	Check to see if the parameters were frequently changed from the host controller.	The SERVOPACK may be faulty. Replace the SERVOPACK. Reconsider the method for writing the parameters.	–
	A malfunction was caused by noise from the AC power supply, ground, static electricity, or other source.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, noise may be the cause.	Implement countermeasures against noise.	*1
	Gas, water drops, or cutting oil entered the SERVOPACK and caused failure of the internal components.	Check the installation conditions.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.021: Parameter Format Error (There is an error in the parameter data format in the SERVOPACK.)	The software version of the SERVOPACK that caused the alarm is older than the software version of the parameters specified to write.	Read the product information to see if the software versions are the same. If they are different, it could be the cause of the alarm.	Write the parameters from another SERVOPACK with the same model and the same software version, and then turn the power OFF and ON again.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.022: System Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The power supply was shut OFF while setting a utility function.	Check the timing of shutting OFF the power supply.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.024: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.025: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.030: Main Circuit Detector Error	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.040: Parameter Setting Error (A parameter setting is outside of the setting range.)	The SERVOPACK and Servomotor capacities do not match each other.	Check the combination of the SERVOPACK and Servomotor capacities.	Select a proper combination of SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A parameter setting is outside of the setting range.	Check the setting ranges of the parameters that have been changed.	Set the parameters to values within the setting ranges.	–
	The electronic gear ratio is outside of the setting range.	Check the electronic gear ratio. The ratio must be within the following range: 0.001 < (Pn20E/Pn210) < 64,000.	Set the electronic gear ratio in the following range: 0.001 < (Pn20E/Pn210) < 64,000.	*1
A.041: Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Check the setting of Pn212 or Pn281.	Set Pn212 or Pn281 to an appropriate value.	*1
A.042: Parameter Combination Error	The speed of program jogging went below the setting range when the electronic gear ratio (Pn20E/Pn210) or the Servomotor was changed.	Check to see if the detection conditions*2 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1
	The speed of program jogging went below the setting range when Pn533 or Pn585 (Program Jogging Speed) was changed.	Check to see if the detection conditions*2 are satisfied.	Increase the setting of Pn533 or Pn585.	*1
	The movement speed of advanced autotuning went below the setting range when the electronic gear ratio (Pn20E/ Pn210) or the Servomotor was changed.	Check to see if the detection conditions*3 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.044: Semi-Closed/ Fully-Closed Loop Control Parameter Setting Error	The setting of the Fully-Closed Module does not match the setting of Pn002 = n.X□□□ (External Encoder Usage).	Check the setting of Pn002 = n.X□□□.	Make sure that the setting of the Fully-closed Module agrees with the setting of Pn002 = n.X□□□.	*1
A.04A: Parameter Setting Error 2	A parameter reserved by the system was changed.	–	Set the following reserved parameters to the default settings. Pn200.2 Pn207.1 Pn50A.0 Pn50A.1 Pn50A.2 Pn50C Pn50D	–
A.050: Combination Error (The capacities of the SERVOPACK and Servomotor do not match.)	The SERVOPACK and Servomotor capacities do not match each other.	Confirm that the following condition is met: 1/4 ≤ (Servomotor capacity/SERVOPACK capacity) ≤ 4	Select a proper combination of the SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the encoder.	Replace the encoder and check to see if the alarm still occurs.	Replace the Servomotor or encoder.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.051: Unsupported Device Alarm	An unsupported Serial Converter Unit or encoder (e.g., an external encoder) is connected to the SERVOPACK.	Check the product combination specifications.	Change to a correct combination of models.	–
A.0b0: Invalid Servo ON Command Alarm	The /S-ON (Servo ON) signal was input from the host controller after a utility function that turns ON the Servomotor was executed.	–	Turn the power supply to the SERVOPACK OFF and ON again. Or, execute a software reset.	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	The regenerative resistor is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	The dynamic brake (DB, emergency stop executed from the SERVOPACK) was frequently activated, or a DB overload alarm occurred.	Check the power consumed by the DB resistor to see how frequently the DB is being used. Or, check the alarm display to see if a DB overload alarm (A.730 or A.731) has occurred.	Change the SERVOPACK model, operating methods, or the mechanisms so that the dynamic brake does not need to be used so frequently.	–
	The regenerative processing capacity was exceeded.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Recheck the operating conditions and load.	*4
	The SERVOPACK regenerative resistance is too small.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Change the regenerative resistance to a value larger than the SERVOPACK minimum allowable resistance.	

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.101: Motor Overcurrent Detected (The current to the motor exceeded the allowable current.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across cable phases U, V, and W, or between the ground and cable phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.300: Regeneration Error	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to one of the following SERVOPACKs: SGD7S-2R8A or -2R8F.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or set Pn600 (Regenerative Resistor Capacity) to 0 (setting unit: ×10 W) if no Regenerative Resistor is required.	*1
	The jumper between the regenerative resistor terminals (B2 and B3) was removed from one of the following SERVOPACKs: SGD7S-120A.	Check to see if the jumper is connected between power supply terminals B2 and B3. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correctly connect a jumper.	*1
	The External Regenerative Resistor or Regenerative Resistor Unit is not wired correctly, or was removed or disconnected.	Check the wiring of the External Regenerative Resistor or Regenerative Resistor Unit. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correct the wiring of the External Regenerative Resistor or Regenerative Resistor Unit.	
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.320: Regenerative Overload	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The external regenerative resistance value or regenerative resistor capacity is too small, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or other means.	Change the regenerative resistance value or capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	*4
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
	The setting of Pn600 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check it see if a Regenerative Resistor is connected and check the setting of Pn600.	Correct the setting of Pn600.	*1
	The setting of Pn603 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check to see if a Regenerative Resistor is connected and check the setting of Pn603.	Correct the setting of Pn603.	*1
	The external regenerative resistance is too high.	Check the regenerative resistance.	Change the regenerative resistance to a correct value or use an External Regenerative Resistor of an appropriate capacity.	*4
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.330: Main Circuit Power Supply Wiring Error (Detected when the main circuit power supply is turned ON.)	The regenerative resistor was disconnected when the SERVOPACK power supply voltage was high.	Measure the resistance of the regenerative resistor using a measuring instrument.	If you are using the regenerative resistor built into the SERVOPACK, replace the SERVOPACK. If you are using an External Regenerative Resistor, replace the External Regenerative Resistor.	–
	DC power was supplied when an AC power supply input was specified in the settings.	Check the power supply to see if it is a DC power supply.	Correct the power supply setting to match the actual power supply.	*1
	AC power was supplied when a DC power supply input was specified in the settings.	Check the power supply to see if it is an AC power supply.	Correct the power supply setting to match the actual power supply.	
	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to an SGD7S-2R8A SERVOPACKs.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or if an External Regenerative Resistor is not required, set Pn600 to 0.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.400: Overvoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the AC/DC power supply voltage within the specified range.	–
	The power supply is not stable or was influenced by a lightning surge.	Measure the power supply voltage.	Improve the power supply conditions, install a surge absorber, and then turn the power supply OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The voltage for AC power supply was too high during acceleration or deceleration.	Check the power supply voltage and the speed and torque during operation.	Set the AC power supply voltage within the specified range.	–
	The external regenerative resistance is too high for the operating conditions.	Check the operating conditions and the regenerative resistance.	Select a regenerative resistance value that is appropriate for the operating conditions and load.	*4
	The moment of inertia ratio or mass ratio exceeded the allowable value.	Check to see if the moment of inertia ratio or mass ratio is within the allowable range.	Increase the deceleration time, or reduce the load.	–
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.410: Undervoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage went below the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*1
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor to the DC reactor terminals (⊖1 and ⊖2) on the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.510: Overspeed (The motor exceeded the maximum speed.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the wiring of the Servomotor.	Make sure that the Servomotor is correctly wired.	–
	A reference value that exceeded the overspeed detection level was input.	Check the input reference.	Reduce the reference value. Or, adjust the gain.	–
	The motor exceeded the maximum speed.	Check the waveform of the motor speed.	Reduce the speed reference input gain and adjust the servo gain. Or, reconsider the operating conditions.	
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.511: Encoder Output Pulse Overspeed	The encoder output pulse frequency exceeded the limit.	Check the encoder output pulse setting.	Decrease the setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution).	*1
	The encoder output pulse frequency exceeded the limit because the motor speed was too high.	Check the encoder output pulse setting and the motor speed.	Reduce the motor speed.	–
A.520: Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the setting of Pn100 (Speed Loop Gain).	*1
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*1
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.521: Autotuning Alarm (Vibration was detected while executing the custom tuning, Easy FFT, or the tuning-less function.)	The Servomotor vibrated considerably while performing the tuning-less function.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio is within the allowable value. Or increase the load level or reduce the rigidity level in the tuning-less level settings.	*1
	The Servomotor vibrated considerably while performing custom tuning or Easy FFT.	Check the waveform of the motor speed.	Check the operating procedure of corresponding function and implement corrections.	*1
A.550: Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum speed.	Check the setting of Pn385, and the upper limits of the maximum motor speed setting and the encoder output resolution setting.	Set Pn385 to a value that does not exceed the maximum motor speed.	*1
A.710: Instantaneous Overload A.720: Continuous Overload	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	*1
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven due to mechanical problems.	Check the operation reference and motor speed.	Correct the mechanical problem.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.730 and A.731: Dynamic Brake Overload (An excessive power consumption by the dynamic brake was detected.)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia ratio or mass ratio. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.740: Inrush Current Limiting Resistor Overload (The main circuit power supply was frequently turned ON and OFF.)	The allowable frequency of the inrush current limiting resistor was exceeded when the main circuit power supply was turned ON and OFF.	–	Reduce the frequency of turning the main circuit power supply ON and OFF.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7A1: Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A2: Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A3: Internal Temperature Sensor Error (An error occurred in the temperature sensor circuit.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7Ab: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.810: Encoder Backup Alarm (Detected at the encoder, but only when an absolute encoder is used.)	The power to the absolute encoder was turned ON for the first time.	Check to see if the power supply was turned ON for the first time.	Set up the encoder.	*1
	The Encoder Cable was disconnected and then connected again.	Check to see if the power supply was turned ON for the first time.	Check the encoder connection and set up the encoder.	
	Power is not being supplied both from the control power supply (+5 V) from the SERVOPACK and from the battery power supply.	Check the encoder connector battery and the connector status.	Replace the battery or implement similar measures to supply power to the encoder, and set up the encoder.	
	A failure occurred in the absolute encoder.	–	If the alarm still occurs after setting up the encoder again, replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.820: Encoder Checksum Alarm (Detected at the encoder.)	A failure occurred in the encoder.	–	■ When Using an Absolute Encoder Set up the encoder again. If the alarm still occurs, the Servomotor may be faulty. Replace the Servomotor. ■ When Using a Single-turn Absolute Encoder or Incremental Encoder The Servomotor may be faulty. Replace the Servomotor.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.830: Encoder Battery Alarm (The absolute encoder battery voltage was lower than the specified level.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*1
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.840: Encoder Data Alarm (Detected at the encoder.)	The encoder malfunctioned.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	The encoder malfunctioned due to noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	–
A.850: Encoder Overspeed (Detected at the encoder when the control power supply is turned ON.)	The Servomotor speed was 200 min^{-1} or higher when the control power supply was turned ON.	Check the motor speed when the power supply is turned ON.	Reduce the Servomotor speed to a value less than 200 min^{-1}, and turn ON the control power supply.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.860: Encoder Overheated (Detected at the encoder.)	The surrounding air temperature around the Servomotor is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40°C or less.	–
	The Servomotor load is greater than the rated load.	Use the accumulated load ratio to check the load.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.861: Motor Overheated	The surrounding temperature around the Servomotor is too high.	Measure the surrounding temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40° or less.	–
	The motor load is greater than the rated load.	Check the load with the accumulated load ratio on the Motion Monitor Tab Page on the SigmaWin+.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the Serial Converter Unit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Serial Converter Unit may be faulty. Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.862: Overheat Alarm	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	The overheat protection input signal line is disconnected or short-circuited.	Check the input voltage with the overheat protection input information on the Motion Monitor Tab Page on the SigmaWin+.	Repair the line for the overheat protection input signal.	–
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.8A0: External Encoder Error	Setting the origin of the absolute linear encoder failed because the motor moved.	Before you set the origin, use the fully-closed feedback pulse counter to confirm that the motor is not moving.	The motor must be stopped while setting the origin position.	*1
	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A1: External Encoder Module Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.8A2: External Incremental Encoder Sensor Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A3: External Absolute Encoder Position Error	A failure occurred in the external absolute encoder.	–	The external absolute encoder may be faulty. Refer to the encoder manufacturer's instruction manual for corrections.	–
A.8A5: External Encoder Overspeed	An overspeed error was detected in the external encoder.	Check the maximum speed of the external encoder.	Keep the external encoder below its maximum speed.	–
A.8A6: External Encoder Overheated	An overheating error was detected in the external encoder.	–	Replace the external encoder.	–
A.AEF: INDEXER Module Alarm	Some kind of alarm has occurred at the INDEXER Module.	Use the SigmaWin+ to check the serial command negative response of the INDEXER Module.	Observe the processing method for serial command negative responses from the INDEXER Module.	*1
A.b33: Current Detection Error 3	A failure occurred in the current detection circuit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF0: System Alarm 0	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF1: System Alarm 1	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF2: System Alarm 2	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF3: System Alarm 3	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF4: System Alarm 4	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.bF5: System Alarm 5	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF6: System Alarm 6	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF7: System Alarm 7	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF8: System Alarm 8	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C10: Servomotor Out of Control (Detected when the servo is turned ON.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the Servomotor wiring.	Make sure that the Servomotor is correctly wired.	–
	A failure occurred in the encoder.	–	If the motor wiring is correct and an alarm still occurs after turning the power supply OFF and ON again, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C54: Polarity Detection Failure 2	An external force was applied to the Servomotor.	–	Increase the setting of Pn495 (Polarity Detection Confirmation Force Reference). Increase the setting of Pn498 (Polarity Detection Allowable Error Range). Increasing the allowable error will also increase the motor temperature.	–
A.C80: Encoder Clear Error or Multiturn Limit Setting Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C90: Encoder Communications Error	There is a faulty contact in the connector or the connector is not wired correctly for the encoder.	Check the condition of the encoder connector.	Reconnect the encoder connector and check the encoder wiring.	*1
	There is a cable disconnection or short-circuit in the encoder. Or, the cable impedance is outside the specified values.	Check the condition of the Encoder Cable.	Use the Encoder Cable within the specified specifications.	–
	One of the following has occurred: corrosion caused by improper temperature, humidity, or gas, a short-circuit caused by entry of water drops or cutting oil, or faulty contact in connector caused by vibration.	Check the operating environment.	Improve the operating environmental, and replace the cable. If the alarm still occurs, replace the SERVOPACK.	*1
	A malfunction was caused by noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	*1
	A failure occurred in the SERVOPACK.	–	Connect the Servomotor to another SERVOPACK, and turn ON the control power supply. If no alarm occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C91: Encoder Communications Position Data Acceleration Rate Error	Noise entered on the signal lines because the Encoder Cable is bent or the sheath is damaged.	Check the condition of the Encoder Cable and connectors.	Check the Encoder Cable to see if it is installed correctly.	*1
	The Encoder Cable is bundled with a high-current line or installed near a high-current line.	Check the installation condition of the Encoder Cable.	Confirm that there is no surge voltage on the Encoder Cable.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the installation condition of the Encoder Cable.	Properly ground the machine to separate it from the FG of the encoder.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C92: Encoder Communications Timer Error	Noise entered on the signal line from the encoder.	–	Implement countermeasures against noise for the encoder wiring.	*1
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CA0: Encoder Parameter Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.Cb0: Encoder Echoback Error	The encoder is wired incorrectly or there is faulty contact.	Check the wiring of the encoder.	Make sure that the encoder is correctly wired.	*1
	The specifications of the Encoder Cable are not correct and noise entered on it.	–	Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	–
	The Encoder Cable is too long and noise entered on it.	–	Rotary Servomotors: The Encoder Cable wiring distance must be 50 m max.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the condition of the Encoder Cable and connectors.	Properly ground the machine to separate it from the FG of the encoder.	–
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor or linear encoder.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CC0: Multiturn Limit Disagreement	When using a Direct Drive Servomotor, the setting of Pn205 (Multiturn Limit Setting) does not agree with the encoder.	Check the setting of Pn205.	Correct the setting of Pn205 (0 to 65,535).	*1
	The multiturn limit of the encoder is different from that of the SERVOPACK. Or, the multiturn limit of the SERVOPACK has been changed.	Check the setting of Pn205 in the SERVOPACK.	Change the setting if the alarm occurs.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.CF1: Reception Failed Error in Feedback Option Module Communications	The cable between the Serial Converter Unit and SERVOPACK is not wired correctly or there is a faulty contact.	Check the wiring of the external encoder.	Correctly wire the cable between the Serial Converter Unit and SERVOPACK.	*1
	A specified cable is not being used between Serial Converter Unit and SERVOPACK.	Check the wiring specifications of the external encoder.	Use a specified cable.	–
	The cable between the Serial Converter Unit and SERVOPACK is too long.	Measure the length of the cable that connects the Serial Converter Unit.	The length of the cable between the Serial Converter Unit and SERVOPACK must be 20 m or less.	–
	The sheath on cable between the Serial Converter Unit and SERVOPACK is broken.	Check the cable that connects the Serial Converter Unit.	Replace the cable between the Serial Converter Unit and SERVOPACK.	–
A.CF2: Timer Stopped Error in Feedback Option Module Communications	Noise entered the cable between the Serial Converter Unit and SERVOPACK.	–	Correct the wiring around the Serial Converter Unit, e.g., separate I/O signal lines from the Main Circuit Cables or ground.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.d00: Position Deviation Overflow (The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.)	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty contacts in the wiring for the Servomotor and encoder.	–
	The position command speed is too fast.	Reduce the position command speed and try operating the SERVOPACK.	Reduce the position reference speed or the reference acceleration rate, or reconsider the electronic gear ratio.	*1
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Reduce the acceleration of the position reference with one of the following methods. • Reduce the acceleration rate (ACC) and deceleration rate (DEC) in the program table. • Reduce the settings of PnB29 (Acceleration Rate) and PnB2B (Deceleration Rate).	–
	The setting of Pn520 (Excessive Position Deviation Alarm Level) is too low for the operating conditions.	Check Pn520 (Excessive Position Deviation Alarm Level) to see if it is set to an appropriate value.	Optimize the setting of Pn520.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.d01: Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Check the position deviation while the servo is OFF.	Optimize the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON).	*1
A.d02: Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if a position reference is input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded.	–	Optimize the setting of Pn520 (Excessive Position Deviation Alarm Level). Or, adjust the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON).	

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.d10: Motor-Load Position Deviation Overflow	The motor direction and external encoder installation orientation are backward.	Check the motor direction and the external encoder installation orientation.	Install the external encoder in the opposite direction, or change the setting of Pn002 = n.X□□□ (External Encoder Usage) to reverse the direction.	*1
	There is an error in the connection between the load (e.g., stage) and external encoder coupling.	Check the coupling of the external encoder.	Check the mechanical coupling.	–
A.d30: Position Data Overflow	The position data exceeded ±1,879,048,192.	Check the input reference pulse counter.	Reconsider the operating specifications.	–
A.E00: Command Option Module IF Initialization Timeout Error	The connection between the SERVOPACK and the command option module is faulty.	Check the connection between the SERVOPACK and the command option module.	Correctly connect the command option module.	–
	A command option module fault occurred.	–	Replace the command option module.	–
	A SERVOPACK fault occurred.	–	Replace the SERVOPACK.	–
A.E02: Command Option Module IF Synchronization Error 1	The timing of synchronization between the servomotor and command option module changed due to change in the communications cycle of the host controller connected to the command option module.	–	Turn the power supply OFF and then ON again. If the alarm occurs again, restart communications processing from the host controller.	–
	The connection between the SERVOPACK and the command option module is faulty.	Check the connection between the SERVOPACK and the command option module.	Correctly connect the command option module.	–
	A command option module fault occurred.	–	Replace the command option module.	–
	A SERVOPACK fault occurred.	–	Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.E03: Command Option Module IF Communications Data Error	An error occurred due to noise in the communications between the SERVOPACK and the command option module.	–	Take measures against noise.	–
	The connection between the SERVOPACK and the command option module is faulty.	Check the connection between the SERVOPACK and the command option module.	Correctly connect the command option module.	–
	A command option module fault occurred.	–	Replace the command option module.	–
	A SERVOPACK fault occurred.	–	Replace the SERVOPACK.	–
A.E70: Command Option Module Detection Failure	The connection between the SERVOPACK and the command option module is faulty.	Check the connection between the SERVOPACK and the command option module.	Correctly connect the command option module.	–
	The command option module is not connected.	–	Correctly connect the command option module.	–
	A command option module fault occurred.	–	Replace the command option module.	–
	A SERVOPACK fault occurred.	–	Replace the SERVOPACK.	–
A.E71: Safety Option Module Detection Failure	The connection between the SERVOPACK and the safety option module is faulty.	Check the connection between the SERVOPACK and the safety option module.	Correctly connect the safety option module.	–
	The safety option module was disconnected.	–	Execute Fn014 (Resetting configuration error of option module) using the digital operator or SigmaWin+ and turn the power supply OFF and then ON again.	*1
	A safety option module fault occurred.	–	Replace the safety option module.	–
	A SERVOPACK fault occurred.	–	Replace the SERVOPACK.	–
A.E72: Feedback Option Module Detection Failure	There is a faulty connection between the SERVOPACK and the Feedback Option Module.	Check the connection between the SERVOPACK and the Feedback Option Module.	Correctly connect the Feedback Option Module.	–
	The Feedback Option Module was disconnected.	–	Reset the Option Module configuration error and turn the power supply to the SERVOPACK OFF and ON again.	*1
	A failure occurred in the Feedback Option Module.	–	Replace the Feedback Option Module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.E73: Unsupported Command Option Module	A command option module fault occurred.	–	Replace the command option module.	–
	A unsupported command option module was connected.	–	Connect a compatible command option module.	–
A.E74: Unsupported Safety Option Module	A safety option module fault occurred.	–	Replace the safety option module.	–
	A unsupported safety option module was connected.	–	Connect a compatible safety option module.	–
A.E75*3: Unsupported Feedback Option Module	A feedback option module fault occurred.	–	Replace the feedback option module.	–
	A unsupported feedback option module was connected.	Refer to the catalog of the connected feedback option module or the manual of the SERVOPACK.	Connect a compatible feedback option module.	–
A.E80: Command Option Module Unmatched Error	The command option module was replaced with a different model.	–	Execute Fn014 (Resetting configuration error of option module) using the digital operator or SigmaWin+ and turn the power supply OFF and then ON again.	–
A.EA2: Alarm in Current Communications between the INDEXER Module and SERVOPACK 1	An error occurred in communications between the INDEXER Module and SERVOPACK during operation.	–	Take steps to reduce noise in the system such as improving frame ground.	*1
A.EA3: Alarm in Current Communications between the INDEXER Module and SERVOPACK 2	An error occurred in communications between the INDEXER Module and SERVOPACK during operation.	–	Take steps to reduce noise in the system such as improving frame ground.	*1
A.Eb1: Safety Function Signal Input Timing Error	The delay between activation of the /HWBB1 and /HWBB2 input signals for the HWBB was ten second or longer.	Measure the time delay between the /HWBB1 and /HWBB2 signals.	The output signal circuits or devices for /HWBB1 and /HWBB2 or the SERVOPACK input signal circuits may be faulty. Alternatively, the input signal cables may be disconnected. Check to see if any of these items are faulty or have been disconnected.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.EC8: Gate Drive Error 1 (An error occurred in the gate drive circuit.) A.EC9: Gate Drive Error 2 (An error occurred in the gate drive circuit.)	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.Ed1: Command Option Module IF Command Timeout Error	Processing of the servo ON command from the command option module is not completed.	–	Input a servo ON command when the motor is stopped.	–
	Processing of the sensor ON command from the command option module is not completed.	–	Check that the encoder is connected properly.	–
A.F10: Power Supply Line Open Phase (The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.)	The three-phase power supply wiring is not correct.	Check the power supply wiring.	Make sure that the power supply is correctly wired.	*1
	The three-phase power supply is unbalanced.	Measure the voltage for each phase of the three-phase power supply.	Balance the power supply by changing phases.	–
	A single-phase power supply was input without specifying a signal-phase AC power supply input (Pn00B = n.□1□□).	Check the power supply and the parameter setting.	Match the parameter setting to the power supply.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
FL-1*5: System Alarm FL-2*5: System Alarm FL-3*5: System Alarm FL-4*5: System Alarm FL-5*5: System Alarm FL-6*5: System Alarm	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
CPF00: Digital Operator Communications Error 1	There is a faulty contact between the Digital Operator and the SERVOPACK.	Check the connector contact.	Disconnect the connector and insert it again. Or, replace the cable.	–
	A malfunction was caused by noise.	–	Keep the Digital Operator or the cable away from sources of noise.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
CPF01: Digital Operator Communications Error 2	A failure occurred in the Digital Operator.	–	Disconnect the Digital Operator and then connect it again. If an alarm still occurs, the Digital Operator may be faulty. Replace the Digital Operator.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)

*2. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Pn533 [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{6 \times 10^5} \leq \dfrac{\text{Pn20E}}{\text{Pn210}}$

- $\text{Maximum motor speed [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \dfrac{\text{Pn20E}}{\text{Pn210}}$

*3. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Rated motor speed [min}^{-1}\text{]} \times 1/3 \times \dfrac{\text{Encoder resolution}}{6 \times 10^5} \leq \dfrac{\text{Pn20E}}{\text{Pn210}}$

- $\text{Maximum motor speed [min}^{-1}\text{]} \times \dfrac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \dfrac{\text{Pn20E}}{\text{Pn210}}$

*4. Refer to the following manual for details.
Σ-7-Series Peripheral Device Selection Manual (Manual No.: SIEP S800001 32)

*5. These alarms are not stored in the alarm history. They are only displayed on the panel display.

3.4.4 INDEXER Module Alarm Displays and Troubleshooting

The INDEXER Module alarm list and the corresponding corrective actions are shown below.

Serial Command Negative Response	Alarm Number	Alarm Name	Meaning	Corrective Action	Servomotor Stop Method	Alarm Reset
E12A	A.AEF	Firmware Execution Alarm	The firmware processing time was too long.	• Upgrade the firmware version. • Reduce the number of functions being used.	Gr.1	N/A
E13A	A.AEF	Firmware Version Unmatched	The SERVOPACK does not supported this function, because the software version do not match.	• Upgrade the SERVOPACK software version. • Use the SERVOPACK that supports the corresponding function. • Use the SERVOPACK with the function set disabled.	Gr.1	N/A
E14A	A.AEF	Parameter Checksum Alarm (Detected only when control power supply is turned ON.)	Incorrect or corrupted parameters are stored in EEPROM. (This alarm can occur if the control power supply is turned OFF while the parameters are being initialized or changed.)	• Initialize the parameters with the PRMINIT command or FnB0B. • If the problem is not solved, correct the parameters.	Gr.1	N/A
E15A	A.AEF	Parameter Version Unmatched (Detected only when the control power supply is turned ON.)	The combination of the firmware version number and the parameter version number is wrong.	• Change the firmware version. • Change the parameter version to match the firmware version.	Gr.1	N/A
E16A	A.AEF	Parameter Out-of-range Alarm (Detected only when control power supply is turned ON.)	The moving method is set to a rotary method (PnB20 = 1, 2, or 3), but the origin set in PnB25 exceeds the software limits set in PnB21 and PnB23.	Correct the origin setting (PnB25) or the software limits (PnB21 and PnB23).	Gr.1	N/A

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Serial Command Negative Response	Alarm Number	Alarm Name	Meaning	Corrective Action	Servo-motor Stop Method	Alarm Reset
E17A	A.E00	Initial Communication Alarm between INDEXER Module and SERVOPACK (Detected only when control power supply is turned ON.)	The INDEXER Module failed in initialization of communications with the SERVOPACK when the control power was turned ON.	Take steps to reduce noise in the system such as improving frame ground.	Gr.1	N/A
	A.AEF		The SERVOPACK is not compatible with the INDEXER Module.	• Upgrade the SERVOPACK's software version. • Replace the SERVOPACK with a SERVOPACK that is compatible with the INDEXER Module.		

	A.C90 or A.040		• The INDEXER Module failed in parameter calculation during initial communications with the SERVOPACK when the control power was turned ON. This can happen in the following cases:
			  • When a parameter has been changed while the encoder is not connected
			  • When a parameter has been changed during occurrence of A.040 alarm
				• Connect the encoder and then change the parameter.
				• Cancel the A.040 alarm and then change the parameter. (If the alarm display is other than A.E00, it can be reset by turning the power OFF and back ON.)		

E18A	A.EA2, A.EA3	Communication Alarm between INDEXER Module and SERVOPACK	An error occurred in communications between the INDEXER Module and SERVOPACK during operation.	Take steps to reduce noise in the system such as improving frame ground.	Gr.1	Available
E19A	A.AEF	Program Table Checksum Alarm (Detected only when control power supply is turned ON.)	The program table stored in flash memory was not recorded properly. (This alarm can occur if the control power supply is turned OFF while the program table is being saved or initialized.)	• Initialize the program table with the PGMINIT command or FnB06. • If the problem is not solved, correct the program table.	Gr.1	Available*1

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Serial Command Negative Response	Alarm Number	Alarm Name	Meaning	Corrective Action	Servo-motor Stop Method	Alarm Reset
E1AA	A.AEF	Program Table Version Unmatched (Detected only when the control power is ON.)	The combination of the firmware version and the program table version is wrong.	• Change the firmware version. • Change the program table version to match the firmware version.	Gr.1	Available*1
E1BA	A.AEF	Program Out-of-range Alarm (Detected only when control power supply is turned ON.)	A value set in the program table is not within the allowed setting range.	• Change the firmware version. • Change the program table version to match the firmware version.	Gr.1	Available*1
E1CA	A.AEF	Zone Table Checksum Alarm (Detected only when control power supply is turned ON.)	The zone table stored in flash memory was not recorded properly. (This alarm can occur if the control power supply is turned OFF while the zone table is being saved or initialized.)	• Initialize the zone table with the ZONEINIT command or FnB07.*2 • If the problem is not solved, correct the zone table.	Gr.1	Available*2
E1DA	A.AEF	ZONE Table Version Unmatched (Detected only when the control power supply is turned ON.)	The combination of the firmware version and the ZONE table version is wrong.	• Change the firmware version. • Change the ZONE table version to match the firmware version.	Gr.1	Available*2
E1EA	A.AEF	Zone Table Out-of-range Alarm (Detected only when control power supply is turned ON.)	A value set in the zone table is not within the allowed setting range.	• Change the firmware version. • Change the ZONE table version to match the firmware version.	Gr.1	Available*2
E1FA	A.AEF	JOG Speed Table Checksum Alarm (Detected only when control power supply is turned ON.)	The JOG speed table stored in flash memory was not recorded properly. (This alarm can occur if the control power supply is turned OFF while the JOG speed table is being saved or initialized.)	• Initialize the JOG speed table with the JSPDINIT command or FnB08. • If the problem is not solved, correct the JOG speed table.	Gr.1	Available*3
E21A	A.AEF	JOG Speed Table Version Unmatched (Detected only when the control power supply is turned ON.)	The combination of the firmware version and the JOG speed table version is wrong.	• Change the firmware version. • Change the JOG speed table version to match the firmware version.	Gr.1	Available*3

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Serial Command Negative Response	Alarm Number	Alarm Name	Meaning	Corrective Action	Servo-motor Stop Method	Alarm Reset
E22A	A.AEF	JOG Speed Table Out-of-range Alarm (Detected only when control power supply is turned ON.)	A value set in the JOG speed table is not within the allowed setting range.	• Change the firmware version. • Change the JOG speed table version to match the firmware version.	Gr.1	Available*3
E23A	A.AEF	Insufficient Registration Distance Alarm	The registration distance was shorter than the deceleration distance when the /RGRT signal went ON to start registration operation. (The current position will exceed the position specified by registration.)	Either increase the registration distance or reduce the deceleration distance (increase the deceleration rate). The registration distance can be set by executing the RDST command or changing the RDST parameter in the program table. The deceleration rate can be changed by executing the DEC command or changing parameter PnB2B.	Gr.1	Available

*1. These alarms can be reset, but a Canceled Program Table Error (E44E) will occur the next time you attempt to start program table operation, so program table operation will not be possible.

*2. These alarms can be reset, but it is possible that the zone signals (POUT0 to POUT7) will be output incorrectly. When using the zone table, correct the zone table without resetting.

*3. These alarms can be reset, but a Canceled JOG Speed Table Error (E46E) will occur the next time you attempt to start JOG speed table operation, so JOG speed table operation will not be possible.

3.4.5 Warning Displays

Warnings are displayed to warn you before an alarm occurs. If a warning occurs in the SERVOPACK, the status is displayed as described below.

◆ Status Display

SERVOPACK Panel Display	The alarm number will be displayed. Refer to the following section for details. 📖 Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
Indicator	Green indicator: Remains unlit Red indicator: Remains lit Refer to the following section for details. 📖 Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
Digital Operator	When a warning occurs, the warning code is displayed at the top left of the screen.
Response to the Alarm or Warning Read Command (ALM)	Warning code
Response to the Most Recent Error Read Command (ERR)	No change
ALM Signal	No change
/WARN Signal	Turns ON.

3.4.6 List of Warnings

◆ Troubleshooting Warnings

This section gives the warning names, warning meanings, and warning code outputs in order of the warning numbers.

Warning Number	Warning Name	Meaning	Warning Code Output		
			/ALO1	/ALO2	/ALO3
A.900	Position Deviation Overflow	The position deviation exceeded the percentage set with the following formula: (Pn520 × Pn51E/100)	H	H	H
A.901	Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)			
A.910	Overload	This warning occurs before an overload alarm (A.710 or A.720) occurs. If the warning is ignored and operation is continued, an alarm may occur.	L	H	H
A.911	Vibration	Abnormal vibration was detected during motor operation. The detection level is the same as A.520. Set whether to output an alarm or a warning by setting Pn310 (Vibration Detection Switch).			

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Warning Number	Warning Name	Meaning	Warning Code Output		
			/ALO1	/ALO2	/ALO3
A.912	Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	H	L	H
A.913	Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.			
A.920	Regenerative Overload	This warning occurs before an A.320 alarm (Regenerative Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.			
A.921	Dynamic Brake Overload	This warning occurs before an A.731 alarm (Dynamic Brake Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.			
A.923	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.			
A.930	Absolute Encoder Battery Error	This warning occurs when the voltage of absolute encoder's battery is low.	L	L	H
A.93B	Overheat Warning	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61C (Overheat Warning Level).	L	L	H
A.942	Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	H	H	L
A.971	Undervoltage	This warning occurs before an A.410 alarm (Undervoltage) occurs. If the warning is ignored and operation is continued, an alarm may occur.	L	L	L
A.9A0	Overtravel	Overtravel was detected while the servo was ON.	H	L	L
A.9b0	Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	H	L	H
A.A9F	Error	Some kind of error has occurred at the INDEXER Module.*	L	H	H

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)

Note: 1. A warning code is not output unless you set Pn001 to n.1□□□ (Output both alarm codes and warning codes).
2. Use Pn008 = n.□X□□ (Warning Detection Selection) to control warning detection.
However, the following warnings are not affected by the setting of Pn008 = n.□X□□ and other parameter settings are required in addition to Pn008 = n.□X□□.

Warning	Parameters That Must Be Set to Select Warning Detection
A.911	Pn310 = n.□□□X (Vibration Detection Setting)
A.930	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection)
A.942	Pn423 = n.□□X□ (Speed Ripple Compensation Information Disagreement Warning Detection Selection)
A.971	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection) (Not affected by the setting of Pn008 = n.□X□□.)
A.9A0	Pn00D = n.X□□□ (Overtravel Warning Detection Selection) (Not affected by the setting of Pn008 = n.□X□□.)
A.9b0	Pn00F = n.□□□X (Preventative Maintenance Selection)

3.4.7 Troubleshooting Warnings

The causes of and corrections for the warnings are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.900: Position Deviation Overflow	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty connections in the wiring for the Servomotor and encoder.	–
	A SERVOPACK gain is too low.	Check the SERVOPACK gains.	Increase the servo gain, e.g., by using autotuning without a host reference.	*
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Reduce the acceleration of the position reference with one of the following methods. • Reduce the acceleration rate (ACC) and deceleration rate (DEC) in the program table. • Reduce the settings of PnB29 (Acceleration Rate) and PnB2B (Deceleration Rate).	–
	The excessive position deviation alarm level (Pn520 × Pn51E/100) is too low for the operating conditions.	Check excessive position deviation alarm level (Pn520 × Pn51E/100) to see if it is set to an appropriate value.	Optimize the settings of Pn520 and Pn51E.	*
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.901: Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)	–	Optimize the setting of Pn528 (Excessive Position Error Warning Level at Servo ON).	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.910: Overload (warning before an A.710 or A.720 alarm occurs)	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	–
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven because of mechanical problems.	Check the operation reference and motor speed.	Remove the mechanical problem.	–
	The overload warning level (Pn52B) is not suitable.	Check that the overload warning level (Pn52B) is suitable.	Set a suitable overload warning level (Pn52B).	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.911: Vibration	Abnormal vibration was detected during motor operation.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the servo gain with custom tuning.	*
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.912: Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.913: Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.920: Regenerative Overload (warning before an A.320 alarm occurs)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	There is insufficient external regenerative resistance, regenerative resistor capacity, or SERVOPACK capacity, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or another means.	Change the regenerative resistance value, regenerative resistance capacity, or SERVOPACK capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	–
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
A.921: Dynamic Brake Overload (warning before an A.731 alarm occurs)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia or mass. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.923: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.930: Absolute Encoder Battery Error (The absolute encoder battery voltage was lower than the specified level.) (Detected only when an absolute encoder is connected.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.93B: Overheat Warning	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.942: Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	–	Reset the speed ripple compensation value on the SigmaWin+.	*
		–	Set Pn423 to n.□□1□ (Do not detect A.942 alarms). However, changing the setting may increase the speed ripple.	*
		–	Set Pn423 to n.□□□0 (Disable torque ripple compensation). However, changing the setting may increase the speed ripple.	*
A.971: Undervoltage	For a 200-V SERVOPACK, the AC power supply voltage dropped below 140 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	For a 100-V SERVOPACK, the AC power supply voltage dropped below 60 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor.	*
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.9A0: Overtravel (Overtravel status was detected.)	Overtravel was detected while the servo was ON.	Check the status of the overtravel signals on the input signal monitor.	Even if an overtravel signal is not shown by the input signal monitor, momentary overtravel may have been detected. Take the following precautions. • Do not specify movements that would cause overtravel from the host controller. • Check the wiring of the overtravel signals. • Implement countermeasures against noise.	*
A.9b0: Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	–	Replace the part. Contact your Yaskawa representative for replacement.	*
A.A9F: Error	An error occurred in the INDEXER Module.	Use the SigmaWin+ to check the serial command negative response of the INDEXER Module.	Observe the processing method for serial command negative responses from the INDEXER Module.	*

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)

3.4.8 INDEXER Module Error Displays and Troubleshooting

Negative responses (error responses) to input signals, serial commands, or operations from the Digital Operator are known as errors.

The servo will not be turned OFF when an error occurs.

◆ Status Displays

SERVOPACK Panel Display	"A.A9F" is displayed for 2 seconds.
Indicator	Red indicator: Flashes for 2 seconds. Refer to the following manual for details. 📖 S-7-Series S-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)
Digital Operator	"A.A9F" is displayed for 2 seconds at the top left of the screen.
Response to the Alarm or Warning Read Command (ALM)	No change
Response to the Most Recent Error Read Command (ERR)	Error code (the most recent (closest) error code)
ALM Signal	No change
/WARN Signal	The signal is valid for 2 seconds.

The INDEXER Module error displays and the corrective actions are shown below.

Serial Command Negative Response	Alarm Number	Error Name	Meaning	Corrective Action
E41E	A.A9F	Program Table Save Failure Error	While writing data to the flash memory, a failure occurred during one of the following operation. • While saving a program table by using a PGMSTORE command • While saving a program table by using FnB03 • While initializing a program table by using a PGMINIT command • While initializing a program table by using FnB06	Repair the hardware.
E42E	A.A9F	Zone Table Save Failure Error	While writing data to the flash memory, a failure occurred during one of the following operation. • While saving a zone table by using a ZONESTORE command • While saving a zone table by using FnB04 • While initializing a zone table by using a ZONEINIT command • While initializing a zone table by using FnB07	Repair the hardware.

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Serial Command Negative Response	Alarm Number	Error Name	Meaning	Corrective Action
E43E	A.A9F	JOG Speed Table Save Failure Error	While writing data to the flash memory, a failure occurred during one of the following operation. • While saving a JOG speed table by using a JSPDSTORE command • While saving a JOG speed table by using FnB05 • While initializing a JOG speed table by using a JSPDINIT command • While initializing a JOG speed table by using FnB08	Repair the hardware.
E44E	A.A9F	Canceled Program Table Error	There was a request to start program table operation even though an E19A or E1BA alarm occurred when the control power supply was turned ON.	Remove the cause of the alarm.
E46E	A.A9F	Canceled JOG Speed Table Error	There was a request to start JOG speed table operation even though an E1FA or E22A alarm occurred when the control power supply was turned ON.	Remove the cause of the alarm.
E47E	A.A9F	Serial Communications Receiving Buffer Overflow Error	There was an overflow in the reception buffer used for serial commands. • An error will occur if too many serial commands are sent consecutively without waiting for the responses. (Normally, the reception buffer will not overflow if there is command/response handshaking.) • When an overflow has occurred, error code E47E will be returned and all of the data that has accumulated in the reception buffer will be discarded.	Wait for a response to be received before sending the next command. The reception buffer can contain up to 100 commands.
E48E	A.A9F	Serial Communications Parity Error	A parity check error occurred with the serial command. • This error will occur if even parity is not being used. • The command that caused this error will be discarded and no response will be returned. • There will be no response, but the /WARN output and LED indicators will indicate that an error has occurred.	• Check the serial communications protocol (PnB00) and bit rate (PnB01) settings. • Check the wiring. • If noise may be causing the problem, take steps to reduce noise such as using communications cables with ferrite cores.

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Serial Command Negative Response	Alarm Number	Error Name	Meaning	Corrective Action
E49E	A.A9F	Serial Communications Framing Error	A stop bit detection error occurred with the serial command. • The command that caused this error will be discarded and no response will be returned. • There will be no response, but the /WARN output and LED indicators will indicate that an error has occurred.	• Check the serial communications protocol (PnB00) and bit rate (PnB01) settings. • Check the wiring. • If noise may be causing the problem, take steps to reduce noise such as using communications cables with ferrite cores.
E4AE	A.A9F	Serial Communications Overrun Error	Serial command reception failed. • The hardware's reception buffer was overwritten with the subsequent data. (Normally, data is read before it is overwritten, so this error does not occur.)	Repair the hardware.
E4BE	A.A9F	Moving Disabled Error due to P-OT	Travel in the forward direction was requested when P-OT was in effect. (Forward movement is disabled when P-OT (forward overtravel) is in effect.)	• When P-OT is being used, move to a position where the P-OT is not in effect. • When P-OT is not being used, disable P-OT in the parameter (PnB0F = 3).
E4CE	A.A9F	Moving Disabled Error due to N-OT	Travel in the reverse direction was requested when N-OT was in effect. (Reverse movement is disabled when N-OT (reverse overtravel) is in effect.)	• When N-OT is being used, move to a position where the N-OT is not in effect. • When N-OT is not being used, disable N-OT in the parameter (PnB10 = 3).

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Serial Command Negative Response	Alarm Number	Error Name	Meaning	Corrective Action
E4DE	A.A9F	Moving Disabled Error due to P-LS	The specified target position exceeds the position reference of forward software limit set in PnB21.	• Check the target position specification. • Check the forward software limit in PnB21. • Check the moving mode (rotary or linear) set in PnB20. • If software limits are not being used, either select a rotary moving mode in PnB20 or disable the software limits by setting PnB21 = PnB23 = 0.
E4EE	A.A9F	Moving Disabled Error due to N-LS	The specified target position exceeds the position reference of reverse software limit set in PnB23.	• Check the target position specification. • Check the reverse software limit in PnB23. • Check the moving mode (rotary or linear) set in PnB20. • If software limits are not being used, either select a rotary moving mode in PnB20 or disable the software limits by setting PnB21 = PnB23 = 0.
E4FE	A.A9F	Position Reference Out-of-range Error	The moving method is set to rotary (PnB20 = 1, 2, or 3) and the target position specification exceeds the position reference limits in PnB21 and PnB23.	• Check the target position specification. • Check the positioning range set with PnB21 and PnB23. • Check the moving method (rotary or linear) set in PnB20.

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Serial Command Negative Response	Alarm Number	Error Name	Meaning	Corrective Action
E51E	A.A9F	Target Position Unspecified Error	Even though the target position was not specified even once, there was a request by the ST command to start positioning or a request by the RS command to start registration positioning.	Specify a target position with a command such as the POS command, STnnnnnnnn command, or RSnnnnnnnn command.
E52E	A.A9F	Registration Distance Unspecified Error	Even though the registration distance was not specified even once, there was a request by the RS command to start registration positioning.	Specify a registration distance with the RDST command.
E53E	A.A9F	Move Reference Duplication Error	There was a new move reference requested even though the system was already moving in a positioning or other traveling operation.	• Send the next move reference request only after the current movement is completed (Position reference distribution is completed). • A movement can be interrupted or canceled with the HOLD or SKIP commands. Also, STOP can be specified in the target position specification (POS) with the program table.

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Serial Command Negative Response	Alarm Number	Error Name	Meaning	Corrective Action
E54E	A.A9F	Servo ON Incomplete Error	The servo is not ON. • There was a positioning request or other move reference request in servo OFF status. The servo went OFF during program table operation. (Program table operation will be interrupted while just the step that was being executed is canceled (If LOOP ≠ 1, the first LOOP is canceled.))	Send the move reference request only after turning the servo ON by turning ON the /S-ON signal, setting PnB0E = 2 so that the /S-ON signal is always ON, or executing the SVON command. There are two possibilities. • The program can be canceled with the /PGMRES signal or PGMRES command. • The servo can be turned ON and the program can be restarted with the /START-STOP signal or the START command.
E55E	A.A9F	Servo ON Failure Error	The servo could not be turned ON within 2 s after turning ON the /S-ON signal or executing the SVON command. • The motor is rotating during servo ON execution. • The main power supply went OFF during servo ON execution. • Hard wire base block status (HWBB status) Error E5BE will occur if there was an alarm when the servo ON request was sent using the SVON command. Error E5CE will occur if the main power supply was OFF when the servo ON request was sent.	• Turn the servo ON when the motor is stopped. • Check the main power supply. • Turn ON signals /HWBB1, /HWBB2. After that, temporarily establish the servo OFF status by turning the /S-ON signal OFF or sending the SVOFF command, then turn the servo ON again.
E56E	A.A9F	Undefined Serial Command Error	• There was a syntax error in the serial command. • There was a number in the serial command longer than 8 digits or 10 digits.	Check the serial command's character string.
E57E	A.A9F	Address Out-of-range Error	The specified address was incorrect for a parameter, program table, zone table, JOG speed table, alarm history, or monitor read/write command.	Check the address.

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Serial Command Negative Response	Alarm Number	Error Name	Meaning	Corrective Action
E58E	A.A9F	Data Out-of-range Error	The specified setting was incorrect in a parameter or program table write command.	Check the setting.
E59E	A.A9F	Communication Failure Error between INDEXER Module and SERVOPACK	Communications between the INDEXER Module and the SERVOPACK have failed.	Check the version of the SERVOPACK.
E5AE	A.A9F	Execution Disabled while Servo ON Error	Some of the utility functions, such as parameter initialization, has been requested while still in the servo ON status. For safety, the following functions cannot be executed in the servo ON status. • Serial commands: Parameter initialization, absolute encoder reset, motor current zero adjustment • SigmaWin+: Parameter initialization	Execute these functions after turning the servo OFF.
E5BE	A.A9F	Execution Disabled while Alarm Activated Error	Servo ON was requested (the SVON command was executed) while there was an alarm.	Turn the servo ON after eliminating the cause of the alarm and clearing the alarm.
E5CE	A.A9F	Execution Disabled while Main Power OFF Error	Servo ON was requested (the SVON command was executed) while the main power supply was OFF.	Turn the servo ON after turning ON the main power supply.
E5DE	A.A9F	Origin Return Method Unspecified Error	The origin return method is not specified. • An origin return start was requested (/HOME signal was turned ON or ZRN command was executed) without setting the origin return method.	Specify the origin return method in PnB31.
E5EE	A.A9F	Execution Disabled during Program Table Operation Error	• There was a request to execute a process that is not allowed during program table operation while program table operation was in progress or on hold. • There was an attempt to change the program table while program table operation was in progress or on hold. • There was a request to start positioning by a serial command while program table operation was in progress or on hold.	Request execution of the process again after canceling program table operation by turning the /PGMRES signal ON.
E5FE	A.A9F	Session Conflict Error	There was a request that could not be executed at the same time as the function that was being executed. Example: There was a request to start program table operation while the program table was being initialized.	Execute the operation again after the execution of the current function is completed.

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Serial Command Negative Response	Alarm Number	Error Name	Meaning	Corrective Action
E61E	A.A9F	Encoder Mismatch Error	There was a request that was incompatible with the connected encoder. Examples: • An Absolute Encoder Reset (ABSPGRES command) was requested when an incremental encoder is connected. • An origin return start was requested (/HOME signal was turned ON or ZRN command was executed) when an absolute encoder is connected. (An absolute encoder can be used as an incremental encoder if parameter Pn002.2 = 1.)	Check the encoder.
E62E	A.A9F	No A.CC0 Alarm Occurred Error	A Multi-turn Limit Setting (MLTLIMSET command) was requested even though alarm A.CC0 has not occurred. (Alarm A.CC0 indicates that Pn205 does not match the setting in the encoder after the multi-turn limit setting in Pn205 was changed and the control power supply was turned OFF and ON.)	Use the Multi-turn Limit Setting operation to adjust the setting in the encoder to match Pn205 only after alarm A.CC0 has occurred.
E63E	A.A9F	Continuous Stop Execution Disabled Error	An attempt was made to execute a continuous stop under conditions where it could not be executed. Examples: • The coordinates have been set to linear moving method. • The immediately-preceding table target position is not ±INFINITE. • The immediately-preceding table target position is ±INFINITE, but the registration distance is set. • A value other than 1 has been set for the execution count.	Execute a continuous stop under conditions where it can be executed.
E65E	A.9F9	Execution Error during Position Deviation Clear	Program table operation, JOG speed table operation, or homing was executed during position deviation clear.	Clear the status of position deviation clear.

Continued on next page.

3.4.9 Troubleshooting Based on the Operation and Conditions of the Servomotor

This section provides troubleshooting based on the operation and conditions of the Servomotor, including causes and corrections.

Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The control power supply is not turned ON.	Measure the voltage between control power supply terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the control power supply is turned ON.	–
	The main circuit power supply is not turned ON.	Measure the voltage across the main circuit power input terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the main circuit power supply is turned ON.	–
	The I/O signal connector (CN1) pins are not wired correctly or are disconnected.	Turn OFF the power supply to the servo system. Check the wiring condition of the I/O signal connector (CN1) pins.	Correct the wiring of the I/O signal connector (CN1) pins.	*
	The wiring for the Servomotor Main Circuit Cables or Encoder Cable is disconnected.	Check the wiring conditions.	Turn OFF the power supply to the servo system. Wire the cable correctly.	–
	There is an overload on the Servomotor.	Operate the Servomotor with no load and check the load status.	Turn OFF the power supply to the servo system. Reduce the load or replace the Servomotor with a Servomotor with a larger capacity.	–
	The type of encoder that is being used does not agree with the setting of Pn002 = n.□X□□ (Encoder Usage).	Check the type of the encoder that is being used and the setting of Pn002 = n.□X□□.	Set Pn002 = n.□X□□ according to the type of the encoder that is being used.	*
	Settings for input signals PnB03 to PnB12 are incorrect.	Check settings of input signals PnB03 to PnB12.	Correct the settings of input signals PnB03 to PnB12.	*
	The /S-ON (Servo ON) signal was not received.	Check the commands sent from the host controller.	Turn ON the /S-ON signal from the host controller.	*
	The P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal is still OFF.	Check the P-OT and N-OT signals.	Turn ON the P-OT and N-OT signals.	*
	The current position of the servomotor is outside the software limit setting range.	Check the error at the INDEXER Module.	Check the motor position and software limit setting (PnB21, PnB23), then move the servomotor into the software limit setting range.	–
	There is no position reference, or it is incorrect.	Check the error at the INDEXER Module.	Set the program table correctly.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Moves Instantaneously, and Then Stops	The safety input signals (/HWBB1 or /HWBB2) were not turned ON.	Check the /HWBB1 and /HWBB2 input signals.	Turn ON the /HWBB1 and /HWBB2 input signals. If you are not using the safety function, connect the Safety Jumper Connector (provided as an accessory) to CN8.	*
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
	There is a mistake in the Servomotor wiring.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Servomotor correctly.	–
	There is a mistake in the wiring of the encoder or Serial Converter Unit.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Serial Converter Unit correctly.	–
Servomotor Speed Is Unstable	There is a faulty connection in the Servomotor wiring.	Turn OFF the power supply to the servo system. The connector connections for the power line (U, V, and W phases) and the encoder or Serial Converter Unit may be unstable. Check the wiring.	Tighten any loose terminals or connectors and correct the wiring.	–
Servomotor Moves without a Reference Input	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Dynamic Brake Does Not Operate	The setting of Pn001 = n.□□□X (Servo OFF or Alarm Group 1 Stopping Method) is not suitable.	Check the setting of Pn001 = n.□□□X.	Set Pn001 = n.□□□X correctly.	–
	The dynamic brake resistor is disconnected.	Check the moment of inertia, motor speed, and dynamic brake frequency of use. If the moment of inertia, motor speed, or dynamic brake frequency of use is excessive, the dynamic brake resistance may be disconnected.	Turn OFF the power supply to the servo system. Replace the SERVOPACK. To prevent disconnection, reduce the load.	–
	There was a failure in the dynamic brake drive circuit.	–	Turn OFF the power supply to the servo system. There is a defective component in the dynamic brake circuit. Replace the SERVOPACK.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	The Servomotor vibrated considerably while performing the tuning-less function with the default settings.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio or mass ratio is within the allowable value, or increase the load level or reduce the rigidity level in the tuning-less level settings.	*
	The machine mounting is not secure.	Turn OFF the power supply to the servo system. Check to see if there are any loose mounting screws.	Tighten the mounting screws.	–
		Turn OFF the power supply to the servo system. Check to see if there is misalignment in the coupling.	Align the coupling.	–
		Turn OFF the power supply to the servo system. Check to see if the coupling is balanced.	Balance the coupling.	–
	The bearings are defective.	Turn OFF the power supply to the servo system. Check for noise and vibration around the bearings.	Replace the Servomotor.	–
	There is a vibration source at the driven machine.	Turn OFF the power supply to the servo system. Check for any foreign matter, damage, or deformation in the machine's moving parts.	Consult with the machine manufacturer.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use shielded twisted-pair wire cables or screened twisted-pair cables with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Make sure that the rotary or Linear Encoder Cable satisfies the specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with a conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Check to see if there is noise interference on the signal line from the encoder.	Turn OFF the power supply to the servo system. Implement countermeasures against noise for the encoder wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
Servomotor Vibrates at Frequency of Approx. 200 to 400 Hz.	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	*
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Large Motor Speed Overshoot on Starting and Stopping	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	*
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–
	The torque reference is saturated.	Check the waveform of the torque reference.	Use the mode switch.	–
	The force limits (Pn483 and Pn484) are set to the default values.	The default values of the force limits and Pn483 = 30% and Pn484 = 30%.	Set Pn483 and Pn484 to appropriate values.	*
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder or Serial Converter Unit wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Overtravel Occurred	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal was input.	Check the external power supply (+24 V) voltage for the input signals.	Correct the external power supply (+24 V) voltage for the input signals.	–
		Check the operating condition of the overtravel limit switches.	Make sure that the overtravel limit switches operate correctly.	–
		Check the wiring of the overtravel limit switches.	Correct the wiring of the overtravel limit switches.	*
		Check the settings of PnB0F and PnB10.	Set the parameters to correct values.	*
	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal malfunctioned.	Check for fluctuation in the external power supply (+24 V) voltage for the input signals.	Eliminate fluctuation from the external power supply (+24 V) voltage for the input signals.	–
		Check to see if the operation of the overtravel limit switches is unstable.	Stabilize the operating condition of the overtravel limit switches.	–
		Check the wiring of the overtravel limit switches (e.g., check for cable damage and loose screws).	Correct the wiring of the overtravel limit switches.	–
	The selection of the Servomotor stopping method is not correct.	Check the servo OFF stopping method set in Pn001 = n.□□□X or PnB1F.	Select a Servomotor stopping method other than coasting to a stop.	*
Improper Stop Position for Overtravel (OT) Signal	The limit switch position and dog length are not appropriate.	–	Install the limit switch at the appropriate position.	–
	The overtravel limit switch position is too close for the coasting distance.	–	Install the overtravel limit switch at the appropriate position.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Position Deviation (without Alarm)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if is satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder wiring or Serial Converter Unit wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor. Replace the Servomotor.	–
	The coupling between the machine and Servomotor is not suitable.	Turn OFF the power supply to the servo system. Check to see if position offset occurs at the coupling between machine and Servomotor.	Correctly secure the coupling between the machine and Servomotor.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Position Deviation (without Alarm)	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	An encoder fault occurred. (The pulse count does not change.)	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Servomotor Overheated	The surrounding air temperature is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature to 40°C or less.	–
	The surface of the Servomotor is dirty.	Turn OFF the power supply to the servo system. Visually check the surface for dirt.	Clean dirt, dust, and oil from the surface.	–
	There is an overload on the Servomotor.	Check the load status with a monitor.	If the Servomotor is overloaded, reduce the load or replace the Servo Drive with a SERVOPACK and Servomotor with larger capacities.	–
	Polarity detection was not performed correctly.	Check to see if electrical angle 2 (electrical angle from polarity origin) at any position is between ±10°.	Correct the settings for the polarity detection-related parameters.	–
Estimating the moment of inertia failed.	The acceleration rate is low and travel distance is short.	Check the Condition Setting Dialog Box used to perform moment of inertia estimation.	Increase the acceleration rate and travel distance.	–

* Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)

3.5 FT83 SERVOPACKs with Analog Voltage/Pulse Train References

3.5.1 Alarm Displays

If an error occurs in the SERVOPACK, the status is displayed as described below.

◆ Status Display

SERVOPACK Panel Display	The alarm number will be displayed. Refer to the following manual for details. 📖 Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)
Digital Operator	The alarm code is displayed at the top left of the screen.
ALM Signal	The alarm signal turns ON. (The photocoupler turns OFF.)
/WARN Signal	No change

3.5.2 List of Alarms

The list of alarms gives the alarm name, alarm meaning, alarm stopping method, alarm reset possibility, and alarm code output in order of the alarm numbers.

Servomotor Stopping Method for Alarms

Refer to the following manual for information on the stopping method for alarms.

📖 Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

Alarm Reset Possibility

Yes: You can use an alarm reset to clear the alarm. However, this assumes that the cause of the alarm has been removed.
No: You cannot clear the alarm.

List of Alarms

Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.020	Parameter Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No	H	H	H
A.021	Parameter Format Error	There is an error in the parameter data format in the SERVOPACK.	Gr.1	No			
A.022	System Checksum Error	There is an error in the parameter data in the SERVOPACK.	Gr.1	No			
A.024	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No			
A.025	System Alarm	An internal program error occurred in the SERVOPACK.	Gr.1	No			
A.030	Main Circuit Detector Error	There is an error in the detection data for the main circuit.	Gr.1	Yes			
A.040	Parameter Setting Error	A parameter setting is outside of the setting range.	Gr.1	No			

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.041	Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Gr.1	No	H	H	H
A.042	Parameter Combination Error	The combination of some parameters exceeds the setting range.	Gr.1	No			
A.044	Semi-Closed/Fully-Closed Loop Control Parameter Setting Error	The settings of the Option Module and Pn002 = n.X□□□ (External Encoder Usage) do not match.	Gr.1	No			
A.04A	Parameter Setting Error 2	There is an error in setting of parameters reserved by the system.	Gr.1	No			
A.050	Combination Error	The capacities of the SERVOPACK and Servomotor do not match.	Gr.1	Yes			
A.051	Unsupported Device Alarm	An unsupported device was connected.	Gr.1	No			
A.0b0	Invalid Servo ON Command Alarm	The /S-ON (Servo ON) signal was input from the host controller after a utility function that turns ON the Servomotor was executed.	Gr.1	Yes			
A.100	Overcurrent Detected	An overcurrent flowed through the power transformer or the heat sink overheated.	Gr.1	No	L	H	H
A.101	Motor Overcurrent Detected	The current to the motor exceeded the allowable current.	Gr.1	No			
A.300	Regeneration Error	There is an error related to regeneration.	Gr.1	Yes	L	L	H
A.320	Regenerative Overload	A regenerative overload occurred.	Gr.2	Yes			
A.330	Main Circuit Power Supply Wiring Error	• The AC power supply input setting or DC power supply input setting is not correct. • The power supply wiring is not correct.	Gr.1	Yes			
A.400	Overvoltage	The main circuit DC voltage is too high.	Gr.1	Yes	H	H	L
A.410	Undervoltage	The main circuit DC voltage is too low.	Gr.2	Yes			
A.510	Overspeed	The motor exceeded the maximum speed.	Gr.1	Yes	L	H	L
A.511	Encoder Output Pulse Overspeed	The pulse output speed for the setting of Pn212 (Encoder Output Pulses) was exceeded.	Gr.1	Yes			
A.520	Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Gr.1	Yes			
A.521	Autotuning Alarm	Vibration was detected during autotuning for the tuning-less function.	Gr.1	Yes			
A.550	Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum motor speed.	Gr.1	Yes			

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.710	Instantaneous Overload	The Servomotor was operating for several seconds to several tens of seconds under a torque that largely exceeded the rating.	Gr.2	Yes	L	L	L
A.720	Continuous Overload	The Servomotor was operating continuously under a torque that exceeded the rating.	Gr.1	Yes			
A.730	Dynamic Brake Overload	When the dynamic brake was applied, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Gr.1	Yes			
A.731							
A.740	Inrush Current Limiting Resistor Overload	The main circuit power supply was frequently turned ON and OFF.	Gr.1	Yes			
A.7A1	Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	Gr.2	Yes			
A.7A2	Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.	Gr.2	Yes			
A.7A3	Internal Temperature Sensor Error	An error occurred in the temperature sensor circuit.	Gr.2	No			
A.7Ab	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Gr.1	Yes			
A.810	Encoder Backup Alarm	The power supplies to the encoder all failed and the position data was lost.	Gr.1	No	H	H	H
A.820	Encoder Checksum Alarm	There is an error in the checksum results for encoder memory.	Gr.1	No			
A.830	Encoder Battery Alarm	The battery voltage was lower than the specified level after the control power supply was turned ON.	Gr.1	Yes			
A.840	Encoder Data Alarm	There is an internal data error in the encoder.	Gr.1	No			
A.850	Encoder Overspeed	The encoder was operating at high speed when the power was turned ON.	Gr.1	No			
A.860	Encoder Overheated	The internal temperature of encoder is too high.	Gr.1	No			
A.861	Motor Overheated	The internal temperature of motor is too high.	Gr.1	No			
A.862	Overheat Alarm	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61B (Overheat Alarm Level).	Gr.1	Yes			
A.8A0	External Encoder Error	An error occurred in the external encoder.	Gr.1	Yes			
A.8A1	External Encoder Module Error	An error occurred in the Serial Converter Unit.	Gr.1	Yes			
A.8A2	External Incremental Encoder Sensor Error	An error occurred in the external encoder.	Gr.1	Yes			
A.8A3	External Absolute Encoder Position Error	An error occurred in the position data of the external encoder.	Gr.1	Yes			
A.8A5	External Encoder Overspeed	An overspeed error occurred in the external encoder.	Gr.1	Yes			
A.8A6	External Encoder Overheated	An overheating error occurred in the external encoder.	Gr.1	Yes			

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.b33	Current Detection Error 3	An error occurred in the current detection circuit.	Gr.1	No	H	H	H
A.bF0	System Alarm 0	Internal program error 0 occurred in the SERVOPACK.	Gr.1	No			
A.bF1	System Alarm 1	Internal program error 1 occurred in the SERVOPACK.	Gr.1	No			
A.bF2	System Alarm 2	Internal program error 2 occurred in the SERVOPACK.	Gr.1	No			
A.bF3	System Alarm 3	Internal program error 3 occurred in the SERVOPACK.	Gr.1	No			
A.bF4	System Alarm 4	Internal program error 4 occurred in the SERVOPACK.	Gr.1	No			
A.bF5	System Alarm 5	Internal program error 5 occurred in the SERVOPACK.	Gr.1	No			
A.bF6	System Alarm 6	Internal program error 6 occurred in the SERVOPACK.	Gr.1	No			
A.bF7	System Alarm 7	Internal program error 7 occurred in the SERVOPACK.	Gr.1	No			
A.bF8	System Alarm 8	Internal program error 8 occurred in the SERVOPACK.	Gr.1	No			
A.C10	Servomotor Out of Control	The Servomotor ran out of control.	Gr.1	Yes	L	H	L
A.C80	Encoder Clear Error or Multiturn Limit Setting Error	The multiturn data for the absolute encoder was not correctly cleared or set.	Gr.1	No			
A.C90	Encoder Communications Error	Communications between the encoder and SERVOPACK is not possible.	Gr.1	No			
A.C91	Encoder Communications Position Data Acceleration Rate Error	An error occurred in calculating the position data of the encoder.	Gr.1	No	L	H	L
A.C92	Encoder Communications Timer Error	An error occurred in the communications timer between the encoder and SERVOPACK.	Gr.1	No			
A.CA0	Encoder Parameter Error	The parameters in the encoder are corrupted.	Gr.1	No			
A.Cb0	Encoder Echoback Error	The contents of communications with the encoder are incorrect.	Gr.1	No			
A.CC0	Multiturn Limit Disagreement	Different multiturn limits have been set in the encoder and the SERVOPACK.	Gr.1	No			
A.CF1	Reception Failed Error in Feedback Option Module Communications	Receiving data from the Feedback Option Module failed.	Gr.1	No			
A.CF2	Timer Stopped Error in Feedback Option Module Communications	An error occurred in the timer for communications with the Feedback Option Module.	Gr.1	No			

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Alarm Number	Alarm Name	Alarm Meaning	Servomotor Stopping Method	Alarm Reset Possible?	Alarm Code Output		
					/ALO1	/ALO2	/ALO3
A.d00	Position Deviation Overflow	The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.	Gr.1	Yes	L	L	H
A.d01	Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Gr.1	Yes			
A.d02	Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if a position reference is input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded before the limit is cleared.	Gr.2	Yes			
A.d10	Motor-Load Position Deviation Overflow	There was too much position deviation between the motor and load during fully-closed loop control.	Gr.2	Yes			
A.d30	Position Data Overflow	The position feedback data exceeded ±1,879,048,192.	Gr.1	No			
A.E71	Safety Option Module Detection Failure	Detection of the safety option module failed.	Gr.1	No	H	L	L
A.E72	Feedback Option Module Detection Failure	Detection of the Feedback Option Module failed.	Gr.1	No			
A.E74	Unsupported Safety Option Module	An unsupported safety option module was connected.	Gr.1	No			
A.E75	Unsupported Feedback Option Module	An unsupported feedback option module was connected.	Gr.1	No			
A.Eb1	Safety Function Signal Input Timing Error	An error occurred in the input timing of the safety function signal.	Gr.1	No			
A.EC8	Gate Drive Error 1	An error occurred in the gate drive circuit.	Gr.1	No			
A.EC9	Gate Drive Error 2	An error occurred in the gate drive circuit.	Gr.1	No			
A.EF9	INDEXER Alarm	An alarm occurred in the INDEXER.	Gr.1	No	H	L	H
A.F10	Power Supply Line Open Phase	The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.	Gr.2	Yes			
FL-1*	System Alarm	An internal program error occurred in the SERVOPACK.	–	No	Undefined.		
FL-2*							
FL-3*							
FL-4*							
FL-5*							
FL-6*							
CPF00	Digital Operator Communications Error 1	Communications were not possible between the Digital Operator (model: JUSP-OP05A-1-E) and the SERVOPACK (e.g., a CPU error occurred).	–	No			
CPF01	Digital Operator Communications Error 2						

* These alarms are not stored in the alarm history. They are only displayed on the panel display.

Note: The A.Eb0, A.Eb2 to A.Eb9, and A.EC0 to A.EC2 alarms can occur when a Safety Module is connected. Refer to the following manual for details.
📖 AC Servo Drive Σ-V-Series/Σ-V-Series for Large-Capacity Models/Σ-7-Series User's Manual Safety Module (Manual No.: SIEP C720829 06)

3.5.3 Troubleshooting Alarms

The causes of and corrections for the alarms are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.020: Parameter Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	Set the power supply voltage within the specified range, and initialize the parameter settings.	*1
	The power supply was shut OFF while writing parameter settings.	Check the timing of shutting OFF the power supply.	Initialize the parameter settings and then set the parameters again.	
	The number of times that parameters were written exceeded the limit.	Check to see if the parameters were frequently changed from the host controller.	The SERVOPACK may be faulty. Replace the SERVOPACK. Reconsider the method for writing the parameters.	*1
	A malfunction was caused by noise from the AC power supply, ground, static electricity, or other source.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, noise may be the cause.	Implement countermeasures against noise.	–
	Gas, water drops, or cutting oil entered the SERVOPACK and caused failure of the internal components.	Check the installation conditions.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.021: Parameter Format Error (There is an error in the parameter data format in the SERVOPACK.)	The software version of the SERVOPACK that caused the alarm is older than the software version of the parameters specified to write.	Read the product information to see if the software versions are the same. If they are different, it could be the cause of the alarm.	Write the parameters from another SERVOPACK with the same model and the same software version, and then turn the power OFF and ON again.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.022: System Checksum Error (There is an error in the parameter data in the SERVOPACK.)	The power supply voltage suddenly dropped.	Measure the power supply voltage.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The power supply was shut OFF while setting a utility function.	Check the timing of shutting OFF the power supply.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	Turn the power supply to the SERVOPACK OFF and ON again. If the alarm still occurs, the SERVOPACK may have failed.	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.024: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.025: System Alarm (An internal program error occurred in the SERVOPACK.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.030: Main Circuit Detector Error	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.040: Parameter Setting Error (A parameter setting is outside of the setting range.)	The SERVOPACK and Servomotor capacities do not match each other.	Check the combination of the SERVOPACK and Servomotor capacities.	Select a proper combination of SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	A parameter setting is outside of the setting range.	Check the setting ranges of the parameters that have been changed.	Set the parameters to values within the setting ranges.	–
	The electronic gear ratio is outside of the setting range.	Check the electronic gear ratio. The ratio must be within the following range: 0.001 < (Pn20E/Pn210) < 64,000.	Set the electronic gear ratio in the following range: 0.001 < (Pn20E/Pn210) < 64,000.	*1
	Out-of-Range Origin Setting	See if the origin is between the settings of Pn638 and Pn63A.	Set the origin between Pn638 and Pn63A.	–
A.041: Encoder Output Pulse Setting Error	The setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution) is outside of the setting range or does not satisfy the setting conditions.	Check the setting of Pn212 or Pn281.	Set Pn212 or Pn281 to an appropriate value.	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.042: Parameter Combination Error	The speed of program jogging went below the setting range when the electronic gear ratio (Pn20E/ Pn210) or the Servomotor was changed.	Check to see if the detection conditions*2 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1
	The speed of program jogging went below the setting range when Pn533 or Pn585 (Program Jogging Speed) was changed.	Check to see if the detection conditions*2 are satisfied.	Increase the setting of Pn533 or Pn585.	*1
	The movement speed of advanced autotuning went below the setting range when the electronic gear ratio (Pn20E/ Pn210) or the Servomotor was changed.	Check to see if the detection conditions*3 are satisfied.	Decrease the setting of the electronic gear ratio (Pn20E/Pn210).	*1
A.044: Semi-Closed/ Fully-Closed Loop Control Parameter Setting Error	The setting of the Fully-Closed Module does not match the setting of Pn002 = n.X□□□ (External Encoder Usage).	Check the setting of Pn002 = n.X□□□.	Make sure that the setting of the Fully-closed Module agrees with the setting of Pn002 = n.X□□□.	*1
A.04A: Parameter Setting Error 2	A parameter reserved by the system was changed.	–	Set the following reserved parameters to the default settings. Pn200.2 Pn207.1 Pn50A.0 Pn50A.1 Pn50A.2 Pn50C Pn50D	–
A.050: Combination Error (The capacities of the SERVOPACK and Servomotor do not match.)	The SERVOPACK and Servomotor capacities do not match each other.	Confirm that the following condition is met: 1/4 ≤ (Servomotor capacity/SERVOPACK capacity) ≤ 4	Select a proper combination of the SERVOPACK and Servomotor capacities.	*1
	A failure occurred in the encoder.	Replace the encoder and check to see if the alarm still occurs.	Replace the Servomotor or encoder.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.051: Unsupported Device Alarm	An unsupported Serial Converter Unit or encoder (e.g., an external encoder) is connected to the SERVOPACK.	Check the product combination specifications.	Change to a correct combination of models.	–
A.0b0: Invalid Servo ON Command Alarm	The /S-ON (Servo ON) signal was input from the host controller after a utility function that turns ON the Servomotor was executed.	–	Turn the power supply to the SERVOPACK OFF and ON again. Or, execute a software reset.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	The regenerative resistor is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	The dynamic brake (DB, emergency stop executed from the SERVOPACK) was frequently activated, or a DB overload alarm occurred.	Check the power consumed by the DB resistor to see how frequently the DB is being used. Or, check the alarm display to see if a DB overload alarm (A.730 or A.731) has occurred.	Change the SERVOPACK model, operating methods, or the mechanisms so that the dynamic brake does not need to be used so frequently.	–
	The regenerative resistor value exceeded the SERVOPACK regenerative processing capacity.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Select a regenerative resistance value that is appropriate for the operating conditions and load.	*4
	The SERVOPACK regenerative resistance is too small.	Check the regenerative load ratio in the SigmaWin+ Motion Monitor Tab Page to see how frequently the regenerative resistor is being used.	Change the regenerative resistance to a value larger than the SERVOPACK minimum allowable resistance.	

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.100: Overcurrent Detected (An overcurrent flowed through the power transformer or the heat sink overheated.)	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.101: Motor Overcurrent Detected (The current to the motor exceeded the allowable current.)	The Main Circuit Cable is not wired correctly or there is faulty contact.	Check the wiring.	Correct the wiring.	*1
	There is a short-circuit or ground fault in a Main Circuit Cable.	Check for short-circuits across cable phases U, V, and W, or between the ground and cable phases U, V, and W.	The cable may be short-circuited. Replace the cable.	
	There is a short-circuit or ground fault inside the Servomotor.	Check for short-circuits across Servomotor phases U, V, and W, or between the ground and Servomotor phases U, V, or W.	The Servomotor may be faulty. Replace the Servomotor.	
	There is a short-circuit or ground fault inside the SERVOPACK.	Check for short-circuits across the Servomotor connection terminals U, V, and W on the SERVOPACK, or between the ground and terminals U, V, or W.	The SERVOPACK may be faulty. Replace the SERVOPACK.	
	A heavy load was applied while the Servomotor was stopped or running at a low speed.	Check to see if the operating conditions exceed Servo Drive specifications.	Reduce the load applied to the Servomotor. Or, increase the operating speed.	–
	A malfunction was caused by noise.	Improve the noise environment, e.g. by improving the wiring or installation conditions, and check to see if the alarm still occurs.	Implement countermeasures against noise, such as correct wiring of the FG. Use an FG wire size equivalent to the SERVOPACK's main circuit wire size.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.300: Regeneration Error	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to one of the following SERVOPACKs: SGD7S-2R8A or -2R8F.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or set Pn600 (Regenerative Resistor Capacity) to 0 (setting unit: ×10 W) if no Regenerative Resistor is required.	*1
	The jumper between the regenerative resistor terminals (B2 and B3) was removed from one of the following SERVOPACKs: SGD7S-120A.	Check to see if the jumper is connected between power supply terminals. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correctly connect a jumper.	*1
	The External Regenerative Resistor or Regenerative Resistor Unit is not wired correctly, or was removed or disconnected.	Check the wiring of the External Regenerative Resistor or Regenerative Resistor Unit. Note: If an External Regenerative Resistor or Regenerative Resistor Unit is connected while the jumper remains connected between B2 and B3, the SERVOPACK may be damaged.	Correct the wiring of the External Regenerative Resistor or Regenerative Resistor Unit.	
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.320: Regenerative Overload	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The external regenerative resistance value or regenerative resistor capacity is too small, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or other means.	Change the regenerative resistance value or capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	*4
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
	The setting of Pn600 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check it see if a Regenerative Resistor is connected and check the setting of Pn600.	Correct the setting of Pn600.	*1
	The setting of Pn603 (Regenerative Resistor Capacity) is smaller than the capacity of the External Regenerative Resistor.	Check to see if a Regenerative Resistor is connected and check the setting of Pn603.	Correct the setting of Pn603.	*1
	The external regenerative resistance is too high.	Check the regenerative resistance.	Change the regenerative resistance to a correct value or use an External Regenerative Resistor of an appropriate capacity.	*4
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.330: Main Circuit Power Supply Wiring Error (Detected when the main circuit power supply is turned ON.)	The regenerative resistor was disconnected when the SERVOPACK power supply voltage was high.	Measure the resistance of the regenerative resistor using a measuring instrument.	If you are using the regenerative resistor built into the SERVOPACK, replace the SERVOPACK. If you are using an External Regenerative Resistor, replace the External Regenerative Resistor.	–
	DC power was supplied when an AC power supply input was specified in the settings.	Check the power supply to see if it is a DC power supply.	Correct the power supply setting to match the actual power supply.	*1
	AC power was supplied when a DC power supply input was specified in the settings.	Check the power supply to see if it is an AC power supply.	Correct the power supply setting to match the actual power supply.	
	Pn600 (Regenerative Resistor Capacity) is not set to 0 and an External Regenerative Resistor is not connected to an SGD7S-2R8A SERVOPACKs.	Check it see if an External Regenerative Resistor is connected and check the setting of Pn600.	Connect an External Regenerative Resistor, or if an External Regenerative Resistor is not required, set Pn600 to 0.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.400: Overvoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the AC/DC power supply voltage within the specified range.	–
	The power supply is not stable or was influenced by a lightning surge.	Measure the power supply voltage.	Improve the power supply conditions, install a surge absorber, and then turn the power supply OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The voltage for AC power supply was too high during acceleration or deceleration.	Check the power supply voltage and the speed and torque during operation.	Set the AC power supply voltage within the specified range.	–
	The external regenerative resistance is too high for the operating conditions.	Check the operating conditions and the regenerative resistance.	Select a regenerative resistance value that is appropriate for the operating conditions and load.	*4
	The moment of inertia ratio or mass ratio exceeded the allowable value.	Check to see if the moment of inertia ratio or mass ratio is within the allowable range.	Increase the deceleration time, or reduce the load.	–
	A failure occurred in the SERVOPACK.	–	While the main circuit power supply is OFF, turn the control power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.410: Undervoltage (Detected in the main circuit power supply section of the SERVOPACK.)	The power supply voltage went below the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	*1
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor to the DC reactor terminals (⊖1 and ⊖2) on the SERVOPACK.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.510: Overspeed (The motor exceeded the maximum speed.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the wiring of the Servomotor.	Make sure that the Servomotor is correctly wired.	–
	A reference value that exceeded the overspeed detection level was input.	Check the input reference.	Reduce the reference value. Or, adjust the gain.	*1
	The motor exceeded the maximum speed.	Check the waveform of the motor speed.	Reduce the speed reference input gain and adjust the servo gain. Or, reconsider the operating conditions.	
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.511: Encoder Output Pulse Overspeed	The encoder output pulse frequency exceeded the limit.	Check the encoder output pulse setting.	Decrease the setting of Pn212 (Encoder Output Pulses) or Pn281 (Encoder Output Resolution).	*1
	The encoder output pulse frequency exceeded the limit because the motor speed was too high.	Check the encoder output pulse setting and the motor speed.	Reduce the motor speed.	–
A.520: Vibration Alarm	Abnormal oscillation was detected in the motor speed.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the setting of Pn100 (Speed Loop Gain).	*1
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	*1
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	*1

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.521: Autotuning Alarm (Vibration was detected while executing the custom tuning, Easy FFT, or the tuning-less function.)	The Servomotor vibrated considerably while performing the tuning-less function.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio is within the allowable value. Or increase the load level or reduce the rigidity level in the tuning-less level settings.	*1
	The Servomotor vibrated considerably while performing custom tuning or Easy FFT.	Check the waveform of the motor speed.	Check the operating procedure of corresponding function and implement corrections.	*1
A.550: Maximum Speed Setting Error	The setting of Pn385 (Maximum Motor Speed) is greater than the maximum speed.	Check the setting of Pn385, and the upper limits of the maximum motor speed setting and the encoder output resolution setting.	Set Pn385 to a value that does not exceed the maximum motor speed.	*1
A.710: Instantaneous Overload A.720: Continuous Overload	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	*1
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven due to mechanical problems.	Check the operation reference and motor speed.	Correct the mechanical problem.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.730 and A.731: Dynamic Brake Overload (An excessive power consumption by the dynamic brake was detected.)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia ratio or mass ratio. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.740: Inrush Current Limiting Resistor Overload (The main circuit power supply was frequently turned ON and OFF.)	The allowable frequency of the inrush current limiting resistor was exceeded when the main circuit power supply was turned ON and OFF.	–	Reduce the frequency of turning the main circuit power supply ON and OFF.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7A1: Internal Temperature Error 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A2: Internal Temperature Error 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	*1
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.7A3: Internal Temperature Sensor Error (An error occurred in the temperature sensor circuit.)	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.7Ab: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.810: Encoder Backup Alarm (Detected at the encoder, but only when an absolute encoder is used.)	The power to the absolute encoder was turned ON for the first time.	Check to see if the power supply was turned ON for the first time.	Set up the encoder.	*1
	The Encoder Cable was disconnected and then connected again.	Check to see if the power supply was turned ON for the first time.	Check the encoder connection and set up the encoder.	
	Power is not being supplied both from the control power supply (+5 V) from the SERVOPACK and from the battery power supply.	Check the encoder connector battery and the connector status.	Replace the battery or implement similar measures to supply power to the encoder, and set up the encoder.	
	A failure occurred in the absolute encoder.	–	If the alarm still occurs after setting up the encoder again, replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.820: Encoder Checksum Alarm (Detected at the encoder.)	A failure occurred in the encoder.	–	■ When Using an Absolute Encoder Set up the encoder again. If the alarm still occurs, the Servomotor may be faulty. Replace the Servomotor. ■ When Using a Single-turn Absolute Encoder or Incremental Encoder The Servomotor may be faulty. Replace the Servomotor.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.830: Encoder Battery Alarm (The absolute encoder battery voltage was lower than the specified level.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	*1
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	*1
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.840: Encoder Data Alarm (Detected at the encoder.)	The encoder malfunctioned.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	The encoder malfunctioned due to noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	–
A.850: Encoder Overspeed (Detected at the encoder when the control power supply is turned ON.)	The Servomotor speed was 200 min^{-1} or higher when the control power supply was turned ON.	Check the motor speed when the power supply is turned ON.	Reduce the Servomotor speed to a value less than 200 min^{-1}, and turn ON the control power supply.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.860: Encoder Overheated (Detected at the encoder.)	The surrounding air temperature around the Servomotor is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40°C or less.	–
	The Servomotor load is greater than the rated load.	Use the accumulated load ratio to check the load.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.861: Motor Overheated	The surrounding temperature around the Servomotor is too high.	Measure the surrounding temperature around the Servomotor.	Reduce the surrounding air temperature of the Servomotor to 40° or less.	–
	The motor load is greater than the rated load.	Check the load with the accumulated load ratio on the Motion Monitor Tab Page on the SigmaWin+.	Operate the Servo Drive so that the motor load remains within the specified range.	*1
	A failure occurred in the Serial Converter Unit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Serial Converter Unit may be faulty. Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.862: Overheat Alarm	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	The overheat protection input signal line is disconnected or short-circuited.	Check the input voltage with the overheat protection input information on the Motion Monitor Tab Page on the SigmaWin+.	Repair the line for the overheat protection input signal.	–
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.8A0: External Encoder Error	Setting the origin of the absolute linear encoder failed because the motor moved.	Before you set the origin, use the fully-closed feedback pulse counter to confirm that the motor is not moving.	The motor must be stopped while setting the origin position.	*1
	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A1: External Encoder Module Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.8A2: External Incremental Encoder Sensor Error	A failure occurred in the external encoder.	–	Replace the external encoder.	–
A.8A3: External Absolute Encoder Position Error	A failure occurred in the external absolute encoder.	–	The external absolute encoder may be faulty. Refer to the encoder manufacturer's instruction manual for corrections.	–
A.8A5: External Encoder Overspeed	An overspeed error was detected in the external encoder.	Check the maximum speed of the external encoder.	Keep the external encoder below its maximum speed.	–
A.8A6: External Encoder Overheated	An overheating error was detected in the external encoder.	–	Replace the external encoder.	–
A.b33: Current Detection Error 3	A failure occurred in the current detection circuit.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF0: System Alarm 0	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF1: System Alarm 1	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF2: System Alarm 2	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF3: System Alarm 3	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF4: System Alarm 4	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF5: System Alarm 5	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.bF6: System Alarm 6	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF7: System Alarm 7	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.bF8: System Alarm 8	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C10: Servomotor Out of Control (Detected when the servo is turned ON.)	The order of phases U, V, and W in the motor wiring is not correct.	Check the Servomotor wiring.	Make sure that the Servomotor is correctly wired.	–
	A failure occurred in the encoder.	–	If the motor wiring is correct and an alarm still occurs after turning the power supply OFF and ON again, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C80: Encoder Clear Error or Multiturn Limit Setting Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C90: Encoder Communications Error	There is a faulty contact in the connector or the connector is not wired correctly for the encoder.	Check the condition of the encoder connector.	Reconnect the encoder connector and check the encoder wiring.	*1
	There is a cable disconnection or short-circuit in the encoder. Or, the cable impedance is outside the specified values.	Check the condition of the Encoder Cable.	Use the Encoder Cable within the specified specifications.	–
	One of the following has occurred: corrosion caused by improper temperature, humidity, or gas, a short-circuit caused by entry of water drops or cutting oil, or faulty contact in connector caused by vibration.	Check the operating environment.	Improve the operating environmental, and replace the cable. If the alarm still occurs, replace the SERVOPACK.	*1
	A malfunction was caused by noise.	–	Correct the wiring around the encoder by separating the Encoder Cable from the Servomotor Main Circuit Cable or by grounding the encoder.	*1
	A failure occurred in the SERVOPACK.	–	Connect the Servomotor to another SERVOPACK, and turn ON the control power supply. If no alarm occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.C91: Encoder Communications Position Data Acceleration Rate Error	Noise entered on the signal lines because the Encoder Cable is bent or the sheath is damaged.	Check the condition of the Encoder Cable and connectors.	Check the Encoder Cable to see if it is installed correctly.	*1
	The Encoder Cable is bundled with a high-current line or installed near a high-current line.	Check the installation condition of the Encoder Cable.	Confirm that there is no surge voltage on the Encoder Cable.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the installation condition of the Encoder Cable.	Properly ground the machine to separate it from the FG of the encoder.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.C92: Encoder Communications Timer Error	Noise entered on the signal line from the encoder.	–	Implement countermeasures against noise for the encoder wiring.	*1
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CA0: Encoder Parameter Error	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.Cb0: Encoder Echoback Error	The encoder is wired incorrectly or there is faulty contact.	Check the wiring of the encoder.	Make sure that the encoder is correctly wired.	*1
	The specifications of the Encoder Cable are not correct and noise entered on it.	–	Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	–
	The Encoder Cable is too long and noise entered on it.	–	Rotary Servomotors: The Encoder Cable wiring distance must be 50 m max.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Check the condition of the Encoder Cable and connectors.	Properly ground the machine to separate it from the FG of the encoder.	–
	Excessive vibration or shock was applied to the encoder.	Check the operating conditions.	Reduce machine vibration. Correctly install the Servomotor.	–
	A failure occurred in the encoder.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the Servomotor may be faulty. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.CC0: Multiturn Limit Disagreement	When using a Direct Drive Servomotor, the setting of Pn205 (Multiturn Limit Setting) does not agree with the encoder.	Check the setting of Pn205.	Correct the setting of Pn205 (0 to 65,535).	*1
	The multiturn limit of the encoder is different from that of the SERVOPACK. Or, the multiturn limit of the SERVOPACK has been changed.	Check the setting of Pn205 in the SERVOPACK.	Change the setting if the alarm occurs.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.CF1: Reception Failed Error in Feedback Option Module Communications	The cable between the Serial Converter Unit and SERVOPACK is not wired correctly or there is a faulty contact.	Check the wiring of the external encoder.	Correctly wire the cable between the Serial Converter Unit and SERVOPACK.	*1
	A specified cable is not being used between Serial Converter Unit and SERVOPACK.	Check the wiring specifications of the external encoder.	Use a specified cable.	–
	The cable between the Serial Converter Unit and SERVOPACK is too long.	Measure the length of the cable that connects the Serial Converter Unit.	The length of the cable between the Serial Converter Unit and SERVOPACK must be 20 m or less.	–
	The sheath on cable between the Serial Converter Unit and SERVOPACK is broken.	Check the cable that connects the Serial Converter Unit.	Replace the cable between the Serial Converter Unit and SERVOPACK.	–
A.CF2: Timer Stopped Error in Feedback Option Module Communications	Noise entered the cable between the Serial Converter Unit and SERVOPACK.	–	Correct the wiring around the Serial Converter Unit, e.g., separate I/O signal lines from the Main Circuit Cables or ground.	–
	A failure occurred in the Serial Converter Unit.	–	Replace the Serial Converter Unit.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.d00: Position Deviation Overflow (The setting of Pn520 (Excessive Position Deviation Alarm Level) was exceeded by the position deviation while the servo was ON.)	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty contacts in the wiring for the Servomotor and encoder.	–
	The position command speed is too fast.	Reduce the position command speed and try operating the SERVOPACK.	Reduce the position reference speed or the reference acceleration rate, or reconsider the electronic gear ratio.	*1
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Reduce the acceleration of the position reference with one of the following methods. • Reduce the acceleration rate (ACC) and deceleration rate (DEC) in the program table. • Reduce the settings of Pn63E (Acceleration Rate) and Pn640 (Deceleration Rate).	*1
	The setting of Pn520 (Excessive Position Deviation Alarm Level) is too low for the operating conditions.	Check Pn520 (Excessive Position Deviation Alarm Level) to see if it is set to an appropriate value.	Optimize the setting of Pn520.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.d01: Position Deviation Overflow Alarm at Servo ON	The servo was turned ON after the position deviation exceeded the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON) while the servo was OFF.	Check the position deviation while the servo is OFF.	Optimize the setting of Pn526 (Excessive Position Deviation Alarm Level at Servo ON).	*1
A.d02: Position Deviation Overflow Alarm for Speed Limit at Servo ON	If position deviation remains in the deviation counter, the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON) limits the speed when the servo is turned ON. This alarm occurs if a position reference is input and the setting of Pn520 (Excessive Position Deviation Alarm Level) is exceeded.	–	Optimize the setting of Pn520 (Excessive Position Deviation Alarm Level). Or, adjust the setting of Pn529 or Pn584 (Speed Limit Level at Servo ON).	

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.d10: Motor-Load Position Deviation Overflow	The motor direction and external encoder installation orientation are backward.	Check the motor direction and the external encoder installation orientation.	Install the external encoder in the opposite direction, or change the setting of Pn002 = n.X□□□ (External Encoder Usage) to reverse the direction.	*1
	There is an error in the connection between the load (e.g., stage) and external encoder coupling.	Check the coupling of the external encoder.	Check the mechanical coupling.	–
A.d30: Position Data Overflow	The position data exceeded ±1,879,048,192.	Check the input reference pulse counter.	Reconsider the operating specifications.	–
A.E71: Safety Option Module Detection Failure	The connection between the SERVOPACK and the safety option module is faulty.	Check the connection between the SERVOPACK and the safety option module.	Correctly connect the safety option module.	–
	The safety option module was disconnected.	–	Execute Fn014 (Resetting configuration error of option module) using the digital operator or SigmaWin+ and turn the power supply OFF and then ON again.	*1
	A safety option module fault occurred.	–	Replace the safety option module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.E72: Feedback Option Module Detection Failure	There is a faulty connection between the SERVOPACK and the Feedback Option Module.	Check the connection between the SERVOPACK and the Feedback Option Module.	Correctly connect the Feedback Option Module.	–
	The Feedback Option Module was disconnected.	–	Reset the Option Module configuration error and turn the power supply to the SERVOPACK OFF and ON again.	*1
	A failure occurred in the Feedback Option Module.	–	Replace the Feedback Option Module.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.E74: Unsupported Safety Option Module	A safety option module fault occurred.	–	Replace the safety option module.	–
	A unsupported safety option module was connected.	–	Connect a compatible safety option module.	–
A.E75*3: Unsupported Feedback Option Module	A feedback option module fault occurred.	–	Replace the feedback option module.	–
	A unsupported feedback option module was connected.	Refer to the catalog of the connected feedback option module or the manual of the SERVOPACK.	Connect a compatible feedback option module.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
A.Eb1: Safety Function Signal Input Timing Error	The delay between activation of the /HWBB1 and /HWBB2 input signals for the HWBB was ten second or longer.	Measure the time delay between the /HWBB1 and /HWBB2 signals.	The output signal circuits or devices for /HWBB1 and /HWBB2 or the SERVOPACK input signal circuits may be faulty. Alternatively, the input signal cables may be disconnected. Check to see if any of these items are faulty or have been disconnected.	–
	A failure occurred in the SERVOPACK.	–	Replace the SERVOPACK.	–
A.EC8: Gate Drive Error 1 (An error occurred in the gate drive circuit.) A.EC9: Gate Drive Error 2 (An error occurred in the gate drive circuit.)	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.EF9: INDEXER Alarm	An alarm occurred in the INDEXER.	Use the SigmaWin+ to identify the INDEXER alarm.	Use the correction for the INDEXER alarm.	*1
A.F10: Power Supply Line Open Phase (The voltage was low for more than one second for phase R, S, or T when the main power supply was ON.)	The three-phase power supply wiring is not correct.	Check the power supply wiring.	Make sure that the power supply is correctly wired.	*1
	The three-phase power supply is unbalanced.	Measure the voltage for each phase of the three-phase power supply.	Balance the power supply by changing phases.	–
	A single-phase power supply was input without specifying a signal-phase AC power supply input (Pn00B = n.□1□□).	Check the power supply and the parameter setting.	Match the parameter setting to the power supply.	*1
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
FL-1*5: System Alarm FL-2*5: System Alarm FL-3*5: System Alarm FL-4*5: System Alarm FL-5*5: System Alarm FL-6*5: System Alarm	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Alarm Number: Alarm Name	Possible Cause	Confirmation	Correction	Reference
CPF00: Digital Operator Communications Error 1	There is a faulty contact between the Digital Operator and the SERVOPACK.	Check the connector contact.	Disconnect the connector and insert it again. Or, replace the cable.	–
	A malfunction was caused by noise.	–	Keep the Digital Operator or the cable away from sources of noise.	–
CPF01: Digital Operator Communications Error 2	A failure occurred in the Digital Operator.	–	Disconnect the Digital Operator and then connect it again. If an alarm still occurs, the Digital Operator may be faulty. Replace the Digital Operator.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

*2. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Pn533 [min}^{-1}\text{]} \times \frac{\text{Encoder resolution}}{6 \times 10^5} \leq \frac{\text{Pn20E}}{\text{Pn210}}$
- $\text{Maximum motor speed [min}^{-1}\text{]} \times \frac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \frac{\text{Pn20E}}{\text{Pn210}}$

*3. Detection Conditions
If either of the following conditions is detected, an alarm will occur.

- $\text{Rated motor speed [min}^{-1}\text{]} \times 1/3 \times \frac{\text{Encoder resolution}}{6 \times 10^5} \leq \frac{\text{Pn20E}}{\text{Pn210}}$
- $\text{Maximum motor speed [min}^{-1}\text{]} \times \frac{\text{Encoder resolution}}{\text{Approx. } 3.66 \times 10^{12}} \geq \frac{\text{Pn20E}}{\text{Pn210}}$

*4. Refer to the following manual for details.
Σ-7-Series AC Servo Drive Peripheral Device Selection Manual (Manual No.: SIEP S800001 32)

*5. These alarms are not stored in the alarm history. They are only displayed on the panel display.

3.5.4 INDEXER Alarm Displays and Troubleshooting

INDEXER alarms and corrections for them are given in the following table.

Error Number	Alarm Number	Alarm Name	Meaning	Corrective Action	Servomotor Stop Method	Alarm Reset
E12A	A.EF9	System Alarm	The firmware processing time was too long.	• Upgrade the firmware version. • Reduce the number of functions being used.	Gr.1	N/A
E13A	A.EF9	Firmware Version Unmatched	The SERVOPACK does not support this function, because the software version do not match.	• Upgrade the SERVOPACK software version. • Use the SERVOPACK that supports the corresponding function. • Use the SERVOPACK with the function set disabled.	Gr.1	N/A
E14A	A.EF9	Parameter Checksum Alarm (Detected only when control power supply is turned ON.)	Incorrect or corrupted parameters are stored in EEPROM. (This alarm can occur if the control power supply is turned OFF while the parameters are being initialized or changed.)	• Initialize the parameters. (Fn005) • If the problem is not solved, correct the parameters.	Gr.1	N/A
E15A	A.EF9	Parameter Version Unmatched (Detected only when the control power supply is turned ON.)	The combination of the firmware version number and the parameter version number is wrong.	• Change the firmware version. • Change the parameter version to match the firmware version.	Gr.1	N/A
E16A	A.EF9	Parameter Out-of-range Alarm (Detected only when control power supply is turned ON.)	The origin position (Pn63C) exceeded the position range (Pn638 and Pn63A) for rotational coordinates (Pn637 not set to n.□□□0).	Correct the origin setting (Pn63C) or the position range (Pn638 and Pn63A).	Gr.1	N/A

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Error Number	Alarm Number	Alarm Name	Meaning	Corrective Action	Servomotor Stop Method	Alarm Reset
E17A	A.C90 or A.040	Initial Communication Alarm between INDEXER Module and SERVOPACK (Detected only when control power supply is turned ON.)	• The INDEXER failed in parameter calculation during initial communications with the SERVOPACK when the control power was turned ON. This can happen in the following cases: • When a parameter has been changed while the encoder is not connected • When a parameter has been changed during occurrence of A.040 alarm	• Connect the encoder and then change the parameter. • Cancel the A.040 alarm and then change the parameter. (If the alarm display is other than A.E00, it can be reset by turning the power OFF and back ON.)	Gr.1	N/A
E19A	A.EF9	Program Table Checksum Alarm (Detected only when control power supply is turned ON.)	The program table stored in flash memory was not recorded properly. (This alarm can occur if the control power supply is turned OFF while the program table is being saved or initialized.)	• Initialize the program table. (Fn063) • If the problem is not solved, correct the program table.	Gr.1	Available*1
E1AA	A.EF9	Program Table Version Unmatched (Detected only when the control power is ON.)	The combination of the firmware version and the program table version is wrong.	• Change the firmware version. • Change the program table version to match the firmware version.	Gr.1	Available*1
E1BA	A.EF9	Program Out-of-range Alarm (Detected only when control power supply is turned ON.)	A value set in the program table is not within the allowed setting range.	• Change the firmware version. • Change the program table version to match the firmware version.	Gr.1	Available*1
E1CA	A.EF9	Zone Table Checksum Alarm (Detected only when control power supply is turned ON.)	The zone table stored in flash memory was not recorded properly. (This alarm can occur if the control power supply is turned OFF while the zone table is being saved or initialized.)	• Initialize the zone table. (Fn064) • If the problem is not solved, correct the zone table.	Gr.1	Available*2

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Error Number	Alarm Number	Alarm Name	Meaning	Corrective Action	Servo-motor Stop Method	Alarm Reset
E1DA	A.EF9	ZONE Table Version Unmatched (Detected only when the control power supply is turned ON.)	The combination of the firmware version and the ZONE table version is wrong.	• Change the firmware version. • Change the ZONE table version to match the firmware version.	Gr.1	Available*2
E1EA	A.EF9	Zone Table Out-of-range Alarm (Detected only when control power supply is turned ON.)	A value set in the zone table is not within the allowed setting range.	• Change the firmware version. • Change the ZONE table version to match the firmware version.	Gr.1	Available*2
E1FA	A.EF9	JOG Speed Table Checksum Alarm (Detected only when control power supply is turned ON.)	The JOG speed table stored in flash memory was not recorded properly. (This alarm can occur if the control power supply is turned OFF while the JOG speed table is being saved or initialized.)	• Initialize the JOG speed table. (Fn065) • If the problem is not solved, correct the JOG speed table.	Gr.1	Available*3
E21A	A.EF9	JOG Speed Table Version Unmatched (Detected only when the control power supply is turned ON.)	The combination of the firmware version and the JOG speed table version is wrong.	• Change the firmware version. • Change the JOG speed table version to match the firmware version.	Gr.1	Available*3
E22A	A.EF9	JOG Speed Table Out-of-range Alarm (Detected only when control power supply is turned ON.)	A value set in the JOG speed table is not within the allowed setting range.	• Change the firmware version. • Change the JOG speed table version to match the firmware version.	Gr.1	Available*3
E23A	A.EF9	Insufficient Registration Distance Alarm	The registration distance was shorter than the deceleration distance when the /RGRT signal went ON to start registration operation. (The current position will exceed the position specified by registration.)	Either increase the registration distance or reduce the deceleration distance (increase the deceleration rate). Registration distance: RDST in the program table Deceleration Rate: Pn640	Gr.1	Available

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Error Number	Alarm Number	Alarm Name	Meaning	Corrective Action	Servo-motor Stop Method	Alarm Reset
E24A	A.9F9	Homing Failure	The torque limit was cleared after torque was increased to the torque limit or before homing completed during pressing homing.	Change the setting value of Pn652 (Pressing Time for Pressing Homing).	Gr.1	Available
E25A	A.9F9	Homing Over-speed	Excessive position deviation due to a mechanical cause during homing.	Fix the mechanical cause and implement countermeasures to prevent excessive position deviation.	Gr.1	Available

*1. These alarms can be reset, but a Canceled Program Table Error (E44E) will occur the next time you attempt to start program table operation, so program table operation will not be possible.

*2. These alarms can be reset, but it is possible that the zone signals (POUT0 to POUT4) will be output incorrectly. When using the zone table, correct the zone table without resetting.

*3. These alarms can be reset, but a Canceled JOG Speed Table Error (E46E) will occur the next time you attempt to start JOG speed table operation, so JOG speed table operation will not be possible.

3.5.5 Warning Displays

Warnings are displayed to warn you before an alarm occurs. If a warning occurs in the SERVOPACK, the status is displayed as described below.

◆ Status Display

SERVOPACK Panel Display	The alarm number will be displayed. Refer to the following manual for details. 📖 Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)
Digital Operator	When a warning occurs, the warning code is displayed at the top left of the screen.
ALM Signal	No change
/WARN Signal	Turns ON.

3.5.6 List of Warnings

This section gives the warning names, warning meanings, and warning code outputs in order of the warning numbers.

Warning Number	Warning Name	Meaning	Warning Code Output		
			/ALO1	/ALO2	/ALO3
A.900	Position Deviation Overflow	The position deviation exceeded the percentage set with the following formula: (Pn520 × Pn51E/100)	H	H	H
A.901	Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)			
A.910	Overload	This warning occurs before an overload alarm (A.710 or A.720) occurs. If the warning is ignored and operation is continued, an alarm may occur.	L	H	H
A.911	Vibration	Abnormal vibration was detected during motor operation. The detection level is the same as A.520. Set whether to output an alarm or a warning by setting Pn310 (Vibration Detection Switch).			
A.912	Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature of the control PCB is abnormal.	H	L	H
A.913	Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature of the power PCB is abnormal.			
A.920	Regenerative Overload	This warning occurs before an A.320 alarm (Regenerative Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.			
A.921	Dynamic Brake Overload	This warning occurs before an A.731 alarm (Dynamic Brake Overload) occurs. If the warning is ignored and operation is continued, an alarm may occur.			
A.923	SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.			
A.930	Absolute Encoder Battery Error	This warning occurs when the voltage of absolute encoder's battery is low.	L	L	H

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Warning Number	Warning Name	Meaning	Warning Code Output		
			/ALO1	/ALO2	/ALO3
A.93B	Overheat Warning	The input voltage (temperature) for the overheat protection input (TH) signal exceeded the setting of Pn61C (Overheat Warning Level).	L	L	H
A.941	Change of Parameters Requires Restart	Parameters have been changed that require the power supply to be turned OFF and ON again.	H	H	L
A.942	Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	H	H	L
A.971	Undervoltage	This warning occurs before an A.410 alarm (Undervoltage) occurs. If the warning is ignored and operation is continued, an alarm may occur.	L	L	L
A.9A0	Overtravel	Overtravel was detected while the servo was ON.	H	L	L
A.9b0	Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	H	L	H
A.9F9	INDEXER Warning	A warning occurred in the INDEXER.	L	H	H

Note: 1. A warning code is not output unless you set Pn001 to n.1□□□ (Output both alarm codes and warning codes).

2. Use Pn008 = n.□X□□ (Warning Detection Selection) to control warning detection.
However, the following warnings are not affected by the setting of Pn008 = n.□X□□ and other parameter settings are required in addition to Pn008 = n.□X□□.

Warning	Parameters That Must Be Set to Select Warning Detection	Reference
A.911	Pn310 = n.□□□X (Vibration Detection Setting)	–
A.930	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection)	–
A.942	Pn423 = n.□□X□ (Speed Ripple Compensation Information Disagreement Warning Detection Selection)	–
A.971	Pn008 = n.□□□X (Low Battery Voltage Alarm/Warning Selection) (Not affected by the setting of Pn008 = n.□X□□.)	–
A.9A0	Pn00D = n.X□□□ (Overtravel Warning Detection Selection) (Not affected by the setting of Pn008 = n.□X□□.)	–
A.9b0	Pn00F = n.□□□X (Preventative Maintenance Selection)	–

3.5.7 Troubleshooting Warnings

The causes of and corrections for the warnings are given in the following table. Contact your Yaskawa representative if you cannot solve a problem with the correction given in the table.

Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.900: Position Deviation Overflow	The Servomotor U, V, and W wiring is not correct.	Check the wiring of the Servomotor's Main Circuit Cables.	Make sure that there are no faulty connections in the wiring for the Servomotor and encoder.	–
	A SERVOPACK gain is too low.	Check the SERVOPACK gains.	Increase the servo gain, e.g., by using autotuning without a host reference.	–
	The acceleration of the position reference is too high.	Reduce the reference acceleration and try operating the SERVOPACK.	Reduce the acceleration of the position reference with one of the following methods. • Reduce the acceleration rate (ACC) and deceleration rate (DEC) in the program table. • Reduce the settings of Pn63F (Acceleration Rate) and Pn640 (Deceleration Rate).	–
	The excessive position deviation alarm level (Pn520 × Pn51E/100) is too low for the operating conditions.	Check excessive position deviation alarm level (Pn520 × Pn51E/100) to see if it is set to an appropriate value.	Optimize the settings of Pn520 and Pn51E.	–
	A failure occurred in the SERVOPACK.	–	Turn the power supply to the SERVOPACK OFF and ON again. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.901: Position Deviation Overflow Alarm at Servo ON	The position deviation when the servo was turned ON exceeded the percentage set with the following formula: (Pn526 × Pn528/100)	–	Optimize the setting of Pn528 (Excessive Position Error Warning Level at Servo ON).	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.910: Overload (warning before an A.710 or A.720 alarm occurs)	The wiring is not correct or there is a faulty contact in the motor or encoder wiring.	Check the wiring.	Make sure that the Servomotor and encoder are correctly wired.	–
	Operation was performed that exceeded the overload protection characteristics.	Check the motor overload characteristics and Run command.	Reconsider the load and operating conditions. Or, increase the motor capacity.	–
	An excessive load was applied during operation because the Servomotor was not driven because of mechanical problems.	Check the operation reference and motor speed.	Remove the mechanical problem.	–
	The overload warning level (Pn52B) is not suitable.	Check that the overload warning level (Pn52B) is suitable.	Set a suitable overload warning level (Pn52B).	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.911: Vibration	Abnormal vibration was detected during motor operation.	Check for abnormal motor noise, and check the speed and torque waveforms during operation.	Reduce the motor speed. Or, reduce the servo gain with custom tuning.	–
	The setting of Pn103 (Moment of Inertia Ratio) is greater than the actual moment of inertia or was greatly changed.	Check the moment of inertia ratio or mass ratio.	Set Pn103 (Moment of Inertia Ratio) to an appropriate value.	–
	The vibration detection level (Pn312 or Pn384) is not suitable.	Check that the vibration detection level (Pn312 or Pn384) is suitable.	Set a suitable vibration detection level (Pn312 or Pn384).	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.912: Internal Temperature Warning 1 (Control Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	–
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.913: Internal Temperature Warning 2 (Power Board Temperature Error)	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat. Or, check the operating status with the SERVOPACK installation environment monitor.	Decrease the surrounding temperature by improving the SERVOPACK installation conditions.	–
	An overload alarm was reset by turning OFF the power supply too many times.	Check the alarm display to see if there is an overload alarm.	Change the method for resetting the alarm.	–
	There was an excessive load or operation was performed that exceeded the regenerative processing capacity.	Use the accumulated load ratio to check the load during operation, and use the regenerative load ratio to check the regenerative processing capacity.	Reconsider the load and operating conditions.	–
	The SERVOPACK installation orientation is not correct or there is insufficient space around the SERVOPACK.	Check the SERVOPACK installation conditions.	Install the SERVOPACK according to specifications.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.920: Regenerative Overload (warning before an A.320 alarm occurs)	The power supply voltage exceeded the specified range.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	There is insufficient external regenerative resistance, regenerative resistor capacity, or SERVOPACK capacity, or there has been a continuous regeneration state.	Check the operating conditions or the capacity using the SigmaJunmaSize+ Capacity Selection Software or another means.	Change the regenerative resistance value, regenerative resistance capacity, or SERVOPACK capacity. Reconsider the operating conditions using the SigmaJunmaSize+ Capacity Selection Software or other means.	–
	There was a continuous regeneration state because a negative load was continuously applied.	Check the load applied to the Servomotor during operation.	Reconsider the system including the servo, machine, and operating conditions.	–
A.921: Dynamic Brake Overload (warning before an A.731 alarm occurs)	The Servomotor was rotated by an external force.	Check the operation status.	Implement measures to ensure that the motor will not be rotated by an external force.	–
	When the Servomotor was stopped with the dynamic brake, the rotational or linear kinetic energy exceeded the capacity of the dynamic brake resistor.	Check the power consumed by the DB resistor to see how frequently the DB is being used.	Reconsider the following: • Reduce the Servomotor command speed. • Decrease the moment of inertia or mass. • Reduce the frequency of stopping with the dynamic brake.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.923: SERVOPACK Built-in Fan Stopped	The fan inside the SERVOPACK stopped.	Check for foreign matter inside the SERVOPACK.	Remove foreign matter from the SERVOPACK. If an alarm still occurs, the SERVOPACK may be faulty. Replace the SERVOPACK.	–
A.930: Absolute Encoder Battery Error (The absolute encoder battery voltage was lower than the specified level.) (Detected only when an absolute encoder is connected.)	The battery connection is faulty or a battery is not connected.	Check the battery connection.	Correct the battery connection.	–
	The battery voltage is lower than the specified value (2.7 V).	Measure the battery voltage.	Replace the battery.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.93B: Overheat Warning	The surrounding temperature is too high.	Check the surrounding temperature using a thermostat.	Lower the surrounding temperature by improving the installation conditions of the machine.	–
	Operation was performed under an excessive load.	Use the accumulated load ratio to check the load during operation.	Reconsider the load and operating conditions.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–
	The sensor attached to the machine is faulty.	–	The sensor attached to the machine may be faulty. Repair the sensor attached to the machine.	–
A.941: Change of Parameters Requires Restart	Parameters have been changed that require the power supply to be turned OFF and ON again.	–	Turn the power supply to the SERVOPACK OFF and ON again.	–
A.942: Speed Ripple Compensation Information Disagreement	The speed ripple compensation information stored in the encoder does not agree with the speed ripple compensation information stored in the SERVOPACK.	–	Reset the speed ripple compensation value on the SigmaWin+.	–
		–	Set Pn423 to n.□□1□ (Do not detect A.942 alarms). However, changing the setting may increase the speed ripple.	–
		–	Set Pn423 to n.□□□0 (Disable torque ripple compensation). However, changing the setting may increase the speed ripple.	–
A.971: Undervoltage	For a 200-V SERVOPACK, the AC power supply voltage dropped below 140 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	For a 100-V SERVOPACK, the AC power supply voltage dropped below 60 V.	Measure the power supply voltage.	Set the power supply voltage within the specified range.	–
	The power supply voltage dropped during operation.	Measure the power supply voltage.	Increase the power supply capacity.	–
	A momentary power interruption occurred.	Measure the power supply voltage.	If you have changed the setting of Pn509 (Momentary Power Interruption Hold Time), decrease the setting.	–
	The SERVOPACK fuse is blown out.	–	Replace the SERVOPACK and connect a reactor.	–
	A failure occurred in the SERVOPACK.	–	The SERVOPACK may be faulty. Replace the SERVOPACK.	–

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Warning Number: Warning Name	Possible Cause	Confirmation	Correction	Reference
A.9A0: Overtravel (Overtravel status was detected.)	Overtravel was detected while the servo was ON.	Check the status of the overtravel signals on the input signal monitor.	Even if an overtravel signal is not shown by the input signal monitor, momentary overtravel may have been detected. Take the following precautions. • Do not specify movements that would cause overtravel from the host controller. • Check the wiring of the overtravel signals. • Implement countermeasures against noise.	–
A.9b0: Preventative Maintenance Warning	One of the consumable parts has reached the end of its service life.	–	Replace the part. Contact your Yaskawa representative for replacement.	–
A.9F9: INDEXER Warning	A warning occurred in the INDEXER.	Use the SigmaWin+ to identify the INDEXER warning.	Use the correction for the INDEXER warning.	page 3-246

3.5.8 INDEXER Warning Displays and Troubleshooting

INDEXER warning displays and corrections for them are given in the following table.

Error No.	Alarm Number	Error Name	Meaning	Corrective Action
E41E	A.9F9	Program Table Save Failure Error	While writing data to the flash memory, a failure occurred during one of the following operation. • While saving a program table by using Fn060 • While initializing a program table by using Fn063	Repair the hardware.
E42E	A.9F9	Zone Table Save Failure Error	While writing data to the flash memory, a failure occurred during one of the following operation. • While saving a zone table by using Fn061 • While initializing a zone table by using Fn064	Repair the hardware.
E43E	A.9F9	JOG Speed Table Save Failure Error	While writing data to the flash memory, a failure occurred during one of the following operation. • While saving a JOG speed table by using Fn061 • While initializing a JOG speed table by using Fn065	Repair the hardware.
E44E	A.9F9	Canceled Program Table Error	There was a request to start program table operation even though an E19A or E1BA alarm occurred when the control power supply was turned ON.	Remove the cause of the alarm.
E46E	A.9F9	Canceled JOG Speed Table Error	There was a request to start JOG speed table operation even though an E1FA or E22A alarm occurred when the control power supply was turned ON.	Remove the cause of the alarm.
E4BE	A.9F9	Moving Disabled Error due to P-OT	Travel in the forward direction was requested when P-OT was in effect. (Forward movement is disabled when P-OT (forward overtravel) is in effect.)	• When P-OT is being used, move to a position where the P-OT is not in effect. • When P-OT is not being used, disable P-OT in the parameter.
E4CE	A.9F9	Moving Disabled Error due to N-OT	Travel in the reverse direction was requested when N-OT was in effect. (Reverse movement is disabled when N-OT (reverse overtravel) is in effect.)	• When N-OT is being used, move to a position where the N-OT is not in effect. • When N-OT is not being used, disable N-OT in the parameter.

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Error No.	Alarm Number	Error Name	Meaning	Corrective Action
E4DE	A.9F9	Moving Disabled Error due to P-LS	The specified target position exceeds the position reference of forward software limit set in Pn638.	• Check the target position specification. • Check the forward software limit in Pn638. • Check the Moving Mode (rotational/linear coordinates) (Pn637= n.□□□X) • If the software limits are not being used, select rotational coordinates with Pn637= n.□□□X (Moving Mode) or disable the software limits by setting Pn638 = Pn63A = 0.
E4EE	A.9F9	Moving Disabled Error due to N-LS	The specified target position exceeds the position reference of reverse software limit set in Pn63A.	• Check the target position specification. • Check the reverse software limit in Pn63A. • Check the setting of the Moving Mode (rotational/linear coordinates) (Pn637= n.□□□X). • If the software limits are not being used, select rotational coordinates for the (i.e., set Pn637 to n.□□□1) or disable the software limits by setting Pn638 = Pn63A = 0.
E4FE	A.9F9	Position Reference Out-of-range Error	The Moving Mode is set to rotational coordinates (i.e., Pn637 is not set to n.□□□0) and the target position designation exceeded the position range setting (Pn638 and Pn63A).	• Check the target position specification. • Check the positioning range set with Pn638 and Pn63A. • Check the setting of the Moving Mode (rotational/linear coordinates) (Pn637= n.□□□X).

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Error No.	Alarm Number	Error Name	Meaning	Corrective Action
E53E	A.9F9	Move Reference Duplication Error	There was a new move reference requested even though the system was already moving in a positioning or other traveling operation.	• Send the next move reference request only after the current movement is completed. • Also, STOP can be specified in the target position specification (POS) with the program table.
E54E	A.9F9	Servo ON Incomplete Error	The servo is not ON. There was a positioning request or other move reference request in servo OFF status. The servo went OFF during program table operation. (Program table operation will be interrupted while just the step that was being executed is canceled (If LOOP ≠ 1, the first LOOP is canceled.))	Request positioning and other operations after turning ON the servo by turning ON the /S-ON signal or setting the /S-ON signal to always be ON. Either just cancel the operation with the /PGMRES signal or turn ON the servo and restart with the /START-STOP signal.
			An E23A alarm (Insufficient Registration Distance Alarm) occurred.	Increase the registration distance or shorten the deceleration distance (i.e., increase the deceleration rate). Registration distance: RDST in the program table Deceleration rate: Pn640
E55E	A.9F9	Servo ON Failure Error	The servo could not be turned ON within 2 s of when the /S-ON signal turned ON. • The motor is rotating during servo ON execution. • The main power supply went OFF during servo ON execution. • Hard wire base block status (HWBB status) If there was already an alarm when a servo ON request made by turning ON the /S-ON signal is received, an E5BE error will occur instead. If the main power supply was OFF, an E5CE error will occur.	• Turn the servo ON when the motor is stopped. • Check the main power supply. • Turn ON the /HWBB1 and /HWBB2 signals. Then turn OFF the /S-ON signal to first turn OFF the servo and then turn ON the servo again.
E58E	A.9F9	Data Out-of-range Error	The specified setting was incorrect in a parameter or program table write command.	Check the setting.
E5DE	A.9F9	Origin Return Method Unspecified Error	The origin return method is not specified. Starting an origin return operation was requested by turning ON the /HOME signal without setting the origin return method.	Specify the origin return method with Pn642 = n.□□□X.

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Error No.	Alarm Number	Error Name	Meaning	Corrective Action
E5EE	A.9F9	Execution Disabled during Program Table Operation Error	• There was a request to execute a process that is not allowed during program table operation while program table operation was in progress or on hold. • There was an attempt to change the program table while program table operation was in progress or on hold.	Request execution of the process again after canceling program table operation by turning the /PGMRES signal ON.
E5FE	A.9F9	Session Conflict Error	There was a request that could not be executed at the same time as the function that was being executed. Example: There was a request to start program table operation while the program table was being initialized.	Execute the operation again after the execution of the current function is completed.
E63E	A.9F9	Continuous Stop Execution Disabled Error	An attempt was made to execute a continuous stop under conditions where it could not be executed. Examples: • The coordinates have been set to linear moving method. • The immediately-preceding table target position is not ±INFINITE. • The immediately-preceding table target position is ±INFINITE, but the registration distance is set. • A value other than 1 has been set for the execution count.	Execute a continuous stop under conditions where it can be executed.
E65E	A.9F9	Execution Error during Position Deviation Clear	Program table operation, JOG speed table operation, or homing was executed during position deviation clear.	Clear the status of position deviation clear.

3.5.9 Troubleshooting Based on the Operation and Conditions of the Servomotor

This section provides troubleshooting based on the operation and conditions of the Servomotor, including causes and corrections.

Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The control power supply is not turned ON.	Measure the voltage between control power supply terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the control power supply is turned ON.	–
	The main circuit power supply is not turned ON.	Measure the voltage across the main circuit power input terminals.	Turn OFF the power supply to the servo system. Correct the wiring so that the main circuit power supply is turned ON.	–
	The I/O signal connector (CN1) pins are not wired correctly or are disconnected.	Turn OFF the power supply to the servo system. Check the wiring condition of the I/O signal connector (CN1) pins.	Correct the wiring of the I/O signal connector (CN1) pins.	–
	The wiring for the Servomotor Main Circuit Cables or Encoder Cable is disconnected.	Check the wiring conditions.	Turn OFF the power supply to the servo system. Wire the cable correctly.	–
	There is an overload on the Servomotor.	Operate the Servomotor with no load and check the load status.	Turn OFF the power supply to the servo system. Reduce the load or replace the Servomotor with a Servomotor with a larger capacity.	–
	The type of encoder that is being used does not agree with the setting of Pn002 = n.□X□□ (Encoder Usage).	Check the type of the encoder that is being used and the setting of Pn002 = n.□X□□.	Set Pn002 = n.□X□□ according to the type of the encoder that is being used.	–
	Settings for input signals Pn630 to Pn64D are incorrect.	Check settings of input signals Pn630 to Pn64D.	Correct the settings of input signals Pn630 to Pn64D.	–
	The /S-ON (Servo ON) signal was not received.	Check the commands sent from the host controller.	Turn ON the /S-ON signal from the host controller.	–
	The P-OT (Forward Drive Prohibit) or N-OT (Reverse Drive Prohibit) signal is still OFF.	Check the P-OT and N-OT signals.	Turn ON the P-OT and N-OT signals.	–
	The current position of the servomotor is outside the software limit setting range.	Check for INDEXER errors.	Check the motor position and software limit setting (Pn638 and Pn63A), then move the servomotor into the software limit setting range.	–
	There is no position reference, or it is incorrect.	Check for INDEXER errors.	Set the program table correctly.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Does Not Start	The safety input signals (/HWBB1 or /HWBB2) were not turned ON.	Check the /HWBB1 and /HWBB2 input signals.	Turn ON the /HWBB1 and /HWBB2 input signals. If you are not using the safety function, connect the Safety Jumper Connector (provided as an accessory) to CN8.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Servomotor Moves Instantaneously, and Then Stops	There is a mistake in the Servomotor wiring.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Servomotor correctly.	–
	There is a mistake in the wiring of the encoder or Serial Converter Unit.	Turn OFF the power supply to the servo system. Check the wiring.	Wire the Serial Converter Unit correctly.	–
Servomotor Speed Is Unstable	There is a faulty connection in the Servomotor wiring.	Turn OFF the power supply to the servo system. The connector connections for the power line (U, V, and W phases) and the encoder or Serial Converter Unit may be unstable. Check the wiring.	Tighten any loose terminals or connectors and correct the wiring.	–
Servomotor Moves without a Reference Input	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Dynamic Brake Does Not Operate	The setting of Pn001 = n.□□□X (Servo OFF or Alarm Group 1 Stopping Method) is not suitable.	Check the setting of Pn001 = n.□□□X.	Set Pn001 = n.□□□X correctly.	–
	The dynamic brake resistor is disconnected.	Check the moment of inertia, motor speed, and dynamic brake frequency of use. If the moment of inertia, motor speed, or dynamic brake frequency of use is excessive, the dynamic brake resistance may be disconnected.	Turn OFF the power supply to the servo system. Replace the SERVOPACK. To prevent disconnection, reduce the load.	–
	There was a failure in the dynamic brake drive circuit.	–	Turn OFF the power supply to the servo system. There is a defective component in the dynamic brake circuit. Replace the SERVOPACK.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	The Servomotor vibrated considerably while performing the tuning-less function with the default settings.	Check the waveform of the motor speed.	Reduce the load so that the moment of inertia ratio or mass ratio is within the allowable value, or increase the load level or reduce the rigidity level in the tuning-less level settings.	–
	The machine mounting is not secure.	Turn OFF the power supply to the servo system. Check to see if there are any loose mounting screws.	Tighten the mounting screws.	–
		Turn OFF the power supply to the servo system. Check to see if there is misalignment in the coupling.	Align the coupling.	–
		Turn OFF the power supply to the servo system. Check to see if the coupling is balanced.	Balance the coupling.	–
	The bearings are defective.	Turn OFF the power supply to the servo system. Check for noise and vibration around the bearings.	Replace the Servomotor.	–
	There is a vibration source at the driven machine.	Turn OFF the power supply to the servo system. Check for any foreign matter, damage, or deformation in the machine's moving parts.	Consult with the machine manufacturer.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use shielded twisted-pair wire cables or screened twisted-pair cables with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Make sure that the rotary or Linear Encoder Cable satisfies the specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with a conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Abnormal Noise from Servomotor	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Check to see if there is noise interference on the signal line from the encoder.	Turn OFF the power supply to the servo system. Implement countermeasures against noise for the encoder wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Servomotor Vibrates at Frequency of Approx. 200 to 400 Hz.	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	–
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–
Large Motor Speed Overshoot on Starting and Stopping	The servo gains are not balanced.	Check to see if the servo gains have been correctly tuned.	Perform autotuning without a host reference.	–
	The setting of Pn100 (Speed Loop Gain) is too high.	Check the setting of Pn100. The default setting is Kv = 40.0 Hz.	Set Pn100 to an appropriate value.	–
	The setting of Pn102 (Position Loop Gain) is too high.	Check the setting of Pn102. The default setting is Kp = 40.0/s.	Set Pn102 to an appropriate value.	–
	The setting of Pn101 (Speed Loop Integral Time Constant) is not appropriate.	Check the setting of Pn101. The default setting is Ti = 20.0 ms.	Set Pn101 to an appropriate value.	–
	The setting of Pn103 (Moment of Inertia Ratio or Mass Ratio) is not appropriate.	Check the setting of Pn103.	Set Pn103 to an appropriate value.	–
	The torque reference is saturated.	Check the waveform of the torque reference.	Use the mode switch.	–
	The force limits (Pn483 and Pn484) are set to the default values.	The default values of the force limits and Pn483 = 30% and Pn484 = 30%.	Set Pn483 and Pn484 to appropriate values.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Absolute Encoder Position Deviation Error (The position that was saved in the host controller when the power was turned OFF is different from the position when the power was next turned ON.)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–
	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder or Serial Converter Unit wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	A failure occurred in the encoder.	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Overtravel Occurred	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal was input.	Check the external power supply (+24 V) voltage for the input signals.	Correct the external power supply (+24 V) voltage for the input signals.	–
		Check the operating condition of the overtravel limit switches.	Make sure that the overtravel limit switches operate correctly.	–
		Check the wiring of the overtravel limit switches.	Correct the wiring of the overtravel limit switches.	–
		Check the settings of PnB0F and PnB10.	Set the parameters to correct values.	–
	The P-OT/N-OT (Forward Drive Prohibit or Reverse Drive Prohibit) signal malfunctioned.	Check for fluctuation in the external power supply (+24 V) voltage for the input signals.	Eliminate fluctuation from the external power supply (+24 V) voltage for the input signals.	–
		Check to see if the operation of the overtravel limit switches is unstable.	Stabilize the operating condition of the overtravel limit switches.	–
		Check the wiring of the overtravel limit switches (e.g., check for cable damage and loose screws).	Correct the wiring of the overtravel limit switches.	–
	The selection of the Servomotor stopping method is not correct.	Check the servo OFF stopping method set in Pn001 = n.□□□X or PnB1F.	Select a Servomotor stopping method other than coasting to a stop.	–
Improper Stop Position for Overtravel (OT) Signal	The limit switch position and dog length are not appropriate.	–	Install the limit switch at the appropriate position.	–
	The overtravel limit switch position is too close for the coasting distance.	–	Install the overtravel limit switch at the appropriate position.	–
Position Deviation (without Alarm)	Noise interference occurred because of incorrect Encoder Cable specifications.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if is satisfies specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because the Encoder Cable is too long.	Turn OFF the power supply to the servo system. Check the length of the Encoder Cable.	Rotary Servomotors: The Encoder Cable length must be 50 m max.	–
	Noise interference occurred because the Encoder Cable is damaged.	Turn OFF the power supply to the servo system. Check the Encoder Cable to see if it is pinched or the sheath is damaged.	Replace the Encoder Cable and correct the cable installation environment.	–
	The Encoder Cable was subjected to excessive noise interference.	Turn OFF the power supply to the servo system. Check to see if the Encoder Cable is bundled with a high-current line or installed near a high-current line.	Correct the cable layout so that no surge is applied by high-current lines.	–
	There is variation in the FG potential because of the influence of machines on the Servomotor side, such as a welder.	Turn OFF the power supply to the servo system. Check to see if the machines are correctly grounded.	Properly ground the machines to separate them from the FG of the encoder.	–

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Problem	Possible Cause	Confirmation	Correction	Reference
Position Deviation (without Alarm)	There is a SERVOPACK pulse counting error due to noise.	Turn OFF the power supply to the servo system. Check to see if there is noise interference on the I/O signal line from the encoder or Serial Converter Unit.	Implement countermeasures against noise for the encoder wiring or Serial Converter Unit wiring.	–
	The encoder was subjected to excessive vibration or shock.	Turn OFF the power supply to the servo system. Check to see if vibration from the machine occurred. Check the Servomotor installation (mounting surface precision, securing state, and alignment).	Reduce machine vibration. Or, improve the mounting conditions of the Servomotor.	–
	The coupling between the machine and Servomotor is not suitable.	Turn OFF the power supply to the servo system. Check to see if position offset occurs at the coupling between machine and Servomotor.	Correctly secure the coupling between the machine and Servomotor.	–
	Noise interference occurred because of incorrect I/O signal cable specifications.	Turn OFF the power supply to the servo system. Check the I/O signal cables to see if they satisfy specifications. Use a shielded twisted-pair wire cable or a screened twisted-pair cable with conductors of at least 0.12 mm^2.	Use cables that satisfy the specifications.	–
	Noise interference occurred because an I/O signal cable is too long.	Turn OFF the power supply to the servo system. Check the lengths of the I/O signal cables.	The I/O signal cables must be no longer than 3 m.	–
	An encoder fault occurred. (The pulse count does not change.)	–	Turn OFF the power supply to the servo system. Replace the Servomotor.	–
	A failure occurred in the SERVOPACK.	–	Turn OFF the power supply to the servo system. Replace the SERVOPACK.	–
Servomotor Overheated	The surrounding air temperature is too high.	Measure the surrounding air temperature around the Servomotor.	Reduce the surrounding air temperature to 40°C or less.	–
	The surface of the Servomotor is dirty.	Turn OFF the power supply to the servo system. Visually check the surface for dirt.	Clean dirt, dust, and oil from the surface.	–
	There is an overload on the Servomotor.	Check the load status with a monitor.	If the Servomotor is overloaded, reduce the load or replace the Servo Drive with a SERVOPACK and Servomotor with larger capacities.	–
	Polarity detection was not performed correctly.	Check to see if electrical angle 2 (electrical angle from polarity origin) at any position is between ±10°.	Correct the settings for the polarity detection-related parameters.	–
Estimating the moment of inertia failed.	The acceleration rate is low and travel distance is short.	Check the Condition Setting Dialog Box used to perform moment of inertia estimation.	Increase the acceleration rate and travel distance.	

Parameter Lists

4

This chapter provides information on the parameters.

4.1 FT82 SERVOPACKs with Analog Voltage/Pulse Train References . . 4-2

4.2 FT82 SERVOPACK with MECHATROLINK-II Communications References . . 4-32

4.3 FT82 SERVOPACK with MECHATROLINK-III Communications References . . 4-67

4.3.1 List of Servo Parameters 4-67
4.3.2 List of MECHATROLINK-III Common Parameters 4-106

4.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules . . 4-114

4.5 FT83 SERVOPACKs with Analog Voltage/Pulse Train References . . 4-138

4.1 FT82 SERVOPACKs with Analog Voltage/Pulse Train References

The following table lists the parameters.

Note: Do not change the following parameters from their default settings.
- Reserved parameter
- Parameters not given in this manual
- Parameters that are not valid for the Servomotor that you are using, as given in the parameter table

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn000	2	Basic Function Selections 0	0000h to 10B1h	–	0000h	All	After restart	Setup	–

	Rotation Direction Selection		Reference
n.□□□X	0	Use CCW as the forward direction.	*1
	1	Use CW as the forward direction. (Reverse Rotation Mode)	

	Control Method Selection		Reference
n.□□X□	0	Speed control with analog references	*1
	1	Position control with pulse train references	
	2	Torque control with analog references	
	3	Internal set speed control with contact commands	
	4	Switching between internal set speed control with contact references and speed control with analog references	
	5	Switching between internal set speed control with contact references and position control with pulse train references	
	6	Switching between internal set speed control with contact references and torque control with analog references	
	7	Switching between position control with pulse train references and speed control with analog references	
	8	Switching between position control with pulse train references and torque control with analog references	
	9	Switching between torque control with analog references and speed control with analog references	
	A	Switching between speed control with analog references and speed control with zero clamping	
	B	Switching between position control with pulse train references and position control with reference pulse inhibition	

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn001	2	Application Function Selections 1	0000h to 1142h	–	0000h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Servo OFF and Group 1 Alarms		Reference
	0	Stop the motor by applying the dynamic brake.	*1
	1	Stop the motor by the applying dynamic brake and then release the dynamic brake.	
	2	Coast the motor to a stop without the dynamic brake.	

n.□□X□	Overtravel Stopping Method		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then servo-lock the motor.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A and then servo-lock the motor.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□X□□	Main Circuit Power Supply AC/DC Input Selection		Reference
	0	Input AC power as the main circuit power supply using the L1, L2, and L3 terminals (do not use shared converter).	*1
	1	Input DC power as the main circuit power supply using the B1/⊕ and ⊖ 2 terminals or the B1 and ⊖ 2 terminals (use an external converter or the shared converter).	

n.X□□□	Warning Code Output Selection		Reference
	0	Output only alarm codes on the ALO1, ALO2, and ALO3 terminals.	*1
	1	Output both warning codes and alarm codes on the ALO1, ALO2, and ALO3 terminals. However, while an warning code is being output, the ALM (Servo Alarm) output signal will remain ON (normal state).	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn002	2	Application Function Selections 2	0000h to 4213h	–	0000h	–	After restart	Setup	–

	Speed/Position Control Option (T-REF Input Allocation)		Applicable Motors	Reference
n.□□□X	0	Do not use T-REF.	All	–
	1	Use T-REF as an external torque limit input.		*1
	2	Use T-REF as a torque feedback input.		*1
	3	Use T-REF as an external torque limit input when /P-CL or /N-CL is ON.		*1

	Torque Control Option (V-REF Input Allocation)		Applicable Motors	Reference
n.□□X□	0	Do not use V-REF.	All	*1
	1	Use V-REF as an external speed limit input.		

	Encoder Usage		Applicable Motors	Reference
n.□X□□	0	Use the encoder according to encoder specifications.	All	*1
	1	Use the encoder as an incremental encoder.		
	2	Use the encoder as a single-turn absolute encoder.	Rotary	

	External Encoder Usage		Applicable Motors	Reference
n.X□□□	0	Do not use an external encoder.	Rotary	*1
	1	The external encoder moves in the forward direction for CCW motor rotation.		
	2	Reserved setting (Do not use.)		
	3	The external encoder moves in the reverse direction for CCW motor rotation.		
	4	Reserved setting (Do not use.)		

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn006	2	Application Function Selections 6	0000h to 105Fh	–	0002h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 1 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn007	2	Application Function Selections 7	0000h to 105Fh	–	0000h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 2 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn008	2	Application Function Selections 8	0000h to 7121h	–	0000h	Rotary	After restart	Setup	–

n.□□□X	Low Battery Voltage Alarm/Warning Selection		Reference
	0	Output alarm (A.830) for low battery voltage.	*1
	1	Output warning (A.930) for low battery voltage.	

n.□□X□	Function Selection for Undervoltage		Reference
	0	Do not detect undervoltage.	*1
	1	Detect undervoltage warning and limit torque at host controller.	
	2	Detect undervoltage warning and limit torque with Pn424 and Pn425 (i.e., only in SERVOPACK).	

n.□X□□	Warning Detection Selection		Reference
	0	Detect warnings.	*1
	1	Do not detect warnings except for A.971.	

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn009	2	Application Function Selections 9	0000h to 0121h	–	0010h	All	After restart	Tuning	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Current Control Mode Selection		Reference
	0	Use current control mode 1.	*1
	1	• SERVOPACK Models SGD7S-R70A, -R90A, -1R6A, -2R8A, -3R8A, -5R5A, and -7R6A: Use current control mode 1. • SERVOPACK Models SGD7S-120A, -180A, -200A, -330A, -470A, -550A, -590A, and -780A: Use current control mode 2.	
	2	Use current control mode 2.	

n.□X□□	Speed Detection Method Selection		Reference
	0	Use speed detection 1.	*1
	1	Use speed detection 2.	

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00A	2	Application Function Selections A	0000h to 0044h	–	0001h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Group 2 Alarms		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□□X□	Stopping Method for Forced Stops		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00B	2	Application Function Selections B	0000h to 1121h	–	0000h	All	After restart	Setup	–

n.□□□X	Operator Parameter Display Selection	Reference
	0 Display only setup parameters.	*1
	1 Display all parameters.	

n.□□X□	Motor Stopping Method for Group 2 Alarms	Reference
	0 Stop the motor by setting the speed reference to 0.	*1
	1 Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	
	2 Set the stopping method with Pn00A = n.□□□X.	

n.□X□□	Power Input Selection for Three-phase SERVOPACK	Reference
	0 Use a three-phase power supply input.	*1
	1 Use a three-phase power supply input as a single-phase power supply input.	

n.X□□□	Reserved parameter (Do not change.)

Pn00C	2	Application Function Selections C	0000h to 0131h	–	0000h	–	After restart	Setup	*1

n.□□□X	Function Selection for Test without a Motor	Applicable Motors
	0 Disable tests without a motor.	All
	1 Enable tests without a motor.	

n.□□X□	Encoder Resolution for Tests without a Motor	Applicable Motors
	0 Use 13 bits.	Rotary
	1 Use 20 bits.	
	2 Use 22 bits.	
	3 Use 24 bits.	

n.□X□□	Encoder Type Selection for Tests without a Motor	Applicable Motors
	0 Use an incremental encoder.	All
	1 Use an absolute encoder.	

n.X□□□	Reserved parameter (Do not change.)

Pn00D	2	Application Function Selections D	0000h to 1001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Overtravel Warning Detection Selection
	0 Do not detect overtravel warnings.
	1 Detect overtravel warnings.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00F	2	Application Function Selections F	0000h to 2011h	–	0000h	All	After restart	Setup	–

n.□□□X	Preventative Maintenance Warning Selection		Reference
	0	Do not detect preventative maintenance warnings.	*1
	1	Detect preventative maintenance warnings.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn010	2	Axis Address Selection for UART/USB Communications	0000h to 007Fh	–	0001h	All	After restart	Setup	–
Pn021	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn022	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn040	2	Reserved parameter (Do not change.)	–	–	0000h	–	–	–	–
Pn081	2	Application Function Selections 81	0000h to 1111h	–	0000h	All	After restart	Setup	*1

n.□□□X	Phase-C Pulse Output Selection		
	0	Output phase-C pulses only in the forward direction.	
	1	Output phase-C pulses in both the forward and reverse directions.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn100	2	Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn101	2	Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn102	2	Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn103	2	Moment of Inertia Ratio	0 to 20,000	1%	100	All	Immediately	Tuning	*1
Pn104	2	Second Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn105	2	Second Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn106	2	Second Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn109	2	Feedforward	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn10A	2	Feedforward Filter Time Constant	0 to 6,400	0.01 ms	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn10B	2	Gain Application Selections	0000h to 5334h	–	0000h	All	–	Setup	–

n.□□□X	Mode Switching Selection		When Enabled	Reference
	0	Use the internal torque reference as the condition (level setting: Pn10C).	Immediately	*1
	1	Use the speed reference as the condition (level setting: Pn10D).		
		Use the speed reference as the condition (level setting: Pn181).		
	2	Use the acceleration reference as the condition (level setting: Pn10E).		
		Use the acceleration reference as the condition (level setting: Pn182).		
	3	Use the position deviation as the condition (level setting: Pn10F).		
	4	Do not use mode switching.		

n.□□X□	Speed Loop Control Method		When Enabled	Reference
	0	PI control	After restart	*1
	1	I-P control		
	2 to 3	Reserved settings (Do not use.)		

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn10C	2	Mode Switching Level for Torque Reference	0 to 800	1%	200	All	Immediately	Tuning	*1
Pn10D	2	Mode Switching Level for Speed Reference	0 to 10,000	1 min^{-1}	0	Rotary	Immediately	Tuning	*1
Pn10E	2	Mode Switching Level for Acceleration	0 to 30,000	1 min^{-1}/s	0	Rotary	Immediately	Tuning	*1
Pn10F	2	Mode Switching Level for Position Deviation	0 to 10,000	1 reference unit	0	All	Immediately	Tuning	*1
Pn11F	2	Position Integral Time Constant	0 to 50,000	0.1 ms	0	All	Immediately	Tuning	*1
Pn121	2	Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn122	2	Second Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn123	2	Friction Compensation Coefficient	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn124	2	Friction Compensation Frequency Correction	-10,000 to 10,000	0.1 Hz	0	All	Immediately	Tuning	*1
Pn125	2	Friction Compensation Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn131	2	Gain Switching Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn132	2	Gain Switching Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn135	2	Gain Switching Waiting Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn136	2	Gain Switching Waiting Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn139	2	Automatic Gain Switching Selections 1	0000h to 0052h	–	0000h	All	Immediately	Tuning	*1

	Gain Switching Selection	
n.□□□X	0	Use manual gain switching. The gain is switched manually with the /G-SEL (Gain Selection) signal.
	1	Reserved setting (Do not use.)
	2	Use automatic gain switching pattern 1. The gain is switched automatically from the first gain to the second gain when switching condition A is satisfied. The gain is switched automatically from the second gain to the first gain when switching condition A is not satisfied.

	Gain Switching Condition A	
n.□□X□	0	/COIN (Positioning Completion Output) signal turns ON.
	1	/COIN (Positioning Completion Output) signal turns OFF.
	2	/NEAR (Near Output) signal turns ON.
	3	/NEAR (Near Output) signal turns OFF.
	4	Position reference filter output is 0 and reference pulse input is OFF.
	5	Position reference pulse input is ON.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn13D	2	Current Gain Level	100 to 2,000	1%	2000	All	Immediately	Tuning	*1
Pn140	2	Model Following Control-Related Selections	0000h to 1121h	–	0100h	All	Immediately	Tuning	–

	Model Following Control Selection		Reference
n.□□□X	0	Do not use model following control.	*1
	1	Use model following control.	

	Vibration Suppression Selection		Reference
n.□□X□	0	Do not perform vibration suppression.	*1
	1	Perform vibration suppression for a specific frequency.	
	2	Perform vibration suppression for two specific frequencies.	

	Vibration Suppression Adjustment Selection		Reference
n.□X□□	0	Do not adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

	Speed Feedforward (VFF)/Torque Feedforward (TFF) Selection		Reference
n.X□□□	0	Do not use model following control and speed/torque feedforward together.	*1
	1	Use model following control and speed/torque feedforward together.	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn141	2	Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn142	2	Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn143	2	Model Following Control Bias in the Forward Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn144	2	Model Following Control Bias in the Reverse Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn145	2	Vibration Suppression 1 Frequency A	10 to 2,500	0.1 Hz	500	All	Immediately	Tuning	*1
Pn146	2	Vibration Suppression 1 Frequency B	10 to 2,500	0.1 Hz	700	All	Immediately	Tuning	*1
Pn147	2	Model Following Control Speed Feedforward Compensation	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn148	2	Second Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn149	2	Second Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn14A	2	Vibration Suppression 2 Frequency	10 to 2,000	0.1 Hz	800	All	Immediately	Tuning	*1
Pn14B	2	Vibration Suppression 2 Correction	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn14F	2	Control-Related Selections	0000h to 0021h	–	0021h	All	After restart	Tuning	–

	Model Following Control Type Selection		Reference
n.□□□X	0	Use model following control type 1.	*1
	1	Use model following control type 2.	

	Tuning-less Type Selection		Reference
n.□□X□	0	Use tuning-less type 1.	*1
	1	Use tuning-less type 2.	
	2	Use tuning-less type 3.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn160	2	Anti-Resonance Control-Related Selections	0000h to 0011h	–	0010h	All	Immediately	Tuning	–

	Anti-Resonance Control Selection		Reference
n.□□□X	0	Do not use anti-resonance control.	*1
	1	Use anti-resonance control.	

	Anti-Resonance Control Adjustment Selection		Reference
n.□□X□	0	Do not adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn161	2	Anti-Resonance Frequency	10 to 20,000	0.1 Hz	1000	All	Immediately	Tuning	*1
Pn162	2	Anti-Resonance Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn163	2	Anti-Resonance Damping Gain	0 to 300	1%	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn164	2	Anti-Resonance Filter Time Constant 1 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn165	2	Anti-Resonance Filter Time Constant 2 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn166	2	Anti-Resonance Damping Gain 2	0 to 1,000	1%	0	All	Immediately	Tuning	*1
Pn170	2	Tuning-less Function-Related Selections	0000h to 2711h	–	1401h	All	–	Setup	*1

n.□□□X	Tuning-less Selection		When Enabled
	0	Disable tuning-less function.	After restart
	1	Enable tuning-less function.	

n.□□X□	Speed Control Method		When Enabled
	0	Use for speed control.	After restart
	1	Use for speed control and use host controller for position control.	

n.□X□□	Rigidity Level		When Enabled
	0 to 7	Set the rigidity level.	Immediately

n.X□□□	Tuning-less Load Level		When Enabled
	0 to 2	Set the load level for the tuning-less function.	Immediately

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn200	2	Position Control Reference For Selections	0000h to 2236h	–	0000h	All	After restart	Setup	–

n.□□□X	Reference Pulse Form		Reference
	0	Sign and pulse train, positive logic.	*1
	1	CW and CCW pulse trains, positive logic	
	2	Two-phase pulse trains with 90° phase differential (phase A and phase B) ×1, positive logic	
	3	Two-phase pulse trains with 90° phase differential (phase A and phase B) ×2, positive logic	
	4	Two-phase pulse trains with 90° phase differential (phase A and phase B) ×4, positive logic	
	5	Sign and pulse train, negative logic.	
	6	CW and CCW pulse trains, negative logic	

n.□□X□	Clear Signal Form		Reference
	0	Clear position deviation when the signal is at high level.	*1
	1	Clear position deviation on the rising edge of the signal.	
	2	Clear position deviation when the signal is at low level.	
	3	Clear position deviation on the falling edge of the signal.	

n.□X□□	Clear Operation		Reference
	0	Clear position deviation at a base block (at servo OFF or when alarm occurs).	*1
	1	Do not clear position error (cleared only with CLR (Clear Position Deviation) signal).	
	2	Clear position deviation when an alarm occurs.	

n.X□□□	Filter Selection		Reference
	0	Use the reference input filter for a line-driver signal. (1 Mpps max.)	*1
	1	Use the reference input filter for an open-collector signal. (200 kpps max.)	
	2	Use reference input filter 2 for a line-driver signal. (1 to 4 Mpps)	

Pn205	2	Multiturn Limit	0 to 65,535	1 rev	65535	Rotary	After restart	Setup	*1

Pn207	2	Position Control Function Selections	0000h to 2210h	–	0000h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Position Control Option		Reference
	0	Do not use V-REF.	*1
	1	Use V-REF as a speed feedback input.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	/COIN (Positioning Completion Output) Signal Output Timing		Reference
	0	Output when the absolute value of the position deviation is the same or less than the setting of Pn522 (Positioning Completed Width).	*1
	1	Output when the absolute value of the position error is the same or less than the setting of Pn522 (Positioning Completed Width) and the reference after the position reference filter is 0.	
	2	Output when the absolute value of the position error is the same or less than the setting of Pn522 (Positioning Completed Width) and the reference input is 0.	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn20A	4	Number of External Encoder Scale Pitches	4 to 1,048,576	1 scale pitch/revolution	32768	Rotary	After restart	Setup	*1
Pn20E	4	Electronic Gear Ratio (Numerator)	1 to 1,073,741,824	1	64	All	After restart	Setup	*1
Pn210	4	Electronic Gear Ratio (Denominator)	1 to 1,073,741,824	1	1	All	After restart	Setup	*1
Pn212	4	Number of Encoder Output Pulses	16 to 1,073,741,824	1 P/Rev	2048	Rotary	After restart	Setup	*1
Pn216	2	Position Reference Acceleration/Deceleration Time Constant	0 to 65,535	0.1 ms	0	All	Immediately after the motor stops	Setup	*1
Pn217	2	Average Position Reference Movement Time	0 to 10,000	0.1 ms	0	All	Immediately after the motor stops	Setup	*1
Pn218	2	Reference Pulse Input Multiplier	1 to 100	× 1	1	All	Immediately	Setup	*1
Pn22A	2	Fully-closed Control Selections	0000h to 1003h	–	0000h	Rotary	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)	
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Fully-closed Control Speed Feedback Selection	
	0	Use motor encoder speed.
	1	Use external encoder speed.

Pn281	2	Encoder Output Resolution	1 to 4,096	1 edge/pitch	20	All	After restart	Setup	*1
Pn300	2	Speed Reference Input Gain	150 to 3,000	0.01 V/Rated motor speed	600	All	Immediately	Setup	*1
Pn301	2	Internal Set Speed 1	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	100	Rotary	Immediately	Setup	*1
Pn302	2	Internal Set Speed 2	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	200	Rotary	Immediately	Setup	*1
Pn303	2	Internal Set Speed 3	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	300	Rotary	Immediately	Setup	*1
Pn304	2	Jogging Speed	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn305	2	Soft Start Acceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn306	2	Soft Start Deceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn307	2	Speed Reference Filter Time Constant	0 to 65,535	0.01 ms	40	All	Immediately	Setup	*1
Pn308	2	Speed Feedback Filter Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1
Pn30A	2	Deceleration Time for Servo OFF and Forced Stops	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn30C	2	Speed Feedforward Average Movement Time	0 to 5,100	0.1 ms	0	All	Immediately	Setup	*1
Pn310	2	Vibration Detection Selections	0000h to 0002h	–	0000h	All	Immediately	Setup	*1

	Vibration Detection Selection	
n.□□□X	0	Do not detect vibration.
	1	Output a warning (A.911) if vibration is detected.
	2	Output an alarm (A.520) if vibration is detected.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn311	2	Vibration Detection Sensitivity	50 to 500	1%	100	All	Immediately	Tuning	*1
Pn312	2	Vibration Detection Level	0 to 5,000	1 min^{-1}	50	Rotary	Immediately	Tuning	*1
Pn316	2	Maximum Motor Speed	0 to 65,535	1 min^{-1}	10000	Rotary	After restart	Setup	*1
Pn324	2	Moment of Inertia Calculation Starting Level	0 to 20,000	1%	300	All	Immediately	Setup	*1
Pn400	2	Torque Reference Input Gain	10 to 100	0.1 V/rated torque	30	All	Immediately	Setup	*1
Pn401	2	First Stage First Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1
Pn402	2	Forward Torque Limit	0 to 800	1%*2	800	Rotary	Immediately	Setup	*1
Pn403	2	Reverse Torque Limit	0 to 800	1%*2	800	Rotary	Immediately	Setup	*1
Pn404	2	Forward External Torque Limit	0 to 800	1%*2	100	All	Immediately	Setup	*1
Pn405	2	Reverse External Torque Limit	0 to 800	1%*2	100	All	Immediately	Setup	*1
Pn406	2	Emergency Stop Torque	0 to 800	1%*2	800	All	Immediately	Setup	*1
Pn407	2	Speed Limit during Torque Control	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn408	2	Torque-Related Function Selections	0000h to 1111h	–	0000h	All	–	Setup	–

n.□□□X	Notch Filter Selection 1		When Enabled	Reference
	0	Disable first stage notch filter.	Immediately	*1
	1	Enable first stage notch filter.		

n.□□X□	Speed Limit Selection		When Enabled	Reference
	0	Use the smaller of the maximum motor speed and the setting of Pn407 as the speed limit.	After restart	*1
		Use the smaller of the maximum motor speed and the setting of Pn480 as the speed limit.		
	1	Use the smaller of the overspeed alarm detection speed and the setting of Pn407 as the speed limit.		
		Use the smaller of the overspeed alarm detection speed and the setting of Pn480 as the speed limit.		

n.□X□□	Notch Filter Selection 2		When Enabled	Reference
	0	Disable second stage notch filter.	Immediately	*1
	1	Enable second stage notch filter.		

n.X□□□	Friction Compensation Function Selection		When Enabled	Reference
	0	Disable friction compensation.	Immediately	*1
	1	Enable friction compensation.		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn409	2	First Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40A	2	First Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40B	2	First Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40C	2	Second Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40D	2	Second Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40E	2	Second Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40F	2	Second Stage Second Torque Reference Filter Frequency	100 to 5,000	1 Hz	4000	All	Immediately	Tuning	*1
Pn410	2	Second Stage Second Torque Reference Filter Q Value	50 to 100	0.01	50	All	Immediately	Tuning	*1
Pn412	2	First Stage Second Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1
Pn415	2	T-REF Filter Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn416	2	Torque-Related Function Selections 2	0000h to 1111h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Notch Filter Selection 3	
	0	Disable third stage notch filter.
	1	Enable third stage notch filter.

n.□□X□	Notch Filter Selection 4	
	0	Disable fourth stage notch filter.
	1	Enable fourth stage notch filter.

n.□X□□	Notch Filter Selection 5	
	0	Disable fifth stage notch filter.
	1	Enable fifth stage notch filter.

n.X□□□	Reserved parameter (Do not change.)

Pn417	2	Third Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn418	2	Third Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn419	2	Third Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41A	2	Fourth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41B	2	Fourth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41C	2	Fourth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41D	2	Fifth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41E	2	Fifth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41F	2	Fifth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn423	2	Speed Ripple Compensation Selections	0000h to 1111h	–	0000h	Rotary	–	Setup	*1

n.□□□X	Speed Ripple Compensation Function Selection		When Enabled
	0	Disable speed ripple compensation.	Immediately
	1	Enable speed ripple compensation.	

n.□□X□	Speed Ripple Compensation Information Disagreement Warning Detection Selection		When Enabled
	0	Detect A.942 alarms.	After restart
	1	Do not detect A.942 alarms.	

n.□X□□	Speed Ripple Compensation Enable Condition Selection		When Enabled
	0	Speed reference	After restart
	1	Motor speed	

n.X□□□	Reserved parameter (Do not change.)

Pn424	2	Torque Limit at Main Circuit Voltage Drop	0 to 100	1%*2	50	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn425	2	Release Time for Torque Limit at Main Circuit Voltage Drop	0 to 1,000	1 ms	100	All	Immediately	Setup	*1
Pn426	2	Torque Feedforward Average Movement Time	0 to 5,100	0.1 ms	0	All	Immediately	Setup	*1
Pn427	2	Speed Ripple Compensation Enable Speed	0 to 10,000	1 min^{-1}	0	Rotary Servomotor	Immediately	Tuning	*1
Pn456	2	Sweep Torque Reference Amplitude	1 to 800	1%	15	All	Immediately	Tuning	*1
Pn460	2	Notch Filter Adjustment Selections 1	0000h to 0101h	–	0101h	All	Immediately	Tuning	*1

n.□□□X	Notch Filter Adjustment Selection 1	
	0	Do not adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Notch Filter Adjustment Selection 2	
	0	Do not adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn475	2	Gravity Compensation-Related Selections	0000h to 0001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Gravity Compensation Selection	
	0	Disable gravity compensation.
	1	Enable gravity compensation.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn476	2	Gravity Compensation Torque	-1,000 to 1,000	0.1%	0	All	Immediately	Tuning	*1
Pn501	2	Zero Clamping Level	0 to 10,000	1 min^{-1}	10	Rotary	Immediately	Setup	*1
Pn502	2	Rotation Detection Level	1 to 10,000	1 min^{-1}	20	Rotary	Immediately	Setup	*1
Pn503	2	Speed Coincidence Detection Signal Output Width	0 to 100	1 min^{-1}	10	Rotary	Immediately	Setup	*1
Pn506	2	Brake Reference-Servo OFF Delay Time	0 to 50	10 ms	0	All	Immediately	Setup	*1
Pn507	2	Brake Reference Output Speed Level	0 to 10,000	1 min^{-1}	100	Rotary	Immediately	Setup	*1
Pn508	2	Servo OFF-Brake Command Waiting Time	10 to 100	10 ms	50	All	Immediately	Setup	*1
Pn509	2	Momentary Power Interruption Hold Time	20 to 50,000	1 ms	20	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50A	2	Input Signal Selections 1	0000h to FFF2h	–	2100h	All	After restart	Setup	–

n.□□□X	Input Signal Allocation Mode		Reference
	0	Use the sequence input signal terminals with the default allocations.	*1
	1	Change the sequence input signal allocations.	
	2	Reserved setting (Do not use.)	

n.□□X□	/S-ON (Servo ON) Signal Allocation		Reference
	0	Active when CN1-40 input signal is ON (closed).	*1
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

n.□X□□	/P-CON (Proportional Control) Signal Allocation		Reference
	0 to F	The allocations are the same as the /S-ON (Servo ON) signal allocations.	*1

n.X□□□	P-OT (Forward Drive Prohibit) Signal Allocation		Reference
	0	Enable forward drive when CN1-40 input signal is ON (closed).	*1
	1	Enable forward drive when CN1-41 input signal is ON (closed).	
	2	Enable forward drive when CN1-42 input signal is ON (closed).	
	3	Enable forward drive when CN1-43 input signal is ON (closed).	
	4	Enable forward drive when CN1-44 input signal is ON (closed).	
	5	Enable forward drive when CN1-45 input signal is ON (closed).	
	6	Enable forward drive when CN1-46 input signal is ON (closed).	
	7	Set the signal to always prohibit forward drive.	
	8	Set the signal to always enable forward drive.	
	9	Enable forward drive when CN1-40 input signal is OFF (open).	
	A	Enable forward drive when CN1-41 input signal is OFF (open).	
	B	Enable forward drive when CN1-42 input signal is OFF (open).	
	C	Enable forward drive when CN1-43 input signal is OFF (open).	
	D	Enable forward drive when CN1-44 input signal is OFF (open).	
	E	Enable forward drive when CN1-45 input signal is OFF (open).	
	F	Enable forward drive when CN1-46 input signal is OFF (open).	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
Pn50B	2	Input Signal Selections 2	0000h to FFFFh	–	6543h	All	After restart	Setup	–

	N-OT (Reverse Drive Prohibit) Signal Allocation		Reference
n.□□□X	0	Enable reverse drive when CN1-40 input signal is ON (closed).	*1
	1	Enable reverse drive when CN1-41 input signal is ON (closed).	
	2	Enable reverse drive when CN1-42 input signal is ON (closed).	
	3	Enable reverse drive when CN1-43 input signal is ON (closed).	
	4	Enable reverse drive when CN1-44 input signal is ON (closed).	
	5	Enable reverse drive when CN1-45 input signal is ON (closed).	
	6	Enable reverse drive when CN1-46 input signal is ON (closed).	
	7	Set the signal to always prohibit reverse drive.	
	8	Set the signal to always enable reverse drive.	
	9	Enable reverse drive when CN1-40 input signal is OFF (open).	
	A	Enable reverse drive when CN1-41 input signal is OFF (open).	
	B	Enable reverse drive when CN1-42 input signal is OFF (open).	
	C	Enable reverse drive when CN1-43 input signal is OFF (open).	
	D	Enable reverse drive when CN1-44 input signal is OFF (open).	
	E	Enable reverse drive when CN1-45 input signal is OFF (open).	
	F	Enable reverse drive when CN1-46 input signal is OFF (open).	

	/ALM-RST (Alarm Reset) Signal Allocation		Reference
n.□□X□	0	Active on signal edge when CN1-40 input signal changes from OFF (open) to ON (closed).	*1
	1	Active on signal edge when CN1-41 input signal changes from OFF (open) to ON (closed).	
	2	Active on signal edge when CN1-42 input signal changes from OFF (open) to ON (closed).	
	3	Active on signal edge when CN1-43 input signal changes from OFF (open) to ON (closed).	
	4	Active on signal edge when CN1-44 input signal changes from OFF (open) to ON (closed).	
	5	Active on signal edge when CN1-45 input signal changes from OFF (open) to ON (closed).	
	6	Active on signal edge when CN1-46 input signal changes from OFF (open) to ON (closed).	
	7	Reserved setting (Do not use.)	
	8	The signal is always inactive.	
	9	Active on signal edge when CN1-40 input signal changes from ON (closed) to OFF (open).	
	A	Active on signal edge when CN1-41 input signal changes from ON (closed) to OFF (open).	
	B	Active on signal edge when CN1-42 input signal changes from ON (closed) to OFF (open).	
	C	Active on signal edge when CN1-43 input signal changes from ON (closed) to OFF (open).	
	D	Active on signal edge when CN1-44 input signal changes from ON (closed) to OFF (open).	
	E	Active on signal edge when CN1-45 input signal changes from ON (closed) to OFF (open).	
	F	Active on signal edge when CN1-46 input signal changes from ON (closed) to OFF (open).	

	/P-CL (Forward External Torque Limit Input) Signal Allocation		Reference
n.□X□□	0 to F	The allocations are the same as the /S-ON (Servo ON) signal allocations.	*1

	/N-CL (Reverse External Torque Limit Input) Signal Allocation		Reference
n.X□□□	0 to F	The allocations are the same as the /S-ON (Servo ON) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50C	2	Input Signal Selections 3	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	/SPD-D (Motor Direction) Signal Allocation		Reference
n.□□□X	0	Active when CN1-40 input signal is ON (closed).	*1
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

	/SPD-A (Internal Set Speed Selection Input) Signal Allocation		Reference
n.□□X□	0 to F	The allocations are the same as the /SPD-D (Motor Direction) signal allocations.	*1

	/SPD-B (Internal Set Speed Selection Input) Signal Allocation		Reference
n.□X□□	0 to F	The allocations are the same as the /SPD-D (Motor Direction) signal allocations.	*1

	/C-SEL (Control Selection Input) Signal Allocation		Reference
n.X□□□	0 to F	The allocations are the same as the /SPD-D (Motor Direction) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50D	2	Input Signal Selections 4	0000h to FFFFh	–	8888h	–	After restart	Setup	–

	/ZCLAMP (Zero Clamping Input) Signal Allocation		Applicable Motors	Reference
n.□□□X	0	Active when CN1-40 input signal is ON (closed).	All	*1
	1	Active when CN1-41 input signal is ON (closed).		
	2	Active when CN1-42 input signal is ON (closed).		
	3	Active when CN1-43 input signal is ON (closed).		
	4	Active when CN1-44 input signal is ON (closed).		
	5	Active when CN1-45 input signal is ON (closed).		
	6	Active when CN1-46 input signal is ON (closed).		
	7	The signal is always active.		
	8	The signal is always inactive.		
	9	Active when CN1-40 input signal is OFF (open).		
	A	Active when CN1-41 input signal is OFF (open).		
	B	Active when CN1-42 input signal is OFF (open).		
	C	Active when CN1-43 input signal is OFF (open).		
	D	Active when CN1-44 input signal is OFF (open).		
	E	Active when CN1-45 input signal is OFF (open).		
	F	Active when CN1-46 input signal is OFF (open).		

n.□□X□	/INHIBIT (Reference Pulse Inhibit Input) Signal Allocation		Applicable Motors	Reference
	0 to F	The allocations are the same as the /ZCLAMP (Zero Clamping Input) signal allocations.	All	*1

n.□X□□	/G-SEL (Gain Selection Input) Signal Allocation		Applicable Motors	Reference
	0 to F	The allocations are the same as the /ZCLAMP (Zero Clamping Input) signal allocations.	All	*1

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50E	2	Output Signal Selections 1	0000h to 6666h	–	3211h	All	After restart	Setup	–

n.□□□X	/COIN (Positioning Completion Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

n.□□X□	/V-CMP (Speed Coincidence Detection Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

n.□X□□	/TGON (Rotation Detection Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

n.X□□□	/S-RDY (Servo Ready) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

Pn50F	2	Output Signal Selections 2	0000h to 6666h	–	0000h	All	After restart	Setup	–

n.□□□X	/CLT (Torque Limit Detection Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

n.□□X□	/VLT (Speed Limit Detection) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

n.□X□□	/BK (Brake Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

n.X□□□	/WARN (Warning Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn510	2	Output Signal Selections 3	0000h to 0666h	–	0000h	All	After restart	Setup	–

n.□□□X	/NEAR (Near Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	/PSELA (Reference Pulse Input Multiplication Switching Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /NEAR (Near) signal allocations.	*1

n.X□□□	Reserved parameter (Do not change.)

Pn512	2	Output Signal Inverse Settings	0000h to 1111h	–	0000h	All	After restart	Setup	*1

n.□□□X	Output Signal Inversion for CN1-25 and CN1-26 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□□X□	Output Signal Inversion for CN1-27 and CN1-28 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□X□□	Output Signal Inversion for CN1-29 and CN1-30 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.X□□□	Output Signal Inversion for CN1-37 Terminal	
	0	The signal is not inverted.
	1	The signal is inverted.

Pn513	2	Output Signal Inverse Settings 2	0000h to 0011h	–	0000h	All	After restart	Setup	*1

n.□□□X	Output Signal Inversion for CN1-38 Terminal	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□□X□	Output Signal Inversion for CN1-39 Terminal	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn514	2	Output Signal Selections 4	0000h to 0666h	–	0000h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)
n.□□X□	Reserved parameter (Do not change.)

	/PM (Preventative Maintenance Output) Signal Allocation		Reference
n.□X□□	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn515	2	Input Signal Selections 6	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	SEN (Absolute Data Request Input) Signal Allocation		Reference
n.□□□X	0	Active when CN1-40 input signal is ON (closed).	*1
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	Enable when 5 V is input to CN1-4.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

	/PSEL (Reference Pulse Input Multiplication Switching Input) Signal Allocation		Reference
n.□□X□	0	Active when CN1-40 input signal is ON (closed).	*1
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always enabled.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn516	2	Input Signal Selections 7	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	FSTP (Forced Stop Input) Signal Allocation		Reference
n.□□□X	0	Enable drive when CN1-40 input signal is ON (closed).	*1
	1	Enable drive when CN1-41 input signal is ON (closed).	
	2	Enable drive when CN1-42 input signal is ON (closed).	
	3	Enable drive when CN1-43 input signal is ON (closed).	
	4	Enable drive when CN1-44 input signal is ON (closed).	
	5	Enable drive when CN1-45 input signal is ON (closed).	
	6	Enable drive when CN1-46 input signal is ON (closed).	
	7	Set the signal to always prohibit drive (always force the motor to stop).	
	8	Set the signal to always enable drive (always disable forcing the motor to stop).	
	9	Enable drive when CN1-40 input signal is OFF (open).	
	A	Enable drive when CN1-41 input signal is OFF (open).	
	B	Enable drive when CN1-42 input signal is OFF (open).	
	C	Enable drive when CN1-43 input signal is OFF (open).	
	D	Enable drive when CN1-44 input signal is OFF (open).	
	E	Enable drive when CN1-45 input signal is OFF (open).	
	F	Enable drive when CN1-46 input signal is OFF (open).	

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn517	2	Output Signal Selections 5	0000h to 0666h	–	0654h	All	After restart	Setup	*1

	ALO1 (Alarm Code Output) Signal Allocation	
n.□□□X	0	Disabled (the above signal output is not used).
	1	Output the signal from the CN1-25 or CN1-26 output terminal.
	2	Output the signal from the CN1-27 or CN1-28 output terminal.
	3	Output the signal from the CN1-29 or CN1-30 output terminal.
	4	Output the signal from the CN1-37 output terminal.
	5	Output the signal from the CN1-38 output terminal.
	6	Output the signal from the CN1-39 output terminal.

	ALO2 (Alarm Code Output) Signal Allocation	
n.□□X□	0 to 6	The allocations are the same as the ALO1 (Alarm Code Output) signal allocations.

	ALO3 (Alarm Code Output) Signal Allocation	
n.□X□□	0 to 6	The allocations are the same as the ALO1 (Alarm Code Output) signal allocations.

n.X□□□	Reserved parameter (Do not change.)

Pn518*3	–	Safety Module-Related Parameters	–	–	–	All	–	–	–

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn51B	4	Motor-Load Position Deviation Overflow Detection Level	0 to 1,073,741,824	1 reference unit	1000	Rotary	Immediately	Setup	*1
Pn51E	2	Position Deviation Overflow Warning Level	10 to 100	1%	100	All	Immediately	Setup	*1
Pn520	4	Position Deviation Overflow Alarm Level	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn522	4	Positioning Completed Width	0 to 1,073,741,824	1 reference unit	7	All	Immediately	Setup	*1
Pn524	4	Near Signal Width	1 to 1,073,741,824	1 reference unit	1073741824	All	Immediately	Setup	*1
Pn526	4	Position Deviation Overflow Alarm Level at Servo ON	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn528	2	Position Deviation Overflow Warning Level at Servo ON	10 to 100	1%	100	All	Immediately	Setup	*1
Pn529	2	Speed Limit Level at Servo ON	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1
Pn52A	2	Multiplier per Fully-closed Rotation	0 to 100	1%	20	Rotary	Immediately	Tuning	*1
Pn52B	2	Overload Warning Level	1 to 100	1%	20	All	Immediately	Setup	*1
Pn52C	2	Base Current Derating at Motor Overload Detection	10 to 100	1%	100	All	After restart	Setup	*1
Pn52F	2	Monitor Display at Startup	0000h to 0FFFh	–	0FFFh	All	Immediately	Setup	*1
Pn530	2	Program Jogging-Related Selections	0000h to 0005h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Program Jogging Operation Pattern	
	0	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	1	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	2	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	3	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	4	(Waiting time in Pn535 → Forward by travel distance in Pn531 → Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	5	(Waiting time in Pn535 → Reverse by travel distance in Pn531 → Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn531	4	Program Jogging Travel Distance	1 to 1,073,741,824	1 reference unit	32768	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn533	2	Program Jogging Movement Speed	1 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn534	2	Program Jogging Acceleration/Deceleration Time	2 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn535	2	Program Jogging Waiting Time	0 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn536	2	Program Jogging Number of Movements	0 to 1,000	Times	1	All	Immediately	Setup	*1
Pn550	2	Analog Monitor 1 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn551	2	Analog Monitor 2 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn552	2	Analog Monitor 1 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn553	2	Analog Monitor 2 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn55A	2	Power Consumption Monitor Unit Time	1 to 1,440	1 min	1	All	Immediately	Setup	–
Pn560	2	Residual Vibration Detection Width	1 to 3,000	0.1%	400	All	Immediately	Setup	*1
Pn561	2	Overshoot Detection Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn600	2	Regenerative Resistor Capacity*4	Depends on model.*5	10 W	0	All	Immediately	Setup	*1
Pn601	2	Dynamic Brake Resistor Allowable Energy Consumption	0 to 65,535	10 J	0	All	After restart	Setup	*6
Pn603	2	Regenerative Resistance	0 to 65,535	10 mΩ	0	All	Immediately	Setup	*1
Pn604	2	Dynamic Brake Resistance	0 to 65,535	10 mΩ	0	All	After restart	Setup	*6
Pn61A	2	Overheat Protection Selections	0000h to 0003h	–	0000h	Linear	After restart	Setup	*1
Pn61B *8	2	Overheat Alarm Level	0 to 500	0.01 V	250	All	Immediately	Setup	*1
Pn61C *8	2	Overheat Warning Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn61D *8	2	Overheat Alarm Filter Time	0 to 65,535	1 s	0	All	Immediately	Setup	*1
Pn621 to Pn628*3	–	Safety Module-Related Parameters	–	–	–	All	–	–	–

n.□□□X	Overheat Protection Selection	
	0	Disable overheat protection.
	1	Use overheat protection in the Yaskawa Linear Servomotor.*7
	2	Monitor a negative voltage input from a sensor attached to the machine and use overheat protection.
	3	Monitor a positive voltage input from a sensor attached to the machine and use overheat protection.

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

*2. Set a percentage of the motor rated torque.

*3. These parameters are for SERVOPACKs with a Safety Module. Refer to the following manual for details.
Σ-V-Series/Σ-V-Series for Large-Capacity Models/Σ-7-Series User's Manual Safety Module (Manual No.: SIEP C720829 06)

*4. Normally set this parameter to 0. If you use an External Regenerative Resistor, set the capacity (W) of the External Regenerative Resistor.

*5. The upper limit is the maximum output capacity (W) of the SERVOPACK.

*6. These parameters are for SERVOPACKs with the dynamic brake option. Refer to the following manual for details.
Σ-7-Series AC Servo Drive Σ-7S/Σ-7W SERVOPACK with Hardware Option Specifications Dynamic Brake Product Manual (Manual No.: SIEP S800001 73)

*7. The SGLFW2 is the only Yaskawa Linear Servomotor that supports this function.

*8. Enabled only when Pn61A is set to n.□□□2 or n.□□□3.

4.2 FT82 SERVOPACK with MECHATROLINK-II Communications References

The following table lists the parameters.

Note: Do not change the following parameters from their default settings.
- Reserved parameters
- Parameters not given in this manual
- Parameters that are not valid for the Servomotor that you are using, as given in the parameter table

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn000	2	Basic Function Selections 0	0000h to 10B1h	–	0000h	All	After restart	Setup	–

n.□□□X	Rotation Direction Selection		Reference
	0	Use CCW as the forward direction.	*1
	1	Use CW as the forward direction. (Reverse Rotation Mode)	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn001	2	Application Function Selections 1	0000h to 1142h	–	0000h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Servo OFF and Group 1 Alarms		Reference
	0	Stop the motor by applying the dynamic brake.	*1
	1	Stop the motor by the applying dynamic brake and then release the dynamic brake.	
	2	Coast the motor to a stop without the dynamic brake.	
n.□□X□	Overtravel Stopping Method		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then servo-lock the motor.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A and then servo-lock the motor.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	
n.□X□□	Main Circuit Power Supply AC/DC Input Selection		Reference
	0	Input AC power as the main circuit power supply using the L1, L2, and L3 terminals (do not use shared converter).	*1
	1	Input DC power as the main circuit power supply using the B1/⊕ and ⊖ 2 terminals or the B1 and ⊖ 2 terminals (use an external converter or the shared converter).	
n.X□□□	Reserved parameter (Do not change.)		

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn002	2	Application Function Selections 2	0000h to 4213h	–	0000h	–	After restart	Setup	–

n.□□□X	MECHATROLINK Command Position and Speed Control Option		Applicable Motors	Reference
	0	Ignore the settings of P_TLIM, NTLIM, and TFF.	All	*2
	1	Use P_TLIM and N_TLIM as torque limits.		
	2	Use TFF as a torque feedback input.		
	3	Use P_TLIM or N_TLIM as the torque limit when P_CL or N_CL in the OPTION field is ON.		

n.□□X□	Torque Control Option		Applicable Motors	Reference
	0	Ignore the setting of the speed limit for torque control (VLIM).	All	*2
	1	Use the speed limit for torque control (VLIM) as the speed limit.		

n.□X□□	Encoder Usage		Applicable Motors	Reference
	0	Use the encoder according to encoder specifications.	All	*1
	1	Use the encoder as an incremental encoder.		
	2	Use the encoder as a single-turn absolute encoder.	Rotary	

n.X□□□	External Encoder Usage		Applicable Motors	Reference
	0	Do not use an external encoder.	Rotary	*1
	1	The external encoder moves in the forward direction for CCW motor rotation.		
	2	Reserved setting (Do not use.)		
	3	The external encoder moves in the reverse direction for CCW motor rotation.		
	4	Reserved setting (Do not use.)		

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn006	2	Application Function Selections 6	0000h to 105Fh	–	0002h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 1 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn007	2	Application Function Selections 7	0000h to 105Fh	–	0000h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 2 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn008	2	Application Function Selections 8	0000h to 7121h	–	4000h	Rotary	After restart	Setup	–

n.□□□X	Low Battery Voltage Alarm/Warning Selection		Reference
	0	Output alarm (A.830) for low battery voltage.	*1
	1	Output warning (A.930) for low battery voltage.	

n.□□X□	Function Selection for Undervoltage		Reference
	0	Do not detect undervoltage.	*1
	1	Detect undervoltage warning and limit torque at host controller.	
	2	Detect undervoltage warning and limit torque with Pn424 and Pn425 (i.e., only in SERVOPACK).	

n.□X□□	Warning Detection Selection		Reference
	0	Detect warnings.	*1
	1	Do not detect warnings except for A.971.	

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn009	2	Application Function Selections 9	0000h to 0121h	–	0010h	All	After restart	Tuning	–

n.□□□X	Reserved parameter (Do not change.)	

n.□□X□	Current Control Mode Selection		Reference
	0	Use current control mode 1.	*1
	1	• SERVOPACK Models SGD7S-R70A, -R90A, -1R6A, -2R8A, -3R8A, -5R5A, and -7R6A: Use current control mode 1. • SERVOPACK Models SGD7S-120A, -180A, -200A, -330A, -470A, -550A, -590A, and -780A: Use current control mode 2.	
	2	Use current control mode 2.	

n.□X□□	Speed Detection Method Selection		Reference
	0	Use speed detection 1.	*1
	1	Use speed detection 2.	

n.X□□□	Reserved parameter (Do not change.)

Pn00A	2	Application Function Selections A	0000h to 0044h	–	0001h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Group 2 Alarms		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□□X□	Stopping Method for Forced Stops		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00B	2	Application Function Selections B	0000h to 1121h	–	0000h	All	After restart	Setup	–

n.□□□X	Operator Parameter Display Selection	Reference
	0 Display only setup parameters.	*1
	1 Display all parameters.	

n.□□X□	Motor Stopping Method for Group 2 Alarms	Reference
	0 Stop the motor by setting the speed reference to 0.	*1
	1 Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	
	2 Set the stopping method with Pn00A = n.□□□X.	

n.□X□□	Power Input Selection for Three-phase SERVOPACK	Reference
	0 Use a three-phase power supply input.	*1
	1 Use a three-phase power supply input as a single-phase power supply input.	

n.X□□□	Reserved parameter (Do not change.)

Pn00C	2	Application Function Selections C	0000h to 0131h	–	0000h	–	After restart	Setup	*1

n.□□□X	Function Selection for Test without a Motor	Applicable Motors
	0 Disable tests without a motor.	All
	1 Enable tests without a motor.	

n.□□X□	Encoder Resolution for Tests without a Motor	Applicable Motors
	0 Use 13 bits.	Rotary
	1 Use 20 bits.	
	2 Use 22 bits.	
	3 Use 24 bits.	

n.□X□□	Encoder Type Selection for Tests without a Motor	Applicable Motors
	0 Use an incremental encoder.	All
	1 Use an absolute encoder.	

n.X□□□	Reserved parameter (Do not change.)

Pn00D	2	Application Function Selections D	0000h to 1001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Overtravel Warning Detection Selection
	0 Do not detect overtravel warnings.
	1 Detect overtravel warnings.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00F	2	Application Function Selections F	0000h to 2011h	–	0000h	All	After restart	Setup	–

n.□□□X	Preventative Maintenance Warning Selection		Reference
	0	Do not detect preventative maintenance warnings.	*1
	1	Detect preventative maintenance warnings.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn021	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn022	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn040	2	Reserved parameter (Do not change.)	–	–	0000h	–	–	–	–
Pn081	2	Application Function Selections 81	0000h to 1111h	–	0000h	All	After restart	Setup	*1

n.□□□X	Phase-C Pulse Output Selection	
	0	Output phase-C pulses only in the forward direction.
	1	Output phase-C pulses in both the forward and reverse directions.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn100	2	Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn101	2	Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn102	2	Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn103	2	Moment of Inertia Ratio	0 to 20,000	1%	100	All	Immediately	Tuning	*1
Pn104	2	Second Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn105	2	Second Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn106	2	Second Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn109	2	Feedforward	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn10A	2	Feedforward Filter Time Constant	0 to 6,400	0.01 ms	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn10B	2	Gain Application Selections	0000h to 5334h	–	0000h	All	–	Setup	–

n.□□□X	Mode Switching Selection		When Enabled	Reference
	0	Use the internal torque reference as the condition (level setting: Pn10C).	Immediately	*1
	1	Use the speed reference as the condition (level setting: Pn10D).		
		Use the speed reference as the condition (level setting: Pn181).		
	2	Use the acceleration reference as the condition (level setting: Pn10E).		
		Use the acceleration reference as the condition (level setting: Pn182).		
	3	Use the position deviation as the condition (level setting: Pn10F).		
	4	Do not use mode switching.		

n.□□X□	Speed Loop Control Method		When Enabled	Reference
	0	PI control	After restart	*1
	1	I-P control		
	2 to 3	Reserved settings (Do not use.)		

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn10C	2	Mode Switching Level for Torque Reference	0 to 800	1%	200	All	Immediately	Tuning	*1
Pn10D	2	Mode Switching Level for Speed Reference	0 to 10,000	1 min^{-1}	0	Rotary	Immediately	Tuning	*1
Pn10E	2	Mode Switching Level for Acceleration	0 to 30,000	1 min^{-1}/s	0	Rotary	Immediately	Tuning	*1
Pn10F	2	Mode Switching Level for Position Deviation	0 to 10,000	1 reference unit	0	All	Immediately	Tuning	*1
Pn11F	2	Position Integral Time Constant	0 to 50,000	0.1 ms	0	All	Immediately	Tuning	*1
Pn121	2	Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn122	2	Second Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn123	2	Friction Compensation Coefficient	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn124	2	Friction Compensation Frequency Correction	-10,000 to 10,000	0.1 Hz	0	All	Immediately	Tuning	*1
Pn125	2	Friction Compensation Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn131	2	Gain Switching Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn132	2	Gain Switching Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn135	2	Gain Switching Waiting Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn136	2	Gain Switching Waiting Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn139	2	Automatic Gain Switching Selections 1	0000h to 0052h	–	0000h	All	Immediately	Tuning	*1

	Gain Switching Selection	
n.□□□X	0	Use manual gain switching. The gain is switched manually with G_SEL in the Option field.
	1	Reserved setting (Do not use.)
	2	Use automatic gain switching pattern 1. The gain is switched automatically from the first gain to the second gain when switching condition A is satisfied. The gain is switched automatically from the second gain to the first gain when switching condition A is not satisfied.

	Gain Switching Condition A	
n.□□X□	0	/COIN (Positioning Completion Output) signal turns ON.
	1	/COIN (Positioning Completion Output) signal turns OFF.
	2	/NEAR (Near Output) signal turns ON.
	3	/NEAR (Near Output) signal turns OFF.
	4	Position reference filter output is 0 and position reference input is OFF.
	5	Position reference input is ON.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn13D	2	Current Gain Level	100 to 2,000	1%	2000	All	Immediately	Tuning	*1
Pn140	2	Model Following Control-Related Selections	0000h to 1121h	–	0100h	All	Immediately	Tuning	–

	Model Following Control Selection		Reference
n.□□□X	0	Do not use model following control.	*1
	1	Use model following control.	

	Vibration Suppression Selection		Reference
n.□□X□	0	Do not perform vibration suppression.	*1
	1	Perform vibration suppression for a specific frequency.	
	2	Perform vibration suppression for two specific frequencies.	

	Vibration Suppression Adjustment Selection		Reference
n.□X□□	0	Do not adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

	Speed Feedforward (VFF)/Torque Feedforward (TFF) Selection		Reference
n.X□□□	0	Do not use model following control and speed/torque feedforward together.	*1
	1	Use model following control and speed/torque feedforward together.	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn141	2	Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn142	2	Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn143	2	Model Following Control Bias in the Forward Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn144	2	Model Following Control Bias in the Reverse Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn145	2	Vibration Suppression 1 Frequency A	10 to 2,500	0.1 Hz	500	All	Immediately	Tuning	*1
Pn146	2	Vibration Suppression 1 Frequency B	10 to 2,500	0.1 Hz	700	All	Immediately	Tuning	*1
Pn147	2	Model Following Control Speed Feedforward Compensation	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn148	2	Second Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn149	2	Second Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn14A	2	Vibration Suppression 2 Frequency	10 to 2,000	0.1 Hz	800	All	Immediately	Tuning	*1
Pn14B	2	Vibration Suppression 2 Correction	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn14F	2	Control-Related Selections	0000h to 0021h	–	0021h	All	After restart	Tuning	–

	Model Following Control Type Selection		Reference
n.□□□X	0	Use model following control type 1.	*1
	1	Use model following control type 2.	

	Tuning-less Type Selection		Reference
n.□□X□	0	Use tuning-less type 1.	*1
	1	Use tuning-less type 2.	
	2	Use tuning-less type 3.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn160	2	Anti-Resonance Control-Related Selections	0000h to 0011h	–	0010h	All	Immediately	Tuning	–

	Anti-Resonance Control Selection		Reference
n.□□□X	0	Do not use anti-resonance control.	*1
	1	Use anti-resonance control.	

	Anti-Resonance Control Adjustment Selection		Reference
n.□□X□	0	Do not adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn161	2	Anti-Resonance Frequency	10 to 20,000	0.1 Hz	1000	All	Immediately	Tuning	*1
Pn162	2	Anti-Resonance Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn163	2	Anti-Resonance Damping Gain	0 to 300	1%	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn164	2	Anti-Resonance Filter Time Constant 1 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn165	2	Anti-Resonance Filter Time Constant 2 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn166	2	Anti-Resonance Damping Gain 2	0 to 1,000	1%	0	All	Immediately	Tuning	*1
Pn170	2	Tuning-less Function-Related Selections	0000h to 2711h	–	1401h	All	–	Setup	*1

n.□□□X	Tuning-less Selection		When Enabled
	0	Disable tuning-less function.	After restart
	1	Enable tuning-less function.	

n.□□X□	Speed Control Method		When Enabled
	0	Use for speed control.	After restart
	1	Use for speed control and use host controller for position control.	

n.□X□□	Rigidity Level		When Enabled
	0 to 7	Set the rigidity level.	Immediately

n.X□□□	Tuning-less Load Level		When Enabled
	0 to 2	Set the load level for the tuning-less function.	Immediately

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn205	2	Multiturn Limit	0 to 65,535	1 rev	65535	Rotary	After restart	Setup	*1
Pn207	2	Position Control Function Selections	0000h to 2210h	–	0010h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	/COIN (Positioning Completion Output) Signal Output Timing		Reference
	0	Output when the absolute value of the position deviation is the same or less than the setting of Pn522 (Positioning Completed Width).	*1
	1	Output when the absolute value of the position error is the same or less than the setting of Pn522 (Positioning Completed Width) and the reference after the position reference filter is 0.	
	2	Output when the absolute value of the position error is the same or less than the setting of Pn522 (Positioning Completed Width) and the reference input is 0.	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn20A	4	Number of External Encoder Scale Pitches	4 to 1,048,576	1 scale pitch/ revolution	32768	Rotary	After restart	Setup	*1
Pn20E	4	Electronic Gear Ratio (Numerator)	1 to 1,073,741,824	1	64	All	After restart	Setup	*1
Pn210	4	Electronic Gear Ratio (Denominator)	1 to 1,073,741,824	1	1	All	After restart	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn212	4	Number of Encoder Output Pulses	16 to 1,073,741,824	1 P/Rev	2048	Rotary	After restart	Setup	*1
Pn22A	2	Fully-closed Control Selections	0000h to 1003h	–	0000h	Rotary	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)	
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Fully-closed Control Speed Feedback Selection	
	0	Use motor encoder speed.
	1	Use external encoder speed.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn230	2	Position Control Expansion Function Selections	0000h to 0001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Backlash Compensation Direction	
	0	Compensate forward references.
	1	Compensate reverse references.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn231	4	Backlash Compensation	-500,000 to 500,000	0.1 reference units	0	All	Immediately	Setup	*1
Pn233	2	Backlash Compensation Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1
Pn281	2	Encoder Output Resolution	1 to 4,096	1 edge/pitch	20	All	After restart	Setup	*1
Pn304	2	Jogging Speed	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn305	2	Soft Start Acceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*2
Pn306	2	Soft Start Deceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*2
Pn308	2	Speed Feedback Filter Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1
Pn30A	2	Deceleration Time for Servo OFF and Forced Stops	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn30C	2	Speed Feedforward Average Movement Time	0 to 5,100	0.1 ms	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn310	2	Vibration Detection Selections	0000h to 0002h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Vibration Detection Selection	
	0	Do not detect vibration.
	1	Output a warning (A.911) if vibration is detected.
	2	Output an alarm (A.520) if vibration is detected.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn311	2	Vibration Detection Sensitivity	50 to 500	1%	100	All	Immediately	Tuning	*1
Pn312	2	Vibration Detection Level	0 to 5,000	1 min^{-1}	50	Rotary	Immediately	Tuning	*1
Pn316	2	Maximum Motor Speed	0 to 65,535	1 min^{-1}	10000	Rotary	After restart	Setup	*1
Pn324	2	Moment of Inertia Calculation Starting Level	0 to 20,000	1%	300	All	Immediately	Setup	*1
Pn401	2	First Stage First Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1
Pn402	2	Forward Torque Limit	0 to 800	1%*3	800	Rotary	Immediately	Setup	*1
Pn403	2	Reverse Torque Limit	0 to 800	1%*3	800	Rotary	Immediately	Setup	*1
Pn404	2	Forward External Torque Limit	0 to 800	1%*3	100	All	Immediately	Setup	*1
Pn405	2	Reverse External Torque Limit	0 to 800	1%*3	100	All	Immediately	Setup	*1
Pn406	2	Emergency Stop Torque	0 to 800	1%*3	800	All	Immediately	Setup	*1
Pn407	2	Speed Limit during Torque Control	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn408	2	Torque-Related Function Selections	0000h to 1111h	–	0000h	All	–	Setup	–

n.□□□X	Notch Filter Selection 1		When Enabled	Reference
	0	Disable first stage notch filter.	Immediately	*1
	1	Enable first stage notch filter.		

n.□□X□	Speed Limit Selection		When Enabled	Reference
	0	Use the smaller of the maximum motor speed and the setting of Pn407 as the speed limit.	After restart	*1
		Use the smaller of the maximum motor speed and the setting of Pn480 as the speed limit.		
	1	Use the smaller of the overspeed alarm detection speed and the setting of Pn407 as the speed limit.		
		Use the smaller of the overspeed alarm detection speed and the setting of Pn480 as the speed limit.		

n.□X□□	Notch Filter Selection 2		When Enabled	Reference
	0	Disable second stage notch filter.	Immediately	*1
	1	Enable second stage notch filter.		

n.X□□□	Friction Compensation Function Selection		When Enabled	Reference
	0	Disable friction compensation.	Immediately	*1
	1	Enable friction compensation.		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn409	2	First Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40A	2	First Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40B	2	First Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40C	2	Second Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40D	2	Second Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40E	2	Second Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40F	2	Second Stage Second Torque Reference Filter Frequency	100 to 5,000	1 Hz	4000	All	Immediately	Tuning	*1
Pn410	2	Second Stage Second Torque Reference Filter Q Value	50 to 100	0.01	50	All	Immediately	Tuning	*1
Pn412	2	First Stage Second Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn416	2	Torque-Related Function Selections 2	0000h to 1111h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Notch Filter Selection 3
0	Disable third stage notch filter.
1	Enable third stage notch filter.

n.□□X□	Notch Filter Selection 4
0	Disable fourth stage notch filter.
1	Enable fourth stage notch filter.

n.□X□□	Notch Filter Selection 5
0	Disable fifth stage notch filter.
1	Enable fifth stage notch filter.

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn417	2	Third Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn418	2	Third Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn419	2	Third Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41A	2	Fourth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41B	2	Fourth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41C	2	Fourth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41D	2	Fifth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41E	2	Fifth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41F	2	Fifth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn423	2	Speed Ripple Compensation Selections	0000h to 1111h	–	0000h	Rotary	–	Setup	*1

n.□□□X	Speed Ripple Compensation Function Selection	When Enabled
0	Disable speed ripple compensation.	Immediately
1	Enable speed ripple compensation.	

n.□□X□	Speed Ripple Compensation Information Disagreement Warning Detection Selection	When Enabled
0	Detect A.942 alarms.	After restart
1	Do not detect A.942 alarms.	

n.□X□□	Speed Ripple Compensation Enable Condition Selection	When Enabled
0	Speed reference	After restart
1	Motor speed	

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn424	2	Torque Limit at Main Circuit Voltage Drop	0 to 100	1%*3	50	All	Immediately	Setup	*1
Pn425	2	Release Time for Torque Limit at Main Circuit Voltage Drop	0 to 1,000	1 ms	100	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn426	2	Torque Feedforward Average Movement Time	0 to 5,100	0.1 ms	0	All	Immediately	Setup	*1
Pn427	2	Speed Ripple Compensation Enable Speed	0 to 10,000	1 min^{-1}	0	Rotary Servomotor	Immediately	Tuning	*1
Pn456	2	Sweep Torque Reference Amplitude	1 to 800	1%	15	All	Immediately	Tuning	*1
Pn460	2	Notch Filter Adjustment Selections 1	0000h to 0101h	–	0101h	All	Immediately	Tuning	*1

n.□□□X	Notch Filter Adjustment Selection 1	
	0	Do not adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Notch Filter Adjustment Selection 2	
	0	Do not adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn475	2	Gravity Compensation-Related Selections	0000h to 0001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Gravity Compensation Selection	
	0	Disable gravity compensation.
	1	Enable gravity compensation.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn476	2	Gravity Compensation Torque	-1,000 to 1,000	0.1%	0	All	Immediately	Tuning	*1
Pn502	2	Rotation Detection Level	1 to 10,000	1 min^{-1}	20	Rotary	Immediately	Setup	*1
Pn503	2	Speed Coincidence Detection Signal Output Width	0 to 100	1 min^{-1}	10	Rotary	Immediately	Setup	*1
Pn506	2	Brake Reference-Servo OFF Delay Time	0 to 50	10 ms	0	All	Immediately	Setup	*1
Pn507	2	Brake Reference Output Speed Level	0 to 10,000	1 min^{-1}	100	Rotary	Immediately	Setup	*1
Pn508	2	Servo OFF-Brake Command Waiting Time	10 to 100	10 ms	50	All	Immediately	Setup	*1
Pn509	2	Momentary Power Interruption Hold Time	20 to 50,000	1 ms	20	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
Pn50A	2	Input Signal Selections 1	0000h to FFF2h	–	1881h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)
n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)

	P-OT (Forward Drive Prohibit) Signal Allocation		Reference
n.X□□□	0	Enable forward drive when CN1-13 input signal is ON (closed).	*1
	1	Enable forward drive when CN1-7 input signal is ON (closed).	
	2	Enable forward drive when CN1-8 input signal is ON (closed).	
	3	Enable forward drive when CN1-9 input signal is ON (closed).	
	4	Enable forward drive when CN1-10 input signal is ON (closed).	
	5	Enable forward drive when CN1-11 input signal is ON (closed).	
	6	Enable forward drive when CN1-12 input signal is ON (closed).	
	7	Set the signal to always prohibit forward drive.	
	8	Set the signal to always enable forward drive.	
	9	Enable forward drive when CN1-13 input signal is OFF (open).	
	A	Enable forward drive when CN1-7 input signal is OFF (open).	
	B	Enable forward drive when CN1-8 input signal is OFF (open).	
	C	Enable forward drive when CN1-9 input signal is OFF (open).	
	D	Enable forward drive when CN1-10 input signal is OFF (open).	
	E	Enable forward drive when CN1-11 input signal is OFF (open).	
	F	Enable forward drive when CN1-12 input signal is OFF (open).	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
Pn50B	2	Input Signal Selections 2	0000h to FFFFh	–	8882h	All	After restart	Setup	–

	N-OT (Reverse Drive Prohibit) Signal Allocation		Reference
n.□□□X	0	Enable reverse drive when CN1-13 input signal is ON (closed).	*1
	1	Enable reverse drive when CN1-7 input signal is ON (closed).	
	2	Enable reverse drive when CN1-8 input signal is ON (closed).	
	3	Enable reverse drive when CN1-9 input signal is ON (closed).	
	4	Enable reverse drive when CN1-10 input signal is ON (closed).	
	5	Enable reverse drive when CN1-11 input signal is ON (closed).	
	6	Enable reverse drive when CN1-12 input signal is ON (closed).	
	7	Set the signal to always prohibit reverse drive.	
	8	Set the signal to always enable reverse drive.	
	9	Enable reverse drive when CN1-13 input signal is OFF (open).	
	A	Enable reverse drive when CN1-7 input signal is OFF (open).	
	B	Enable reverse drive when CN1-8 input signal is OFF (open).	
	C	Enable reverse drive when CN1-9 input signal is OFF (open).	
	D	Enable reverse drive when CN1-10 input signal is OFF (open).	
	E	Enable reverse drive when CN1-11 input signal is OFF (open).	
	F	Enable reverse drive when CN1-12 input signal is OFF (open).	

n.□□X□	Reserved parameter (Do not change.)

	/P-CL (Forward External Torque Limit Input) Signal Allocation		Reference
n.□X□□	0	Active when CN1-13 input signal is ON (closed).	*1
	1	Active when CN1-7 input signal is ON (closed).	
	2	Active when CN1-8 input signal is ON (closed).	
	3	Active when CN1-9 input signal is ON (closed).	
	4	Active when CN1-10 input signal is ON (closed).	
	5	Active when CN1-11 input signal is ON (closed).	
	6	Active when CN1-12 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-13 input signal is OFF (open).	
	A	Active when CN1-7 input signal is OFF (open).	
	B	Active when CN1-8 input signal is OFF (open).	
	C	Active when CN1-9 input signal is OFF (open).	
	D	Active when CN1-10 input signal is OFF (open).	
	E	Active when CN1-11 input signal is OFF (open).	
	F	Active when CN1-12 input signal is OFF (open).	

	/N-CL (Reverse External Torque Limit Input) Signal Allocation		Reference
n.X□□□	0 to F	The allocations are the same as the /P-CL (Forward External Torque Limit Input) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50E	2	Output Signal Selections 1	0000h to 6666h	–	0000h	All	After restart	Setup	–

	/COIN (Positioning Completion Output) Signal Allocation		Reference
n.□□□X	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-1 or CN1-2 output terminal.	
	2	Output the signal from the CN1-23 or CN1-24 output terminal.	
	3	Output the signal from the CN1-25 or CN1-26 output terminal.	
	4 to 6	Reserved setting (Do not use.)	

	/V-CMP (Speed Coincidence Detection Output) Signal Allocation		Reference
n.□□X□	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

	/TGON (Rotation Detection Output) Signal Allocation		Reference
n.□X□□	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

	/S-RDY (Servo Ready) Signal Allocation		Reference
n.X□□□	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50F	2	Output Signal Selections 2	0000h to 6666h	–	0100h	All	After restart	Setup	–

	/CLT (Torque Limit Detection Output) Signal Allocation		Reference
n.□□□X	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-1 or CN1-2 output terminal.	
	2	Output the signal from the CN1-23 or CN1-24 output terminal.	
	3	Output the signal from the CN1-25 or CN1-26 output terminal.	
	4 to 6	Reserved setting (Do not use.)	

	/VLT (Speed Limit Detection) Signal Allocation		Reference
n.□□X□	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

	/BK (Brake Output) Signal Allocation		Reference
n.□X□□	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

	/WARN (Warning Output) Signal Allocation		Reference
n.X□□□	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn510	2	Output Signal Selections 3	0000h to 0666h	–	0000h	All	After restart	Setup	–

	/NEAR (Near Output) Signal Allocation		Reference
n.□□□X	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-1 or CN1-2 output terminal.	
	2	Output the signal from the CN1-23 or CN1-24 output terminal.	
	3	Output the signal from the CN1-25 or CN1-26 output terminal.	
	4 to 6	Reserved setting (Do not use.)	

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn511	2	Input Signal Selections 5	0000h to FFFFh	–	6543h	All	After restart	Setup	*1

	/DEC (Origin Return Deceleration Switch Input) Signal Allocation	
n.□□□X	0	Active when CN1-13 input signal is ON (closed).
	1	Active when CN1-7 input signal is ON (closed).
	2	Active when CN1-8 input signal is ON (closed).
	3	Active when CN1-9 input signal is ON (closed).
	4	Active when CN1-10 input signal is ON (closed).
	5	Active when CN1-11 input signal is ON (closed).
	6	Active when CN1-12 input signal is ON (closed).
	7	The signal is always active.
	8	The signal is always inactive.
	9	Active when CN1-13 input signal is OFF (open).
	A	Active when CN1-7 input signal is OFF (open).
	B	Active when CN1-8 input signal is OFF (open).
	C	Active when CN1-9 input signal is OFF (open).
	D	Active when CN1-10 input signal is OFF (open).
	E	Active when CN1-11 input signal is OFF (open).
	F	Active when CN1-12 input signal is OFF (open).

	/EXT1 (External Latch Input 1) Signal Allocation	
n.□□X□	0 to 3	The signal is always inactive.
	4	Active when CN1-10 input signal is ON (closed).
	5	Active when CN1-11 input signal is ON (closed).
	6	Active when CN1-12 input signal is ON (closed).
	D	Active when CN1-10 input signal is OFF (open).
	E	Active when CN1-11 input signal is OFF (open).
	F	Active when CN1-12 input signal is OFF (open).
	7 to C	The signal is always inactive.

	/EXT2 (External Latch Input 2) Signal Allocation	
n.□X□□	0 to F	The allocations are the same as the /EXT1 (External Latch Input 1) signal allocations.

	/EXT3 (External Latch Input 3) Signal Allocation	
n.X□□□	0 to F	The allocations are the same as the /EXT1 (External Latch Input 1) signal allocations.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn512	2	Output Signal Inverse Settings	0000h to 1111h	–	0000h	All	After restart	Setup	*1

n.□□□X	Output Signal Inversion for CN1-1 and CN1-2 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.
n.□□X□	Output Signal Inversion for CN1-23 and CN1-24 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.
n.□X□□	Output Signal Inversion for CN1-25 and CN1-26 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn514	2	Output Signal Selections 4	0000h to 0666h	–	0000h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)		
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	/PM (Preventative Maintenance Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-1 or CN1-2 output terminal.	
	2	Output the signal from the CN1-23 or CN1-24 output terminal.	
	3	Output the signal from the CN1-25 or CN1-26 output terminal.	
	4 to 6	Reserved setting (Do not use.)	
n.X□□□	Reserved parameter (Do not change.)		

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn516	2	Input Signal Selections 7	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	FSTP (Forced Stop Input) Signal Allocation		Reference
n.□□□X	0	Enable drive when CN1-13 input signal is ON (closed).	*1
	1	Enable drive when CN1-7 input signal is ON (closed).	
	2	Enable drive when CN1-8 input signal is ON (closed).	
	3	Enable drive when CN1-9 input signal is ON (closed).	
	4	Enable drive when CN1-10 input signal is ON (closed).	
	5	Enable drive when CN1-11 input signal is ON (closed).	
	6	Enable drive when CN1-12 input signal is ON (closed).	
	7	Set the signal to always prohibit drive (always force the motor to stop).	
	8	Set the signal to always enable drive (always disable forcing the motor to stop).	
	9	Enable drive when CN1-13 input signal is OFF (open).	
	A	Enable drive when CN1-7 input signal is OFF (open).	
	B	Enable drive when CN1-8 input signal is OFF (open).	
	C	Enable drive when CN1-9 input signal is OFF (open).	
	D	Enable drive when CN1-10 input signal is OFF (open).	
	E	Enable drive when CN1-11 input signal is OFF (open).	
	F	Enable drive when CN1-12 input signal is OFF (open).	

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn518*4	–	Safety Module-Related Parameters	–	–	–	All	–	–	–
Pn51B	4	Motor-Load Position Deviation Overflow Detection Level	0 to 1,073,741,824	1 reference unit	1000	Rotary	Immediately	Setup	*1
Pn51E	2	Position Deviation Overflow Warning Level	10 to 100	1%	100	All	Immediately	Setup	*1
Pn520	4	Position Deviation Overflow Alarm Level	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn522	4	Positioning Completed Width	0 to 1,073,741,824	1 reference unit	7	All	Immediately	Setup	*1
Pn524	4	Near Signal Width	1 to 1,073,741,824	1 reference unit	1073741824	All	Immediately	Setup	*1
Pn526	4	Position Deviation Overflow Alarm Level at Servo ON	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn528	2	Position Deviation Overflow Warning Level at Servo ON	10 to 100	1%	100	All	Immediately	Setup	*1
Pn529	2	Speed Limit Level at Servo ON	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1
Pn52A	2	Multiplier per Fully-closed Rotation	0 to 100	1%	20	Rotary	Immediately	Tuning	*1
Pn52B	2	Overload Warning Level	1 to 100	1%	20	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn52C	2	Base Current Derating at Motor Overload Detection	10 to 100	1%	100	All	After restart	Setup	*1
Pn530	2	Program Jogging-Related Selections	0000h to 0005h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Program Jogging Operation Pattern	
	0	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	1	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	2	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	3	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	4	(Waiting time in Pn535 → Forward by travel distance in Pn531 → Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	5	(Waiting time in Pn535 → Reverse by travel distance in Pn531 → Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn531	4	Program Jogging Travel Distance	1 to 1,073,741,824	1 reference unit	32768	All	Immediately	Setup	*1
Pn533	2	Program Jogging Movement Speed	1 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn534	2	Program Jogging Acceleration/Deceleration Time	2 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn535	2	Program Jogging Waiting Time	0 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn536	2	Program Jogging Number of Movements	0 to 1,000	Times	1	All	Immediately	Setup	*1
Pn550	2	Analog Monitor 1 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn551	2	Analog Monitor 2 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn552	2	Analog Monitor 1 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn553	2	Analog Monitor 2 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn55A	2	Power Consumption Monitor Unit Time	1 to 1,440	1 min	1	All	Immediately	Setup	–
Pn560	2	Residual Vibration Detection Width	1 to 3,000	0.1%	400	All	Immediately	Setup	*1
Pn561	2	Overshoot Detection Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn600	2	Regenerative Resistor Capacity*5	Depends on model.*6	10 W	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn601	2	Dynamic Brake Resistor Allowable Energy Consumption	0 to 65,535	10 J	0	All	After restart	Setup	*7
Pn603	2	Regenerative Resistance	0 to 65,535	10 mΩ	0	All	Immediately	Setup	*1
Pn604	2	Dynamic Brake Resistance	0 to 65,535	10 mΩ	0	All	After restart	Setup	*7
Pn61A	2	Overheat Protection Selections	0000h to 0003h	–	0000h	Linear	After restart	Setup	*1

n.□□□X	Overheat Protection Selection
	0: Disable overheat protection.
	1: Use overheat protection in the Yaskawa Linear Servomotor.*8
	2: Monitor a negative voltage input from a sensor attached to the machine and use overheat protection.
	3: Monitor a positive voltage input from a sensor attached to the machine and use overheat protection.

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn61B *9	2	Overheat Alarm Level	0 to 500	0.01 V	250	All	Immediately	Setup	*1
Pn61C *9	2	Overheat Warning Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn61D *9	2	Overheat Alarm Filter Time	0 to 65,535	1 s	0	All	Immediately	Setup	*1
Pn621 to Pn628*4	–	Safety Module-Related Parameters	–	–	–	All	–	–	–
Pn800	2	Communications Controls	0000h to 0F73h	–	0040h	All	Immediately	Setup	*2

n.□□□X	MECHATROLINK Communications Check Mask for Debugging
	0: Do not mask.
	1: Ignore MECHATROLINK communications errors (A.E60).
	2: Ignore WDT errors (A.E50).
	3: Ignore both MECHATROLINK communications errors (A.E60) and WDT errors (A.E50).

n.□□X□	Warning Check Masks
	0: Do not mask.
	1: Ignore data setting warnings (A.94□).
	2: Ignore command warnings (A.95□).
	3: Ignore both A.94□ and A.95□ warnings.
	4: Ignore communications warnings (A.96□).
	5: Ignore both A.94□ and A.96□ warnings.
	6: Ignore both A.95□ and A.96□ warnings.
	7: Ignore A.94□, A.95□, and A.96□ warnings.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn801	2	Application Function Selections 6 (Software Limits)	0000h to 0103h	–	0003h	All	Immediately	Setup	*1

n.□□□X	Software Limit Selection
	0 Enable both forward and reverse software limits.
	1 Disable forward software limit.
	2 Disable reverse software limit.
	3 Disable both forward and reverse software limits.

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Software Limit Check for References
	0 Do not perform software limit checks for references.
	1 Perform software limit checks for references.

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn803	2	Origin Range	0 to 250	1 reference unit	10	All	Immediately	Setup	*2
Pn804	4	Forward Software Limit	-1,073,741,823 to 1,073,741,823	1 reference unit	1073741823	All	Immediately	Setup	*1
Pn806	4	Reverse Software Limit	-1,073,741,823 to 1,073,741,823	1 reference unit	-1073741823	All	Immediately	Setup	*1
Pn808	4	Absolute Encoder Origin Offset	-1,073,741,823 to 1,073,741,823	1 reference unit	0	All	Immediately *10	Setup	*1
Pn80A	2	First Stage Linear Acceleration Constant	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn80B	2	Second Stage Linear Acceleration Constant	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn80C	2	Acceleration Constant Switching Speed	0 to 65,535	100 reference units/s	0	All	Immediately *11	Setup	*2
Pn80D	2	First Stage Linear Deceleration Constant	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn80E	2	Second Stage Linear Deceleration Constant	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn80F	2	Deceleration Constant Switching Speed	0 to 65,535	100 reference units/s	0	All	Immediately *11	Setup	*2
Pn810	2	Exponential Acceleration/Deceleration Bias	0 to 65,535	100 reference units/s	0	All	Immediately *12	Setup	*2
Pn811	2	Exponential Acceleration/Deceleration Time Constant	0 to 5,100	0.1 ms	0	All	Immediately *12	Setup	*2
Pn812	2	Movement Average Time	0 to 5,100	0.1 ms	0	All	Immediately *12	Setup	*2
Pn814	4	External Positioning Final Travel Distance	-1,073,741,823 to 1,073,741,823	1 reference unit	100	All	Immediately	Setup	*2

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn816	2	Origin Return Mode Settings	0000h to 0001h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Origin Return Direction	
	0	Return in forward direction.
	1	Return in reverse direction.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn817 *13	2	Origin Approach Speed 1	0 to 65,535	100 reference units/s	50	All	Immediately *11	Setup	*2
Pn818 *14	2	Origin Approach Speed 2	0 to 65,535	100 reference units/s	5	All	Immediately *11	Setup	*2
Pn819	4	Final Travel Distance for Origin Return	-1,073,741,823 to 1,073,741,823	1 reference unit	100	All	Immediately	Setup	*2
Pn81E	2	Input Signal Monitor Selections	0000h to AAAAh	–	0000h	All	Immediately	Setup	*2

n.□□□X	IO12 Signal Mapping	
	0	Do not map.
	1	Monitor CN1-13 input terminal.
	2	Monitor CN1-7 input terminal.
	3	Monitor CN1-8 input terminal.
	4	Monitor CN1-9 input terminal.
	5	Monitor CN1-10 input terminal.
	6	Monitor CN1-11 input terminal.
	7	Monitor CN1-12 input terminal.
n.□□X□	IO13 Signal Mapping	
	0 to 7	The mappings are the same as the IO12 signal mappings.
n.□X□□	IO14 Signal Mapping	
	0 to 7	The mappings are the same as the IO12 signal mappings.
n.X□□□	IO15 Signal Mapping	
	0 to 7	The mappings are the same as the IO12 signal mappings.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn81F	2	Command Data Allocations	0000h to 1111h	–	0000h	All	After restart	Setup	*2

n.□□□X	Option Field Allocation	
	0	Disable option field allocation.
	1	Enable option field allocation.
n.□□X□	Position Control Command TFF/TLIM Allocation	
	0	Disable allocation.
	1	Enable allocation.
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn820	4	Forward Latching Area	-2,147,483,648 to 2,147,483,647	1 reference unit	0	All	Immediately	Setup	*2
Pn822	4	Reverse Latching Area	-2,147,483,648 to 2,147,483,647	1 reference unit	0	All	Immediately	Setup	*2

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn824	2	Option Monitor 1 Selection	0000h to FFFFh	–	0000h	–	Immediately	Setup	*2

Setting	Monitor	Applicable Motors
High-Speed Monitor Region		
0000h	Motor speed [1000000h/overspeed detection speed]	All
0001h	Speed reference [1000000h/overspeed detection speed]	All
0002h	Torque [1000000h/maximum torque]	All
0003h	Position deviation (lower 32 bits) [reference units]	All
0004h	Position deviation (upper 32 bits) [reference units]	All
000Ah	Encoder count (lower 32 bits) [reference units]	All
000Bh	Encoder count (upper 32 bits) [reference units]	All
000Ch	FPG count (lower 32 bits) [reference units]	All
000Dh	FPG count (upper 32 bits) [reference units]	All
Low-Speed Monitor Region		
0010h	Un000: Motor speed [min^{-1}]	All
0011h	Un001: Speed Reference [min^{-1}]	All
0012h	Un002: Torque Reference [%]	All
0013h	Un003: Rotational Angle 1 [encoder pulses] Number of encoder pulses from origin within one encoder rotation displayed in decimal	All
0014h	Un004: Rotational Angle 2 [deg] Electrical angle from polarity origin	All
0015h	Un005: Input Signal Monitor	All
0016h	Un006: Output Signal Monitor	All
0017h	Un007: Input Reference Speed [min^{-1}]	All
0018h	Un008: Position Deviation [reference units]	All
0019h	Un009: Accumulated Load Ratio [%]	All
001Ah	Un00A: Regenerative Load Ratio [%]	All
001Bh	Un00B: Dynamic Brake Resistor Power Consumption [%]	All
001Ch	Un00C: Input Reference Pulse Counter [reference units]	All
001Dh	Un00D: Feedback Pulse Counter [encoder pulses]	All
001Eh	Un00E: Fully-closed Loop Feedback Pulse Counter [external encoder resolution]	Rotary
0023h	Initial multiturn data [Rev]	Rotary
0024h	Initial incremental data [pulses]	Rotary
0040h	Un025: SERVOPACK Installation Environment Monitor	All
0041h	Un026: Servomotor Installation Environment Monitor	All
0042h	Un027: Built-in Fan Remaining Life Ratio	All
0043h	Un028: Capacitor Remaining Life Ratio	All
0044h	Un029: Surge Prevention Circuit Remaining Life Ratio	All
0045h	Un02A: Dynamic Brake Circuit Remaining Life Ratio	All
0046h	Un032: Instantaneous Power	All
0047h	Un033: Power Consumption	All
0048h	Un034: Cumulative Power Consumption	All
Communications Module Only		
0080h	Previous value of latched feedback position (LPOS) [encoder pulses]	All
All Areas		
Other values	Reserved settings (Do not use.)	All

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn825	2	Option Monitor 2 Selection	0000h to FFFFh	–	0000h	All	Immediately	Setup	*2

0000h to 0080h	The settings are the same as those for the Option Monitor 1 Selection.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn827	2	Linear Deceleration Constant 1 for Stopping	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn829	2	SVOFF Waiting Time (for SVOFF at Deceleration to Stop)	0 to 65,535	10 ms	0	All	Immediately *11	Setup	*2
Pn82A	2	Option Field Allocations 1	0000h to 1E1Eh	–	1813h	All	After restart	Setup	*2

n.□□□X	ACCFIL Allocation (Option)	
	0	Allocate bits 0 and 1 to ACCFIL.
	1	Allocate bits 1 and 2 to ACCFIL.
	2	Allocate bits 2 and 3 to ACCFIL.
	3	Allocate bits 3 and 4 to ACCFIL.
	4	Allocate bits 4 and 5 to ACCFIL.
	5	Allocate bits 5 and 6 to ACCFIL.
	6	Allocate bits 6 and 7 to ACCFIL.
	7	Allocate bits 7 and 8 to ACCFIL.
	8	Allocate bits 8 and 9 to ACCFIL.
	9	Allocate bits 9 and 10 to ACCFIL.
	A	Allocate bits 10 and 11 to ACCFIL.
	B	Allocate bits 11 and 12 to ACCFIL.
	C	Allocate bits 12 and 13 to ACCFIL.
	D	Allocate bits 13 and 14 to ACCFIL.
	E	Allocate bits 14 and 15 to ACCFIL.

n.□□X□	ACCFIL Allocation Enable/Disable Selection	
	0	Disable ACCFIL allocation.
	1	Enable ACCFIL allocation.

n.□X□□	G_SEL Allocation (Option)	
	0 to E	The settings are the same as for the ACCFIL allocations.

n. X□□□	G_SEL Allocation Enable/Disable Selection	
	0	Disable G_SEL allocation.
	1	Enable G_SEL allocation.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn82B	2	Option Field Allocations 2	0000h to 1F1Fh	–	1D1Ch	All	After restart	Setup	*2

n.□□□X	V_PPI Allocation (Option)
	0 Allocate bit 0 to V_PPI.
	1 Allocate bit 1 to V_PPI.
	2 Allocate bit 2 to V_PPI.
	3 Allocate bit 3 to V_PPI.
	4 Allocate bit 4 to V_PPI.
	5 Allocate bit 5 to V_PPI.
	6 Allocate bit 6 to V_PPI.
	7 Allocate bit 7 to V_PPI.
	8 Allocate bit 8 to V_PPI.
	9 Allocate bit 9 to V_PPI.
	A Allocate bit 10 to V_PPI.
	B Allocate bit 11 to V_PPI.
	C Allocate bit 12 to V_PPI.
	D Allocate bit 13 to V_PPI.
	E Allocate bit 14 to V_PPI.
	F Allocate bit 15 to V_PPI.

n.□□X□	V_PPI Allocation Enable/Disable Selection
	0 Disable V_PPI allocation.
	1 Enable V_PPI allocation.

n.□X□□	P_PI_CLR Allocation (Option)
	0 to F The settings are the same as for the V_PPI allocations.

n.X□□□	P_PI_CLR Allocation Enable/Disable Selection
	0 Disable P_PI_CLR allocation.
	1 Enable P_PI_CLR allocation.

Pn82C	2	Option Field Allocations 3	0000h to 1F1Fh	–	1F1Eh	All	After restart	Setup	*2

n.□□□X	P_CL Allocation (Option)
	0 to F The settings are the same as for the V_PPI allocations.

n.□□X□	P_CL Allocation Enable/Disable Selection
	0 Disable P_CL allocation.
	1 Enable P_CL allocation.

n.□X□□	N_CL Allocation (Option)
	0 to F The settings are the same as for the V_PPI allocations.

n.X□□□	N_CL Allocation Enable/Disable Selection
	0 Disable N_CL allocation.
	1 Enable N_CL allocation.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn82D	2	Option Field Allocations 4	0000h to 1F1Ch	–	0000h	All	After restart	Setup	*2

n.□□□X	BANK_SEL1 Allocation (Option)
	0	Allocate bits 0 to 3 to BANK_SEL1.
	1	Allocate bits 1 to 4 to BANK_SEL1.
	2	Allocate bits 2 to 5 to BANK_SEL1.
	3	Allocate bits 3 to 6 to BANK_SEL1.
	4	Allocate bits 4 to 7 to BANK_SEL1.
	5	Allocate bits 5 to 8 to BANK_SEL1.
	6	Allocate bits 6 to 9 to BANK_SEL1.
	7	Allocate bits 7 to 10 to BANK_SEL1.
	8	Allocate bits 8 to 11 to BANK_SEL1.
	9	Allocate bits 9 to 12 to BANK_SEL1.
	A	Allocate bits 10 to 13 to BANK_SEL1.
	B	Allocate bits 11 to 14 to BANK_SEL1.
	C	Allocate bits 12 to 15 to BANK_SEL1.

n.□□X□	BANK_SEL1 Allocation Enable/Disable Selection
	0	Disable BANK_SEL1 allocation.
	1	Enable BANK_SEL1 allocation.

n.□X□□	LT_DISABLE Allocation (Option)
	0 to F	The settings are the same as for the V_PPI allocations.

n.X□□□	LT_DISABLE Allocation Enable/Disable Selection
	0	Disable LT_DISABLE allocation.
	1	Enable LT_DISABLE allocation.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn82E	2	Option Field Allocations 5	0000h to 1D1Fh	–	0000h	All	After restart	Setup	*2

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	OUT_SIGNAL Allocation (Option)
	0 Allocate bits 0 to 2 to OUT_SIGNAL.
	1 Allocate bits 1 to 3 to OUT_SIGNAL.
	2 Allocate bits 2 to 4 to OUT_SIGNAL.
	3 Allocate bits 3 to 5 to OUT_SIGNAL.
	4 Allocate bits 4 to 6 to OUT_SIGNAL.
	5 Allocate bits 5 to 7 to OUT_SIGNAL.
	6 Allocate bits 6 to 8 to OUT_SIGNAL.
	7 Allocate bits 7 to 9 to OUT_SIGNAL.
	8 Allocate bits 8 to 10 to OUT_SIGNAL.
	9 Allocate bits 9 to 11 to OUT_SIGNAL.
	A Allocate bits 10 to 12 to OUT_SIGNAL.
	B Allocate bits 11 to 13 to OUT_SIGNAL.
	C Allocate bits 12 to 14 to OUT_SIGNAL.
	D Allocate bits 13 to 15 to OUT_SIGNAL.

n.X□□□	OUT_SIGNAL Allocation Enable/Disable Selection
	0 Disable OUT_SIGNAL allocation.
	1 Enable OUT_SIGNAL allocation.

Pn833	2	Motion Settings	0000h to 0001h	–	0000h	All	After restart	Setup	*2

n.□□□X	Linear Acceleration/Deceleration Constant Selection
	0 Use Pn80A to Pn80F and Pn827. (The settings of Pn834 to Pn840 are ignored.)
	1 Use Pn834 to Pn840. (The settings of Pn80A to Pn80F and Pn827 are ignored.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn834	4	First Stage Linear Acceleration Constant 2	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn836	4	Second Stage Linear Acceleration Constant 2	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn838	4	Acceleration Constant Switching Speed 2	0 to 2,097,152,000	1 reference unit/s	0	All	Immediately *11	Setup	*2
Pn83A	4	First Stage Linear Deceleration Constant 2	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn83C	4	Second Stage Linear Deceleration Constant 2	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn83E	4	Deceleration Constant Switching Speed 2	0 to 2,097,152,000	1 reference unit/s	0	All	Immediately *11	Setup	*2
Pn840	4	Linear Deceleration Constant 2 for Stopping	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *11	Setup	*2
Pn842 *13	4	Second Origin Approach Speed 1	0 to 20,971,520	100 reference units/s	0	All	Immediately *11	Setup	*2
Pn844 *14	4	Second Origin Approach Speed 2	0 to 20,971,520	100 reference units/s	0	All	Immediately *11	Setup	*2
Pn850	2	Number of Latch Sequences	0 to 8	–	0	All	Immediately	Setup	*2
Pn851	2	Continuous Latch Sequence Count	0 to 255	–	0	All	Immediately	Setup	*2
Pn852	2	Latch Sequence 1 to 4 Settings	0000h to 3333h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Latch Sequence 1 Signal Selection	
	0	Phase C
	1	EXT1 signal
	2	EXT2 signal
	3	EXT3 signal

n.□□X□	Latch Sequence 2 Signal Selection	
	0 to 3	The settings are the same as those for the Latch Sequence 1 Signal Selection.

n.□X□□	Latch Sequence 3 Signal Selection	
	0 to 3	The settings are the same as those for the Latch Sequence 1 Signal Selection.

n.X□□□	Latch Sequence 4 Signal Selection	
	0 to 3	The settings are the same as those for the Latch Sequence 1 Signal Selection.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn853	2	Latch Sequence 5 to 8 Settings	0000h to 3333h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Latch Sequence 5 Signal Selection
0	Phase C
1	EXT1 signal
2	EXT2 signal
3	EXT3 signal

n.□□X□	Latch Sequence 6 Signal Selection
0 to 3	The settings are the same as those for the Latch Sequence 5 Signal Selection.

n.□X□□	Latch Sequence 7 Signal Selection
0 to 3	The settings are the same as those for the Latch Sequence 5 Signal Selection.

n.X□□□	Latch Sequence 8 Signal Selection
0 to 3	The settings are the same as those for the Latch Sequence 5 Signal Selection.

Pn880	2	Station Address Monitor (for maintenance, read only)	40h to 5Fh	–	–	All	–	Setup	–
Pn881	2	Set Transmission Byte Count Monitor [bytes] (for maintenance, read only)	17, 32	–	–	All	–	Setup	–
Pn882	2	Transmission Cycle Setting Monitor [× 0.25 μs] (for maintenance, read only)	0h to FFFFh	–	–	All	–	Setup	–
Pn883	2	Communications Cycle Setting Monitor [transmission cycles] (for maintenance, read only)	0 to 32	–	–	All	–	Setup	–
Pn884	2	Communications Controls 2	0000h to 0001h	–	0000h	All	Immediately	Setup	-

n.□□□X	MECHATROLINK Communications Error Holding Brake Signal Setting
0	Maintain the status set by the BRK_ON or BRK_OFF command when a MECHATROLINK communications error occurs.
1	Apply the holding brake when a MECHATROLINK communications error occurs.

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn88A	2	MECHATROLINK Receive Error Counter Monitor (for maintenance, read only)	0 to 65,535	–	0	All	Immediately	Setup	–
Pn890 to Pn89E	4	Command Data Monitor during Alarm/Warning (for maintenance, read only)	0h to FFFFFFFFh	–	0h	All	Immediately	Setup	*2

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn8A0 to Pn8AE	4	Response Data Monitor during Alarm/Warning (for maintenance, read only)	0h to FFFFFFFFh	–	0h	All	Immediately	Setup	*2
Pn900	2	Number of Parameter Banks	0 to 16	–	0	All	After restart	Setup	*2
Pn901	2	Number of Parameter Bank Members	0 to 15	–	0	All	After restart	Setup	*2
Pn902 to Pn910	2	Parameter Bank Member Definition	0000h to 08FFh	–	0h	All	After restart	Setup	*2
Pn920 to Pn95F	2	Parameter Bank Data (Not saved in nonvolatile memory.)	0000h to FFFFh	–	0h	All	Immediately	Setup	*2

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual (Manual No.: SIEP S800001 27)

*2. Refer to the following manual for details.
Σ-7-Series AC Servo Drive MECHATROLINK-II Communications Command Manual (Manual No.: SIEP S800001 30)

*3. Set a percentage of the motor rated torque.

*4. These parameters are for SERVOPACKs with a Safety Module. Refer to the following manual for details.
Σ-V-Series/Σ-V-Series for Large-Capacity Models/Σ-7-Series User's Manual Safety Module (Manual No.: SIEP C720829 06)

*5. Normally set this parameter to 0. If you use an External Regenerative Resistor, set the capacity (W) of the External Regenerative Resistor.

*6. The upper limit is the maximum output capacity (W) of the SERVOPACK.

*7. These parameters are for SERVOPACKs with the dynamic brake option. Refer to the following manual for details.
Σ-7-Series AC Servo Drive Σ-7S/Σ-7W SERVOPACK with Hardware Option Specifications Dynamic Brake Product Manual (Manual No.: SIEP S800001 73)

*8. The SGLFW2 is the only Yaskawa Linear Servomotor that supports this function.

*9. Enabled only when Pn61A is set to n.□□□2 or n.□□□3.

*10. The parameter setting is enabled after SENS_ON command execution is completed.

*11. Change the setting when the reference is stopped (i.e., while DEN is set to 1). If you change the setting during operation, the reference output will be affected.

*12. The settings are updated only if the reference is stopped (i.e., only if DEN is set to 1).

*13. The setting of Pn842 is valid while Pn817 is set to 0.

*14. The setting of Pn844 is valid while Pn818 is set to 0.

4.3 FT82 SERVOPACK with MECHATROLINK-III Communications References

The following table lists the parameters.

Note: Do not change the following parameters from their default settings.
- Reserved parameters
- Parameters not given in this manual
- Parameters that are not valid for the Servomotor that you are using, as given in the parameter table

4.3.1 List of Servo Parameters

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn000	2	Basic Function Selections 0	0000h to 10B1h	–	0000h	All	After restart	Setup	–

n.□□□X	Rotation Direction Selection		Reference
	0	Use CCW as the forward direction.	*1
	1	Use CW as the forward direction. (Reverse Rotation Mode)	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn001	2	Application Function Selections 1	0000h to 1142h	–	0000h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Servo OFF and Group 1 Alarms		Reference
	0	Stop the motor by applying the dynamic brake.	*1
	1	Stop the motor by the applying dynamic brake and then release the dynamic brake.	
	2	Coast the motor to a stop without the dynamic brake.	

n.□□X□	Overtravel Stopping Method		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then servo-lock the motor.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A and then servo-lock the motor.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□X□□	Main Circuit Power Supply AC/DC Input Selection		Reference
	0	Input AC power as the main circuit power supply using the L1, L2, and L3 terminals (do not use shared converter).	*1
	1	Input DC power as the main circuit power supply using the B1/⊕ and ⊖ 2 terminals or the B1 and ⊖ 2 terminals (use an external converter or the shared converter).	
n.X□□□	Reserved parameter (Do not change.)		

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn002	2	Application Function Selections 2	0000h to 4213h	–	0011h	–	After restart	Setup	–

n.□□□X	MECHATROLINK Command Position and Speed Control Option		Applicable Motors	Reference
	0	Reserved setting (Do not use.)	All	*2
	1	Use TLIM as the torque limit.		
	2	Reserved setting (Do not use.)		
	3	Reserved setting (Do not use.)		

n.□□X□	Torque Control Option		Applicable Motors	Reference
	0	Reserved setting (Do not use.)	All	*2
	1	Use the speed limit for torque control (VLIM) as the speed limit.		

n.□X□□	Encoder Usage		Applicable Motors	Reference
	0	Use the encoder according to encoder specifications.	All	*1
	1	Use the encoder as an incremental encoder.		
	2	Use the encoder as a single-turn absolute encoder.	Rotary	

n.X□□□	External Encoder Usage		Applicable Motors	Reference
	0	Do not use an external encoder.	Rotary	*1
	1	The external encoder moves in the forward direction for CCW motor rotation.		
	2	Reserved setting (Do not use.)		
	3	The external encoder moves in the reverse direction for CCW motor rotation.		
	4	Reserved setting (Do not use.)		

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn006	2	Application Function Selections 6	0000h to 105Fh	–	0002h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 1 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn007	2	Application Function Selections 7	0000h to 105Fh	–	0000h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 2 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn008	2	Application Function Selections 8	0000h to 7121h	–	4000h	Rotary	After restart	Setup	–

n.□□□X	Low Battery Voltage Alarm/Warning Selection		Reference
	0	Output alarm (A.830) for low battery voltage.	*1
	1	Output warning (A.930) for low battery voltage.	
n.□□X□	Function Selection for Undervoltage		Reference
	0	Do not detect undervoltage.	*1
	1	Detect undervoltage warning and limit torque at host controller.	
	2	Detect undervoltage warning and limit torque with Pn424 and Pn425 (i.e., only in SERVOPACK).	
n.□X□□	Warning Detection Selection		Reference
	0	Detect warnings.	*1
	1	Do not detect warnings except for A.971.	
n.X□□□	Reserved parameter (Do not change.)		

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn009	2	Application Function Selections 9	0000h to 0121h	–	0010h	All	After restart	Tuning	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Current Control Mode Selection		Reference
	0	Use current control mode 1.	*1
	1	• SERVOPACK Models SGD7S-R70A, -R90A, -1R6A, -2R8A, -3R8A, -5R5A, and -7R6A: Use current control mode 1. • SERVOPACK Models SGD7S-120A, -180A, -200A, -330A, -470A, -550A, -590A, and -780A: Use current control mode 2.	
	2	Use current control mode 2.	

n.□X□□	Speed Detection Method Selection		Reference
	0	Use speed detection 1.	*1
	1	Use speed detection 2.	

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00A	2	Application Function Selections A	0000h to 0044h	–	0001h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Group 2 Alarms		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□□X□	Stopping Method for Forced Stops		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00B	2	Application Function Selections B	0000h to 1121h	–	0000h	All	After restart	Setup	–

n.□□□X	Operator Parameter Display Selection		Reference
	0	Display only setup parameters.	*1
	1	Display all parameters.	

n.□□X□	Motor Stopping Method for Group 2 Alarms		Reference
	0	Stop the motor by setting the speed reference to 0.	*1
	1	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	
	2	Set the stopping method with Pn00A = n.□□□X.	

n.□X□□	Power Input Selection for Three-phase SERVOPACK		Reference
	0	Use a three-phase power supply input.	*1
	1	Use a three-phase power supply input as a single-phase power supply input.	

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00C	2	Application Function Selections C	0000h to 0131h	–	0000h	–	After restart	Setup	*1

n.□□□X	Function Selection for Test without a Motor		Applicable Motors
	0	Disable tests without a motor.	All
	1	Enable tests without a motor.	

n.□□X□	Encoder Resolution for Tests without a Motor		Applicable Motors
	0	Use 13 bits.	Rotary
	1	Use 20 bits.	
	2	Use 22 bits.	
	3	Use 24 bits.	

n.□X□□	Encoder Type Selection for Tests without a Motor		Applicable Motors
	0	Use an incremental encoder.	All
	1	Use an absolute encoder.	

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00D	2	Application Function Selections D	0000h to 1001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Overtravel Warning Detection Selection	
	0	Do not detect overtravel warnings.
	1	Detect overtravel warnings.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00F	2	Application Function Selections F	0000h to 2011h	–	0000h	All	After restart	Setup	–

n.□□□X	Preventative Maintenance Warning Selection		Reference
	0	Do not detect preventative maintenance warnings.	*1
	1	Detect preventative maintenance warnings.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn021	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn022	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn040	2	Reserved parameter (Do not change.)	–	–	0000h	–	–	–	–
Pn081	2	Application Function Selections 81	0000h to 1111h	–	0000h	All	After restart	Setup	*1

n.□□□X	Phase-C Pulse Output Selection	
	0	Output phase-C pulses only in the forward direction.
	1	Output phase-C pulses in both the forward and reverse directions.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn100	2	Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn101	2	Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn102	2	Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn103	2	Moment of Inertia Ratio	0 to 20,000	1%	100	All	Immediately	Tuning	*1
Pn104	2	Second Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn105	2	Second Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn106	2	Second Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn109	2	Feedforward	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn10A	2	Feedforward Filter Time Constant	0 to 6,400	0.01 ms	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn10B	2	Gain Application Selections	0000h to 5334h	–	0000h	All	–	Setup	–

	Mode Switching Selection		When Enabled	Reference
n.□□□X	0	Use the internal torque reference as the condition (level setting: Pn10C).	Immediately	*1
	1	Use the speed reference as the condition (level setting: Pn10D).		
		Use the speed reference as the condition (level setting: Pn181).		
	2	Use the acceleration reference as the condition (level setting: Pn10E).		
		Use the acceleration reference as the condition (level setting: Pn182).		
	3	Use the position deviation as the condition (level setting: Pn10F).		
	4	Do not use mode switching.		

	Speed Loop Control Method		When Enabled	Reference
n.□□X□	0	PI control	After restart	*1
	1	I-P control		
	2 to 3	Reserved settings (Do not use.)		

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn10C	2	Mode Switching Level for Torque Reference	0 to 800	1%	200	All	Immediately	Tuning	*1
Pn10D	2	Mode Switching Level for Speed Reference	0 to 10,000	1 min^{-1}	0	Rotary	Immediately	Tuning	*1
Pn10E	2	Mode Switching Level for Acceleration	0 to 30,000	1 min^{-1}/s	0	Rotary	Immediately	Tuning	*1
Pn10F	2	Mode Switching Level for Position Deviation	0 to 10,000	1 reference unit	0	All	Immediately	Tuning	*1
Pn11F	2	Position Integral Time Constant	0 to 50,000	0.1 ms	0	All	Immediately	Tuning	*1
Pn121	2	Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn122	2	Second Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn123	2	Friction Compensation Coefficient	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn124	2	Friction Compensation Frequency Correction	-10,000 to 10,000	0.1 Hz	0	All	Immediately	Tuning	*1
Pn125	2	Friction Compensation Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn131	2	Gain Switching Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn132	2	Gain Switching Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn135	2	Gain Switching Waiting Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn136	2	Gain Switching Waiting Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn139	2	Automatic Gain Switching Selections 1	0000h to 0052h	–	0000h	All	Immediately	Tuning	*1

	Gain Switching Selection	
n.□□□X	0	Use manual gain switching. The gain is switched manually with G-SEL in the servo command output signals (SVCMD_IO).
	1	Reserved setting (Do not use.)
	2	Use automatic gain switching pattern 1. The gain is switched automatically from the first gain to the second gain when switching condition A is satisfied. The gain is switched automatically from the second gain to the first gain when switching condition A is not satisfied.

	Gain Switching Condition A	
n.□□X□	0	/COIN (Positioning Completion Output) signal turns ON.
	1	/COIN (Positioning Completion Output) signal turns OFF.
	2	/NEAR (Near Output) signal turns ON.
	3	/NEAR (Near Output) signal turns OFF.
	4	Position reference filter output is 0 and position reference input is OFF.
	5	Position reference input is ON.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn13D	2	Current Gain Level	100 to 2,000	1%	2000	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn140	2	Model Following Control-Related Selections	0000h to 1121h	–	0100h	All	Immediately	Tuning	–

n.□□□X	Model Following Control Selection		Reference
	0	Do not use model following control.	*1
	1	Use model following control.	

n.□□X□	Vibration Suppression Selection		Reference
	0	Do not perform vibration suppression.	*1
	1	Perform vibration suppression for a specific frequency.	
	2	Perform vibration suppression for two specific frequencies.	

n.□X□□	Vibration Suppression Adjustment Selection		Reference
	0	Do not adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

n.X□□□	Speed Feedforward (VFF)/Torque Feedforward (TFF) Selection		Reference
	0	Do not use model following control and speed/torque feedforward together.	*1
	1	Use model following control and speed/torque feedforward together.	

Pn141	2	Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn142	2	Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn143	2	Model Following Control Bias in the Forward Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn144	2	Model Following Control Bias in the Reverse Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn145	2	Vibration Suppression 1 Frequency A	10 to 2,500	0.1 Hz	500	All	Immediately	Tuning	*1
Pn146	2	Vibration Suppression 1 Frequency B	10 to 2,500	0.1 Hz	700	All	Immediately	Tuning	*1
Pn147	2	Model Following Control Speed Feedforward Compensation	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn148	2	Second Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn149	2	Second Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn14A	2	Vibration Suppression 2 Frequency	10 to 2,000	0.1 Hz	800	All	Immediately	Tuning	*1
Pn14B	2	Vibration Suppression 2 Correction	10 to 1,000	1%	100	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn14F	2	Control-Related Selections	0000h to 0021h	–	0021h	All	After restart	Tuning	–

n.□□□X	Model Following Control Type Selection		Reference
	0	Use model following control type 1.	*1
	1	Use model following control type 2.	

n.□□X□	Tuning-less Type Selection		Reference
	0	Use tuning-less type 1.	*1
	1	Use tuning-less type 2.	
	2	Use tuning-less type 3.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn160	2	Anti-Resonance Control-Related Selections	0000h to 0011h	–	0010h	All	Immediately	Tuning	–

n.□□□X	Anti-Resonance Control Selection		Reference
	0	Do not use anti-resonance control.	*1
	1	Use anti-resonance control.	

n.□□X□	Anti-Resonance Control Adjustment Selection		Reference
	0	Do not adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn161	2	Anti-Resonance Frequency	10 to 20,000	0.1 Hz	1000	All	Immediately	Tuning	*1
Pn162	2	Anti-Resonance Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn163	2	Anti-Resonance Damping Gain	0 to 300	1%	0	All	Immediately	Tuning	*1
Pn164	2	Anti-Resonance Filter Time Constant 1 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn165	2	Anti-Resonance Filter Time Constant 2 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn166	2	Anti-Resonance Damping Gain 2	0 to 1,000	1%	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn170	2	Tuning-less Function-Related Selections	0000h to 2711h	–	1401h	All	–	Setup	*1

n.□□□X	Tuning-less Selection		When Enabled
	0	Disable tuning-less function.	After restart
	1	Enable tuning-less function.	

n.□□X□	Speed Control Method		When Enabled
	0	Use for speed control.	After restart
	1	Use for speed control and use host controller for position control.	

n.□X□□	Rigidity Level		When Enabled
	0 to 7	Set the rigidity level.	Immediately

n.X□□□	Tuning-less Load Level		When Enabled
	0 to 2	Set the load level for the tuning-less function.	Immediately

Pn205	2	Multiturn Limit	0 to 65,535	1 rev	65535	Rotary	After restart	Setup	*1
Pn207	2	Position Control Function Selections	0000h to 2210h	–	0010h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)
n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)

n.X□□□	/COIN (Positioning Completion Output) Signal Output Timing		Reference
	0	Output when the absolute value of the position deviation is the same or less than the setting of Pn522 (Positioning Completed Width).	*1
	1	Output when the absolute value of the position error is the same or less than the setting of Pn522 (Positioning Completed Width) and the reference after the position reference filter is 0.	
	2	Output when the absolute value of the position error is the same or less than the setting of Pn522 (Positioning Completed Width) and the reference input is 0.	

Pn20A	4	Number of External Encoder Scale Pitches	4 to 1,048,576	1 scale pitch/revolution	32768	Rotary	After restart	Setup	*1
Pn20E	4	Electronic Gear Ratio (Numerator)	1 to 1,073,741,824	1	16	All	After restart	Setup	*1
Pn210	4	Electronic Gear Ratio (Denominator)	1 to 1,073,741,824	1	1	All	After restart	Setup	*1
Pn212	4	Number of Encoder Output Pulses	16 to 1,073,741,824	1 P/Rev	2048	Rotary	After restart	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn22A	2	Fully-closed Control Selections	0000h to 1003h	–	0000h	Rotary	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)	
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Fully-closed Control Speed Feedback Selection	
	0	Use motor encoder speed.
	1	Use external encoder speed.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn230	2	Position Control Expansion Function Selections	0000h to 0001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Backlash Compensation Direction	
	0	Compensate forward references.
	1	Compensate reverse references.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn231	4	Backlash Compensation	-500,000 to 500,000	0.1 reference units	0	All	Immediately	Setup	*1
Pn233	2	Backlash Compensation Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1
Pn281	2	Encoder Output Resolution	1 to 4,096	1 edge/pitch	20	All	After restart	Setup	*1
Pn304	2	Jogging Speed	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn305	2	Soft Start Acceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*2
Pn306	2	Soft Start Deceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*2
Pn308	2	Speed Feedback Filter Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1
Pn30A	2	Deceleration Time for Servo OFF and Forced Stops	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn30C	2	Speed Feedforward Average Movement Time	0 to 5,100	0.1 ms	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn310	2	Vibration Detection Selections	0000h to 0002h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Vibration Detection Selection	
	0	Do not detect vibration.
	1	Output a warning (A.911) if vibration is detected.
	2	Output an alarm (A.520) if vibration is detected.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn311	2	Vibration Detection Sensitivity	50 to 500	1%	100	All	Immediately	Tuning	*1
Pn312	2	Vibration Detection Level	0 to 5,000	1 min^{-1}	50	Rotary	Immediately	Tuning	*1
Pn316	2	Maximum Motor Speed	0 to 65,535	1 min^{-1}	10000	Rotary	After restart	Setup	*1
Pn324	2	Moment of Inertia Calculation Starting Level	0 to 20,000	1%	300	All	Immediately	Setup	*1
Pn401	2	First Stage First Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1
Pn402	2	Forward Torque Limit	0 to 800	1%*3	800	Rotary	Immediately	Setup	*1
Pn403	2	Reverse Torque Limit	0 to 800	1%*3	800	Rotary	Immediately	Setup	*1
Pn404	2	Forward External Torque Limit	0 to 800	1%*3	100	All	Immediately	Setup	*1
Pn405	2	Reverse External Torque Limit	0 to 800	1%*3	100	All	Immediately	Setup	*1
Pn406	2	Emergency Stop Torque	0 to 800	1%*3	800	All	Immediately	Setup	*1
Pn407	2	Speed Limit during Torque Control	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn408	2	Torque-Related Function Selections	0000h to 1111h	–	0000h	All	–	Setup	–

n.□□□X	Notch Filter Selection 1		When Enabled	Reference
	0	Disable first stage notch filter.	Immediately	*1
	1	Enable first stage notch filter.		

n.□□X□	Speed Limit Selection		When Enabled	Reference
	0	Use the smaller of the maximum motor speed and the setting of Pn407 as the speed limit.	After restart	*1
		Use the smaller of the maximum motor speed and the setting of Pn480 as the speed limit.		
	1	Use the smaller of the overspeed alarm detection speed and the setting of Pn407 as the speed limit.		
		Use the smaller of the overspeed alarm detection speed and the setting of Pn480 as the speed limit.		

n.□X□□	Notch Filter Selection 2		When Enabled	Reference
	0	Disable second stage notch filter.	Immediately	*1
	1	Enable second stage notch filter.		

n.X□□□	Friction Compensation Function Selection		When Enabled	Reference
	0	Disable friction compensation.	Immediately	*1
	1	Enable friction compensation.		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn409	2	First Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40A	2	First Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40B	2	First Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40C	2	Second Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40D	2	Second Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40E	2	Second Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40F	2	Second Stage Second Torque Reference Filter Frequency	100 to 5,000	1 Hz	4000	All	Immediately	Tuning	*1
Pn410	2	Second Stage Second Torque Reference Filter Q Value	50 to 100	0.01	50	All	Immediately	Tuning	*1
Pn412	2	First Stage Second Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn416	2	Torque-Related Function Selections 2	0000h to 1111h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Notch Filter Selection 3	
	0	Disable third stage notch filter.
	1	Enable third stage notch filter.

n.□□X□	Notch Filter Selection 4	
	0	Disable fourth stage notch filter.
	1	Enable fourth stage notch filter.

n.□X□□	Notch Filter Selection 5	
	0	Disable fifth stage notch filter.
	1	Enable fifth stage notch filter.

n.X□□□	Reserved parameter (Do not change.)

Pn417	2	Third Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn418	2	Third Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn419	2	Third Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41A	2	Fourth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41B	2	Fourth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41C	2	Fourth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41D	2	Fifth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41E	2	Fifth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41F	2	Fifth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn423	2	Speed Ripple Compensation Selections	0000h to 1111h	–	0000h	Rotary	–	Setup	*1

n.□□□X	Speed Ripple Compensation Function Selection		When Enabled
	0	Disable speed ripple compensation.	Immediately
	1	Enable speed ripple compensation.	

n.□□X□	Speed Ripple Compensation Information Disagreement Warning Detection Selection		When Enabled
	0	Detect A.942 alarms.	After restart
	1	Do not detect A.942 alarms.	

n.□X□□	Speed Ripple Compensation Enable Condition Selection		When Enabled
	0	Speed reference	After restart
	1	Motor speed	

n.X□□□	Reserved parameter (Do not change.)

Pn424	2	Torque Limit at Main Circuit Voltage Drop	0 to 100	1%*3	50	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn425	2	Release Time for Torque Limit at Main Circuit Voltage Drop	0 to 1,000	1 ms	100	All	Immediately	Setup	*1
Pn426	2	Torque Feedforward Average Movement Time	0 to 5,100	0.1 ms	0	All	Immediately	Setup	*1
Pn427	2	Speed Ripple Compensation Enable Speed	0 to 10,000	1 min^{-1}	0	Rotary Servomotor	Immediately	Tuning	*1
Pn456	2	Sweep Torque Reference Amplitude	1 to 800	1%	15	All	Immediately	Tuning	*1
Pn460	2	Notch Filter Adjustment Selections 1	0000h to 0101h	–	0101h	All	Immediately	Tuning	*1

n.□□□X	Notch Filter Adjustment Selection 1	
	0	Do not adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Notch Filter Adjustment Selection 2	
	0	Do not adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn475	2	Gravity Compensation-Related Selections	0000h to 0001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Gravity Compensation Selection	
	0	Disable gravity compensation.
	1	Enable gravity compensation.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn476	2	Gravity Compensation Torque	-1,000 to 1,000	0.1%	0	All	Immediately	Tuning	*1
Pn502	2	Rotation Detection Level	1 to 10,000	1 min^{-1}	20	Rotary	Immediately	Setup	*1
Pn503	2	Speed Coincidence Detection Signal Output Width	0 to 100	1 min^{-1}	10	Rotary	Immediately	Setup	*1
Pn506	2	Brake Reference-Servo OFF Delay Time	0 to 50	10 ms	0	All	Immediately	Setup	*1
Pn507	2	Brake Reference Output Speed Level	0 to 10,000	1 min^{-1}	100	Rotary	Immediately	Setup	*1
Pn508	2	Servo OFF-Brake Command Waiting Time	10 to 100	10 ms	50	All	Immediately	Setup	*1
Pn509	2	Momentary Power Interruption Hold Time	20 to 50,000	1 ms	20	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
Pn50A	2	Input Signal Selections 1	0000h to FFF2h	–	1881h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)
n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)

	P-OT (Forward Drive Prohibit) Signal Allocation		Reference
n.X□□□	0	Enable forward drive when CN1-13 input signal is ON (closed).	*1
	1	Enable forward drive when CN1-7 input signal is ON (closed).	
	2	Enable forward drive when CN1-8 input signal is ON (closed).	
	3	Enable forward drive when CN1-9 input signal is ON (closed).	
	4	Enable forward drive when CN1-10 input signal is ON (closed).	
	5	Enable forward drive when CN1-11 input signal is ON (closed).	
	6	Enable forward drive when CN1-12 input signal is ON (closed).	
	7	Set the signal to always prohibit forward drive.	
	8	Set the signal to always enable forward drive.	
	9	Enable forward drive when CN1-13 input signal is OFF (open).	
	A	Enable forward drive when CN1-7 input signal is OFF (open).	
	B	Enable forward drive when CN1-8 input signal is OFF (open).	
	C	Enable forward drive when CN1-9 input signal is OFF (open).	
	D	Enable forward drive when CN1-10 input signal is OFF (open).	
	E	Enable forward drive when CN1-11 input signal is OFF (open).	
	F	Enable forward drive when CN1-12 input signal is OFF (open).	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
Pn50B	2	Input Signal Selections 2	0000h to FFFFh	–	8882h	All	After restart	Setup	–

	N-OT (Reverse Drive Prohibit) Signal Allocation		Reference
n.□□□X	0	Enable reverse drive when CN1-13 input signal is ON (closed).	*1
	1	Enable reverse drive when CN1-7 input signal is ON (closed).	
	2	Enable reverse drive when CN1-8 input signal is ON (closed).	
	3	Enable reverse drive when CN1-9 input signal is ON (closed).	
	4	Enable reverse drive when CN1-10 input signal is ON (closed).	
	5	Enable reverse drive when CN1-11 input signal is ON (closed).	
	6	Enable reverse drive when CN1-12 input signal is ON (closed).	
	7	Set the signal to always prohibit reverse drive.	
	8	Set the signal to always enable reverse drive.	
	9	Enable reverse drive when CN1-13 input signal is OFF (open).	
	A	Enable reverse drive when CN1-7 input signal is OFF (open).	
	B	Enable reverse drive when CN1-8 input signal is OFF (open).	
	C	Enable reverse drive when CN1-9 input signal is OFF (open).	
	D	Enable reverse drive when CN1-10 input signal is OFF (open).	
	E	Enable reverse drive when CN1-11 input signal is OFF (open).	
	F	Enable reverse drive when CN1-12 input signal is OFF (open).	

n.□□X□	Reserved parameter (Do not change.)

	/P-CL (Forward External Torque Limit Input) Signal Allocation		Reference
n.□X□□	0	Active when CN1-13 input signal is ON (closed).	*1
	1	Active when CN1-7 input signal is ON (closed).	
	2	Active when CN1-8 input signal is ON (closed).	
	3	Active when CN1-9 input signal is ON (closed).	
	4	Active when CN1-10 input signal is ON (closed).	
	5	Active when CN1-11 input signal is ON (closed).	
	6	Active when CN1-12 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-13 input signal is OFF (open).	
	A	Active when CN1-7 input signal is OFF (open).	
	B	Active when CN1-8 input signal is OFF (open).	
	C	Active when CN1-9 input signal is OFF (open).	
	D	Active when CN1-10 input signal is OFF (open).	
	E	Active when CN1-11 input signal is OFF (open).	
	F	Active when CN1-12 input signal is OFF (open).	

	/N-CL (Reverse External Torque Limit Input) Signal Allocation		Reference
n.X□□□	0 to F	The allocations are the same as the /P-CL (Forward External Torque Limit Input) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50E	2	Output Signal Selections 1	0000h to 6666h	–	0000h	All	After restart	Setup	–

n.□□□X	/COIN (Positioning Completion Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-1 or CN1-2 output terminal.	
	2	Output the signal from the CN1-23 or CN1-24 output terminal.	
	3	Output the signal from the CN1-25 or CN1-26 output terminal.	
	4 to 6	Reserved setting (Do not use.)	

n.□□X□	/V-CMP (Speed Coincidence Detection Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

n.□X□□	/TGON (Rotation Detection Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

n.X□□□	/S-RDY (Servo Ready) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

Pn50F	2	Output Signal Selections 2	0000h to 6666h	–	0100h	All	After restart	Setup	–

n.□□□X	/CLT (Torque Limit Detection Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-1 or CN1-2 output terminal.	
	2	Output the signal from the CN1-23 or CN1-24 output terminal.	
	3	Output the signal from the CN1-25 or CN1-26 output terminal.	
	4 to 6	Reserved setting (Do not use.)	

n.□□X□	/VLT (Speed Limit Detection) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

n.□X□□	/BK (Brake Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

n.X□□□	/WARN (Warning Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn510	2	Output Signal Selections 3	0000h to 0666h	–	0000h	All	After restart	Setup	–

	/NEAR (Near Output) Signal Allocation		Reference
n.□□□X	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-1 or CN1-2 output terminal.	
	2	Output the signal from the CN1-23 or CN1-24 output terminal.	
	3	Output the signal from the CN1-25 or CN1-26 output terminal.	
	4 to 6	Reserved setting (Do not use.)	

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn511	2	Input Signal Selections 5	0000h to FFFFh	–	6543h	All	After restart	Setup	*1

	/DEC (Origin Return Deceleration Switch Input) Signal Allocation	
n.□□□X	0	Active when CN1-13 input signal is ON (closed).
	1	Active when CN1-7 input signal is ON (closed).
	2	Active when CN1-8 input signal is ON (closed).
	3	Active when CN1-9 input signal is ON (closed).
	4	Active when CN1-10 input signal is ON (closed).
	5	Active when CN1-11 input signal is ON (closed).
	6	Active when CN1-12 input signal is ON (closed).
	7	The signal is always active.
	8	The signal is always inactive.
	9	Active when CN1-13 input signal is OFF (open).
	A	Active when CN1-7 input signal is OFF (open).
	B	Active when CN1-8 input signal is OFF (open).
	C	Active when CN1-9 input signal is OFF (open).
	D	Active when CN1-10 input signal is OFF (open).
	E	Active when CN1-11 input signal is OFF (open).
	F	Active when CN1-12 input signal is OFF (open).

	/EXT1 (External Latch Input 1) Signal Allocation	
n.□□X□	0 to 3	The signal is always inactive.
	4	Active when CN1-10 input signal is ON (closed).
	5	Active when CN1-11 input signal is ON (closed).
	6	Active when CN1-12 input signal is ON (closed).
	D	Active when CN1-10 input signal is OFF (open).
	E	Active when CN1-11 input signal is OFF (open).
	F	Active when CN1-12 input signal is OFF (open).
	7 to C	The signal is always inactive.

	/EXT2 (External Latch Input 2) Signal Allocation	
n.□X□□	0 to F	The allocations are the same as the /EXT1 (External Latch Input 1) signal allocations.

	/EXT3 (External Latch Input 3) Signal Allocation	
n.X□□□	0 to F	The allocations are the same as the /EXT1 (External Latch Input 1) signal allocations.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn512	2	Output Signal Inverse Settings	0000h to 1111h	–	0000h	All	After restart	Setup	*1

n.□□□X	Output Signal Inversion for CN1-1 and CN1-2 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□□X□	Output Signal Inversion for CN1-23 and CN1-24 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□X□□	Output Signal Inversion for CN1-25 and CN1-26 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn514	2	Output Signal Selections 4	0000h to 0666h	–	0000h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	/PM (Preventative Maintenance Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-1 or CN1-2 output terminal.	
	2	Output the signal from the CN1-23 or CN1-24 output terminal.	
	3	Output the signal from the CN1-25 or CN1-26 output terminal.	
	4 to 6	Reserved setting (Do not use.)	

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn516	2	Input Signal Selections 7	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	FSTP (Forced Stop Input) Signal Allocation		Reference
n.□□□X	0	Enable drive when CN1-13 input signal is ON (closed).	*1
	1	Enable drive when CN1-7 input signal is ON (closed).	
	2	Enable drive when CN1-8 input signal is ON (closed).	
	3	Enable drive when CN1-9 input signal is ON (closed).	
	4	Enable drive when CN1-10 input signal is ON (closed).	
	5	Enable drive when CN1-11 input signal is ON (closed).	
	6	Enable drive when CN1-12 input signal is ON (closed).	
	7	Set the signal to always prohibit drive (always force the motor to stop).	
	8	Set the signal to always enable drive (always disable forcing the motor to stop).	
	9	Enable drive when CN1-13 input signal is OFF (open).	
	A	Enable drive when CN1-7 input signal is OFF (open).	
	B	Enable drive when CN1-8 input signal is OFF (open).	
	C	Enable drive when CN1-9 input signal is OFF (open).	
	D	Enable drive when CN1-10 input signal is OFF (open).	
	E	Enable drive when CN1-11 input signal is OFF (open).	
	F	Enable drive when CN1-12 input signal is OFF (open).	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn518*4	–	Safety Module-Related Parameters	–	–	–	All	–	–	–
Pn51B	4	Motor-Load Position Deviation Overflow Detection Level	0 to 1,073,741,824	1 reference unit	1000	Rotary	Immediately	Setup	*1
Pn51E	2	Position Deviation Overflow Warning Level	10 to 100	1%	100	All	Immediately	Setup	*1
Pn520	4	Position Deviation Overflow Alarm Level	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn522	4	Positioning Completed Width	0 to 1,073,741,824	1 reference unit	7	All	Immediately	Setup	*1
Pn524	4	Near Signal Width	1 to 1,073,741,824	1 reference unit	1073741824	All	Immediately	Setup	*1
Pn526	4	Position Deviation Overflow Alarm Level at Servo ON	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn528	2	Position Deviation Overflow Warning Level at Servo ON	10 to 100	1%	100	All	Immediately	Setup	*1
Pn529	2	Speed Limit Level at Servo ON	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1
Pn52A	2	Multiplier per Fully-closed Rotation	0 to 100	1%	20	Rotary	Immediately	Tuning	*1
Pn52B	2	Overload Warning Level	1 to 100	1%	20	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn52C	2	Base Current Derating at Motor Overload Detection	10 to 100	1%	100	All	After restart	Setup	*1
Pn530	2	Program Jogging-Related Selections	0000h to 0005h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Program Jogging Operation Pattern	
	0	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	1	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	2	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	3	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	4	(Waiting time in Pn535 → Forward by travel distance in Pn531 → Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	5	(Waiting time in Pn535 → Reverse by travel distance in Pn531 → Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn531	4	Program Jogging Travel Distance	1 to 1,073,741,824	1 reference unit	32768	All	Immediately	Setup	*1
Pn533	2	Program Jogging Movement Speed	1 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn534	2	Program Jogging Acceleration/Deceleration Time	2 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn535	2	Program Jogging Waiting Time	0 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn536	2	Program Jogging Number of Movements	0 to 1,000	Times	1	All	Immediately	Setup	*1
Pn550	2	Analog Monitor 1 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn551	2	Analog Monitor 2 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn552	2	Analog Monitor 1 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn553	2	Analog Monitor 2 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn55A	2	Power Consumption Monitor Unit Time	1 to 1,440	1 min	1	All	Immediately	Setup	–
Pn560	2	Residual Vibration Detection Width	1 to 3,000	0.1%	400	All	Immediately	Setup	*1
Pn561	2	Overshoot Detection Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn600	2	Regenerative Resistor Capacity*5	Depends on model.*6	10 W	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn601	2	Dynamic Brake Resistor Allowable Energy Consumption	0 to 65,535	10 J	0	All	After restart	Setup	*7
Pn603	2	Regenerative Resistance	0 to 65,535	10 mΩ	0	All	Immediately	Setup	*1
Pn604	2	Dynamic Brake Resistance	0 to 65,535	10 mΩ	0	All	After restart	Setup	*7
Pn61A	2	Overheat Protection Selections	0000h to 0003h	–	0000h	Linear	After restart	Setup	*1

n.□□□X	Overheat Protection Selection	
	0	Disable overheat protection.
	1	Use overheat protection in the Yaskawa Linear Servomotor.*8
	2	Monitor a negative voltage input from a sensor attached to the machine and use overheat protection.
	3	Monitor a positive voltage input from a sensor attached to the machine and use overheat protection.

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn61B *9	2	Overheat Alarm Level	0 to 500	0.01 V	250	All	Immediately	Setup	*1
Pn61C *9	2	Overheat Warning Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn61D *9	2	Overheat Alarm Filter Time	0 to 65,535	1 s	0	All	Immediately	Setup	*1
Pn621 to Pn628*4	–	Safety Module-Related Parameters	–	–	–	All	–	–	–

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn800	2	Communications Controls	0000h to 1FF3h	–	1040h	All	Immediately	Setup	–

n.□□□X	MECHATROLINK Communications Check Mask for Debugging	
	0	Do not mask.
	1	Ignore MECHATROLINK communications errors (A.E60).
	2	Ignore WDT errors (A.E50).
	3	Ignore both MECHATROLINK communications errors (A.E60) and WDT errors (A.E50).

n.□□X□	Warning Check Masks	
	0	Do not mask.
	1	Ignore data setting warnings (A.94□).
	2	Ignore command warnings (A.95□).
	3	Ignore both A.94□ and A.95□ warnings.
	4	Ignore communications warnings (A.96□).
	5	Ignore both A.94□ and A.96□ warnings.
	6	Ignore both A.95□ and A.96□ warnings.
	7	Ignore A.94□, A.95□, and A.96□ warnings.
	8	Ignore data setting warnings (A.97A and A.97b).
	9	Ignore A.94□, A.97A, and A.97b warnings.
	A	Ignore A.95□, A.97A, and A.97b warnings.
	B	Ignore A.94□, A.95□, A.97A, and A.97b warnings.
	C	Ignore A.96□, A.97A, and A.97b warnings.
	D	Ignore A.94□, A.96□, A.97A, and A.97b warnings.
	E	Ignore A.95□, A.96□, A.97A, and A.97b warnings.
	F	Ignore A.94□, A.95□, A.96□, A.97A, and A.97b warnings.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□ M3 *8	Automatic Warning Clear Selection for Debugging *8	
	0	Retain warnings for debugging.
	1	Automatically clear warnings (MECHATROLINK-III specification).

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn801	2	Application Function Selections 6 (Software Limits)	0000h to 0103h	–	0003h	All	Immediately	Setup	*1

n.□□□X	Software Limit Selection	
	0	Enable both forward and reverse software limits.
	1	Disable forward software limit.
	2	Disable reverse software limit.
	3	Disable both forward and reverse software limits.

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Software Limit Check for References	
	0	Do not perform software limit checks for references.
	1	Perform software limit checks for references.

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn803	2	Origin Range	0 to 250	1 reference unit	10	All	Immediately	Setup	*2

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn804	4	Forward Software Limit	-1,073,741,823 to 1,073,741,823	1 reference unit	107374 1823	All	Immediately	Setup	*1
Pn806	4	Reverse Software Limit	-1,073,741,823 to 1,073,741,823	1 reference unit	-10737 41823	All	Immediately	Setup	*1
Pn808	4	Absolute Encoder Origin Offset	-1,073,741,823 to 1,073,741,823	1 reference unit	0	All	Immediately *11	Setup	*1
Pn80A	2	First Stage Linear Acceleration Constant	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn80B	2	Second Stage Linear Acceleration Constant	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn80C	2	Acceleration Constant Switching Speed	0 to 65,535	100 reference units/s	0	All	Immediately *12	Setup	*2
Pn80D	2	First Stage Linear Deceleration Constant	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn80E	2	Second Stage Linear Deceleration Constant	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn80F	2	Deceleration Constant Switching Speed	0 to 65,535	100 reference units/s	0	All	Immediately *12	Setup	*2
Pn810	2	Exponential Acceleration/Deceleration Bias	0 to 65,535	100 reference units/s	0	All	Immediately *13	Setup	*2
Pn811	2	Exponential Acceleration/Deceleration Time Constant	0 to 5,100	0.1 ms	0	All	Immediately *13	Setup	*2
Pn812	2	Movement Average Time	0 to 5,100	0.1 ms	0	All	Immediately *13	Setup	*2
Pn814	4	External Positioning Final Travel Distance	-1,073,741,823 to 1,073,741,823	1 reference unit	100	All	Immediately	Setup	*2
Pn816 M2 *15	2	Origin Return Mode Settings	0000h to 0001h	–	0000h	All	Immediately	Setup	*14
Pn817 *16	2	Origin Approach Speed 1	0 to 65,535	100 reference units/s	50	All	Immediately *12	Setup	*2
Pn818 *17	2	Origin Approach Speed 2	0 to 65,535	100 reference units/s	5	All	Immediately *12	Setup	*2
Pn819	4	Final Travel Distance for Origin Return	-1,073,741,823 to 1,073,741,823	1 reference unit	100	All	Immediately	Setup	*2

n.□□□X	Origin Return Direction	
	0	Return in forward direction.
	1	Return in reverse direction.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn81E M2 *15	2	Input Signal Monitor Selections	0000h to 7777h	–	0000h	All	Immediately	Setup	*14

n.□□□X	IO12 Signal Mapping	
	0	Do not map.
	1	Monitor CN1-13 input terminal.
	2	Monitor CN1-7 input terminal.
	3	Monitor CN1-8 input terminal.
	4	Monitor CN1-9 input terminal.
	5	Monitor CN1-10 input terminal.
	6	Monitor CN1-11 input terminal.
	7	Monitor CN1-12 input terminal.

n.□□X□	IO13 Signal Mapping	
	0 to 7	The mappings are the same as the IO12 signal mappings.

n.□X□□	IO14 Signal Mapping	
	0 to 7	The mappings are the same as the IO12 signal mappings.

n.X□□□	IO15 Signal Mapping	
	0 to 7	The mappings are the same as the IO12 signal mappings.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn81F M2 *15	2	Command Data Allocations	0000h to 1111h	–	0010h	All	After restart	Setup	*14

n.□□□X	Option Field Allocation	
	0	Disable option field allocation.
	1	Enable option field allocation.

n.□□X□	Position Control Command TFF/TLIM Allocation	
	0	Disable allocation.
	1	Enable allocation.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn820	4	Forward Latching Area	-2,147,483,648 to 2,147,483,647	1 reference unit	0	All	Immediately	Setup	*2
Pn822	4	Reverse Latching Area	-2,147,483,648 to 2,147,483,647	1 reference unit	0	All	Immediately	Setup	*2

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn824 M3 *10	2	Option Monitor 1 Selection	0000h to FFFFh	–	0000h	–	Immediately	Setup	*2

Setting	Monitor	Applicable Motors
High-Speed Monitor Region		
0000h	Motor speed [1000000h/overspeed detection speed]	All
0001h	Speed reference [1000000h/overspeed detection speed]	All
0002h	Torque [1000000h/maximum torque]	All
0003h	Position deviation (lower 32 bits) [reference units]	All
0004h	Position deviation (upper 32 bits) [reference units]	All
000Ah	Encoder count (lower 32 bits) [reference units]	All
000Bh	Encoder count (upper 32 bits) [reference units]	All
000Ch	FPG count (lower 32 bits) [reference units]	All
000Dh	FPG count (upper 32 bits) [reference units]	All
Low-Speed Monitor Region		
0010h	Un000: Motor speed [min^{-1}]	All
0011h	Un001: Speed Reference [min^{-1}]	All
0012h	Un002: Torque Reference [%]	All
0013h	Un003: Rotational Angle 1 [encoder pulses] Number of encoder pulses from origin within one encoder rotation displayed in decimal	All
0014h	Un004: Rotational Angle 2 [deg] Electrical angle from polarity origin	All
0015h	Un005: Input Signal Monitor	All
0016h	Un006: Output Signal Monitor	All
0017h	Un007: Input Reference Speed [min^{-1}]	All
0018h	Un008: Position Deviation [reference units]	All
0019h	Un009: Accumulated Load Ratio [%]	All
001Ah	Un00A: Regenerative Load Ratio [%]	All
001Bh	Un00B: Dynamic Brake Resistor Power Consumption [%]	All
001Ch	Un00C: Input Reference Pulse Counter [reference units]	All
001Dh	Un00D: Feedback Pulse Counter [encoder pulses]	All
001Eh	Un00E: Fully-closed Loop Feedback Pulse Counter [external encoder resolution]	Rotary
0023h	Initial multiturn data [Rev]	Rotary
0024h	Initial incremental data [pulses]	Rotary
0040h	Un025: SERVOPACK Installation Environment Monitor	All
0041h	Un026: Servomotor Installation Environment Monitor	All
0042h	Un027: Built-in Fan Remaining Life Ratio	All
0043h	Un028: Capacitor Remaining Life Ratio	All
0044h	Un029: Surge Prevention Circuit Remaining Life Ratio	All
0045h	Un02A: Dynamic Brake Circuit Remaining Life Ratio	All
0046h	Un032: Instantaneous Power	All
0047h	Un033: Power Consumption	All
0048h	Un034: Cumulative Power Consumption	All
Communications Module Only		
0080h	Previous value of latched feedback position (LPOS1) [encoder pulses]	All
0081h	Previous value of latched feedback position (LPOS2) [encoder pulses]	All
0084h	Continuous Latch Status (EX STATUS)	All
All Areas		
Other values	Reserved settings (Do not use.)	All

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn825	2	Option Monitor 2 Selection	0000h to FFFFh	–	0000h	All	Immediately	Setup	*2

0000h to 0084h	The settings are the same as those for the Option Monitor 1 Selection.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn827	2	Linear Deceleration Constant 1 for Stopping	1 to 65,535	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn829	2	SVOFF Waiting Time (for SVOFF at Deceleration to Stop)	0 to 65,535	10 ms	0	All	Immediately *12	Setup	*2
Pn82A M2 *15	2	Option Field Allocations 1	0000h to 1E1Eh	–	1813h	All	After restart	Setup	*14

n.□□□X	ACCFIL Allocation (Option)	
	0	Allocate bits 0 and 1 to ACCFIL.
	1	Allocate bits 1 and 2 to ACCFIL.
	2	Allocate bits 2 and 3 to ACCFIL.
	3	Allocate bits 3 and 4 to ACCFIL.
	4	Allocate bits 4 and 5 to ACCFIL.
	5	Allocate bits 5 and 6 to ACCFIL.
	6	Allocate bits 6 and 7 to ACCFIL.
	7	Allocate bits 7 and 8 to ACCFIL.
	8	Allocate bits 8 and 9 to ACCFIL.
	9	Allocate bits 9 and 10 to ACCFIL.
	A	Allocate bits 10 and 11 to ACCFIL.
	B	Allocate bits 11 and 12 to ACCFIL.
	C	Allocate bits 12 and 13 to ACCFIL.
	D	Allocate bits 13 and 14 to ACCFIL.
	E	Allocate bits 14 and 15 to ACCFIL.

n.□□X□	ACCFIL Allocation Enable/Disable Selection	
	0	Disable ACCFIL allocation.
	1	Enable ACCFIL allocation.

n.□X□□	G_SEL Allocation (Option)	
	0 to E	The settings are the same as for the ACCFIL allocations.

n. X□□□	G_SEL Allocation Enable/Disable Selection	
	0	Disable G_SEL allocation.
	1	Enable G_SEL allocation.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
Pn82B M2 *15	2	Option Field Allocations 2	0000h to 1F1Fh	–	1D1Ch	All	After restart	Setup	*14

n.□□□X	V_PPI Allocation (Option)
	0 Allocate bit 0 to V_PPI.
	1 Allocate bit 1 to V_PPI.
	2 Allocate bit 2 to V_PPI.
	3 Allocate bit 3 to V_PPI.
	4 Allocate bit 4 to V_PPI.
	5 Allocate bit 5 to V_PPI.
	6 Allocate bit 6 to V_PPI.
	7 Allocate bit 7 to V_PPI.
	8 Allocate bit 8 to V_PPI.
	9 Allocate bit 9 to V_PPI.
	A Allocate bit 10 to V_PPI.
	B Allocate bit 11 to V_PPI.
	C Allocate bit 12 to V_PPI.
	D Allocate bit 13 to V_PPI.
	E Allocate bit 14 to V_PPI.
	F Allocate bit 15 to V_PPI.

n.□□X□	V_PPI Allocation Enable/Disable Selection
	0 Disable V_PPI allocation.
	1 Enable V_PPI allocation.

n.□X□□	P_PI_CLR Allocation (Option)
	0 to F The settings are the same as for the V_PPI allocations.

n.X□□□	P_PI_CLR Allocation Enable/Disable Selection
	0 Disable P_PI_CLR allocation.
	1 Enable P_PI_CLR allocation.

Pn82C M2 *15	2	Option Field Allocations 3	0000h to 1F1Fh	–	1F1Eh	All	After restart	Setup	*14

n.□□□X	P_CL Allocation (Option)
	0 to F The settings are the same as for the V_PPI allocations.

n.□□X□	P_CL Allocation Enable/Disable Selection
	0 Disable P_CL allocation.
	1 Enable P_CL allocation.

n.□X□□	N_CL Allocation (Option)
	0 to F The settings are the same as for the V_PPI allocations.

n.X□□□	N_CL Allocation Enable/Disable Selection
	0 Disable N_CL allocation.
	1 Enable N_CL allocation.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn82D M2 *15	2	Option Field Allocations 4	0000h to 1F1Ch	–	0000h	All	After restart	Setup	*14

n.□□□X	BANK_SEL1 Allocation (Option)	
	0	Allocate bits 0 to 3 to BANK_SEL1.
	1	Allocate bits 1 to 4 to BANK_SEL1.
	2	Allocate bits 2 to 5 to BANK_SEL1.
	3	Allocate bits 3 to 6 to BANK_SEL1.
	4	Allocate bits 4 to 7 to BANK_SEL1.
	5	Allocate bits 5 to 8 to BANK_SEL1.
	6	Allocate bits 6 to 9 to BANK_SEL1.
	7	Allocate bits 7 to 10 to BANK_SEL1.
	8	Allocate bits 8 to 11 to BANK_SEL1.
	9	Allocate bits 9 to 12 to BANK_SEL1.
	A	Allocate bits 10 to 13 to BANK_SEL1.
	B	Allocate bits 11 to 14 to BANK_SEL1.
	C	Allocate bits 12 to 15 to BANK_SEL1.

n.□□X□	BANK_SEL1 Allocation Enable/Disable Selection	
	0	Disable BANK_SEL1 allocation.
	1	Enable BANK_SEL1 allocation.

n.□X□□	LT_DISABLE Allocation (Option)	
	0 to F	The settings are the same as for the V_PPI allocations.

n.X□□□	LT_DISABLE Allocation Enable/Disable Selection	
	0	Disable LT_DISABLE allocation.
	1	Enable LT_DISABLE allocation.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn82E M2 *15	2	Option Field Allocations 5	0000h to 1D1Fh	–	0000h	All	After restart	Setup	*14

n.□□□X	Reserved parameter (Do not change.)	

n.□□X□	Reserved parameter (Do not change.)	

n.□X□□	OUT_SIGNAL Allocation (Option)	
	0	Allocate bits 0 to 2 to OUT_SIGNAL.
	1	Allocate bits 1 to 3 to OUT_SIGNAL.
	2	Allocate bits 2 to 4 to OUT_SIGNAL.
	3	Allocate bits 3 to 5 to OUT_SIGNAL.
	4	Allocate bits 4 to 6 to OUT_SIGNAL.
	5	Allocate bits 5 to 7 to OUT_SIGNAL.
	6	Allocate bits 6 to 8 to OUT_SIGNAL.
	7	Allocate bits 7 to 9 to OUT_SIGNAL.
	8	Allocate bits 8 to 10 to OUT_SIGNAL.
	9	Allocate bits 9 to 11 to OUT_SIGNAL.
	A	Allocate bits 10 to 12 to OUT_SIGNAL.
	B	Allocate bits 11 to 13 to OUT_SIGNAL.
	C	Allocate bits 12 to 14 to OUT_SIGNAL.
	D	Allocate bits 13 to 15 to OUT_SIGNAL.

n.X□□□	OUT_SIGNAL Allocation Enable/Disable Selection	
	0	Disable OUT_SIGNAL allocation.
	1	Enable OUT_SIGNAL allocation.

Pn833	2	Motion Settings	0000h to 0001h	–	0000h	All	After restart	Setup	*2

n.□□□X	Linear Acceleration/Deceleration Constant Selection	
	0	Use Pn80A to Pn80F and Pn827. (The settings of Pn834 to Pn840 are ignored.)
	1	Use Pn834 to Pn840. (The settings of Pn80A to Pn80F and Pn827 are ignored.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn834	4	First Stage Linear Acceleration Constant 2	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn836	4	Second Stage Linear Acceleration Constant 2	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn838	4	Acceleration Constant Switching Speed 2	0 to 2,097,152,000	1 reference unit/s	0	All	Immediately *12	Setup	*2
Pn83A	4	First Stage Linear Deceleration Constant 2	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn83C	4	Second Stage Linear Deceleration Constant 2	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn83E	4	Deceleration Constant Switching Speed 2	0 to 2,097,152,000	1 reference unit/s	0	All	Immediately *12	Setup	*2
Pn840	4	Linear Deceleration Constant 2 for Stopping	1 to 20,971,520	10,000 reference units/s^2	100	All	Immediately *12	Setup	*2
Pn842 *16	4	Second Origin Approach Speed 1	0 to 20,971,520	100 reference units/s	0	All	Immediately *12	Setup	*2
Pn844 *17	4	Second Origin Approach Speed 2	0 to 20,971,520	100 reference units/s	0	All	Immediately *12	Setup	*2
Pn846	2	POSING Command Scurve Acceleration/ Deceleration Rate	0 to 50	1%	0	All	Immediately *12	Setup	–
Pn850	2	Number of Latch Sequences	0 to 8	–	0	All	Immediately	Setup	*2
Pn851	2	Continuous Latch Sequence Count	0 to 255	–	0	All	Immediately	Setup	*2
Pn852	2	Latch Sequence 1 to 4 Settings	0000h to 3333h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Latch Sequence 1 Signal Selection
0	Phase C
1	EXT1 signal
2	EXT2 signal
3	EXT3 signal

n.□□X□	Latch Sequence 2 Signal Selection
0 to 3	The settings are the same as those for the Latch Sequence 1 Signal Selection.

n.□X□□	Latch Sequence 3 Signal Selection
0 to 3	The settings are the same as those for the Latch Sequence 1 Signal Selection.

n.X□□□	Latch Sequence 4 Signal Selection
0 to 3	The settings are the same as those for the Latch Sequence 1 Signal Selection.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn853	2	Latch Sequence 5 to 8 Settings	0000h to 3333h	–	0000h	All	Immediately	Setup	*2

	Latch Sequence 5 Signal Selection	
n.□□□X	0	Phase C
	1	EXT1 signal
	2	EXT2 signal
	3	EXT3 signal

	Latch Sequence 6 Signal Selection	
n.□□X□	0 to 3	The settings are the same as those for the Latch Sequence 5 Signal Selection.

	Latch Sequence 7 Signal Selection	
n.□X□□	0 to 3	The settings are the same as those for the Latch Sequence 5 Signal Selection.

	Latch Sequence 8 Signal Selection	
n.X□□□	0 to 3	The settings are the same as those for the Latch Sequence 5 Signal Selection.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn860 M3 *10	2	SVCMD_IO Input Signal Monitor Allocations 1	0000h to 1717h	–	0000h	All	Immediately	Setup	*2

	Input Signal Monitor Allocation for CN1-13 (SVCMD_IO)	
n.□□□X	0	Allocate bit 24 (IO_STS1) to CN1-13 input signal monitor.
	1	Allocate bit 25 (IO_STS2) to CN1-13 input signal monitor.
	2	Allocate bit 26 (IO_STS3) to CN1-13 input signal monitor.
	3	Allocate bit 27 (IO_STS4) to CN1-13 input signal monitor.
	4	Allocate bit 28 (IO_STS5) to CN1-13 input signal monitor.
	5	Allocate bit 29 (IO_STS6) to CN1-13 input signal monitor.
	6	Allocate bit 30 (IO_STS7) to CN1-13 input signal monitor.
	7	Allocate bit 31 (IO_STS8) to CN1-13 input signal monitor.

	CN1-13 Input Signal Monitor Enable/Disable Selection	
n.□□X□	0	Disable allocation for CN1-13 input signal monitor.
	1	Enable allocation for CN1-13 input signal monitor.

	Input Signal Monitor Allocation for CN1-7 (SVCMD_IO)	
n.□X□□	0 to 7	The settings are the same as the CN1-13 allocations.

	CN1-7 Input Signal Monitor Enable/Disable Selection	
n.X□□□	0	Disable allocation for CN1-7 input signal monitor.
	1	Enable allocation for CN1-7 input signal monitor.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn861 M3 *10	2	SVCMD_IO Input Signal Monitor Allocations 2	0000h to 1717h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Input Signal Monitor Allocation for CN1-8 (SVCMD_IO)	
	0 to 7	The settings are the same as the CN1-13 allocations.
n.□□X□	CN1-8 Input Signal Monitor Enable/Disable Selection	
	0	Disable allocation for CN1-8 input signal monitor.
	1	Enable allocation for CN1-8 input signal monitor.
n.□X□□	Input Signal Monitor Allocation for CN1-9 (SVCMD_IO)	
	0 to 7	The settings are the same as the CN1-13 allocations.
n.X□□□	CN1-9 Input Signal Monitor Enable/Disable Selection	
	0	Disable allocation for CN1-9 input signal monitor.
	1	Enable allocation for CN1-9 input signal monitor.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn862 M3 *10	2	SVCMD_IO Input Signal Monitor Allocations 3	0000h to 1717h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Input Signal Monitor Allocation for CN1-10 (SVCMD_IO)	
	0 to 7	The settings are the same as the CN1-13 allocations.
n.□□X□	CN1-10 Input Signal Monitor Enable/Disable Selection	
	0	Disable allocation for CN1-10 input signal monitor.
	1	Enable allocation for CN1-10 input signal monitor.
n.□X□□	Input Signal Monitor Allocation for CN1-11 (SVCMD_IO)	
	0 to 7	The settings are the same as the CN1-13 allocations.
n.X□□□	CN1-11 Input Signal Monitor Enable/Disable Selection	
	0	Disable allocation for CN1-11 input signal monitor.
	1	Enable allocation for CN1-11 input signal monitor.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn863 M3 *10	2	SVCMD_IO Input Signal Monitor Allocations 4	0000h to 1717h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Input Signal Monitor Allocation for CN1-12 (SVCMD_IO)	
	0 to 7	The settings are the same as the CN1-13 allocations.
n.□□X□	CN1-12 Input Signal Monitor Enable/Disable Selection	
	0	Disable allocation for CN1-12 input signal monitor.
	1	Enable allocation for CN1-12 input signal monitor.
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn868 M3 *10	2	SVCMD_IO Output Signal Monitor Allocations 1	0000h to 1717h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Output Signal Monitor Allocation for CN1-1 and CN1-2 (SVCMD_IO)
0	Allocate bit 24 (IO_STS1) to CN1-1/CN1-2 output signal monitor.
1	Allocate bit 25 (IO_STS2) to CN1-1/CN1-2 output signal monitor.
2	Allocate bit 26 (IO_STS3) to CN1-1/CN1-2 output signal monitor.
3	Allocate bit 27 (IO_STS4) to CN1-1/CN1-2 output signal monitor.
4	Allocate bit 28 (IO_STS5) to CN1-1/CN1-2 output signal monitor.
5	Allocate bit 29 (IO_STS6) to CN1-1/CN1-2 output signal monitor.
6	Allocate bit 30 (IO_STS7) to CN1-1/CN1-2 output signal monitor.
7	Allocate bit 31 (IO_STS8) to CN1-1/CN1-2 output signal monitor.

n.□□X□	CN1-1/CN1-2 Output Signal Monitor Enable/Disable Selection
0	Disable allocation for CN1-1/CN1-2 output signal monitor.
1	Enable allocation for CN1-1/CN1-2 output signal monitor.

n.□X□□	Output Signal Monitor Allocation for CN1-23 and CN1-24 (SVCMD_IO)
0 to 7	The settings are the same as the CN1-1/CN1-2 allocations.

n.X□□□	CN1-23/CN1-24 Output Signal Monitor Enable/Disable Selection
0	Disable allocation for CN1-23/CN1-24 output signal monitor.
1	Enable allocation for CN1-23/CN1-24 output signal monitor.

Pn869 M3 *10	2	SVCMD_IO Output Signal Monitor Allocations 2	0000h to 1717h	–	0000h	All	Immediately	Setup	*2

n.□□□X	Output Signal Monitor Allocation for CN1-25 and CN1-26 (SVCMD_IO)
0 to 7	The settings are the same as the CN1-1/CN1-2 allocations.

n.□□X□	CN1-25/CN1-26 Output Signal Monitor Enable/Disable Selection
0	Disable allocation for CN1-25/CN1-26 output signal monitor.
1	Enable allocation for CN1-25/CN1-26 output signal monitor.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn880	2	Station Address Monitor (for maintenance, read only)	03h to EFh	–	–	All	–	Setup	–
Pn881	2	Set Transmission Byte Count Monitor [bytes] (for maintenance, read only)	17, 32, 48	–	–	All	–	Setup	–
Pn882	2	Transmission Cycle Setting Monitor [× 0.25 μs] (for maintenance, read only)	0h to FFFFh	–	–	All	–	Setup	–
Pn883	2	Communications Cycle Setting Monitor [transmission cycles] (for maintenance, read only)	0 to 32	–	–	All	–	Setup	–

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn884 M3 *10	2	Communications Controls 2	0000h to 0001h	–	0000h	All	Immediately	Setup	*2

n.□□□X	MECHATROLINK Communications Error Holding Brake Signal Setting	
	0	Maintain the status set by the BRK_ON or BRK_OFF command when a MECHATROLINK communications error occurs.
	1	Apply the holding brake when a MECHATROLINK communications error occurs.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn88A	2	MECHATROLINK Receive Error Counter Monitor (for maintenance, read only)	0 to 65,535	–	0	All	Immediately	Setup	–
Pn890 to Pn8A6	4	Command Data Monitor during Alarm/Warning (for maintenance, read only)	0h to FFFFFFFFh	–	0h	All	Immediately	Setup	*2
Pn8A8 to Pn8BE	4	Response Data Monitor during Alarm/Warning (for maintenance, read only)	0h to FFFFFFFFh	–	0h	All	Immediately	Setup	*2
Pn900	2	Number of Parameter Banks	0 to 16	–	0	All	After restart	Setup	*2
Pn901	2	Number of Parameter Bank Members	0 to 15	–	0	All	After restart	Setup	*2
Pn902 to Pn910	2	Parameter Bank Member Definition	0000h to 08FFh	–	0h	All	After restart	Setup	*2
Pn920 to Pn95F	2	Parameter Bank Data (Not saved in nonvolatile memory.)	0000h to FFFFh	–	0h	All	Immediately	Setup	*2

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual (Manual No.: SIEP S800001 28)

*2. Refer to the following manual for details.
Σ-7-Series AC Servo Drive MECHATROLINK-III Communications Standard Servo Profile Command Manual (Manual No.: SIEP S800001 31)

*3. Set a percentage of the motor rated torque.

*4. These parameters are for SERVOPACKs with a Safety Module. Refer to the following manual for details.
Σ-V-Series/Σ-V-Series for Large-Capacity Models/Σ-7-Series User's Manual Safety Module (Manual No.: SIEP C720829 06)

*5. Normally set this parameter to 0. If you use an External Regenerative Resistor, set the capacity (W) of the External Regenerative Resistor.

*6. The upper limit is the maximum output capacity (W) of the SERVOPACK.

*7. These parameters are for SERVOPACKs with the dynamic brake option. Refer to the following manual for details.
Σ-7-Series AC Servo Drive Σ-7S/Σ-7W SERVOPACK with Hardware Option Specifications Dynamic Brake Product Manual (Manual No.: SIEP S800001 73)

*8. The SGLFW2 is the only Yaskawa Linear Servomotor that supports this function.

*9. Enabled only when Pn61A is set to n.□□□2 or n.□□□3.

*10. This parameter is valid only when the MECHATROLINK-III standard servo profile is used.

*11. The parameter setting is enabled after SENS_ON command execution is completed.

*12. Change the setting when the reference is stopped (i.e., while DEN is set to 1). If you change the setting during operation, the reference output will be affected.

*13. The settings are updated only if the reference is stopped (i.e., only if DEN is set to 1).

*14. Refer to the following manual for details.
Σ-7-Series AC Servo Drive MECHATROLINK-II Communications Command Manual (Manual No.: SIEP S800001 30)

*15. This parameter is valid only when the MECHATROLINK-II-compatible profile is used.

*16. The setting of Pn842 is valid while Pn817 is set to 0.

*17. The setting of Pn844 is valid while Pn818 is set to 0.

4.3.2 List of MECHATROLINK-III Common Parameters

The following table lists the common MECHATROLINK-III parameters. These common parameters are used to make settings from the host controller via MECHATROLINK communications. Do not change the settings with the Digital Operator or any other device.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
01 PnA02	4	Encoder Type Selection (read only)	0h or 1h	–	–	All	–	Device information
		0000h: Absolute encoder 0001h: Incremental encoder						
02 PnA04	4	Motor Type Selection (read only)	0h or 1h	–	–	All	–	
		0000h: Rotary Servomotor 0001h: Linear Servomotor						
03 PnA06	4	Semi-closed/Fully-closed Selection (read only)	0h or 1h	–	–	All	–	
		0000h: Semi-closed 0001h: Fully-closed						
04 PnA08	4	Rated Motor Speed (read only)	0h to FFFFFFFFh	1 min^{-1}	–	All	–	
05 PnA0A	4	Maximum Output Speed (read only)	0h to FFFFFFFFh	1 min^{-1}	–	All	–	
06 PnA0C	4	Speed Multiplier (read only)	-1,073,741,823 to 1,073,741,823	–	–	All	–	
07 PnA0E	4	Rated Torque (read only)	0h to FFFFFFFFh	1 N·m	–	All	–	
08 PnA10	4	Maximum Output Torque (read only)	0h to FFFFFFFFh	1 N·m	–	All	–	
09 PnA12	4	Torque Multiplier (read only)	-1,073,741,823 to 1,073,741,823	–	–	All	–	
0A PnA14	4	Resolution (read only)	0h to FFFFFFFFh	1 pulse/rev	–	Rotary	–	

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Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
21 PnA42	4	Electronic Gear Ratio (Numerator)	1 to 1,073,741,824	–	16	All	After restart	Machine specifications
22 PnA44	4	Electronic Gear Ratio (Denominator)	1 to 1,073,741,824	–	1	All	After restart	
23 PnA46	4	Absolute Encoder Origin Offset	-1,073,741,823 to 1,073,741,823	1 reference unit	0	All	Immediately[*1]	
24 PnA48	4	Multiturn Limit Setting	0 to 65,535	1 Rev	65535	Rotary	After restart	
25 PnA4A	4	Limit Setting	0h to 33h	–	0000h	All	After restart	
		Bit 0: P-OT (0: Enabled, 1: Disabled) Bit 1: N-OT (0: Enabled, 1: Disabled) Bit 2: Reserved. Bit 3: Reserved. Bit 4: P-SOT (0: Disabled, 1: Enabled) Bit 5: N-SOT (0: Disabled, 1: Enabled) Bits 6 to 31: Reserved.						
26 PnA4C	4	Forward Software Limit	-1,073,741,823 to 1,073,741,823	1 reference unit	1073741823	All	Immediately	
27 PnA4E	4	Reserved parameter (Do not change.)	–	–	0	All	Immediately	
28 PnA50	4	Reverse Software Limit	-1,073,741,823 to 1,073,741,823	1 reference unit	-1073741823	All	Immediately	
29 PnA52	4	Reserved parameter (Do not change.)	–	–	0	All	Immediately	
41 PnA82	4	Speed Unit Selection[*2]	0h to 4h	–	0h	All	After restart	Unit settings
		0000h: Reference units/s 0001h: Reference units/min 0002h: Percentage (%) of rated speed[*3] 0003h: min^{-1}[*3] 0004h: Maximum motor speed/40000000h[*4]						
42 PnA84	4	Speed Base Unit Selection[*3, *4] (Set the value of n from the following formula: Speed unit selection (41 PnA82) × 10^n)	-3 to 3	–	0	All	After restart	
43 PnA86	4	Position Unit Selection	0h	–	0h	All	After restart	
		0000h: Reference units						

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Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
44 PnA88	4	Position Base Unit Selection (Set the value of n from the following formula: Position unit selection (43 PnA86) × 10^n)	0	–	0	All	After restart	Unit settings
45 PnA8A	4	Acceleration Unit Selection	0h	–	0h	All	After restart	
	0000h	Reference units/s^2						
46 PnA8C	4	Acceleration Base Unit Selection (Set the value of n from the following formula: Acceleration unit selection (45 PnA8A) × 10^n)	4 to 6	–	4	All	After restart	
47 PnA8E	4	Torque Unit Selection	1h to 2h	–	1h	All	After restart	
	0001h	Percentage (%) of rated torque						
	0002h	Maximum torque/40000000h*5						
48 PnA90	4	Torque Base Unit Selection*5 (Set the value of n from the following formula: Torque unit selection (47 PnA8E) × 10^n)	-5 to 0	–	0	All	After restart	
49 PnA92	4	Supported Unit Systems (read only)	–	–	0601011Fh	All	–	
	Speed Units							
	Bit 0	Reference units/s (1: Enabled)						
	Bit 1	Reference units/min (1: Enabled)						
	Bit 2	Percentage (%) of rated speed (1: Enabled)						
	Bit 3	min^{-1} (rpm) (1: Enabled)						
	Bit 4	Maximum motor speed/4000000h (1: Enabled)						
	Bits 5 to 7	Reserved (0: Disabled).						
	Position Units							
	Bit 8	Reference units (1: Enabled)						
	Bits 9 to 15	Reserved (0: Disabled).						
	Acceleration Units							
	Bit 16	Reference units/s^2 (1: Enabled)						
	Bit 17	ms (acceleration time required to reach rated speed) (0: Disabled)						
	Bits 18 to 23	Reserved (0: Disabled).						
	Torque Units							
	Bit 24	N·m (0: Disabled)						
	Bit 25	Percentage (%) of rated torque (1: Enabled)						
	Bit 26	Maximum torque/40000000h						
	Bits 27 to 31	Reserved (0: Disabled).						

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Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
61 PnAC2	4	Speed Loop Gain	1,000 to 2,000,000	0.001 Hz [0.1 Hz]	40000	All	Immediately	Tuning
62 PnAC4	4	Speed Loop Integral Time Constant	150 to 512,000	1 µs [0.01 ms]	20000	All	Immediately	
63 PnAC6	4	Position Loop Gain	1,000 to 2,000,000	0.001/s [0.1/s]	40000	All	Immediately	
64 PnAC8	4	Feedforward Compensation	0 to 100	1%	0	All	Immediately	
65 PnACA	4	Position Loop Integral Time Constant	0 to 5,000,000	1 µs [0.1 ms]	0	All	Immediately	
66 PnACC	4	Positioning Completed Width	0 to 1,073,741,824	1 reference unit	7	All	Immediately	
67 PnACE	4	Near Signal Width	1 to 1,073,741,824	1 reference unit	1073741824	All	Immediately	
81 PnB02	4	Exponential Acceleration/Deceleration Time Constant	0 to 510,000	1 µs [0.1 ms]	0	All	Immediately*6	
82 PnB04	4	Average Movement Time	0 to 510,000	1 µs [0.1 ms]	0	All	Immediately*6	
83 PnB06	4	External Positioning Final Travel Distance	-1,073,741,823 to 1,073,741,823	1 reference unit	100	All	Immediately	
84 PnB08	4	Origin Approach Speed	0 to 1,073,741,823	10^{-3} min^{-1}	× 5,000h reference units/s converted to 10^{-3} min^{-1}	All	Immediately	
85 PnB0A	4	Origin Return Creep Speed	0 to 1,073,741,823	10^{-3} min^{-1}	× 500h reference units/s converted to 10^{-3} min^{-1}	All	Immediately	
86 PnB0C	4	Final Travel Distance for Origin Return	-1,073,741,823 to 1,073,741,823	1 reference unit	100	All	Immediately	
87 PnB0E	4	Fixed Monitor Selection 1	0 to 15	–	1h	All	Immediately	

0	APOS
1	CPOS
2	PERR
3	LPOS1
4	LPOS2
5	FSPD
6	CSPD
7	TRQ
8	ALARM
9	MPOS
10	Reserved (undefined value).
11	Reserved (undefined value).
12	CMN1 (common monitor 1)
13	CMN2 (common monitor 2)
14	OMN1 (optional monitor 1)
15	OMN2 (optional monitor 2)

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Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
88 PnB10	4	Fixed Monitor Selection 2	0 to 15	–	0h	All	Immediately	Command-related parameters

0 to 15	The settings are the same as those for Fixed Monitor Selection 1.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
89 PnB12	4	SEL_MON (CMN1) Monitor Selection 1	0 to 9	–	0h	All	Immediately	Command-related parameters

0	TPOS (target position in reference coordinate system)
1	IPOS (reference position in reference coordinate system)
2	POS_OFFSET (offset set in POS_SET (Set Coordinate System) command)
3	TSPD (target speed)
4	SPD_LIM (speed limit)
5	TRQ_LIM (torque limit)
6	SV_STAT (servo actual operating status) Monitor Description Byte 1: Current communications phase 00h: Phase 0 01h: Phase 1 02h: Phase 2 03h: Phase 3 Byte 2: Current control mode 00h: Position control mode 01h: Speed control mode 02h: Torque control mode Byte 3: Reserved Byte 4: Expansion signal monitor

Bit	Name	Description	Value	Setting
Bit 0	LT_RDY1	Processing status for latch detection for LT_REQ1 in SVCMD_CTRL region	0	Latch detection not yet processed.
			1	Processing latch detection in progress.
Bit 1	LT_RDY1	Processing status for latch detection for LT_REQ2 in SVCMD_CTRL region	0	Latch detection not yet processed.
			1	Processing latch detection in progress.
Bits 2 and 3	LT_SEL1R	Latch signal	0	Phase C
			1	External input signal 1
			2	External input signal 2
			3	External input signal 3
Bits 4 and 5	LT_SEL2R	Latch signal	0	Phase C
			1	External input signal 1
			2	External input signal 2
			3	External input signal 3
Bit 6	Reserved (0).			

7	Reserved.	
8	INIT_PGPOS (Low)	Lower 32 bits of initial encoder position converted to 64-bit position reference data
9	INIT_PGPOS (High)	Upper 32 bits of initial encoder position converted to 64-bit position reference data

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Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
8A PnB14	4	SEL_MON (CMN2) Monitor Selection 2	0 to 9	–	0h	All	Immediately	Command-related parameters
	0 to 9	The settings are the same as those for SEL_MON Monitor Selection 1.						
8B PnB16	4	Origin Detection Width	0 to 250	1 reference unit	10	All	Immediately	
8C PnB18	4	Forward Torque Limit	0 to 800	1%	100	All	Immediately	
8D PnB1A	4	Reverse Torque Limit	0 to 800	1%	100	All	Immediately	
8E PnB1C	4	Zero Speed Detection Range	1,000 to 10,000,000	10^{-3} min^{-1}	20000	All	Immediately	
8F PnB1E	4	Speed Coincidence Signal Detection Width	0 to 100,000	10^{-3} min^{-1}	10000	All	Immediately	
90 PnB20	4	Servo Command Control Field Enable/ Disable Selections (read only)	–	–	0FFF3F3Fh	All	–	

Bit 0	CMD_PAUSE (1: Enabled)
Bit 1	CMD_CANCEL (1: Enabled)
Bits 2 and 3	STOP_MODE (1: Enabled)
Bits 4 and 5	ACCFIL (1: Enabled)
Bits 6 and 7	Reserved (0: Disabled).
Bit 8	LT_REQ1 (1: Enabled)
Bit 9	LT_REQ2 (1: Enabled)
Bits 10 and 11	LT_SEL1 (1: Enabled)
Bits 12 and 13	LT_SEL2 (1: Enabled)
Bits 14 and 15	Reserved (0: Disabled).
Bits 16 to 19	SEL_MON1 (1: Enabled)
Bits 20 to 23	SEL_MON2 (1: Enabled)
Bits 24 to 27	SEL_MON3 (1: Enabled)
Bits 28 to 31	Reserved (0: Disabled).

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Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
91 PnB22	4	Servo Status Field Enable/Disable Selections (read only)	–	–	0FFF3F33h	All	–	Command-related parameters

Bit 0	CMD_PAUSE_CMP (1: Enabled)
Bit 1	CMD_CANCEL_CMP (1: Enabled)
Bit 2 and 3	Reserved (0: Disabled).
Bits 4 and 5	ACCFIL (1: Enabled)
Bits 6 and 7	Reserved (0: Disabled).
Bit 8	L_CMP1 (1: Enabled)
Bit 9	L_CMP2 (1: Enabled)
Bit 10	POS_RDY (1: Enabled)
Bit 11	PON (1: Enabled)
Bit 12	M_RDY (1: Enabled)
Bit 13	SV_ON (1: Enabled)
Bits 14 and 15	Reserved (0: Disabled).
Bits 16 to 19	SEL_MON1 (1: Enabled)
Bits 20 to 23	SEL_MON2 (1: Enabled)
Bits 24 to 27	SEL_MON3 (1: Enabled)
Bits 28 to 31	Reserved (0: Disabled).

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
92 PnB24	4	Output Bit Enable/ Disable Selections (read only)	–	–	007F01F0h	All	–	Command-related parameters

Bits 0 to 3	Reserved (0: Disabled).
Bit 4	V_PPI (1: Enabled)
Bit 5	P_PPI (1: Enabled)
Bit 6	P_CL (1: Enabled)
Bit 7	N_CL (1: Enabled)
Bit 8	G_SEL (1: Enabled)
Bits 9 to 11	G_SEL (0: Disabled)
Bits 12 to 15	Reserved (0: Disabled).
Bits 16 to 19	BANK_SEL (1: Enabled)
Bits 20 to 22	SO1 to SO3 (1: Enabled)
Bit 23	Reserved (0: Disabled).
Bits 24 to 31	Reserved (0: Disabled).

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Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
93 PnB26	4	Input Bit Enable/Disable Selections (read only)	–	–	FF0FFEFEh	All	–	Command-related parameters

Bit 0	Reserved (0: Disabled).
Bit 1	DEC (1: Enabled)
Bit 2	P-OT (1: Enabled)
Bit 3	N-OT (1: Enabled)
Bit 4	EXT1 (1: Enabled)
Bit 5	EXT2 (1: Enabled)
Bit 6	EXT3 (1: Enabled)
Bit 7	ESTP (1: Enabled)
Bit 8	Reserved (0: Disabled).
Bit 9	BRK_ON (1: Enabled)
Bit 10	P-SOT (1: Enabled)
Bit 11	N-SOT (1: Enabled)
Bit 12	DEN (1: Enabled)
Bit 13	NEAR (1: Enabled)
Bit 14	PSET (1: Enabled)
Bit 15	ZPOINT (1: Enabled)
Bit 16	T_LIM (1: Enabled)
Bit 17	V_LIM (1: Enabled)
Bit 18	V_CMP (1: Enabled)
Bit 19	ZSPD (1: Enabled)
Bits 20 to 23	Reserved (0: Disabled).
Bits 24 to 31	I0_STS1 to I0_STS8 (1: Enabled)

*1. The parameter setting is enabled after SENS_ON command execution is completed.
*2. When using fully-closed loop control, set the reference units/s.
*3. If you set the Speed Unit Selection (parameter 41) to either 0002h or 0003h, set the Speed Base Unit Selection (parameter 42) to a number between -3 and 0.
*4. If you set the Speed Unit Selection (parameter 41) to 0004h, set the Speed Base Unit Selection (parameter 42) to 0.
*5. If you set the Torque Unit Selection (parameter 47) to 0002h, set the Torque Base Unit Selection (parameter 48) to 0.
*6. Change the setting when the reference is stopped (i.e., while DEN is set to 1). If you change the setting during operation, the reference output will be affected.

4.4 Command Option Attachable-type FT82 SERVOPACKs with INDEXER Modules

The following table lists the parameters.

Note: Do not change the following parameters from their default settings.
- Reserved parameters
- Parameters not given in this manual
- Parameters that are not valid for the Servomotor that you are using, as given in the parameter table


Note

- The following parameters will be set automatically when the INDEXER Module is mounted. Do not change the settings of these parameters.
  Pn002 = n.□□□X, Pn205, Pn207 = n.X□□□, Pn50A to Pn512, Pn517, and Pn522
- Parameters that are unique to the INDEXER Module will be set automatically the first time the power supply is turned on after the INDEXER Module is mounted. Up to 10 s may be required for the SERVOPACK to start.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn000	2	Basic Function Selections 0	0000h to 10B1h	–	0000h	All	After restart	Setup	–

n.□□□X	Rotation Direction Selection		Reference
	0	Use CCW as the forward direction.	*1
	1	Use CW as the forward direction. (Reverse Rotation Mode)	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn001	2	Application Function Selections 1	0000h to 1142h	–	0000h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Servo OFF and Group 1 Alarms		Reference
	0	Stop the motor by applying the dynamic brake.	*1
	1	Stop the motor by the applying dynamic brake and then release the dynamic brake.	
	2	Coast the motor to a stop without the dynamic brake.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Main Circuit Power Supply AC/DC Input Selection		Reference
	0	Input AC power as the main circuit power supply using the L1, L2, and L3 terminals (do not use shared converter).	*1
	1	Input DC power as the main circuit power supply using the B1/⊕ and ⊖ 2 terminals or the B1 and ⊖ 2 terminals (use an external converter or the shared converter).	
n.X□□□	Warning Code Output Selection		Reference
	0	Output only alarm codes on the /ALO1 to /ALO3 terminals.	*1
	1	Output both warning codes and alarm codes on the /ALO1 to /ALO3 terminals. If there is an alarm, the alarm code is output.	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn002	2	Application Function Selections 2	0000h to 4213h	–	0000h*2	–	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

			Applicable Motors	Reference
n.□X□□	Encoder Usage			
	0	Use the encoder according to encoder specifications.	All	*1
	1	Use the encoder as an incremental encoder.		
	2	Use the encoder as a single-turn absolute encoder.	Rotary	

			Applicable Motors	Reference
n.X□□□	External Encoder Usage			
	0	Do not use an external encoder.	Rotary	*1
	1	The external encoder moves in the forward direction for CCW motor rotation.		
	2	Reserved setting (Do not use.)		
	3	The external encoder moves in the reverse direction for CCW motor rotation.		
	4	Reserved setting (Do not use.)		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn006	2	Application Function Selections 6	0000h to 105Fh	–	0002h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 1 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn007	2	Application Function Selections 7	0000h to 105Fh	–	0000h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 2 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn008	2	Application Function Selections 8	0000h to 7121h	–	4000h	Rotary	After restart	Setup	–

n.□□□X	Low Battery Voltage Alarm/Warning Selection		Reference
	0	Output alarm (A.830) for low battery voltage.	*1
	1	Output warning (A.930) for low battery voltage.	

n.□□X□	Function Selection for Undervoltage		Reference
	0	Do not detect undervoltage.	*1
	1	Detect undervoltage warning and limit torque at host controller.	
	2	Detect undervoltage warning and limit torque with Pn424 and Pn425 (i.e., only in SERVOPACK).	

n.□X□□	Warning Detection Selection		Reference
	0	Detect warnings.	*1
	1	Do not detect warnings except for A.971.	

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
Pn009	2	Application Function Selections 9	0000h to 0121h	–	0010h	All	After restart	Tuning	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Current Control Mode Selection		Reference
	0	Use current control mode 1.	*1
	1	• SERVOPACK Models SGD7S-R70A, -R90A, -1R6A, -2R8A, -3R8A, -5R5A, and -7R6A: Use current control mode 1. • SERVOPACK Models SGD7S-120A, -180A, -200A, -330A, -470A, -550A, -590A, and -780A: Use current control mode 2.	
	2	Use current control mode 2.	

n.□X□□	Speed Detection Method Selection		Reference
	0	Use speed detection 1.	*1
	1	Use speed detection 2.	

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
Pn00A	2	Application Function Selections A	0000h to 0044h	–	0001h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Group 2 Alarms		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00B	2	Application Function Selections B	0000h to 1121h	–	0000h	All	After restart	Setup	–

n.□□□X		Operator Parameter Display Selection	Reference
	0	Display only setup parameters.	*1
	1	Display all parameters.	

n.□□X□		Motor Stopping Method for Group 2 Alarms	Reference
	0	Stop the motor by setting the speed reference to 0.	*1
	1	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	
	2	Set the stopping method with Pn00A = n.□□□X.	

n.□X□□		Power Input Selection for Three-phase SERVOPACK	Reference
	0	Use a three-phase power supply input.	*1
	1	Use a three-phase power supply input and as a single-phase power supply input.	

n.X□□□	Reserved parameter (Do not change.)

Pn00C	2	Application Function Selections C	0000h to 0131h	–	0000h	–	After restart	Setup	*1

n.□□□X		Function Selection for Test without a Motor	Applicable Motors
	0	Disable tests without a motor.	All
	1	Enable tests without a motor.	

n.□□X□		Encoder Resolution for Tests without a Motor	Applicable Motors
	0	Use 13 bits.	Rotary
	1	Use 20 bits.	
	2	Use 22 bits.	
	3	Use 24 bits.	

n.□X□□		Encoder Type Selection for Tests without a Motor	Applicable Motors
	0	Use an incremental encoder.	All
	1	Use an absolute encoder.	

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00D	2	Application Function Selections D	0000h to 1001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Stand-alone Mode (Test Operation) Selection	
	0	Enable connection with the Command Option Module.
	1	Disable connection with the Command Option Module.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Overtravel Warning Detection Selection	
	0	Do not detect overtravel warnings.
	1	Detect overtravel warnings.

Pn00E	2	Reserved parameter (Do not change.)	–	–	0000	All	–	–	–
Pn00F	2	Application Function Selections F	0000h to 2011h	–	0000h	All	After restart	Setup	–

n.□□□X	Preventative Maintenance Warning Selection		Reference
	0	Do not detect preventative maintenance warnings.	*1
	1	Detect preventative maintenance warnings.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn010	2	Axis Address Selection (For UART/USB communications)	0000h to 007Fh	–	0001h	All	After restart	Setup	–
Pn021	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn022	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn040	2	Reserved parameter (Do not change.)	–	–	0000h	–	–	–	–
Pn081	2	Application Function Selections 81	0000h to 1111h	–	0000h	All	After restart	Setup	*1

n.□□□X	Phase-C Pulse Output Selection	
	0	Output phase-C pulses only in the forward direction.
	1	Output phase-C pulses in both the forward and reverse directions.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn100	2	Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn101	2	Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn102	2	Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn103	2	Moment of Inertia Ratio	0 to 20,000	1%	100	All	Immediately	Tuning	*1
Pn104	2	Second Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn105	2	Second Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn106	2	Second Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn109	2	Feedforward	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn10A	2	Feedforward Filter Time Constant	0 to 6,400	0.01 ms	0	All	Immediately	Tuning	*1
Pn10B	2	Gain Application Selections	0000h to 5334h	–	0000h	All	–	Setup	–

	Mode Switching Selection		When Enabled	Reference
n.□□□X	0	Use the internal torque reference as the condition (level setting: Pn10C).	Immediately	*1
	1	Use the speed reference as the condition (level setting: Pn10D).		
		Use the speed reference as the condition (level setting: Pn181).		
	2	Use the acceleration reference as the condition (level setting: Pn10E).		
		Use the acceleration reference as the condition (level setting: Pn182).		
	3	Use the position deviation as the condition (level setting: Pn10F).		
	4	Do not use mode switching.		

	Speed Loop Control Method		When Enabled	Reference
n.□□X□	0	PI control	After restart	*1
	1	I-P control		
	2 to 3	Reserved settings (Do not use.)		

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn10C	2	Mode Switching Level for Torque Reference	0 to 800	1%	200	All	Immediately	Tuning	*1
Pn10D	2	Mode Switching Level for Speed Reference	0 to 10,000	1 min^{-1}	0	Rotary	Immediately	Tuning	*1
Pn10E	2	Mode Switching Level for Acceleration	0 to 30,000	1 min^{-1}/s	0	Rotary	Immediately	Tuning	*1
Pn10F	2	Mode Switching Level for Position Deviation	0 to 10,000	1 reference unit	0	All	Immediately	Tuning	*1
Pn11F	2	Position Integral Time Constant	0 to 50,000	0.1 ms	0	All	Immediately	Tuning	*1
Pn121	2	Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn122	2	Second Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn123	2	Friction Compensation Coefficient	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn124	2	Friction Compensation Frequency Correction	-10,000 to 10,000	0.1 Hz	0	All	Immediately	Tuning	*1
Pn125	2	Friction Compensation Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn131	2	Gain Switching Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn132	2	Gain Switching Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn135	2	Gain Switching Waiting Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn136	2	Gain Switching Waiting Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn139	2	Automatic Gain Switching Selections 1	0000h to 0052h	–	0000h	All	Immediately	Tuning	*1

	Gain Switching Selection	
n.□□□X	0	Disable automatic gain switching.
	1	Reserved setting (Do not use.)
	2	Enable automatic gain switching.

	Gain Switching Condition A	
n.□□X□	0	/COIN (Positioning Completion Output) signal turns ON.
	1	/COIN (Positioning Completion Output) signal turns OFF.
	2	/NEAR (Near Output) signal turns ON.
	3	/NEAR (Near Output) signal turns OFF.
	4	Position reference filter output is 0 and position reference input is OFF.
	5	Position reference input is ON.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn13D	2	Current Gain Level	100 to 2,000	1%	2000	All	Immediately	Tuning	*1
Pn140	2	Model Following Control-Related Selections	0000h to 1121h	–	0100h	All	Immediately	Tuning	–

	Model Following Control Selection		Reference
n.□□□X	0	Do not use model following control.	*1
	1	Use model following control.	

	Vibration Suppression Selection		Reference
n.□□X□	0	Do not perform vibration suppression.	*1
	1	Perform vibration suppression for a specific frequency.	
	2	Perform vibration suppression for two specific frequencies.	

	Vibration Suppression Adjustment Selection		Reference
n.□X□□	0	Do not adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

n.X□□□	Reserved parameter (Do not change.)	

Pn141	2	Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn142	2	Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn143	2	Model Following Control Bias in the Forward Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn144	2	Model Following Control Bias in the Reverse Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn145	2	Vibration Suppression 1 Frequency A	10 to 2,500	0.1 Hz	500	All	Immediately	Tuning	*1
Pn146	2	Vibration Suppression 1 Frequency B	10 to 2,500	0.1 Hz	700	All	Immediately	Tuning	*1
Pn147	2	Model Following Control Speed Feedforward Compensation	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn148	2	Second Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn149	2	Second Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn14A	2	Vibration Suppression 2 Frequency	10 to 2,000	0.1 Hz	800	All	Immediately	Tuning	*1
Pn14B	2	Vibration Suppression 2 Correction	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn14F	2	Control-Related Selections	0000h to 0021h	–	0021h	All	After restart	Tuning	–

	Model Following Control Type Selection		Reference
n.□□□X	0	Use model following control type 1.	*1
	1	Use model following control type 2.	

	Tuning-less Type Selection		Reference
n.□□X□	0	Use tuning-less type 1.	*1
	1	Use tuning-less type 2.	
	2	Use tuning-less type 3.	

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn160	2	Anti-Resonance Control-Related Selections	0000h to 0011h	–	0010h	All	Immediately	Tuning	–

	Anti-Resonance Control Selection		Reference
n.□□□X	0	Do not use anti-resonance control.	*1
	1	Use anti-resonance control.	

	Anti-Resonance Control Adjustment Selection		Reference
n.□□X□	0	Do not adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn161	2	Anti-Resonance Frequency	10 to 20,000	0.1 Hz	1000	All	Immediately	Tuning	*1
Pn162	2	Anti-Resonance Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn163	2	Anti-Resonance Damping Gain	0 to 300	1%	0	All	Immediately	Tuning	*1
Pn164	2	Anti-Resonance Filter Time Constant 1 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn165	2	Anti-Resonance Filter Time Constant 2 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn166	2	Anti-Resonance Damping Gain 2	0 to 1,000	1%	0	All	Immediately	Tuning	*1
Pn170	2	Tuning-less Function-Related Selections	0000h to 2711h	–	1401h	All	–	Setup	*1

n.□□□X	Tuning-less Selection		When Enabled
	0	Disable tuning-less function.	After restart
	1	Enable tuning-less function.	

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Rigidity Level		When Enabled
	0 to 7	Set the rigidity level.	Immediately

n.X□□□	Tuning-less Load Level		When Enabled
	0 to 2	Set the load level for the tuning-less function.	Immediately

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn205	2	Multiturn Limit	0 to 65,535	1 rev	65535*3	Rotary	After restart	Setup	*1
Pn207	2	Reserved parameter (Do not change.)	–	–	0010h*2	All	–	–	–
Pn20A	2	Number of External Encoder Scale Pitches	4 to 1,048,576	1 scale pitch/ revolution	32768	Rotary	After restart	Setup	*1
Pn20E	2	Electronic Gear Ratio (Numerator)	1 to 1,073,741,824	1	64	All	After restart	Setup	*1
Pn210	2	Electronic Gear Ratio (Denominator)	1 to 1,073,741,824	1	1	All	After restart	Setup	*1
Pn212	2	Number of Encoder Output Pulses	16 to 1,073,741,824	1 P/Rev	2048	Rotary	After restart	Setup	*1
Pn217	2	Average Movement Time of Position Reference	0 to 10,000	0.1 ms	0	All	After the change and also after the motor has stopped	Setup	–
Pn22A	2	Fully-closed Control Selections	0000h to 1003h	–	0000h	Rotary	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Fully-closed Control Speed Feedback Selection	
	0	Use motor encoder speed.
	1	Use external encoder speed.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn230	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn231	2	Reserved parameter (Do not change.)	–	–	0	All	–	–	–
Pn233	2	Reserved parameter (Do not change.)	–	–	0	All	–	–	–
Pn281	2	Encoder Output Resolution	1 to 4,096	1 edge/pitch	20	All	After restart	Setup	*1
Pn304	2	Jogging Speed	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn305	2	Soft Start Acceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn306	2	Soft Start Deceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn308	2	Speed Feedback Filter Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1
Pn30A	2	Deceleration Time for Servo OFF and Forced Stops	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn30C	2	Reserved parameter (Do not change.)	–	–	0	All	–	–	–
Pn310	2	Vibration Detection Selections	0000h to 0002h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Vibration Detection Selection	
	0	Do not detect vibration.
	1	Output a warning (A.911) if vibration is detected.
	2	Output an alarm (A.520) if vibration is detected.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn311	2	Vibration Detection Sensitivity	50 to 500	1%	100	All	Immediately	Tuning	*1
Pn312	2	Vibration Detection Level	0 to 5,000	1 min^{-1}	50	Rotary	Immediately	Tuning	*1
Pn316	2	Maximum Motor Speed	0 to 65,535	1 min^{-1}	10000	Rotary	After restart	Setup	*1
Pn324	2	Moment of Inertia Calculation Starting Level	0 to 20,000	1%	300	All	Immediately	Setup	*1
Pn401	2	First Stage First Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1
Pn402	2	Forward Torque Limit	0 to 800	1%*4	800	Rotary	Immediately	Setup	*1
Pn403	2	Reverse Torque Limit	0 to 800	1%*4	800	Rotary	Immediately	Setup	*1
Pn404	2	Reserved parameter (Do not change.)	–	–	100	All	–	–	–
Pn405	2	Reserved parameter (Do not change.)	–	–	100	All	–	–	–
Pn406	2	Emergency Stop Torque	0 to 800	1%*4	800	All	Immediately	Setup	*1
Pn407	2	Reserved parameter (Do not change.)	–	–	10000	Rotary	–	–	–

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn408	2	Torque-Related Function Selections	0000h to 1111h	–	0000h	All	–	Setup	–

n.□□□X	Notch Filter Selection 1		When Enabled	Reference
	0	Disable first stage notch filter.	Immediately	*1
	1	Enable first stage notch filter.		

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Notch Filter Selection 2		When Enabled	Reference
	0	Disable second stage notch filter.	Immediately	*1
	1	Enable second stage notch filter.		

n.X□□□	Friction Compensation Function Selection		When Enabled	Reference
	0	Disable friction compensation.	Immediately	*1
	1	Enable friction compensation.		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn409	2	First Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40A	2	First Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40B	2	First Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40C	2	Second Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40D	2	Second Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40E	2	Second Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40F	2	Second Stage Second Torque Reference Filter Frequency	100 to 5,000	1 Hz	4000	All	Immediately	Tuning	*1
Pn410	2	Second Stage Second Torque Reference Filter Q Value	50 to 100	0.01	50	All	Immediately	Tuning	*1
Pn412	2	First Stage Second Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1
Pn416	2	Torque-Related Function Selections 2	0000h to 1111h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Notch Filter Selection 3	
	0	Disable third stage notch filter.
	1	Enable third stage notch filter.

n.□□X□	Notch Filter Selection 4	
	0	Disable fourth stage notch filter.
	1	Enable fourth stage notch filter.

n.□X□□	Notch Filter Selection 5	
	0	Disable fifth stage notch filter.
	1	Enable fifth stage notch filter.

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn417	2	Third Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn418	2	Third Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn419	2	Third Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41A	2	Fourth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41B	2	Fourth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41C	2	Fourth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41D	2	Fifth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41E	2	Fifth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41F	2	Fifth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn423	2	Speed Ripple Compensation Selections	0000h to 1111h	–	0000h	Rotary	–	Setup	*1

n.□□□X	Speed Ripple Compensation Function Selection		When Enabled
	0	Disable speed ripple compensation.	Immediately
	1	Enable speed ripple compensation.	

n.□□X□	Speed Ripple Compensation Information Disagreement Warning Detection Selection		When Enabled
	0	Detect A.942 alarms.	After restart
	1	Do not detect A.942 alarms.	

n.□X□□	Speed Ripple Compensation Enable Condition Selection		When Enabled
	0	Speed reference	After restart
	1	Motor speed	

n.X□□□	Reserved parameter (Do not change.)

Pn424	2	Torque Limit at Main Circuit Voltage Drop	0 to 100	1%*4	50	All	Immediately	Setup	*1
Pn425	2	Release Time for Torque Limit at Main Circuit Voltage Drop	0 to 1,000	1 ms	100	All	Immediately	Setup	*1
Pn426	2	Reserved parameter (Do not change.)	–	–	0	All	–	–	–
Pn427	2	Speed Ripple Compensation Enable Speed	0 to 10,000	1 min^{-1}	0	Rotary Servomotor	Immediately	Tuning	*1
Pn456	2	Sweep Torque Reference Amplitude	1 to 800	1%	15	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn460	2	Notch Filter Adjustment Selections 1	0000h to 0101h	–	0101h	All	Immediately	Tuning	*1

n.□□□X	Notch Filter Adjustment Selection 1	
	0	Do not adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Notch Filter Adjustment Selection 2	
	0	Do not adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.X□□□	Reserved parameter (Do not change.)	

Pn475	2	Gravity Compensation-Related Selections	0000h to 0001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Gravity Compensation Selection	
	0	Disable gravity compensation.
	1	Enable gravity compensation.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn476	2	Gravity Compensation Torque	-1,000 to 1,000	0.1%	0	All	Immediately	Tuning	*1
Pn502	2	Rotation Detection Level	0 to 10,000	1 min^{-1}	20	Rotary	Immediately	Setup	*1
Pn503	2	Reserved parameter (Do not change.)	–	–	10	Rotary	–	–	–
Pn506	2	Brake Reference-Servo OFF Delay Time	0 to 50	10 ms	0	All	Immediately	Setup	*1
Pn507	2	Brake Reference Output Speed Level	0 to 10,000	1 min^{-1}	100	Rotary	Immediately	Setup	*1
Pn508	2	Servo OFF-Brake Command Waiting Time	10 to 100	10 ms	50	All	Immediately	Setup	*1
Pn509	2	Momentary Power Interruption Hold Time	20 to 50,000	1 ms	20	All	Immediately	Setup	*1
Pn50A	2	Reserved parameter (Do not change.)	–	–	1881h*2	All	–	–	–
Pn50B	2	Reserved parameter (Do not change.)	–	–	8882h*2	All	–	–	–
Pn50E	2	Reserved parameter (Do not change.)	–	–	0000h*5	All	–	–	–
Pn50F	2	Reserved parameter (Do not change.)	–	–	0100h*6	All	–	–	–
Pn510	2	Reserved parameter (Do not change.)	–	–	0000h*1	All	–	–	–
Pn511	2	Reserved parameter (Do not change.)	–	–	6543h*7	All	–	–	–

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn512	2	Reserved parameter (Do not change.)	–	–	0000h*8	All	–	–	–
Pn514	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn516	2	Reserved parameter (Do not change.)	–	–	8888h	All	–	–	–
Pn517	2	Reserved parameter (Do not change.)	–	–	0000h*9	All	–	–	–
Pn518	2	Safety Module-Related Parameters	–	–	–	All	–	–	–
Pn51B	2	Motor-Load Position Deviation Overflow Detection Level	0 to 1,073,741,824	1 reference unit	1000	Rotary	Immediately	Setup	*1
Pn51E	2	Position Deviation Overflow Warning Level	10 to 100	1%	100	All	Immediately	Setup	*1
Pn520	2	Position Deviation Overflow Alarm Level	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn522	2	Reserved parameter (Do not change.)	–	–	7*10	All	–	–	–
Pn524	2	Reserved parameter (Do not change.)	–	–	1073741824	All	–	–	–
Pn526	2	Position Deviation Overflow Alarm Level at Servo ON	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn528	2	Position Deviation Overflow Warning Level at Servo ON	10 to 100	1%	100	All	Immediately	Setup	*1
Pn529	2	Speed Limit Level at Servo ON	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1
Pn52A	2	Multiplier per Fully-closed Rotation	0 to 100	1%	20	Rotary	Immediately	Tuning	*1
Pn52B	2	Overload Warning Level	1 to 100	1%	20	All	Immediately	Setup	*1
Pn52C	2	Base Current Derating at Motor Overload Detection	10 to 100	1%	100	All	After restart	Setup	*1
Pn530	2	Program Jogging-Related Selections	0000h to 0005h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Program Jogging Operation Pattern	
	0	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	1	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	2	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	3	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	4	(Waiting time in Pn535 → Forward by travel distance in Pn531 → Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	5	(Waiting time in Pn535 → Reverse by travel distance in Pn531 → Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn531	2	Program Jogging Travel Distance	1 to 1,073,741,824	1 reference unit	32768	All	Immediately	Setup	*1
Pn533	2	Program Jogging Movement Speed	1 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn534	2	Program Jogging Acceleration/Deceleration Time	2 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn535	2	Program Jogging Waiting Time	0 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn536	2	Program Jogging Number of Movements	0 to 1,000	Times	1	All	Immediately	Setup	*1
Pn550	2	Analog Monitor 1 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn551	2	Analog Monitor 2 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn552	2	Analog Monitor 1 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn553	2	Analog Monitor 2 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn55A	2	Power Consumption Monitor Unit Time	1 to 1,440	1 min	1	All	Immediately	Setup	–
Pn560	2	Residual Vibration Detection Width	1 to 3,000	0.1%	400	All	Immediately	Setup	*1
Pn561	2	Overshoot Detection Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn600	2	Regenerative Resistor Capacity*11	Depends on model.*12	10 W	0	All	Immediately	Setup	*1
Pn601	2	Dynamic Brake Resistor Allowable Energy Consumption	0 to 65,535	10 J	0	All	After restart	Setup	*13
Pn603	2	Regenerative Resistance	0 to 65,535	10 mΩ	0	All	Immediately	Setup	*1
Pn604	2	Dynamic Brake Resistance	0 to 65,535	10 mΩ	0	All	After restart	Setup	*13
Pn61A	2	Overheat Protection Selections	0000h to 0003h	–	0000h	Linear	After restart	Setup	*1

n.□□□X	Overheat Protection Selection	
	0	Disable overheat protection.
	1	Use overheat protection in the Yaskawa Linear Servomotor.*14
	2	Monitor a negative voltage input from a sensor attached to the machine and use overheat protection.
	3	Monitor a positive voltage input from a sensor attached to the machine and use overheat protection.

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn61B *15	2	Overheat Alarm Level	0 to 500	0.01 V	250	All	Immediately	Setup	*1
Pn61C *15	2	Overheat Warning Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn61D *15	2	Overheat Alarm Filter Time	0 to 65,535	1 s	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB00	2	Serial Communication Protocol	0 to 9	–	1	All	After restart	Setup	*1

0	Full-duplex wiring is used for communications method.
1	Full-duplex wiring is used for communications method. Echoback is performed for each character.
2	Half-duplex wiring is used for communications method. CR is used as delimiter.
3	Half-duplex wiring is used for communications method. CR is used as delimiter. Echoback is performed for each character.
4	Half-duplex wiring is used for communications method. CR is used as delimiter. Echoback is performed for each command.
5	Half-duplex wiring is used for communications method. CRLF is used as delimiter.
6	Half-duplex wiring is used for communications method. CRLF is used as delimiter. Echoback is performed for each character.
7	Half-duplex wiring is used for communications method. CRLF is used as delimiter. Echoback is performed for each command.
8, 9	Reserved parameter

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB01	2	Bit rate	0 to 2	–	0	All	After restart	Setup	*1

0	Sets bit rate at 9600 bps.
1	Sets bit rate at 19200 bps.
2	Sets bit rate at 38400 bps.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB02	2	Response “OK”	0, 1	–	1	All	Immediately	Setup	*1

0	Does not return OK response.
1	Returns OK response.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB03	2	/MODE 0/1	0 to 3	–	0	All	After restart	Setup	*1

0	When input signal is ON (closed), mode is set to Mode 0.
1	When input signal is OFF (open), mode is set to Mode 0.
2	Always Mode 0
3	Always Mode 1

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB04	2	/START-STOP; /HOME	0 to 3	–	0	All	After restart	Setup	*1

0	• When /MODE signal is ON (closed) (mode 0): Start program table operation when the /START-STOP signal turns ON (closes). Stop program table operation when the /START-STOP signal turns OFF (opens). • When /MODE signal is OFF (open) (mode 1): Turn ON (close) the /HOME signal to start an origin return.
1	• When /MODE signal is ON (closed) (mode 0): Start program table operation when the /START-STOP signal turns OFF (opens). Stop program table operation when the /START-STOP signal turns ON (closes). • When /MODE signal is OFF (open) (mode 1): Turn OFF (open) the /HOME signal to start an origin return.
2, 3	• When /MODE signal is ON (closed) (mode 0): Do not use the /START-STOP signal. • When /MODE signal is OFF (open) (mode 1): Do not use the /HOME signal.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB05	2	/PGMRES; /JOGP	0 to 3	–	0	All	After restart	Setup	*1

0	• When /MODE signal is ON (closed) (mode 0): Turn ON (close) the /PGMRES signal to reset and cancel program table operation. • When /MODE signal is OFF (open) (mode 1): Jog forward while the /JOGP signal is ON (closed).
1	• When /MODE signal is ON (closed) (mode 0): Turn OFF (open) the /PGMRES signal to reset and cancel program table operation. • When /MODE signal is OFF (open) (mode 1): Jog forward while the /JOGP signal is OFF (open).
2, 3	• When /MODE signal is ON (closed) (mode 0): Do not reset program table operation. • When /MODE signal is OFF (open) (mode 1): Do not perform jogging.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB06	2	/SEL0; /JOGN	0 to 3	–	0	All	After restart	Setup	*1

0	• When /MODE signal is ON (closed) (mode 0): /SEL0 signal is active when ON (closed). • When /MODE signal is OFF (open) (mode 1): Jog in reverse while the /JOGP signal is ON (closed).
1	• When /MODE signal is ON (closed) (mode 0): The /SEL0 signal is active when OFF (open). • When /MODE signal is OFF (open) (mode 1): Jog in reverse while the /JOGN signal is OFF (open).
2	• When /MODE signal is ON (closed) (mode 0): The /SEL0 signal is always active. • When /MODE signal is OFF (open) (mode 1): Do not perform jogging.
3	• When /MODE signal is ON (closed) (mode 0): The /SEL0 signal is always inactive. • When /MODE signal is OFF (open) (mode 1): Do not perform jogging.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB07	2	/SEL1; /JOG0	0 to 3	–	0	All	After restart	Setup	*1

0	• When /MODE signal is ON (closed) (mode 0): /SEL1 signal is active when ON (closed). • When /MODE signal is OFF (open) (mode 1): /JOG0 signal is active when ON (closed).
1	• When /MODE signal is ON (closed) (mode 0): The /SEL1 signal is active when OFF (open). • When /MODE signal is OFF (open) (mode 1): The /JOG0 signal is active when OFF (open).
2	• When /MODE signal is ON (closed) (mode 0): The /SEL1 signal is always active. • When /MODE signal is OFF (open) (mode 1): The /JOG0 signal is always active.
3	• When /MODE signal is ON (closed) (mode 0): The /SEL1 signal is always inactive. • When /MODE signal is OFF (open) (mode 1): The /JOG0 signal is always inactive.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB08	2	/SEL2; /JOG1	0 to 3	–	0	All	After restart	Setup	*1

0	• When /MODE signal is ON (closed) (mode 0): /SEL2 signal is active when ON (closed). • When /MODE signal is OFF (open) (mode 1): /JOG1 signal is active when ON (closed).
1	• When /MODE signal is ON (closed) (mode 0): The /SEL2 signal is active when OFF (open). • When /MODE signal is OFF (open) (mode 1): The /JOG1 signal is active when OFF (open).
2	• When /MODE signal is ON (closed) (mode 0): The /SEL2 signal is always active. • When /MODE signal is OFF (open) (mode 1): The /JOG1 signal is always active.
3	• When /MODE signal is ON (closed) (mode 0): The /SEL2 signal is always inactive. • When /MODE signal is OFF (open) (mode 1): The /JOG1 signal is always inactive.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB09	2	/SEL3; /JOG2	0 to 3	–	0	All	After restart	Setup	*1

0	• When /MODE signal is ON (closed) (mode 0): /SEL3 signal is active when ON (closed). • When /MODE signal is OFF (open) (mode 1): /JOG2 signal is active when ON (closed).
1	• When /MODE signal is ON (closed) (mode 0): The /SEL3 signal is active when OFF (open). • When /MODE signal is OFF (open) (mode 1): The /JOG2 signal is active when OFF (open).
2	• When /MODE signal is ON (closed) (mode 0): The /SEL3 signal is always active. • When /MODE signal is OFF (open) (mode 1): The /JOG2 signal is always active.
3	• When /MODE signal is ON (closed) (mode 0): The /SEL3 signal is always inactive. • When /MODE signal is OFF (open) (mode 1): The /JOG2 signal is always inactive.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB0A	2	/SEL4; /JOG3	0 to 3	–	0	All	After restart	Setup	*1

0	• When /MODE signal is ON (closed) (mode 0): /SEL4 signal is active when ON (closed). • When /MODE signal is OFF (open) (mode 1): /JOG3 signal is active when ON (closed).
1	• When /MODE signal is ON (closed) (mode 0): The /SEL4 signal is active when OFF (open). • When /MODE signal is OFF (open) (mode 1): The /JOG3 signal is active when OFF (open).
2	• When /MODE signal is ON (closed) (mode 0): The /SEL4 signal is always active. • When /MODE signal is OFF (open) (mode 1): The /JOG3 signal is always active.
3	• When /MODE signal is ON (closed) (mode 0): The /SEL4 signal is always inactive. • When /MODE signal is OFF (open) (mode 1): The /JOG3 signal is always inactive.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB0B	2	/SEL5	0 to 3	–	0	All	After restart	Setup	*1

0	The /SEL5 signal is active when ON (closed).
1	The /SEL5 signal is active when OFF (open).
2	The /SEL5 signal is always active.
3	The /SEL5 signal is always inactive.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB0C	2	/SEL6	0 to 3	–	0	All	After restart	Setup	*1

0	The /SEL6 signal is active when ON (closed).
1	The /SEL6 signal is active when OFF (open).
2	The /SEL6 signal is always active.
3	The /SEL6 signal is always inactive.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB0D	2	/SEL7	0 to 3	–	0	All	After restart	Setup	*1

0	The /SEL7 signal is active when ON (closed).
1	The /SEL7 signal is active when OFF (open).
2	The /SEL7 signal is always active.
3	The /SEL7 signal is always inactive.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB0E	2	/S-ON	0 to 3	–	0	All	After restart	Setup	*1

0	The system changes to the SERVO ON state (power is supplied) and operation is enabled when the /S-ON signal turns ON (closes).
1	The system changes to the SERVO ON state (power is supplied) and operation is enabled when the /S-ON signal turns OFF (opens).
2	The system is always in the SERVO ON state.
3	The system is always in the SERVO OFF state.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB0F	2	P-OT	0 to 3	–	0	All	After restart	Setup	*1

0	When input signal is OFF (open), forward run is prohibited (forward overtravel).
1	When input signal is ON (closed), forward run is prohibited (forward overtravel).
2	Forward run is always prohibited (forward overtravel).
3	Forward run is always enabled. (P-OT signal is not used.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB10	2	N-OT	0 to 3	–	0	All	After restart	Setup	*1

0	When input signal is OFF (open), reverse run is prohibited (reverse overtravel).
1	When input signal is ON (closed), reverse run is prohibited (reverse overtravel).
2	Reverse run is always prohibited (reverse overtravel).
3	Reverse run is always enabled. (N-OT signal is not used.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB11	2	/DEC	0 to 3	–	0	All	After restart	Setup	*1

0	Starts deceleration in an origin return when input signal is ON (closed).
1	Starts deceleration in an origin return when input signal is OFF (open).
2	Sets the origin return limit switch always ON.
3	Sets the origin return limit switch always OFF.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB12	2	/RGRT	0 to 3	–	0	All	After restart	Setup	*1

0	Starts registration by switching input signal from OFF (open) to ON (closed).
1	Starts registration by switching input signal from ON (close) to OFF (open).
2, 3	Does not start registration.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB13	2	/INPOSITION	0 to 3	–	0	All	After restart	Setup	*1

0	When positioning has been completed, photocoupler becomes ON (closed).
1	When positioning has been completed, photocoupler becomes OFF (open).
2, 3	Reserved.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB14	2	/POUT0	0, 1	–	0	All	After restart	Setup	*1

0	The /POUT0 signal turns ON (opens) when programmable output 0 is active.
1	The /POUT0 signal turns OFF (closes) when programmable output 0 is active.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB15	2	/POUT1	0, 1	–	0	All	After restart	Setup	*1

0	The /POUT1 signal turns ON (opens) when programmable output 1 is active.
1	The /POUT1 signal turns OFF (closes) when programmable output 1 is active.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classi-fication	Refer-ence
PnB16	2	/POUT2	0, 1	–	0	All	After restart	Setup	*1

0	The /POUT2 signal turns ON (opens) when programmable output 2 is active.
1	The /POUT2 signal turns OFF (closes) when programmable output 2 is active.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB17	2	/POUT3	0, 1	–	0	All	After restart	Setup	*1
		0 The /POUT3 signal turns ON (opens) when programmable output 3 is active. 1 The /POUT3 signal turns OFF (closes) when programmable output 3 is active.							
PnB18	2	/POUT4	0, 1	–	0	All	After restart	Setup	*1
		0 The /POUT4 signal turns ON (opens) when programmable output 4 is active. 1 The /POUT4 signal turns OFF (closes) when programmable output 4 is active.							
PnB19	2	/POUT5	0, 1	–	0	All	After restart	Setup	*1
		0 The /POUT5 signal turns ON (opens) when programmable output 5 is active. 1 The /POUT5 signal turns OFF (closes) when programmable output 5 is active.							
PnB1A	2	/POUT6	0, 1	–	0	All	After restart	Setup	*1
		0 The /POUT6 signal turns ON (opens) when programmable output 6 is active. 1 The /POUT6 signal turns OFF (closes) when programmable output 6 is active.							
PnB1B	2	/POUT7	0, 1	–	0	All	After restart	Setup	*1
		0 The /POUT7 signal turns ON (opens) when programmable output 7 is active. 1 The /POUT7 signal turns OFF (closes) when programmable output 7 is active.							
PnB1C	2	/WARN	0, 1	–	0	All	After restart	Setup	*1
		0 The /WARN signal turns ON (closes) when the output when an error or warning occurs (error/warning status). 1 The /WARN signal turns OFF (opens) when the output when an error or warning occurs (error/warning status).							
PnB1D	2	/BK	0, 1	–	0	All	After restart	Setup	*1
		0 When braking signal /BK is ON (closed), brake is released. 1 When braking signal /BK is OFF (open), brake is released.							
PnB1E	2	/S-RDY	0, 1	–	0	All	After restart	Setup	*1
		0 Turn ON (close) the /S-RDY signal when the servo is ready. 1 Turn OFF (open) the /S-RDY signal when the servo is ready.							
PnB1F	2	Overtravel (OT) Stop Method	0 to 2	–	0	All	After restart	Setup	*1
		0 Stops the motor with the same method as when the servo is turned OFF (according to setting of Pn001 = n.□□□X). 1 Stops motor immediately, and then changes motor state to servo lock. 2 Decelerates motor to a stop at deceleration rate set with PnB2B, and then changes motor state to servo lock.							

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB20	2	Moving Mode	0 to 3	–	0	All	After restart	Setup	*1
		0 Sets coordinates to linear type. 1 Sets coordinates to rotary type. Moving mode is set as shortest path. 2 Sets coordinates to rotary type. Moving mode is always set as forward. 3 Sets coordinates to rotary type. Moving mode is always set as reverse.							
PnB21	4	Linear coordinates (PnB20 = 0000h): Forward Software Limit (P-LS) Rotational coordinates (PnB20 ≠ 0000h): Last Rotational Coordinate	-99999999 to +99999999 *16	1 reference unit	+99999999	All	After restart	Setup	*1
PnB23	4	Linear coordinates (PnB20 = 0000h): Reverse Software Limit (N-LS) Rotational coordinates (PnB20 ≠ 0000h): First Rotational Coordinate	-99999999 to +99999999 *16	1 reference unit	-99999999	All	After restart	Setup	*1
PnB25	4	When using an incremental encoder: Origin When using an absolute encoder: Absolute Encoder Offset	-99999999 to +99999999 *16	1 reference unit	0	All	After restart	Setup	*1
PnB27	4	Positioning/Registration Speed	1 to 99999999*16	1000 Reference units/min	1000	All	After restart	Setup	*1
PnB29	4	Acceleration rate	1 to 99999999*16	1000 (Reference units/min) /ms	1000	All	Immediately	Setup	*1
PnB2B	4	Deceleration rate	1 to 99999999*16	1000 (Reference units/min) /ms	1000	All	Immediately	Setup	*1
PnB2D	4	/INPOSITION Width	1 to 99999	1 reference unit	1	All	Immediately	Setup	*1
PnB2F	4	/NEAR Width	1 to 99999	1 reference unit	1	All	Immediately	Setup	*1
PnB31	2	Origin Return Method	0 to 3	–	0	All	After restart	Setup	*1
		0 Origin returns are not executed. 1 /DEC and phase C are used for an origin return. 2 Only /DEC is used for an origin return. 3 Only phase C is used for an origin return.							
PnB32	2	Origin Return Direction	0, 1	–	0	All	Immediately	Setup	*1
		0 /HOME or ZRN command is used for an origin return in forward direction. 1 /HOME or ZRN command is used for an origin return in reverse direction.							

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
PnB33	4	Origin Return Moving Speed	1 to 99999999*16	1000 Reference units/min	1000	All	Immediately	Setup	*1
PnB35	4	Origin Return Approach Speed	1 to 99999999*16	1000 Reference units/min	1000	All	Immediately	Setup	*1
PnB37	4	Origin Return Creep Speed	1 to 99999999*16	1000 Reference units/min	1000	All	Immediately	Setup	*1
PnB39	4	Origin Return Final Move Distance	-99999999 to +99999999 *16	1 reference unit	0	All	Immediately	Setup	*1
PnB3B to PnB4D	4	Reserved parameters (Do not change.)	–	–	0	All	–	Setup	–
PnB4F	2	ZONE Signal Setting	0000h, 0001h	–	0000h	All	After restart	Setup	*1
		0000h	When the control power supply is turned ON or the SERVOPACK is reset, the /POUT0 to /POUT7 signals are disabled.						
		0001h	When control power is turned ON or SERVOPACK is reset, the /POUT0 to /POUT7 signals are the ZONE signals.						
PnB50	2	Backlash Compensation	-1000 to +1000	1 reference unit	0	All	Immediately	Setup	*1
PnB51	2	/ALO Output Selection	0 to 1	–	0	All	After restart	Setup	*1
		0	Does not output /ALO1 to /ALO3. (/WARN, /BK, and /S-RDY are output.)						
		1	Outputs /ALO1 to /ALO3. (/WARN, /BK, and /S-RDY are not output.)						
PnB52	2	/ALM-RST	0 to 3	–	0	All	After restart	Setup	*1
		0	Resets alarms by switching input signal from OFF (open) to ON (closed).						
		1	Resets alarms by switching input signal from ON (closed) to OFF (open).						
		2, 3	Does not reset alarms. (Signal is ignored.)						
PnB53	2	Input Signal Monitor IN1 Polarity Selection	0000h to 00FFh	–	0050h	All	After restart	Setup	–
		Bit 0	Input Signal Monitor IN1 Bit 0 (/SVON) (0: Do not invert the data (default setting), 1: Invert the data.)						
		Bit 1	Input Signal Monitor IN1 Bit 1 (/ALM-RST) (0: Do not invert the data (default setting), 1: Invert the data.)						
		Bit 2	Input Signal Monitor IN1 Bit 2 (/P-OT) (0: Do not invert the data (default setting), 1: Invert the data.)						
		Bit 3	Input Signal Monitor IN1 Bit 3 (/N-OT) (0: Do not invert the data (default setting), 1: Invert the data.)						
		Bit 4	Input Signal Monitor IN1 Bit 4 (/DEC) (0: Do not invert the data, 1: Invert the data (default setting).)						
		Bit 5	Input Signal Monitor IN1 Bit 5 (not used) (0: Do not invert the data (default setting), 1: Invert the data.)						
		Bit 6	Input Signal Monitor IN1 Bit 6 (/RGRT) (0: Do not invert the data, 1: Invert the data (default setting).)						
		Bit 7	Input Signal Monitor IN1 Bit 7 (not used) (0: Do not invert the data (default setting), 1: Invert the data.)						
PnB54	2	Speed/Position Expansion Function Selection	0 or 1	–	0	All	After restart	Setup	–

*1. Refer to the following manual for details.

Σ-7-Series Σ-7S SERVOPACK Command Option Attachable Type with INDEXER Module Product Manual (Manual No.: SIEP S800001 64)

*2. The following parameters are automatically set when the INDEXER Module is mounted to the SERVOPACK. Do not change the setting.
- Pn002 = n.□□□0
- Pn207 = n.1□□□
- Pn50A = 8881h
- Pn50B = 8888h
- Pn510 = 0000h

*3. This parameter is automatically set to 0 if a single-turn absolute encoder is used and Pn002 is set to n.□0□□.

*4. Set a percentage of the motor rated torque.

*5. When the INDEXER Module is mounted to the SERVOPACK, Pn50E is set to 0000h or 3000h according to the setting of PnB51. Do not change the setting.

*6. When the INDEXER Module is mounted to the SERVOPACK, Pn50F is set to 0000h or 1200h according to the setting of PnB51. Do not change the setting.

*7. When the INDEXER Module is mounted to the SERVOPACK, this parameter is automatically set according to the settings of PnB11 and PnB12. (Pn511 = n.8□■8, where □ = 4, 8, or D and ■ = 6, 8, or F) Do not change the setting.

*8. When the INDEXER Module is mounted to the SERVOPACK, this parameter is automatically set according to the settings of PnB1C, PnB1D, PnB1E, and PnB51. (Pn512 = n.0□□□, where □ = 0 or 1) Do not change the setting.

*9. When the INDEXER Module is mounted to the SERVOPACK, Pn517 is set to 0000h or 0321h according to the setting of PnB51. Do not change the setting.

*10. When the INDEXER Module is mounted to the SERVOPACK, this parameter is automatically set to between 0 and 99,999 according to the setting of PnB2D. Do not change the setting.

*11. Normally set this parameter to 0. If you use an External Regenerative Resistor, set the capacity (W) of the External Regenerative Resistor.

*12. The upper limit is the maximum output capacity (W) of the SERVOPACK.

*13. These parameters are for SERVOPACKs with the Dynamic Brake Hardware Option. Refer to the following manual for details.
Σ-7-Series Σ-7S/Σ-7W SERVOPACK with Dynamic Brake Hardware Option Specifications Product Manual (Manual No.: SIEP S800001 73)

*14. The SGLFW2 is the only Yaskawa Linear Servomotor that supports this function.

*15. Enabled only when Pn61A is set to n.□□□2 or n.□□□3.

*16. If you set PnB54 to 1 (Enable Expansion Mode), the following setting ranges will change.

Parameter No.	Name	Setting Range
PnB21	• Linear coordinates (PnB20 = 0000h): Forward Software Limit (P-LS) • Rotational coordinates (PnB20 ≠ 0000h): Last Rotational Coordinate	-536,870,911 to +536,870,911
PnB23	• Linear coordinates (PnB20 = 0000h): Reverse Software Limit (N-LS) • Rotational coordinates (PnB20 ≠ 0000h): First Rotational Coordinate	-536,870,911 to +536,870,911
PnB25	• When using an incremental encoder: Origin • When using an absolute encoder: Absolute Encoder Offset	-1,073,741,823 to +1,073,741,823
PnB27	Positioning/Registration Speed	1 to 99,999,999
PnB29	Acceleration Rate	1 to 99,999,999
PnB2B	Deceleration Rate	1 to 99,999,999
PnB33	Origin Return Movement Speed	1 to 99,999,999
PnB35	Origin Approach Speed	1 to 99,999,999
PnB37	Origin Return Creep Speed	1 to 99,999,999
PnB39	Origin Return Final Travel Distance	-1,073,741,823 to +1,073,741,823

4.5 FT83 SERVOPACKs with Analog Voltage/Pulse Train References

The following table lists the parameters.

Note: Do not change the following parameters from their default settings.
- Reserved parameters
- Parameters not given in this manual
- Parameters that are not valid for the Servomotor that you are using, as given in the parameter table

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn000	2	Basic Function Selections 0	0000h to 10B1h	–	0010h	All	After restart	Setup	–

	Rotation Direction Selection		Reference
n.□□□X	0	Use CCW as the forward direction.	*1
	1	Use CW as the forward direction. (Reverse Rotation Mode)	

	Control Method Selection		Reference
n.□□X□	0	Switching between speed control with analog references and program table operation	*1
	1	Switching between position control with pulse train references and program table operation	
	2	Switching between torque control with analog references and program table operation	
	3	Internal set speed control with contact commands	
	4	Switching between internal set speed control with contact references and speed control with analog references	
	5	Switching between internal set speed control with contact references and position control with pulse train references	
	6	Switching between internal set speed control with contact references and torque control with analog references	
	7	Switching between position control with pulse train references and speed control with analog references	
	8	Switching between position control with pulse train references and torque control with analog references	
	9	Switching between torque control with analog references and speed control with analog references	
	A	Switching between speed control with analog references and speed control with zero clamping	
	B	Switching between position control with pulse train references and position control with reference pulse inhibition	

n.□X□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn001	2	Application Function Selections 1	0000h to 1142h	–	0000h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Servo OFF and Group 1 Alarms		Reference
	0	Stop the motor by applying the dynamic brake.	*1
	1	Stop the motor by the applying dynamic brake and then release the dynamic brake.	
	2	Coast the motor to a stop without the dynamic brake.	

n.□□X□	Overtravel Stopping Method		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then servo-lock the motor.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A and then servo-lock the motor.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□X□□	Main Circuit Power Supply AC/DC Input Selection		Reference
	0	Input AC power as the main circuit power supply using the L1, L2, and L3 terminals (do not use shared converter).	*1
	1	Input DC power as the main circuit power supply using the B1/⊕ and ⊖ 2 terminals or the B1 and ⊖ 2 terminals (use an external converter or the shared converter).	

n.X□□□	Warning Code Output Selection		Reference
	0	Output only alarm codes on the ALO1, ALO2, and ALO3 terminals.	*1
	1	Output both warning codes and alarm codes on the ALO1, ALO2, and ALO3 terminals. However, while an warning code is being output, the ALM (Servo Alarm) output signal will remain ON (normal state).	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn002	2	Application Function Selections 2	0000h to 4213h	–	0000h	–	After restart	Setup	–

n.□□□X	Speed/Position Control Option (T-REF Input Allocation)		Applicable Motors	Reference
	0	Do not use T-REF.	All	–
	1	Use T-REF as an external torque limit input.		*1
	2	Use T-REF as a torque feedback input.		*1
	3	Use T-REF as an external torque limit input when /P-CL or /N-CL is ON.		*1

n.□□X□	Torque Control Option (V-REF Input Allocation)		Applicable Motors	Reference
	0	Do not use V-REF.	All	*1
	1	Use V-REF as an external speed limit input.		

n.□X□□	Encoder Usage		Applicable Motors	Reference
	0	Use the encoder according to encoder specifications.	All	*1
	1	Use the encoder as an incremental encoder.		
	2	Use the encoder as a single-turn absolute encoder.	Rotary	

n.X□□□	External Encoder Usage		Applicable Motors	Reference
	0	Do not use an external encoder.	Rotary	*1
	1	The external encoder moves in the forward direction for CCW motor rotation.		
	2	Reserved setting (Do not use.)		
	3	The external encoder moves in the reverse direction for CCW motor rotation.		
	4	Reserved setting (Do not use.)		

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn006	2	Application Function Selections 6	0000h to 105Fh	–	0002h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 1 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn007	2	Application Function Selections 7	0000h to 105Fh	–	0000h	All	Immediately	Setup	*1

n.□□XX	Analog Monitor 2 Signal Selection	
	00	Motor speed (1 V/1,000 min^{-1})
	01	Speed reference (1 V/1,000 min^{-1})
	02	Torque reference (1 V/100% rated torque)
	03	Position deviation (0.05 V/reference unit)
	04	Position amplifier deviation (after electronic gear) (0.05 V/encoder pulse unit)
	05	Position reference speed (1 V/1,000 min^{-1})
	06	Reserved setting (Do not use.)
	07	Load-motor position deviation (0.01 V/reference unit)
	08	Positioning completion (positioning completed: 5 V, positioning not completed: 0 V)
	09	Speed feedforward (1 V/1,000 min^{-1})
	0A	Torque feedforward (1 V/100% rated torque)
	0B	Active gain (1st gain: 1 V, 2nd gain: 2 V)
	0C	Completion of position reference distribution (completed: 5 V, not completed: 0 V)
	0D	External encoder speed (1 V/1,000 min^{-1}: value at the motor shaft)
	0E	Reserved setting (Do not use.)
	0F	Reserved setting (Do not use.)
	10	Main circuit DC voltage
	11 to 5F	Reserved settings (Do not use.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn008	2	Application Function Selections 8	0000h to 7121h	–	0000h	Rotary	After restart	Setup	–

n.□□□X	Low Battery Voltage Alarm/Warning Selection		Reference
	0	Output alarm (A.830) for low battery voltage.	*1
	1	Output warning (A.930) for low battery voltage.	

n.□□X□	Function Selection for Undervoltage		Reference
	0	Do not detect undervoltage.	*1
	1	Detect undervoltage warning and limit torque at host controller.	
	2	Detect undervoltage warning and limit torque with Pn424 and Pn425 (i.e., only in SERVOPACK).	

n.□X□□	Warning Detection Selection		Reference
	0	Detect warnings.	*1
	1	Do not detect warnings except for A.971.	

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn009	2	Application Function Selections 9	0000h to 0121h	–	0010h	All	After restart	Tuning	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Current Control Mode Selection		Reference
	0	Use current control mode 1.	*1
	1	• SERVOPACK Models SGD7S-R70A, -R90A, -1R6A, -2R8A, -3R8A, -5R5A, and -7R6A: Use current control mode 1. • SERVOPACK Models SGD7S-120A, -180A, -200A, -330A, -470A, -550A, -590A, and -780A: Use current control mode 2.	
	2	Use current control mode 2.	

n.□X□□	Speed Detection Method Selection		Reference
	0	Use speed detection 1.	*1
	1	Use speed detection 2.	

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00A	2	Application Function Selections A	0000h to 0044h	–	0001h	All	After restart	Setup	–

n.□□□X	Motor Stopping Method for Group 2 Alarms		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□□X□	Stopping Method for Forced Stops		Reference
	0	Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	*1
	1	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	2	Decelerate the motor to a stop using the torque set in Pn406 as the maximum torque and then let the motor coast.	
	3	Decelerate the motor to a stop using the deceleration time set in Pn30A. Use the setting of Pn001 = n.□□□X for the status after stopping.	
	4	Decelerate the motor to a stop using the deceleration time set in Pn30A and then let the motor coast.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00B	2	Application Function Selections B	0000h to 1121h	–	0000h	All	After restart	Setup	–

n.□□□X	Operator Parameter Display Selection	Reference
	0 Display only setup parameters.	*1
	1 Display all parameters.	

n.□□X□	Motor Stopping Method for Group 2 Alarms	Reference
	0 Stop the motor by setting the speed reference to 0.	*1
	1 Apply the dynamic brake or coast the motor to a stop (use the stopping method set in Pn001 = n.□□□X).	
	2 Set the stopping method with Pn00A = n.□□□X.	

n.□X□□	Power Input Selection for Three-phase SERVOPACK	Reference
	0 Use a three-phase power supply input.	*1
	1 Use a three-phase power supply input as a single-phase power supply input.	

n.X□□□	Reserved parameter (Do not change.)

Pn00C	2	Application Function Selections C	0000h to 0131h	–	0000h	–	After restart	Setup	*1

n.□□□X	Function Selection for Test without a Motor	Applicable Motors
	0 Disable tests without a motor.	All
	1 Enable tests without a motor.	

n.□□X□	Encoder Resolution for Tests without a Motor	Applicable Motors
	0 Use 13 bits.	Rotary
	1 Use 20 bits.	
	2 Use 22 bits.	
	3 Use 24 bits.	

n.□X□□	Encoder Type Selection for Tests without a Motor	Applicable Motors
	0 Use an incremental encoder.	All
	1 Use an absolute encoder.	

n.X□□□	Reserved parameter (Do not change.)

Pn00D	2	Application Function Selections D	0000h to 1001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Overtravel Warning Detection Selection
	0 Do not detect overtravel warnings.
	1 Detect overtravel warnings.

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn00F	2	Application Function Selections F	0000h to 2011h	–	0000h	All	After restart	Setup	–

n.□□□X	Preventative Maintenance Warning Selection		Reference
	0	Do not detect preventative maintenance warnings.	*1
	1	Detect preventative maintenance warnings.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn010	2	Axis Address Selection for UART/USB Communications	0000h to 007Fh	–	0001h	All	After restart	Setup	–
Pn021	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn022	2	Reserved parameter (Do not change.)	–	–	0000h	All	–	–	–
Pn040	2	Reserved parameter (Do not change.)	–	–	0000h	–	–	–	–
Pn081	2	Application Function Selections 81	0000h to 1111h	–	0000h	All	After restart	Setup	*1

n.□□□X	Phase-C Pulse Output Selection		
	0	Output phase-C pulses only in the forward direction.	
	1	Output phase-C pulses in both the forward and reverse directions.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn100	2	Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn101	2	Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn102	2	Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn103	2	Moment of Inertia Ratio	0 to 20,000	1%	100	All	Immediately	Tuning	*1
Pn104	2	Second Speed Loop Gain	10 to 20,000	0.1 Hz	400	All	Immediately	Tuning	*1
Pn105	2	Second Speed Loop Integral Time Constant	15 to 51,200	0.01 ms	2000	All	Immediately	Tuning	*1
Pn106	2	Second Position Loop Gain	10 to 20,000	0.1/s	400	All	Immediately	Tuning	*1
Pn109	2	Feedforward	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn10A	2	Feedforward Filter Time Constant	0 to 6,400	0.01 ms	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn10B	2	Gain Application Selections	0000h to 5334h	–	0000h	All	–	Setup	–

n.□□□X	Mode Switching Selection		When Enabled	Reference
	0	Use the internal torque reference as the condition (level setting: Pn10C).	Immediately	*1
	1	Use the speed reference as the condition (level setting: Pn10D).		
		Use the speed reference as the condition (level setting: Pn181).		
	2	Use the acceleration reference as the condition (level setting: Pn10E).		
		Use the acceleration reference as the condition (level setting: Pn182).		
	3	Use the position deviation as the condition (level setting: Pn10F).		
	4	Do not use mode switching.		

n.□□X□	Speed Loop Control Method		When Enabled	Reference
	0	PI control	After restart	*1
	1	I-P control		
	2 to 3	Reserved settings (Do not use.)		

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn10C	2	Mode Switching Level for Torque Reference	0 to 800	1%	200	All	Immediately	Tuning	*1
Pn10D	2	Mode Switching Level for Speed Reference	0 to 10,000	1 min^{-1}	0	Rotary	Immediately	Tuning	*1
Pn10E	2	Mode Switching Level for Acceleration	0 to 30,000	1 min^{-1}/s	0	Rotary	Immediately	Tuning	*1
Pn10F	2	Mode Switching Level for Position Deviation	0 to 10,000	1 reference unit	0	All	Immediately	Tuning	*1
Pn11F	2	Position Integral Time Constant	0 to 50,000	0.1 ms	0	All	Immediately	Tuning	*1
Pn121	2	Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn122	2	Second Friction Compensation Gain	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn123	2	Friction Compensation Coefficient	0 to 100	1%	0	All	Immediately	Tuning	*1
Pn124	2	Friction Compensation Frequency Correction	-10,000 to 10,000	0.1 Hz	0	All	Immediately	Tuning	*1
Pn125	2	Friction Compensation Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn131	2	Gain Switching Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn132	2	Gain Switching Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn135	2	Gain Switching Waiting Time 1	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1
Pn136	2	Gain Switching Waiting Time 2	0 to 65,535	1 ms	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn139	2	Automatic Gain Switching Selections 1	0000h to 0052h	–	0000h	All	Immediately	Tuning	*1

	Gain Switching Selection	
n.□□□X	0	Use manual gain switching. The gain is switched manually with the /G-SEL (Gain Selection) signal.
	1	Reserved setting (Do not use.)
	2	Use automatic gain switching pattern 1. The gain is switched automatically from the first gain to the second gain when switching condition A is satisfied. The gain is switched automatically from the second gain to the first gain when switching condition A is not satisfied.

	Gain Switching Condition A	
n.□□X□	0	/COIN (Positioning Completion Output) signal turns ON.
	1	/COIN (Positioning Completion Output) signal turns OFF.
	2	/NEAR (Near Output) signal turns ON.
	3	/NEAR (Near Output) signal turns OFF.
	4	Position reference filter output is 0 and reference pulse input is OFF.
	5	Position reference pulse input is ON.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn13D	2	Current Gain Level	100 to 2,000	1%	2000	All	Immediately	Tuning	*1
Pn140	2	Model Following Control-Related Selections	0000h to 1121h	–	0100h	All	Immediately	Tuning	–

	Model Following Control Selection		Reference
n.□□□X	0	Do not use model following control.	*1
	1	Use model following control.	

	Vibration Suppression Selection		Reference
n.□□X□	0	Do not perform vibration suppression.	*1
	1	Perform vibration suppression for a specific frequency.	
	2	Perform vibration suppression for two specific frequencies.	

	Vibration Suppression Adjustment Selection		Reference
n.□X□□	0	Do not adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust vibration suppression automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

	Speed Feedforward (VFF)/Torque Feedforward (TFF) Selection		Reference
n.X□□□	0	Do not use model following control and speed/torque feedforward together.	*1
	1	Use model following control and speed/torque feedforward together.	

Pn141	2	Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn142	2	Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn143	2	Model Following Control Bias in the Forward Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn144	2	Model Following Control Bias in the Reverse Direction	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn145	2	Vibration Suppression 1 Frequency A	10 to 2,500	0.1 Hz	500	All	Immediately	Tuning	*1
Pn146	2	Vibration Suppression 1 Frequency B	10 to 2,500	0.1 Hz	700	All	Immediately	Tuning	*1
Pn147	2	Model Following Control Speed Feedforward Compensation	0 to 10,000	0.1%	1000	All	Immediately	Tuning	*1
Pn148	2	Second Model Following Control Gain	10 to 20,000	0.1/s	500	All	Immediately	Tuning	*1
Pn149	2	Second Model Following Control Gain Correction	500 to 2,000	0.1%	1000	All	Immediately	Tuning	*1
Pn14A	2	Vibration Suppression 2 Frequency	10 to 2,000	0.1 Hz	800	All	Immediately	Tuning	*1
Pn14B	2	Vibration Suppression 2 Correction	10 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn14F	2	Control-Related Selections	0000h to 0021h	–	0021h	All	After restart	Tuning	–

n.□□□X	Model Following Control Type Selection		Reference
	0	Use model following control type 1.	*1
	1	Use model following control type 2.	

n.□□X□	Tuning-less Type Selection		Reference
	0	Use tuning-less type 1.	*1
	1	Use tuning-less type 2.	
	2	Use tuning-less type 3.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn160	2	Anti-Resonance Control-Related Selections	0000h to 0011h	–	0010h	All	Immediately	Tuning	–

n.□□□X	Anti-Resonance Control Selection		Reference
	0	Do not use anti-resonance control.	*1
	1	Use anti-resonance control.	

n.□□X□	Anti-Resonance Control Adjustment Selection		Reference
	0	Do not adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	*1
	1	Adjust anti-resonance control automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Pn161	2	Anti-Resonance Frequency	10 to 20,000	0.1 Hz	1000	All	Immediately	Tuning	*1
Pn162	2	Anti-Resonance Gain Correction	1 to 1,000	1%	100	All	Immediately	Tuning	*1
Pn163	2	Anti-Resonance Damping Gain	0 to 300	1%	0	All	Immediately	Tuning	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn164	2	Anti-Resonance Filter Time Constant 1 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn165	2	Anti-Resonance Filter Time Constant 2 Correction	-1,000 to 1,000	0.01 ms	0	All	Immediately	Tuning	*1
Pn166	2	Anti-Resonance Damping Gain 2	0 to 1,000	1%	0	All	Immediately	Tuning	*1
Pn170	2	Tuning-less Function-Related Selections	0000h to 2711h	–	1401h	All	–	Setup	*1

n.□□□X	Tuning-less Selection		When Enabled
	0	Disable tuning-less function.	After restart
	1	Enable tuning-less function.	

n.□□X□	Speed Control Method		When Enabled
	0	Use for speed control.	After restart
	1	Use for speed control and use host controller for position control.	

n.□X□□	Rigidity Level		When Enabled
	0 to 7	Set the rigidity level.	Immediately

n.X□□□	Tuning-less Load Level		When Enabled
	0 to 2	Set the load level for the tuning-less function.	Immediately

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn200	2	Position Control Reference For Selections	0000h to 2236h	–	0000h	All	After restart	Setup	–

n.□□□X	Reference Pulse Form		Reference
	0	Sign and pulse train, positive logic.	*1
	1	CW and CCW pulse trains, positive logic	
	2	Two-phase pulse trains with 90° phase differential (phase A and phase B) ×1, positive logic	
	3	Two-phase pulse trains with 90° phase differential (phase A and phase B) ×2, positive logic	
	4	Two-phase pulse trains with 90° phase differential (phase A and phase B) ×4, positive logic	
	5	Sign and pulse train, negative logic.	
	6	CW and CCW pulse trains, negative logic	

n.□□X□	Clear Signal Form		Reference
	0	Clear position deviation when the signal is at high level.	*1
	1	Clear position deviation on the rising edge of the signal.	
	2	Clear position deviation when the signal is at low level.	
	3	Clear position deviation on the falling edge of the signal.	

n.□X□□	Clear Operation		Reference
	0	Clear position deviation at a base block (at servo OFF or when alarm occurs).	*1
	1	Do not clear position error (cleared only with CLR (Clear Position Deviation) signal).	
	2	Clear position deviation when an alarm occurs.	

n.X□□□	Filter Selection		Reference
	0	Use the reference input filter for a line-driver signal. (1 Mpps max.)	*1
	1	Use the reference input filter for an open-collector signal. (200 kpps max.)	
	2	Use reference input filter 2 for a line-driver signal. (1 to 4 Mpps)	

Pn205	2	Multiturn Limit	0 to 65,535	1 rev	65535	Rotary	After restart	Setup	*1
Pn207	2	Position Control Function Selections	0000h to 2210h	–	2000h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Position Control Option		Reference
	0	Do not use V-REF.	*1
	1	Use V-REF as a speed feedback input.	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	/COIN (Positioning Completion Output) Signal Output Timing		Reference
	0	Output when the absolute value of the position deviation is the same or less than the setting of Pn522 (Positioning Completed Width).	*1
	1	Output when the absolute value of the position error is the same or less than the setting of Pn522 (Positioning Completed Width) and the reference after the position reference filter is 0.	
	2	Output when the absolute value of the position error is the same or less than the setting of Pn522 (Positioning Completed Width) and the reference input is 0.	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn20A	4	Number of External Encoder Scale Pitches	4 to 1,048,576	1 scale pitch/revolution	32768	Rotary	After restart	Setup	*1
Pn20E	4	Electronic Gear Ratio (Numerator)	1 to 1,073,741,824	1	64	All	After restart	Setup	*1
Pn210	4	Electronic Gear Ratio (Denominator)	1 to 1,073,741,824	1	1	All	After restart	Setup	*1
Pn212	4	Number of Encoder Output Pulses	16 to 1,073,741,824	1 P/Rev	2048	Rotary	After restart	Setup	*1
Pn216	2	Position Reference Acceleration/Deceleration Time Constant	0 to 65,535	0.1 ms	0	All	Immediately after the motor stops	Setup	*1
Pn217	2	Average Position Reference Movement Time	0 to 10,000	0.1 ms	0	All	Immediately after the motor stops	Setup	*1
Pn218	2	Reference Pulse Input Multiplier	1 to 100	× 1	1	All	Immediately	Setup	*1
Pn22A	2	Fully-closed Control Selections	0000h to 1003h	–	0000h	Rotary	After restart	Setup	*1

n.□□□X	Reserved parameter (Do not change.)	
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Fully-closed Control Speed Feedback Selection	
	0	Use motor encoder speed.
	1	Use external encoder speed.

Pn281	2	Encoder Output Resolution	1 to 4,096	1 edge/pitch	20	All	After restart	Setup	*1
Pn300	2	Speed Reference Input Gain	150 to 3,000	0.01 V/Rated motor speed	600	All	Immediately	Setup	*1
Pn301	2	Internal Set Speed 1	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	100	Rotary	Immediately	Setup	*1
Pn302	2	Internal Set Speed 2	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	200	Rotary	Immediately	Setup	*1
Pn303	2	Internal Set Speed 3	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	300	Rotary	Immediately	Setup	*1
Pn304	2	Jogging Speed	0 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn305	2	Soft Start Acceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn306	2	Soft Start Deceleration Time	0 to 10,000	1 ms	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn307	2	Speed Reference Filter Time Constant	0 to 65,535	0.01 ms	40	All	Immediately	Setup	*1
Pn308	2	Speed Feedback Filter Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1
Pn30A	2	Deceleration Time for Servo OFF and Forced Stops	0 to 10,000	1 ms	0	All	Immediately	Setup	*1
Pn30C	2	Speed Feedforward Average Movement Time	0 to 5,100	0.1 ms	0	All	Immediately	Setup	*1
Pn310	2	Vibration Detection Selections	0000h to 0002h	–	0000h	All	Immediately	Setup	*1

	Vibration Detection Selection	
n.□□□X	0	Do not detect vibration.
	1	Output a warning (A.911) if vibration is detected.
	2	Output an alarm (A.520) if vibration is detected.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn311	2	Vibration Detection Sensitivity	50 to 500	1%	100	All	Immediately	Tuning	*1
Pn312	2	Vibration Detection Level	0 to 5,000	1 min^{-1}	50	Rotary	Immediately	Tuning	*1
Pn316	2	Maximum Motor Speed	0 to 65,535	1 min^{-1}	10000	Rotary	After restart	Setup	*1
Pn324	2	Moment of Inertia Calculation Starting Level	0 to 20,000	1%	300	All	Immediately	Setup	*1
Pn400	2	Torque Reference Input Gain	10 to 100	0.1 V/rated torque	30	All	Immediately	Setup	*1
Pn401	2	First Stage First Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1
Pn402	2	Forward Torque Limit	0 to 800	1%*2	800	Rotary	Immediately	Setup	*1
Pn403	2	Reverse Torque Limit	0 to 800	1%*2	800	Rotary	Immediately	Setup	*1
Pn404	2	Forward External Torque Limit	0 to 800	1%*2	100	All	Immediately	Setup	*1
Pn405	2	Reverse External Torque Limit	0 to 800	1%*2	100	All	Immediately	Setup	*1
Pn406	2	Emergency Stop Torque	0 to 800	1%*2	800	All	Immediately	Setup	*1
Pn407	2	Speed Limit during Torque Control	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn408	2	Torque-Related Function Selections	0000h to 1111h	–	0000h	All	–	Setup	–

n.□□□X	Notch Filter Selection 1		When Enabled	Reference
	0	Disable first stage notch filter.	Immediately	*1
	1	Enable first stage notch filter.		

n.□□X□	Speed Limit Selection		When Enabled	Reference
	0	Use the smaller of the maximum motor speed and the setting of Pn407 as the speed limit.	After restart	*1
		Use the smaller of the maximum motor speed and the setting of Pn480 as the speed limit.		
	1	Use the smaller of the overspeed alarm detection speed and the setting of Pn407 as the speed limit.		
		Use the smaller of the overspeed alarm detection speed and the setting of Pn480 as the speed limit.		

n.□X□□	Notch Filter Selection 2		When Enabled	Reference
	0	Disable second stage notch filter.	Immediately	*1
	1	Enable second stage notch filter.		

n.X□□□	Friction Compensation Function Selection		When Enabled	Reference
	0	Disable friction compensation.	Immediately	*1
	1	Enable friction compensation.		

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn409	2	First Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40A	2	First Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40B	2	First Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40C	2	Second Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn40D	2	Second Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn40E	2	Second Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn40F	2	Second Stage Second Torque Reference Filter Frequency	100 to 5,000	1 Hz	4000	All	Immediately	Tuning	*1
Pn410	2	Second Stage Second Torque Reference Filter Q Value	50 to 100	0.01	50	All	Immediately	Tuning	*1
Pn412	2	First Stage Second Torque Reference Filter Time Constant	0 to 65,535	0.01 ms	100	All	Immediately	Tuning	*1
Pn415	2	T-REF Filter Time Constant	0 to 65,535	0.01 ms	0	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn416	2	Torque-Related Function Selections 2	0000h to 1111h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Notch Filter Selection 3	
	0	Disable third stage notch filter.
	1	Enable third stage notch filter.

n.□□X□	Notch Filter Selection 4	
	0	Disable fourth stage notch filter.
	1	Enable fourth stage notch filter.

n.□X□□	Notch Filter Selection 5	
	0	Disable fifth stage notch filter.
	1	Enable fifth stage notch filter.

n.X□□□	Reserved parameter (Do not change.)

Pn417	2	Third Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn418	2	Third Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn419	2	Third Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41A	2	Fourth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41B	2	Fourth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41C	2	Fourth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn41D	2	Fifth Stage Notch Filter Frequency	50 to 5,000	1 Hz	5000	All	Immediately	Tuning	*1
Pn41E	2	Fifth Stage Notch Filter Q Value	50 to 1,000	0.01	70	All	Immediately	Tuning	*1
Pn41F	2	Fifth Stage Notch Filter Depth	0 to 1,000	0.001	0	All	Immediately	Tuning	*1
Pn423	2	Speed Ripple Compensation Selections	0000h to 1111h	–	0000h	Rotary	–	Setup	*1

n.□□□X	Speed Ripple Compensation Function Selection		When Enabled
	0	Disable speed ripple compensation.	Immediately
	1	Enable speed ripple compensation.	

n.□□X□	Speed Ripple Compensation Information Disagreement Warning Detection Selection		When Enabled
	0	Detect A.942 alarms.	After restart
	1	Do not detect A.942 alarms.	

n.□X□□	Speed Ripple Compensation Enable Condition Selection		When Enabled
	0	Speed reference	After restart
	1	Motor speed	

n.X□□□	Reserved parameter (Do not change.)

Pn424	2	Torque Limit at Main Circuit Voltage Drop	0 to 100	1%*1	50	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn425	2	Release Time for Torque Limit at Main Circuit Voltage Drop	0 to 1,000	1 ms	100	All	Immediately	Setup	*1
Pn426	2	Torque Feedforward Average Movement Time	0 to 5,100	0.1 ms	0	All	Immediately	Setup	*1
Pn427	2	Speed Ripple Compensation Enable Speed	0 to 10,000	1 min^{-1}	0	Rotary Servomotor	Immediately	Tuning	*1
Pn456	2	Sweep Torque Reference Amplitude	1 to 800	1%	15	All	Immediately	Tuning	*1
Pn460	2	Notch Filter Adjustment Selections 1	0000h to 0101h	–	0101h	All	Immediately	Tuning	*1

n.□□□X	Notch Filter Adjustment Selection 1	
	0	Do not adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the first stage notch filter automatically during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Notch Filter Adjustment Selection 2	
	0	Do not adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
	1	Adjust the second stage notch filter automatically when the tuning-less function is enabled or during execution of autotuning without a host reference, autotuning with a host reference, and custom tuning.
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn475	2	Gravity Compensation-Related Selections	0000h to 0001h	–	0000h	All	After restart	Setup	*1

n.□□□X	Gravity Compensation Selection	
	0	Disable gravity compensation.
	1	Enable gravity compensation.
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn476	2	Gravity Compensation Torque	-1,000 to 1,000	0.1%	0	All	Immediately	Tuning	*1
Pn501	2	Zero Clamping Level	0 to 10,000	1 min^{-1}	10	Rotary	Immediately	Setup	*1
Pn502	2	Rotation Detection Level	1 to 10,000	1 min^{-1}	20	Rotary	Immediately	Setup	*1
Pn503	2	Speed Coincidence Detection Signal Output Width	0 to 100	1 min^{-1}	10	Rotary	Immediately	Setup	*1
Pn506	2	Brake Reference-Servo OFF Delay Time	0 to 50	10 ms	0	All	Immediately	Setup	*1
Pn507	2	Brake Reference Output Speed Level	0 to 10,000	1 min^{-1}	100	Rotary	Immediately	Setup	*1
Pn508	2	Servo OFF-Brake Command Waiting Time	10 to 100	10 ms	50	All	Immediately	Setup	*1
Pn509	2	Momentary Power Interruption Hold Time	20 to 50,000	1 ms	20	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50A	2	Input Signal Selections 1	0000h to FFF2h	–	8801h	All	After restart	Setup	–

n.□□□X	Input Signal Allocation Mode		Reference
	0	Use the sequence input signal terminals with the default allocations.	*1
	1	Change the sequence input signal allocations.	
	2	Reserved setting (Do not use.)	

n.□□X□	/S-ON (Servo ON) Signal Allocation		Reference
	0	Active when CN1-40 input signal is ON (closed).	*1
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

n.□X□□	/P-CON (Proportional Control) Signal Allocation		Reference
	0 to F	The allocations are the same as the /S-ON (Servo ON) signal allocations.	*1

n.X□□□	P-OT (Forward Drive Prohibit) Signal Allocation		Reference
	0	Enable forward drive when CN1-40 input signal is ON (closed).	*1
	1	Enable forward drive when CN1-41 input signal is ON (closed).	
	2	Enable forward drive when CN1-42 input signal is ON (closed).	
	3	Enable forward drive when CN1-43 input signal is ON (closed).	
	4	Enable forward drive when CN1-44 input signal is ON (closed).	
	5	Enable forward drive when CN1-45 input signal is ON (closed).	
	6	Enable forward drive when CN1-46 input signal is ON (closed).	
	7	Set the signal to always prohibit forward drive.	
	8	Set the signal to always enable forward drive.	
	9	Enable forward drive when CN1-40 input signal is OFF (open).	
	A	Enable forward drive when CN1-41 input signal is OFF (open).	
	B	Enable forward drive when CN1-42 input signal is OFF (open).	
	C	Enable forward drive when CN1-43 input signal is OFF (open).	
	D	Enable forward drive when CN1-44 input signal is OFF (open).	
	E	Enable forward drive when CN1-45 input signal is OFF (open).	
	F	Enable forward drive when CN1-46 input signal is OFF (open).	

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50B	2	Input Signal Selections 2	0000h to FFFFh	–	8868h	All	After restart	Setup	–

	N-OT (Reverse Drive Prohibit) Signal Allocation		Reference
n.□□□X	0	Enable reverse drive when CN1-40 input signal is ON (closed).	*1
	1	Enable reverse drive when CN1-41 input signal is ON (closed).	
	2	Enable reverse drive when CN1-42 input signal is ON (closed).	
	3	Enable reverse drive when CN1-43 input signal is ON (closed).	
	4	Enable reverse drive when CN1-44 input signal is ON (closed).	
	5	Enable reverse drive when CN1-45 input signal is ON (closed).	
	6	Enable reverse drive when CN1-46 input signal is ON (closed).	
	7	Set the signal to always prohibit reverse drive.	
	8	Set the signal to always enable reverse drive.	
	9	Enable reverse drive when CN1-40 input signal is OFF (open).	
	A	Enable reverse drive when CN1-41 input signal is OFF (open).	
	B	Enable reverse drive when CN1-42 input signal is OFF (open).	
	C	Enable reverse drive when CN1-43 input signal is OFF (open).	
	D	Enable reverse drive when CN1-44 input signal is OFF (open).	
	E	Enable reverse drive when CN1-45 input signal is OFF (open).	
	F	Enable reverse drive when CN1-46 input signal is OFF (open).	

	/ALM-RST (Alarm Reset) Signal Allocation		Reference
n.□□X□	0	Active on signal edge when CN1-40 input signal changes from OFF (open) to ON (closed).	*1
	1	Active on signal edge when CN1-41 input signal changes from OFF (open) to ON (closed).	
	2	Active on signal edge when CN1-42 input signal changes from OFF (open) to ON (closed).	
	3	Active on signal edge when CN1-43 input signal changes from OFF (open) to ON (closed).	
	4	Active on signal edge when CN1-44 input signal changes from OFF (open) to ON (closed).	
	5	Active on signal edge when CN1-45 input signal changes from OFF (open) to ON (closed).	
	6	Active on signal edge when CN1-46 input signal changes from OFF (open) to ON (closed).	
	7	Reserved setting (Do not use.)	
	8	The signal is always inactive.	
	9	Active on signal edge when CN1-40 input signal changes from ON (closed) to OFF (open).	
	A	Active on signal edge when CN1-41 input signal changes from ON (closed) to OFF (open).	
	B	Active on signal edge when CN1-42 input signal changes from ON (closed) to OFF (open).	
	C	Active on signal edge when CN1-43 input signal changes from ON (closed) to OFF (open).	
	D	Active on signal edge when CN1-44 input signal changes from ON (closed) to OFF (open).	
	E	Active on signal edge when CN1-45 input signal changes from ON (closed) to OFF (open).	
	F	Active on signal edge when CN1-46 input signal changes from ON (closed) to OFF (open).	

	/P-CL (Forward External Torque Limit Input) Signal Allocation		Reference
n.□X□□	0 to F	The allocations are the same as the /S-ON (Servo ON) signal allocations.	*1

	/N-CL (Reverse External Torque Limit Input) Signal Allocation		Reference
n.X□□□	0 to F	The allocations are the same as the /S-ON (Servo ON) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50C	2	Input Signal Selections 3	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	/SPD-D (Motor Direction) Signal Allocation		Reference
n.□□□X	0	Active when CN1-40 input signal is ON (closed).	*1
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

	/SPD-A (Internal Set Speed Selection Input) Signal Allocation		Reference
n.□□X□	0 to F	The allocations are the same as the /SPD-D (Motor Direction) signal allocations.	*1

	/SPD-B (Internal Set Speed Selection Input) Signal Allocation		Reference
n.□X□□	0 to F	The allocations are the same as the /SPD-D (Motor Direction) signal allocations.	*1

	/C-SEL (Control Selection Input) Signal Allocation		Reference
n.X□□□	0 to F	The allocations are the same as the /SPD-D (Motor Direction) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50D	2	Input Signal Selections 4	0000h to FFFFh	–	0888h	–	After restart	Setup	–

n.□□□X	/ZCLAMP (Zero Clamping Input) Signal Allocation		Applicable Motors	Reference
	0	Active when CN1-40 input signal is ON (closed).	All	*1
	1	Active when CN1-41 input signal is ON (closed).		
	2	Active when CN1-42 input signal is ON (closed).		
	3	Active when CN1-43 input signal is ON (closed).		
	4	Active when CN1-44 input signal is ON (closed).		
	5	Active when CN1-45 input signal is ON (closed).		
	6	Active when CN1-46 input signal is ON (closed).		
	7	The signal is always active.		
	8	The signal is always inactive.		
	9	Active when CN1-40 input signal is OFF (open).		
	A	Active when CN1-41 input signal is OFF (open).		
	B	Active when CN1-42 input signal is OFF (open).		
	C	Active when CN1-43 input signal is OFF (open).		
	D	Active when CN1-44 input signal is OFF (open).		
	E	Active when CN1-45 input signal is OFF (open).		
	F	Active when CN1-46 input signal is OFF (open).		

n.□□X□	/INHIBIT (Reference Pulse Inhibit Input) Signal Allocation		Applicable Motors	Reference
	0 to F	The allocations are the same as the /ZCLAMP (Zero Clamping Input) signal allocations.	All	*1

n.□X□□	/G-SEL (Gain Selection Input) Signal Allocation		Applicable Motors	Reference
	0 to F	The allocations are the same as the /ZCLAMP (Zero Clamping Input) signal allocations.	All	*1

n.X□□□	Reserved parameter (Do not change.)

Pn50E	2	Output Signal Selections 1	0000h to 6666h	–	2011h	All	After restart	Setup	–

n.□□□X	/COIN (Positioning Completion Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

n.□□X□	/V-CMP (Speed Coincidence Detection Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

n.□X□□	/TGON (Rotation Detection Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

n.X□□□	/S-RDY (Servo Ready) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /COIN (Positioning Completion) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn50F	2	Output Signal Selections 2	0000h to 6666h	–	0300h	All	After restart	Setup	–

n.□□□X	/CLT (Torque Limit Detection Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

n.□□X□	/VLT (Speed Limit Detection) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

n.□X□□	/BK (Brake Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

n.X□□□	/WARN (Warning Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /CLT (Torque Limit Detection Output) signal allocations.	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn510	2	Output Signal Selections 3	0000h to 0666h	–	0000h	All	After restart	Setup	–

n.□□□X	/NEAR (Near Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	/PSELA (Reference Pulse Input Multiplication Switching Output) Signal Allocation		Reference
	0 to 6	The allocations are the same as the /NEAR (Near) signal allocations.	*1

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn512	2	Output Signal Inverse Settings	0000h to 1111h	–	0000h	All	After restart	Setup	–

n.□□□X	Output Signal Inversion for CN1-25 and CN1-26 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□□X□	Output Signal Inversion for CN1-27 and CN1-28 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□X□□	Output Signal Inversion for CN1-29 and CN1-30 Terminals	
	0	The signal is not inverted.
	1	The signal is inverted.

n.X□□□	Output Signal Inversion for CN1-37 Terminal	
	0	The signal is not inverted.
	1	The signal is inverted.

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn513	2	Output Signal Inverse Settings 2	0000h to 0011h	–	0000h	All	After restart	Setup	–

n.□□□X	Output Signal Inversion for CN1-38 Terminal	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□□X□	Output Signal Inversion for CN1-39 Terminal	
	0	The signal is not inverted.
	1	The signal is inverted.

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn514	2	Output Signal Selections 4	0000h to 0666h	–	0000h	All	After restart	Setup	–

n.□□□X	Reserved parameter (Do not change.)

n.□□X□	Reserved parameter (Do not change.)

n.□X□□	/PM (Preventative Maintenance Output) Signal Allocation		Reference
	0	Disabled (the above signal output is not used).	*1
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn515	2	Input Signal Selections 6	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	SEN (Absolute Data Request Input) Signal Allocation		Reference
n.□□□X	0	Active when CN1-40 input signal is ON (closed).	*1
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	Enable when 5 V is input to CN1-4.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

	/PSEL (Reference Pulse Input Multiplication Switching Input) Signal Allocation		Reference
n.□□X□	0	Active when CN1-40 input signal is ON (closed).	*1
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always enabled.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn516	2	Input Signal Selections 7	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	FSTP (Forced Stop Input) Signal Allocation		Reference
n.□□□X	0	Enable drive when CN1-40 input signal is ON (closed).	*1
	1	Enable drive when CN1-41 input signal is ON (closed).	
	2	Enable drive when CN1-42 input signal is ON (closed).	
	3	Enable drive when CN1-43 input signal is ON (closed).	
	4	Enable drive when CN1-44 input signal is ON (closed).	
	5	Enable drive when CN1-45 input signal is ON (closed).	
	6	Enable drive when CN1-46 input signal is ON (closed).	
	7	Set the signal to always prohibit drive (always force the motor to stop).	
	8	Set the signal to always enable drive (always disable forcing the motor to stop).	
	9	Enable drive when CN1-40 input signal is OFF (open).	
	A	Enable drive when CN1-41 input signal is OFF (open).	
	B	Enable drive when CN1-42 input signal is OFF (open).	
	C	Enable drive when CN1-43 input signal is OFF (open).	
	D	Enable drive when CN1-44 input signal is OFF (open).	
	E	Enable drive when CN1-45 input signal is OFF (open).	
	F	Enable drive when CN1-46 input signal is OFF (open).	

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn517	2	Output Signal Selections 5	0000h to 0666h	–	0000h	All	After restart	Setup	*1

	ALO1 (Alarm Code Output) Signal Allocation	
n.□□□X	0	Disabled (the above signal output is not used).
	1	Output the signal from the CN1-25 or CN1-26 output terminal.
	2	Output the signal from the CN1-27 or CN1-28 output terminal.
	3	Output the signal from the CN1-29 or CN1-30 output terminal.
	4	Output the signal from the CN1-37 output terminal.
	5	Output the signal from the CN1-38 output terminal.
	6	Output the signal from the CN1-39 output terminal.

	ALO2 (Alarm Code Output) Signal Allocation	
n.□□X□	0 to 6	The allocations are the same as the ALO1 (Alarm Code Output) signal allocations.

	ALO3 (Alarm Code Output) Signal Allocation	
n.□X□□	0 to 6	The allocations are the same as the ALO1 (Alarm Code Output) signal allocations.

n.X□□□	Reserved parameter (Do not change.)

Pn518*3	–	Safety Module-Related Parameters	–	–	–	All	–	–	–

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn51B	4	Motor-Load Position Deviation Overflow Detection Level	0 to 1,073,741,824	1 reference unit	1000	Rotary	Immediately	Setup	*1
Pn51E	2	Position Deviation Overflow Warning Level	10 to 100	1%	100	All	Immediately	Setup	*1
Pn520	4	Position Deviation Overflow Alarm Level	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn522	4	Positioning Completed Width	0 to 1,073,741,824	1 reference unit	7	All	Immediately	Setup	*1
Pn524	4	Near Signal Width	1 to 1,073,741,824	1 reference unit	1073741824	All	Immediately	Setup	*1
Pn526	4	Position Deviation Overflow Alarm Level at Servo ON	1 to 1,073,741,823	1 reference unit	5242880	All	Immediately	Setup	*1
Pn528	2	Position Deviation Overflow Warning Level at Servo ON	10 to 100	1%	100	All	Immediately	Setup	*1
Pn529	2	Speed Limit Level at Servo ON	0 to 10,000	1 min^{-1}	10000	Rotary	Immediately	Setup	*1
Pn52A	2	Multiplier per Fully-closed Rotation	0 to 100	1%	20	Rotary	Immediately	Tuning	*1
Pn52B	2	Overload Warning Level	1 to 100	1%	20	All	Immediately	Setup	*1
Pn52C	2	Base Current Derating at Motor Overload Detection	10 to 100	1%	100	All	After restart	Setup	*1
Pn52F	2	Monitor Display at Startup	0000h to 0FFFh	–	0FFFh	All	Immediately	Setup	*1
Pn530	2	Program Jogging-Related Selections	0000h to 0005h	–	0000h	All	Immediately	Setup	*1

n.□□□X	Program Jogging Operation Pattern	
	0	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	1	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	2	(Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	3	(Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536 (Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
	4	(Waiting time in Pn535 → Forward by travel distance in Pn531 → Waiting time in Pn535 → Reverse by travel distance in Pn531) × Number of movements in Pn536
	5	(Waiting time in Pn535 → Reverse by travel distance in Pn531 → Waiting time in Pn535 → Forward by travel distance in Pn531) × Number of movements in Pn536
n.□□X□	Reserved parameter (Do not change.)	
n.□X□□	Reserved parameter (Do not change.)	
n.X□□□	Reserved parameter (Do not change.)	

Pn531	4	Program Jogging Travel Distance	1 to 1,073,741,824	1 reference unit	32768	All	Immediately	Setup	*1

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn533	2	Program Jogging Movement Speed	1 to 10,000	Rotary: 1 min^{-1} Direct Drive: 0.1 min^{-1}	500	Rotary	Immediately	Setup	*1
Pn534	2	Program Jogging Acceleration/Deceleration Time	2 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn535	2	Program Jogging Waiting Time	0 to 10,000	1 ms	100	All	Immediately	Setup	*1
Pn536	2	Program Jogging Number of Movements	0 to 1,000	Times	1	All	Immediately	Setup	*1
Pn550	2	Analog Monitor 1 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn551	2	Analog Monitor 2 Offset Voltage	-10,000 to 10,000	0.1 V	0	All	Immediately	Setup	*1
Pn552	2	Analog Monitor 1 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn553	2	Analog Monitor 2 Magnification	-10,000 to 10,000	× 0.01	100	All	Immediately	Setup	*1
Pn55A	2	Power Consumption Monitor Unit Time	1 to 1,440	1 min	1	All	Immediately	Setup	–
Pn560	2	Residual Vibration Detection Width	1 to 3,000	0.1%	400	All	Immediately	Setup	–
Pn561	2	Overshoot Detection Level	0 to 100	1%	100	All	Immediately	Setup	–
Pn600	2	Regenerative Resistor Capacity*4	Depends on model.*5	10 W	0	All	Immediately	Setup	–
Pn601	2	Dynamic Brake Resistor Allowable Energy Consumption	0 to 65,535	10 J	0	All	After restart	Setup	*6
Pn603	2	Regenerative Resistance	0 to 65,535	10 mΩ	0	All	Immediately	Setup	–
Pn604	2	Dynamic Brake Resistance	0 to 65,535	10 mΩ	0	All	After restart	Setup	*6
Pn61A	2	Overheat Protection Selections	0000h to 0003h	–	0000h	Linear	After restart	Setup	*1

n.□□□X	Overheat Protection Selection	
	0	Disable overheat protection.
	1	Use overheat protection in the Yaskawa Linear Servomotor.*7
	2	Monitor a negative voltage input from a sensor attached to the machine and use overheat protection.
	3	Monitor a positive voltage input from a sensor attached to the machine and use overheat protection.

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn61B *8	2	Overheat Alarm Level	0 to 500	0.01 V	250	All	Immediately	Setup	*1
Pn61C *8	2	Overheat Warning Level	0 to 100	1%	100	All	Immediately	Setup	*1
Pn61D *8	2	Overheat Alarm Filter Time	0 to 65,535	1 s	0	All	Immediately	Setup	*1
Pn621 to Pn628*3	–	Safety Module-Related Parameters	–	–	–	All	–	–	–

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn630	2	Input Signal Selections 10	0000h to FFFFh	–	6221h	All	After restart	Setup	–

n.□□□X	/MODE 0/1 (Mode Switch Input) Signal Allocation		Reference
	0	Mode 0 is used when CN1-40 input signal is ON (closed).	*9
	1	Mode 0 is used when CN1-41 input signal is ON (closed).	
	2	Mode 0 is used when CN1-42 input signal is ON (closed).	
	3	Mode 0 is used when CN1-43 input signal is ON (closed).	
	4	Mode 0 is used when CN1-44 input signal is ON (closed).	
	5	Mode 0 is used when CN1-45 input signal is ON (closed).	
	6	Mode 0 is used when CN1-46 input signal is ON (closed).	
	7	The signal always specifies mode 0.	
	8	The signal always specifies mode 1.	
	9	Mode 0 is used when CN1-40 input signal is OFF (open).	
	A	Mode 0 is used when CN1-41 input signal is OFF (open).	
	B	Mode 0 is used when CN1-42 input signal is OFF (open).	
	C	Mode 0 is used when CN1-43 input signal is OFF (open).	
	D	Mode 0 is used when CN1-44 input signal is OFF (open).	
	E	Mode 0 is used when CN1-45 input signal is OFF (open).	
	F	Mode 0 is used when CN1-46 input signal is OFF (open).	

n.□□X□	/START-STOP (Program Table Operation Start-Stop Input) Signal Allocation		Reference
	0	Active when CN1-40 input signal is ON (closed).	*9
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

n.□X□□	/HOME (Origin Return Input) Signal Allocation		Reference
	0 to F	The settings are the same as for /START-STOP (Program Table Operation Start-Stop Input) Signal Allocation.	*9

n.X□□□	/PGMRES (Program Table Operation Reset Input) Signal Allocation		Reference
	0 to F	The settings are the same as for /START-STOP (Program Table Operation Start-Stop Input) Signal Allocation.	*9

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn631	2	Input Signal Selections 11	0000h to FFFFh	–	8543h	All	After restart	Setup	–

n.□□□X	/SEL0 (Program Step Selection Input 0) Signal Allocation		Reference
	0	Active when CN1-40 input signal is ON (closed).	*9
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

n.□□X□	/SEL1 (Program Step Selection Input 1) Signal Allocation		Reference
	0 to F	The settings are the same as for /SEL0 (Program Step Selection Input 0) Signal Allocation.	*9

n.□X□□	/SEL2 (Program Step Selection Input 2) Signal Allocation		Reference
	0 to F	The settings are the same as for /SEL0 (Program Step Selection Input 0) Signal Allocation.	*9

n.X□□□	/SEL3 (Program Step Selection Input 3) Signal Allocation		Reference
	0 to F	The settings are the same as for /SEL0 (Program Step Selection Input 0) Signal Allocation.	*9

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn632	2	Input Signal Selections 12	0000h to FFFFh	–	5438h	All	After restart	Setup	–

n.□□□X	/SEL4 (Program Step Selection Input 4) Signal Allocation		Reference
	0	Active when CN1-40 input signal is ON (closed).	*9
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

n.□□X□	/JOGP (Forward Jog Input) Signal Allocation		Reference
	0 to F	The settings are the same as for /SEL4 (Program Step Selection Input 4) Signal Allocation.	*9

n.□X□□	/JOGN (Reverse Jog Input) Signal Allocation		Reference
	0 to F	The settings are the same as for /SEL4 (Program Step Selection Input 4) Signal Allocation.	*9

n.X□□□	/JOG0 (Jog Speed Table Selection Input 0) Signal Allocation		Reference
	0 to F	The settings are the same as for /SEL4 (Program Step Selection Input 4) Signal Allocation.	*9

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn633	2	Input Signal Selections 13	0000h to FFFFh	–	8888h	All	After restart	Setup	–

	/JOG1 (Jog Speed Table Selection Input 1) Signal Allocation		Reference
n.□□□X	0	Active when CN1-40 input signal is ON (closed).	*9
	1	Active when CN1-41 input signal is ON (closed).	
	2	Active when CN1-42 input signal is ON (closed).	
	3	Active when CN1-43 input signal is ON (closed).	
	4	Active when CN1-44 input signal is ON (closed).	
	5	Active when CN1-45 input signal is ON (closed).	
	6	Active when CN1-46 input signal is ON (closed).	
	7	The signal is always active.	
	8	The signal is always inactive.	
	9	Active when CN1-40 input signal is OFF (open).	
	A	Active when CN1-41 input signal is OFF (open).	
	B	Active when CN1-42 input signal is OFF (open).	
	C	Active when CN1-43 input signal is OFF (open).	
	D	Active when CN1-44 input signal is OFF (open).	
	E	Active when CN1-45 input signal is OFF (open).	
	F	Active when CN1-46 input signal is OFF (open).	

	/JOG2 (Jog Speed Table Selection Input 2) Signal Allocation		Reference
n.□□X□	0 to F	The settings are the same as for /JOG1 (Jog Speed Table Selection Input 1) Signal Allocation.	*9

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn634	2	Input Signal Selections 14	0000h to 0013h	–	0002h	All	After restart	Setup	–

	SI8 Signal Selection		Reference
n.□□□X	0	Do not allocate an input signal to CN1-14 and CN1-15.	*9
	1	Allocate the CLR signal as the input signal to CN1-14 and CN1-15.	
	2	Allocate the /DEC signal as the input signal to CN1-14 and CN1-15.	
	3	Allocate the /RGRT signal as the input signal to CN1-14 and CN1-15.	

	SI8 Signal Selection Logic		Reference
n.□□X□	0	Active when CN1-14 and CN1-15 input signal is ON (closed).	*9
	1	Active when CN1-14 and CN1-15 input signal is OFF (open).	

n.□X□□	Reserved parameter (Do not change.)

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn635	2	Output Signal Selections 10	0000h to 6666h	–	0654h	All	After restart	Setup	–

	/POUT0 (Programmable Output 0) Signal Allocation		Reference
n.□□□X	0	Disabled (the above signal output is not used).	*9
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

	/POUT1 (Programmable Output 1) Signal Allocation		Reference
n.□□X□	0 to 6	The settings are the same as for /POUT0 (Programmable Output 0) Signal Allocation.	*9

	/POUT2 (Programmable Output 2) Signal Allocation		Reference
n.□X□□	0 to 6	The settings are the same as for /POUT0 (Programmable Output 0) Signal Allocation.	*9

	/POUT3 (Programmable Output 3) Signal Allocation		Reference
n.X□□□	0 to 6	The settings are the same as for /POUT0 (Programmable Output 0) Signal Allocation.	*9

Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn636	2	Output Signal Selections 11	0000h to 0666h	–	0000h	All	After restart	Setup	–

	/POUT4 (Programmable Output 4) Signal Allocation		Reference
n.□□□X	0	Disabled (the above signal output is not used).	*9
	1	Output the signal from the CN1-25 or CN1-26 output terminal.	
	2	Output the signal from the CN1-27 or CN1-28 output terminal.	
	3	Output the signal from the CN1-29 or CN1-30 output terminal.	
	4	Output the signal from the CN1-37 output terminal.	
	5	Output the signal from the CN1-38 output terminal.	
	6	Output the signal from the CN1-39 output terminal.	

	/POSRDY (Origin Return Completed Output) Signal Allocation		Reference
n.□□X□	0 to 6	The settings are the same as for /POUT4 (Programmable Output 4) Signal Allocation.	*9

	/DEN (Positioning Reference Distribution Output) Signal Allocation		Reference
n.□X□□	0 to 6	The settings are the same as for /POUT4 (Programmable Output 4) Signal Allocation.	*9

n.X□□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn637	2	Moving Mode	0000h to 0003h	–	0000h	All	After restart	Setup	–

	Moving Mode		Reference
n.□□□X	0	Use linear coordinates.	*9
	1	Use rotational coordinates. Use the shortest path.	
	2	Use rotational coordinates. Always move forward.	
	3	Use rotational coordinates. Always move in reverse.	

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)
n.X□□□	Reserved parameter (Do not change.)

Pn638	4	Forward Software Limit (P-LS)/End Point of Rotational Coordinates	-536,870,911 to +536,870,911	Reference units	+536,870,911	All	After restart	Setup	*9
Pn63A	4	Reverse Software Limit (N-LS)/Starting Point of Rotational Coordinates	-536,870,911 to +536,870,911	Reference units	-536,870,911	All	After restart	Setup	*9
Pn63C	4	Origin Position/Absolute Encoder Offset	-1,073,741,823 to +1,073,741,823	Reference units	0	All	After restart	Setup	*9
Pn63E	4	Acceleration Rate	1 to 199,999,999	1,000/ms (reference units/min)	1000	All	Immediately	Setup	*9
Pn640	4	Deceleration Rate	1 to 199,999,999	1,000/ms (reference units/min)	1000	All	Immediately	Setup	*9
Pn642	2	Origin Return Method	0000h to 0004h	–	0000h	All	After restart	–	–

	Origin Return Method		Reference
n.□□□X	0	Origin returns are not executed.	*9
	1	Use the /DEC signal and phase C for origin returns.	
	2	Use the /DEC signal for origin returns.	
	3	Use phase C for origin returns.	
	4	Pressing homing is performed.*10	

n.□□X□	Reserved parameter (Do not change.)
n.□X□□	Reserved parameter (Do not change.)

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Parameter No.	Size	Name	Setting Range	Setting Unit	Default Setting	Applicable Motors	When Enabled	Classification	Reference
Pn643	2	Origin Return Direction	0000h to 0001h	–	0000h	All	Immediately	–	–

			Reference
n.□□□X	0	When the /HOME signal turns ON, an origin return is performed in the forward direction.	*9
	1	When the /HOME signal turns ON, an origin return is performed in the reverse direction.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn644	4	Origin Return Movement Speed	1 to 199,999,999	1,000 reference units/min	1000	All	Immediately	Setup	*9
Pn646	4	Origin Approach Speed	1 to 199,999,999	1,000 reference units/min	1000	All	Immediately	Setup	*9
Pn648	4	Origin Return Creep Speed	1 to 199,999,999	1,000 reference units/min	1000	All	Immediately	Setup	*9
Pn64A	4	Origin Return Final Travel Distance	-1,073,741,823 to +1,073,741,823	Reference units	0	All	Immediately	Setup	*9
Pn64C	2	Zone Signal Setting	0000h to 0001h	–	0000h	All	After restart	Setup	–

			Reference
n.□□□X	0	When the control power supply is turned ON or the SERVOPACK is reset, the /POUT0 to /POUT2 signals are inactive.	*9
	1	When the control power supply is turned ON or the SERVOPACK is reset, the /POUT0 to /POUT2 signals are used as zone signals.	
n.□□X□	Reserved parameter (Do not change.)		
n.□X□□	Reserved parameter (Do not change.)		
n.X□□□	Reserved parameter (Do not change.)		

Pn64D	2	Reserved parameter (Do not change.)	–	–	0000h	–	–	–	–
Pn650	2	Pressing Torque for Pressing Homing	0 to 100	%	25	All	Immediately	Setup	*9
Pn651	2	Pressing Detection Time for Pressing Homing	0 to 10,000	ms	250	All	Immediately	Setup	*9
Pn652	2	Pressing Time for Pressing Homing	0 to 10,000	ms	250	All	Immediately	Setup	*9
Pn653	2	Overspeed Detection Level for Pressing Homing	1 to 199,999,999	1,000 reference units/min	2,000	All	Immediately	Setup	*9
Pn655	2	Absolute Encoder Origin	-1,073,741,823 to +1,073,741,823	Reference units	0	All	After restart	Setup	*9

*1. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual (Manual No.: SIEP S800001 26)

*2. Set a percentage of the rated motor torque.

*3. These parameters are for SERVOPACKs with a Safety Module. Refer to the following manual for details.
Σ-V-Series/Σ-V-Series for Large-Capacity Models/Σ-7-Series User's Manual Safety Module (Manual No.: SIEP C720829 06)

*4. Normally set this parameter to 0. If you use an External Regenerative Resistor, set the capacity (W) of the External Regenerative Resistor.

*5. The upper limit is the maximum output capacity (W) of the SERVOPACK.

*6. These parameters are for SERVOPACKs with the Dynamic Brake Option. Refer to the following manual for details.
Σ-7-Series AC Servo Drive Σ-7S/S-7W SERVOPACK with Dynamic Brake Hardware Option Specifications Product Manual (Manual No.: SIEP S800001 73)

*7. The SGLFW2 is the only Yaskawa Linear Servomotor that supports this function.

*8. Enabled only when Pn61A is set to n.□□□2 or n.□□□3.

*9. Refer to the following manual for details.
Σ-7-Series Σ-7S SERVOPACK with FT/EX Specification for Indexing Application Product Manual (Manual No.: SIEP S800001 84)

*10. Pressing homing (Pn642 = n.□□□4) can be used with SERVOPACK software versions 0028F794 and higher.

Index

A

alarm code output
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 3-146
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - - 3-3
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-205
alarm reset possibility - - - - - - - - - - - - - - - 3-50, 3-98

B

base block (BB) - xv

C

coefficient of speed fluctuation
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - - 2-15
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 2-9
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - 2-12
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - - 2-5
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 2-19

I

INDEXER alarm displays and troubleshooting
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-234
INDEXER Module alarm displays and troubleshooting
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 3-177
INDEXER Module error displays and troubleshooting
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 3-189
INDEXER warning displays and troubleshooting
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-246

L

list of alarms
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 3-146
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - 3-50
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - 3-98
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - - 3-3
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-205
list of MECHATROLINK-III common parameters - - - - 4-106
list of parameters
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 4-114
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 4-32
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - - 4-67
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - - 4-2
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 4-138
list of warnings
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 3-181
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 3-80
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - 3-128
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-34
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-238

M

Main Circuit Cable - xv

P

parameters
notation (numeric settings) - - - - - - - - - - - - - - - - xvi
notation (selecting functions) - - - - - - - - - - - - - - - xvi

R

ratings - 2-2

S

serial communications method - - - - - - - - - - - - - - - 2-18
Servo Drive - xv
servo lock - xv
servo OFF - xv
servo ON - xv
Servo System - xv
Servomotor - xv
SERVOPACK - xv
SigmaWin+ - xv
specifications
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - - 2-15
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 2-9
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - 2-12
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - - 2-5
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 2-19

storage humidity
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - -2-15
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 2-9
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - -2-12
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 2-5
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - -2-19
storage temperature
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - -2-15
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 2-9
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - -2-12
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 2-5
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - -2-19
surrounding air humidity
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - -2-15
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 2-9
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - -2-12
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 2-5
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - -2-19
surrounding air temperature
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - -2-15
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 2-9
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - -2-12
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 2-5
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - -2-19

T

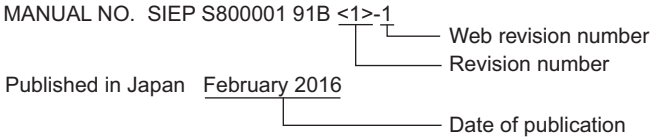
troubleshooting alarms
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 3-151
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - -3-55
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - 3-103
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-9
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-210
troubleshooting warnings
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 3-183
FT82 SERVOPACK with MECHATROLINK-II
Communications References - - - - - - - - - - - - - - 3-82
FT82 SERVOPACK with MECHATROLINK-III
Communications References - - - - - - - - - - - - - 3-130
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-35
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-240

W

warning code output
Command Option Attachable-type
FT82 SERVOPACKs with INDEXER Modules - - - - 3-181
FT82 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-34
FT83 SERVOPACKs with Analog Voltage/
Pulse Train References - - - - - - - - - - - - - - - - - 3-238

Revision History

The date of publication, revision number, and web revision number are given at the bottom right of the back cover. Refer to the following example.



Date of Publication	Rev. No.	Web Rev. No.	Section	Revised Contents
September 2018	<5>	0	All chapters	Partly revised.
			Back cover	Revision: Address
May 2018	<4>	1	Preface	Partly revised.
			Chapter 4	Revision: Pn040
December 2017		0	Chapter 3	Deletion: A.F50
				Revision: A.300
			3.4.8, 3.5.8	Addition: E65E
			3.5.4	Addition: E24A, E25A
			3.5.6, 3.5.7	Addition: A.941
			Chapter 4	Revision: Pn460
			4.3, 4.4	Revision: Settings of PnB00 to PnB20, PnB31, PnB32
			4.5	Addition: Pn650, Pn651, Pn652, Pn653, Pn655
				Partly revised.
September 2017	<3>	0	Preface	Revision: Information on certification for standards
			Back cover	Revision: Address
March 2017	<2>	0	Preface, 1.4.1, Chapter 3, Chapter 4	Partly revised.
			1.6	Newly added.
			2.1	Addition: Information on input current of control power supply
			2.3	Addition: Information on overheat protection input
			Chapter 3	Addition: A.862 and A.93B
			Chapter 4	Addition: Pn022, Pn475, Pn476, Pn61A, Pn61B, Pn61C, and Pn61D
				Deletion: Pn52D
			Back cover	Revision: Address
February 2016	<1>	1	3.1.3, 3.2.3, 3.3.3, 3.4.3, 3.5.3	Revision: A.860
November 2015		0	All chapters	Addition: Information on SERVOPACKs with a single-phase, 100-VAC power supply input
			Chapter 3	Addition: A.bF5, A.bF6, A.bF7, A.bF8, and FL-6
			Back cover	Revision: Address
September 2015	–	–	–	First edition

Σ-7-Series AC Servo Drive

Σ-7S SERVOPACK with FT/EX Specification for Application with Special Motor, SGM7D Motor

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MANUAL NO. SIEP S800001 91F <5>-0

Published in Japan September 2018
18-9-14
Original instructions