

YASKAWA

HV600

NARROW BYPASS INSTALLATION & STARTUP

AC DRIVE BYPASS FOR HVAC FAN & PUMP APPLICATIONS

CATALOG CODE:

H6BPxxxx

CAPACITIES:

208 V: 0.5 to 25 HP

480 V: 0.5 to 60 HP

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Table of Contents

| | | |
|-----|---|----|
| i. | Preface and General Precautions | 7 |
| i.1 | Definitions | 8 |
| | Product Description | 8 |
| | Glossary | 8 |
| | About Registered Trademarks | 8 |
| i.2 | Using the Product Safely | 10 |
| | Explanation of Signal Words | 10 |
| | General Safety | 10 |
| | Warning Labels | 12 |
| | Cybersecurity | 13 |
| | Warranty Information | 13 |
| 1. | Receiving | 15 |
| 1.1 | Section Safety | 16 |
| 1.2 | Catalog Code and Nameplate Check | 17 |
| | Narrow Bypass Nameplate | 17 |
| | Drive Nameplate | 18 |
| | How to Read Narrow Bypass Catalog Codes | 18 |
| 2. | Mechanical Installation | 21 |
| 2.1 | Section Safety | 22 |
| 2.2 | Installation Environment | 24 |
| 2.3 | Narrow Bypass Installation Position and Clearances | 25 |
| 2.4 | Bypass Components | 26 |
| 2.5 | Narrow Bypass Component Names | 27 |
| 2.6 | Moving the Bypass | 29 |
| | Using the Mounting Rails to Move the Bypass | 29 |
| 2.7 | Removing/Reattaching Covers | 31 |
| | Removing/Reattaching the Bypass Cover Using Procedure 1 | 31 |
| | Removing/Reattaching the Drive Cover Using Procedure A | 32 |
| 3. | Electrical Installation | 35 |
| 3.1 | Section Safety | 36 |
| 3.2 | Wiring Diagram | 38 |
| | Standard Connection Diagram | 38 |
| 3.3 | Main Circuit Wiring | 42 |
| | Narrow Bypass Input and Output Power Wiring Connections | 42 |
| | Factory Recommended Branch Circuit Protection | 43 |

| | | |
|------|---|-----|
| | Wire Selection | 43 |
| | Main Circuit Terminal and Motor Wiring | 44 |
| | Protection of Main Circuit Terminals | 45 |
| 3.4 | Main Circuit Terminal Wiring Procedure | 46 |
| | Narrow Bypass Main Circuit Terminal Block Wiring Procedure | 46 |
| 3.5 | Bypass Controller | 48 |
| | Wiring the Bypass Control Circuit Terminal | 52 |
| 3.6 | Drive Control Circuit | 54 |
| | Wiring the Drive Control Circuit Terminal | 59 |
| 3.7 | Control I/O Connections | 62 |
| | Set Input Signals for MFAI Terminals A1 and A2 | 62 |
| | Set Output Signals for MFAO Terminals FM, AM | 62 |
| 3.8 | Connect the Bypass to a PC | 64 |
| 3.9 | Motor Application Precautions | 65 |
| | Precautions for Existing Standard Motors | 65 |
| | Precautions for Specialized Motors | 65 |
| | Notes on the Power Transmission Mechanism | 66 |
| 4. | Startup Procedure and Test Run | 67 |
| 4.1 | Section Safety | 68 |
| 4.2 | Keypad: Names and Functions | 69 |
| | LCD Display | 70 |
| | AUTO LED and HAND LED Indications | 71 |
| | Keypad Mode and Menu Displays | 73 |
| 4.3 | Start-up, Test Operation, and Rotation Check | 75 |
| | Items to Check before You Energize the Bypass | 75 |
| | Bypass Start-Up Procedure | 76 |
| | Test Run and Rotation Check | 77 |
| 4.4 | Auto-Tuning | 81 |
| | Auto-Tuning for Induction Motors | 81 |
| | Precautions before Auto-Tuning | 81 |
| 4.5 | Fine Tuning during Test Runs (Adjust the Control Function) | 83 |
| | V/f Control | 83 |
| 5. | Troubleshooting | 85 |
| 5.1 | Section Safety | 86 |
| 5.2 | Types of Faults, Minor Faults, Alarms, and Errors | 88 |
| 5.3 | Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically | 89 |
| 5.4 | Faults, Minor Faults, Alarms, and Error Codes Listed by Decimal Value for Use with BACnet/Modbus | 96 |
| 5.5 | Faults | 102 |
| 5.6 | Minor Faults/Alarms | 126 |
| 5.7 | Parameter Setting Errors | 139 |
| 5.8 | Auto-Tuning Errors | 142 |
| 5.9 | Backup Function Operating Mode Display and Errors | 145 |
| 5.10 | Bypass Status Messages | 146 |
| 5.11 | Diagnosing and Resetting Faults | 147 |
| | Fault and Power Loss Occur at the Same Time | 147 |
| | Fault Occurs Without Power Loss | 147 |

| | |
|--|------------|
| Fault Reset | 147 |
| 6. Specifications | 149 |
| 6.1 Section Safety | 150 |
| 6.2 208 V Narrow Model Specifications | 151 |
| 6.3 480 V Narrow Model Specifications | 153 |
| 6.4 Common Bypass Specifications | 155 |
| 6.5 Drive Watt Loss and Derating | 157 |
| 6.6 Peripheral Devices and Options | 158 |
| Bypass Options | 158 |
| Option Installation Procedure | 159 |
| 6.7 Periodic Inspection and Maintenance | 163 |
| 7. Parameter List | 165 |
| 7.1 How to Read the Parameter List | 166 |
| Terms that Identify Parameters | 166 |
| Parameter Groups | 166 |
| 7.2 A: Initialization Parameters | 168 |
| 7.3 b: Application | 171 |
| 7.4 C: Tuning | 178 |
| 7.5 d: Reference Settings | 180 |
| 7.6 E: Motor Parameters | 182 |
| 7.7 F: Options | 184 |
| 7.8 H: Terminal Functions | 189 |
| 7.9 L: Protection Functions | 206 |
| 7.10 n: Special Adjustment | 213 |
| 7.11 o: Keypad-Related Settings | 214 |
| 7.12 S: Special Applications | 220 |
| 7.13 Y: Application Features | 229 |
| 7.14 Z: Bypass Parameters | 237 |
| 7.15 U: Monitors | 245 |
| 8. Network Communications | 261 |
| 8.1 Section Safety | 262 |
| 8.2 Fieldbus Network Support | 263 |
| 8.3 BACnet Communications | 264 |
| Configure Master/Slave | 264 |
| Communication Specifications | 264 |
| Communication with the Controller | 265 |
| Bypass Operations by Serial Communications | 266 |
| BACnet Objects Supported | 267 |
| Accessing Drive Parameters and the Enter Command | 278 |
| Self-Diagnostics | 279 |
| BACnet Protocol Implementation Conformance Statement | 280 |
| 8.4 Other Embedded Communication Protocols | 283 |
| 9. Standards Compliance | 285 |
| 9.1 Section Safety | 286 |

| | | |
|------|---|-----|
| 9.2 | UL Standards | 288 |
| | Area of Use..... | 288 |
| 9.3 | Seismic Standards | 289 |
| 9.4 | European Standards..... | 290 |
| | EU Declaration of Conformity | 290 |
| | CE Low Voltage Directive Compliance | 290 |
| | EMC Directive | 290 |
| 10 | Disposal | 297 |
| 10.1 | Section Safety | 298 |
| 10.2 | Disposal Instructions..... | 299 |
| 10.3 | WEEE Directive..... | 300 |
| | Index | 301 |
| | Revision History | 305 |

Preface and General Precautions

This chapter gives information about important safety precautions for the use of this product. Failure to obey these precautions can cause serious injury or death, or damage to the product or related devices and systems. Yaskawa must not be held responsible for any injury or equipment damage as a result of the failure to observe these precautions and instructions.

| | | |
|------------|---------------------------------------|-----------|
| i.1 | Definitions | 8 |
| i.2 | Using the Product Safely | 10 |

i.1 Definitions

These instructions contain the information necessary to use the product correctly. Read and understand the safety information and precautions before you start to use the product.

◆ Product Description

The HV600 bypass provides a way to bypass the drive and allow the motor to operate directly from the AC line at full speed. It incorporates an AC drive and a two or three-contactor bypass arrangement in a single UL listed enclosure. The two electrically-interlocked IEC-rated contactors isolate the drive from the load when operating in Bypass Mode.

Control logic provides industry standard Hand/Off/Auto functions, BAS Interlock, and safety circuit interlocks in both Drive and Bypass operating modes.

Bypass components include: a fused 120 Vac control circuit transformer, an input disconnect, motor overload, DC link choke, EMC filter, and an HOA keypad with LCD display.

The HV600 drive, a component of the bypass package, is a pulse width modulated drive for three-phase AC induction motors. This type of drive is also known as an adjustable frequency drive, variable frequency drive, AC Drive, AFD, ASD, VFD, and inverter.

The drive is a variable torque AC drive, designed specifically for HVAC applications in building automation, including fans, blowers and pumps.

The bypass has embedded communications for the popular building automation protocols, BACnet (MSTP), N2, P1, and Modbus®.

The LCD keypad is equipped with Hand/Off/Auto functions. Optional DriveWizard software allows upload/download, as well as graphing and monitoring of drive parameters from a PC for ease of drive management.

Built-in PI control eliminates the need for closed loop output signals from a building automation system. It includes feedback display, inverse, square root and differential control functions, and maintains setpoint for closed loop control of fans and pumps for pressure, flow, or temperature regulation. There is also an additional independent PI control for external devices.

◆ Glossary

| Phrase | Definition |
|--------|-------------------------------|
| Bypass | YASKAWA AC Drive Bypass HV600 |
| Drive | YASKAWA AC Drive HV600 |
| MFAI | Multi-Function Analog Input |
| MFAO | Multi-Function Analog Output |
| MFDI | Multi-Function Digital Input |
| MFDO | Multi-Function Digital Output |
| V/f | V/f Control |

◆ About Registered Trademarks

- APOGEE FLN is a registered trademark of Siemens Building Technologies, Inc.
- APOGEE Anywhere is a trademark of Siemens Building Technologies, Inc.
- BACnet is a trademark of the American Society of Heating, Refrigerating, and Air-Conditioning Engineers (ASHRAE).
- EtherNet/IP is a registered trademark of Open DeviceNet Vendor Association, Inc. (ODVA).
- LonWorks and LonTalk are registered trademarks of Echelon Corporation.
- Metasys N2 is a trademark of Johnson Controls, Inc.
- Modbus is a registered trademark of Schneider Electric SA.
- PROFINET is a registered trademark of PROFIBUS International.

- Other company names and product names in this document are trademarks or registered trademarks of the respective companies.

i.2 Using the Product Safely

◆ Explanation of Signal Words

WARNING

Read and understand this manual before you install, operate, or do maintenance on the drive. Install the drive as specified by this manual and local codes.

The symbols in this section identify safety messages in this manual. If you do not obey these safety messages, the hazards can cause serious injury, death, or damage to the products and related equipment and systems.

These identifier words categorize and emphasize important safety precautions in these instructions.

DANGER

This signal word identifies a hazard that will cause serious injury or death if you do not prevent it.

WARNING

This signal word identifies a hazard that can cause death or serious injuries if you do not prevent it.

CAUTION

Identifies a hazardous situation, which, if not avoided, can cause minor or moderate injury.

NOTICE

This signal word identifies a property damage message that is not related to personal injury.

◆ General Safety

General Precautions

- Some figures in the instructions include options and bypasses without covers or safety shields to more clearly show the inside of the bypass. Replace covers and shields before operation. Use options and bypasses only as specified by the instructions.
- The figures in this manual are examples only. All figures do not apply to all products included in this manual.
- Yaskawa can change the products, specifications, and content of the instructions without notice to make the product and/or the instructions better.
- If you damage or lose these instructions, contact a Yaskawa representative or the nearest Yaskawa sales office on the rear cover of the manual, and tell them the document number to order new copies.

DANGER

Do not ignore the safety messages in this manual.

If you ignore the safety messages in this manual, it will cause serious injury or death. The manufacturer is not responsible for injuries or damage to equipment.

Electrical Shock Hazard

Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe.

If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

⚠ WARNING**Arc Flash Hazard**

Obey local codes and Arc Flash safety requirements contained in the Standard for Electrical Safety in the Workplace NFPA 70E (2009 Edition or later) and the Workplace Electrical Safety, Canadian Standards Association (CSA) Z462-12. Obey safe work procedures and use applicable personal protective equipment (PPE).

If you do not obey these requirements and procedures, it can cause serious injury or death.

Crush Hazard

Test the system to make sure that the bypass operates safely after you wire the bypass and set parameters.

If you do not test the system, it can cause damage to equipment or serious injury or death.

Sudden Movement Hazard

Before you do a test run, make sure that the setting values for virtual input and output function parameters are correct. Virtual input and output functions can have different default settings and operation than wired input and output functions.

Incorrect function settings can cause serious injury or death.

Remove all personnel and objects from the area around the bypass, motor, and machine and attach covers, couplings, shaft keys, and machine loads before you energize the bypass.

If personnel are too close or if there are missing parts, it can cause serious injury or death.

Electrical Shock Hazard

Do not modify the bypass body, drive body, bypass circuitry, or drive circuitry.

Modifications to bypass and drive body and circuitry can cause serious injury or death, will cause damage to the bypass and drive, and will void the warranty. Yaskawa is not responsible for modifications of the product made by the user.

Only let approved personnel install, wire, maintain, examine, replace parts, and repair the bypass.

If personnel are not approved, it can cause serious injury or death.

Do not remove covers or touch circuit boards while the bypass is energized.

If you touch the internal components of an energized bypass, it can cause serious injury or death.

After the bypass blows a fuse or trips a GFCI, do not immediately energize the bypass or operate peripheral devices. Wait for the time specified on the warning label at a minimum and make sure that all indicators are OFF. Then check the wiring and peripheral device ratings to find the cause of the problem. If you do not know the cause of the problem, contact Yaskawa before you energize the bypass or peripheral devices.

If you do not fix the problem before you operate the bypass or peripheral devices, it can cause serious injury or death.

Damage to Equipment

Do not apply incorrect voltage to the main circuit of the bypass. Operate the bypass in the specified range of the input voltage on the nameplate.

Voltages that are higher than the permitted nameplate tolerance can cause damage to the bypass.

Fire Hazard

Install sufficient branch circuit short circuit protection as specified by applicable codes and this manual. The bypass is suitable for circuits that supply not more than 100,000 RMS symmetrical amperes, 240 Vac maximum (208/240 V), 480 Vac maximum (480 V).

Incorrect branch circuit short circuit protection can cause serious injury or death.

⚠ CAUTION

Crush Hazard

Tighten terminal cover screws and hold the case safely when you move the bypass.
If the bypass or covers fall, it can cause moderate injury.

NOTICE

Use an inverter-duty motor with reinforced insulation and windings applicable for use with an AC drive.

If the motor does not have the correct insulation, it can cause a short circuit or ground fault from insulation deterioration.

Damage to Equipment

When you touch the bypass, drive, and circuit boards, make sure that you observe correct electrostatic discharge (ESD) procedures.

If you do not follow procedures, it can cause ESD damage to the drive and bypass circuitry.

Do not do a withstand voltage test or use a megohmmeter or megger insulation tester on the bypass.

These tests can cause damage to the bypass.

Do not operate a bypass or connected equipment that has damaged or missing parts.

You can cause damage to the bypass and connected equipment.

Do not use steam or other disinfectants to fumigate wood for packaging the bypass. Use alternative methods, for example heat treatment, before you package the components.

Gas from wood packaging fumigated with halogen disinfectants, for example fluorine, chlorine, bromine, iodine or DOP gas (phthalic acid ester), can cause damage to the bypass.

◆ Warning Labels

The drive warning label is in the location shown in [Figure i.1](#). Use the drive as specified by this information.

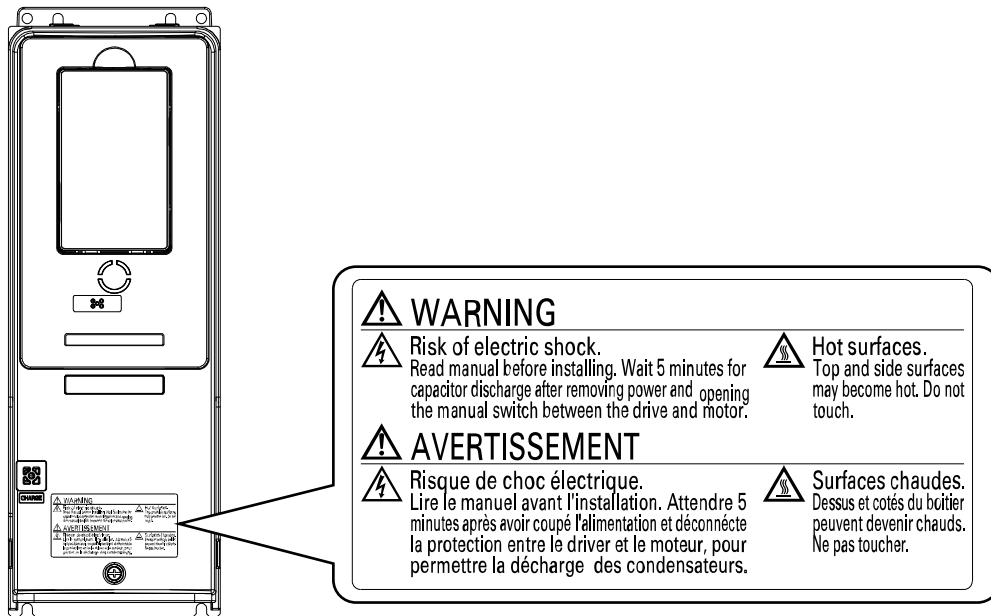


Figure i.1 Drive Warning Label Content and Location

The bypass warning labels are in the locations shown in [Figure i.2](#). Use the bypass as specified by this information.

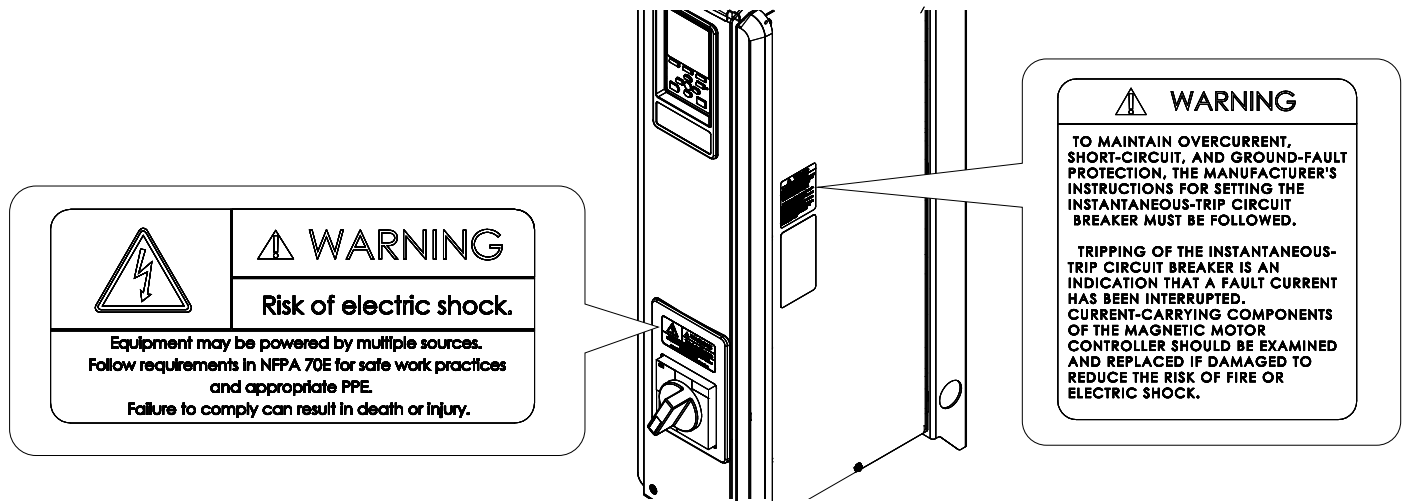


Figure i.2 Bypass Warning Labels and Locations

◆ Cybersecurity

This product is designed to connect and communicate information and data through a network interface. It is the sole responsibility of the customer to provide and continuously guarantee a secure connection between the product and the customer's network or if applicable, any other network. The customer must establish and maintain the appropriate measures (such as, but not limited to, the installation of firewalls, the application of authentication measures, the encryption of data, the installation of antivirus programs, etc.) to protect the product, the network, its system and the interface against all types of security breaches, unauthorized access, interference, intrusion, leakage and/or theft of data or information. Yaskawa and its affiliates are not responsible for damages and/or losses related to such security breaches, any unauthorized access, interference, intrusion, leakage and/or theft of data or information.

◆ Warranty Information

■ Exclusion of Liability

- This product is not designed and manufactured for use in life-support machines or systems.
- Contact a Yaskawa representative or your Yaskawa sales representative if you are considering the application of this product for special purposes, such as machines or systems used for passenger cars, medicine, airplanes and aerospace, nuclear power, electric power, or undersea relaying.

⚠ WARNING

Injury to Personnel

When you use this product in applications where its failure could cause the loss of human life, a serious accident, or physical injury, you must install applicable safety devices.

If you do not correctly install safety devices, it can cause serious injury or death.

Receiving

This chapter gives information about the different drive models and features, and how to examine the drive when you receive it.

| | | |
|------------|--|-----------|
| 1.1 | Section Safety | 16 |
| 1.2 | Catalog Code and Nameplate Check..... | 17 |

1.1 Section Safety

 **DANGER**

Do not ignore the safety messages in this manual.

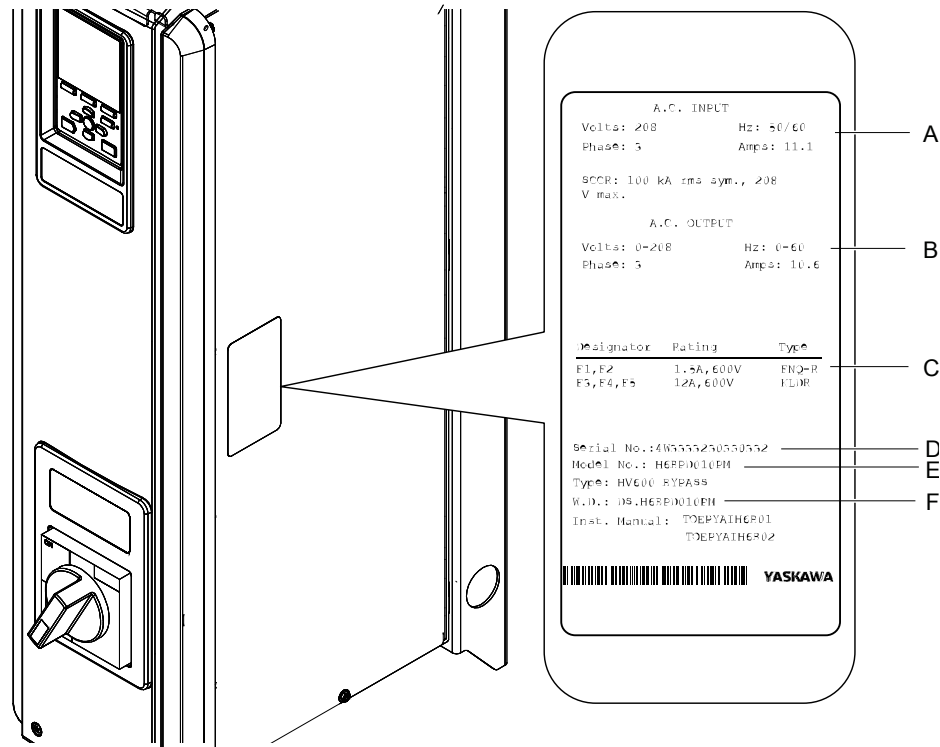
If you ignore the safety messages in this manual, it will cause serious injury or death. The manufacturer is not responsible for injuries or damage to equipment.

1.2 Catalog Code and Nameplate Check

Please examine these items after you received the bypass:

- Examine the bypass and drive for damage or missing parts. Immediately contact the shipping company if there is damage. The Yaskawa warranty does not cover damage from shipping.
- Examine the model number on the bypass nameplate to make sure that you received the correct model.
- If you received a product different than what you ordered or your product has a defect, contact Yaskawa or your nearest sales representative.

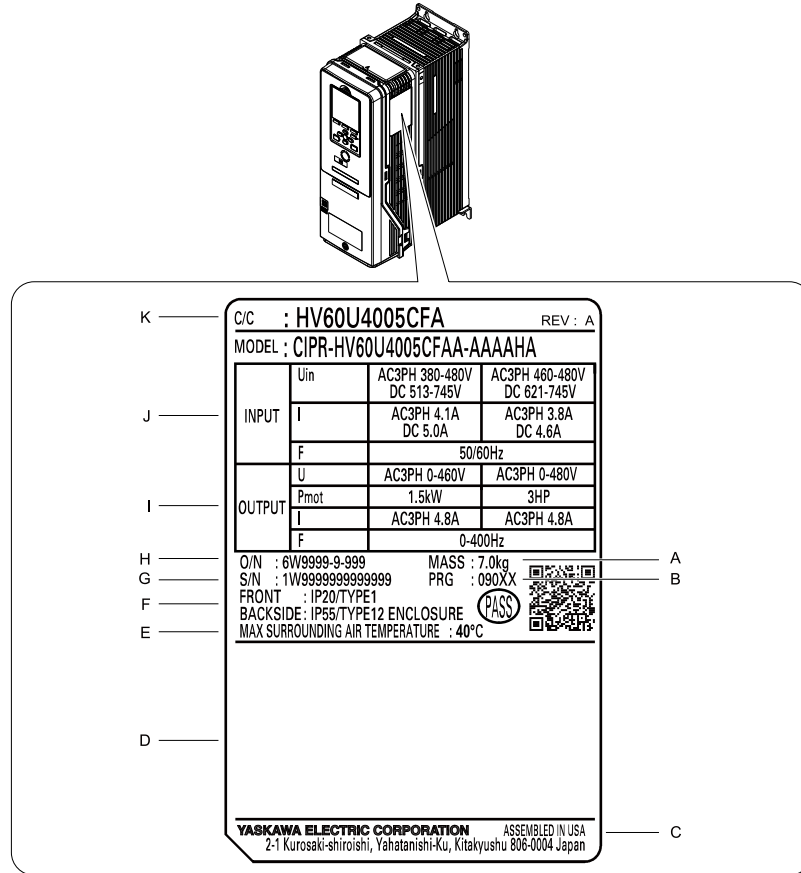
◆ Narrow Bypass Nameplate



- | | |
|-------------------------------------|-------------------------------|
| A - Input specifications | D - Serial number |
| B - Output specifications | E - Bypass model number |
| C - Replacement fuse specifications | F - Schematic document number |

Figure 1.1 Narrow Bypass Nameplate Location Example

◆ Drive Nameplate



- A - Weight
- B - Drive software version
- C - The address of the head office of Yaskawa Electric Corporation
- D - Accreditation standards
- E - Ambient Temperature Setting
- F - Protection design
- G - Product number
- H - Serial number
- I - Output specifications
- J - Input specifications
- K - Catalog code

Figure 1.2 Drive Nameplate Location

◆ How to Read Narrow Bypass Catalog Codes

Use the information in Figure 1.3 and Table 1.1 to read the bypass catalog codes.

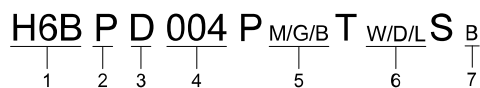


Figure 1.3 Narrow Bypass Catalog Code

Table 1.1 Narrow Bypass Catalog Code Details

| No. | Description |
|-----|---|
| 1 | Product series |
| 2 | Bypass type <ul style="list-style-type: none"> • P: IP20/UL Type 1 Narrow • N: IP55/UL Type 12 Narrow |
| 3 | Input power supply voltage <ul style="list-style-type: none"> • D: Three-Phase 208 V • B: Three-Phase 480 V |

| No. | Description |
|-----|--|
| 4 | Bypass output amps |
| 5 | Power options <ul style="list-style-type: none"> • M: Lockable circuit breaker (100 kA SCCR Panel Rating) • B: 3-contactor bypass • G: Drive input service switch |
| 6 | Control options <ul style="list-style-type: none"> • W: Custom nameplate • D: EtherNet/IP • L: LonWorks |
| 7 | Special options <ul style="list-style-type: none"> • B: Bluetooth HOA keypad |

■ Narrow Bypass Models, Drive Models, and Capacities

Table 1.2 Three-Phase AC 208 V Narrow Models and Capacities (NEMA Rating)

| Bypass Model H6BP | Capacity | | | Drive Catalog Code HV60U | Electrical Schematic | Weight (lb) |
|----------------------|----------|-----------|------------|-----------------------------|----------------------|-------------|
| | HP | Input (A) | Output (A) | | | |
| D002 | 0.5 | 2.9 | 2.4 | 2011 | DS.H6BP.01 | 55 |
| D003 | 0.75 | 4.0 | 3.5 | 2011 | DS.H6BP.01 | 55 |
| D004 | 1 | 5.1 | 4.6 | 2011 | DS.H6BP.01 | 55 |
| D007 | 2 | 8.0 | 7.5 | 2011 | DS.H6BP.01 | 55 |
| D010 | 3 | 11.1 | 10.6 | 2011 | DS.H6BP.01 | 55 |
| D016 | 5 | 17.2 | 16.7 | 2017 | DS.H6BP.01 | 55 |
| D024 | 7.5 | 24.7 | 24.2 | 2024 | DS.H6BP.01 | 62 |
| D030 | 10 | 31.3 | 30.8 | 2031 | DS.H6BP.01 | 64 |
| D046 | 15 | 46.7 | 46.2 | 2046 | DS.H6BP.01 | 87 |
| D059 | 20 | 59.9 | 59.4 | 2059 | DS.H6BP.01 | 92 |
| D074 | 25 | 75.3 | 74.8 | 2075 | DS.H6BP.01 | 128 |

Table 1.3 Three-Phase AC 480 V Narrow Models and Capacities (NEMA Rating)

| Bypass Model H6BP | Capacity | | | Drive Catalog Code HV60U | Electrical Schematic | Weight (lb) |
|----------------------|----------|-----------|------------|-----------------------------|----------------------|-------------|
| | HP | Input (A) | Output (A) | | | |
| B1P1 | 0.5 | 1.3 | 1.1 | 4005 | DS.H6BP.01 | 56 |
| B001 | 0.75 | 1.8 | 1.6 | 4005 | DS.H6BP.01 | 56 |
| B002 | 1 | 2.3 | 2.1 | 4005 | DS.H6BP.01 | 56 |
| B003 | 2 | 3.6 | 3.4 | 4005 | DS.H6BP.01 | 56 |
| B004 | 3 | 5.0 | 4.8 | 4005 | DS.H6BP.01 | 56 |
| B007 | 4 | 7.8 | 7.6 | 4008 | DS.H6BP.01 | 56 |
| B011 | 7.5 | 11.2 | 11.0 | 4011 | DS.H6BP.01 | 56 |
| B014 | 10 | 14.2 | 14.0 | 4014 | DS.H6BP.01 | 56 |
| B021 | 15 | 21.2 | 21.0 | 4021 | DS.H6BP.01 | 62 |
| B027 | 20 | 27.2 | 27.0 | 4027 | DS.H6BP.01 | 65 |
| B034 | 25 | 34.2 | 34.0 | 4034 | DS.H6BP.01 | 81 |
| B040 | 30 | 40.2 | 40.0 | 4040 | DS.H6BP.01 | 90 |
| B052 | 40 | 52.2 | 52.0 | 4052 | DS.H6BP.01 | 96 |
| B065 | 50 | 65.2 | 65.0 | 4065 | DS.H6BP.01 | 121 |
| B077 | 60 | 77.2 | 77.0 | 4077 | DS.H6BP.01 | 135 |

Mechanical Installation

This chapter explains how to properly mount and install the drive.

| | | |
|------------|---|-----------|
| 2.1 | Section Safety | 22 |
| 2.2 | Installation Environment | 24 |
| 2.3 | Narrow Bypass Installation Position and Clearances | 25 |
| 2.4 | Bypass Components | 26 |
| 2.5 | Narrow Bypass Component Names | 27 |
| 2.6 | Moving the Bypass | 29 |
| 2.7 | Removing/Reattaching Covers | 31 |

2.1 Section Safety

WARNING

Electrical Shock Hazard

Only let approved personnel install, wire, maintain, examine, replace parts, and repair the bypass.

If personnel are not approved, it can cause serious injury or death.

Do not modify the bypass body, drive body, bypass circuitry, or drive circuitry.

Modifications to bypass and drive body and circuitry can cause serious injury or death, will cause damage to the bypass and drive, and will void the warranty. Yaskawa is not responsible for modifications of the product made by the user.

Fire Hazard

Do not put flammable or combustible materials on top of the bypass and do not install the bypass near flammable or combustible materials. Attach the bypass to metal or other noncombustible material.

Flammable and combustible materials can start a fire and cause serious injury or death.

Crush Hazard

Only approved personnel can operate a crane or hoist to move the bypass.

If unapproved personnel operate a crane or hoist, it can cause serious injury or death from falling equipment.

Before you hang the bypass vertically, use screws to correctly attach the front cover and other components.

If you do not secure the front cover, it can fall and cause minor injury.

When you use a crane or hoist to lift the bypass during installation or removal, prevent more than 1.96 m/s² (0.2 G) vibration or impact.

Too much vibration or impact can cause serious injury or death from falling equipment.

When you lift the bypass during installation or removal, do not try to turn it over and do not ignore a hanging bypass.

If you move a hanging bypass too much or if you ignore it, it can fall and cause serious injury or death.

Use a crane or hoist to move large bypasses when necessary.

If you try to move a large bypass without a crane or hoist, it can cause serious injury or death.

CAUTION

Crush Hazard

Tighten terminal cover screws and hold the case safely when you move the bypass.

If the bypass or covers fall, it can cause moderate injury.

NOTICE

Do not let unwanted objects, for example metal shavings or wire clippings, fall into the bypass during installation. Put a temporary cover over the bypass during installation. Remove the temporary cover before start-up.

Unwanted objects inside of the bypass can cause damage to the bypass.

Damage to Equipment

When you touch the drive and bypass circuit boards, make sure that you observe correct electrostatic discharge (ESD) procedures.

If you do not follow procedures, it can cause ESD damage to the drive and bypass circuitry.

Install vibration-proof rubber on the base of the motor or use the frequency jump function in the bypass to prevent specific frequencies that vibrate the motor.

Motor or system resonant vibration can occur in fixed speed machines that are converted to variable speed. Too much vibration can cause damage to equipment.

2.2 Installation Environment

The installation environment is important for the lifespan of the product and to make sure that the bypass performance is correct. Make sure that the installation environment agrees with these specifications.

| Environment | Conditions |
|-----------------------------|---|
| Area of Use | Indoors |
| Ambient Temperature Setting | IP20/UL Type 1: -10 °C to +40 °C (14 °F to 104 °F) IP55/UL Type 12: -10 °C to +40 °C (14 °F to 104 °F) • Do not let the bypass freeze. |
| Humidity | 98% RH or less Do not let condensation form on the bypass. |
| Storage Temperature | -20 °C to +70 °C (-4 °F to +158 °F) (short-term temperature during transportation) |
| Surrounding Area | Pollution degree 2 or less Install the bypass in an area without: <ul style="list-style-type: none"> • Oil mist, corrosive or flammable gas, or dust • Metal powder, oil, water, or other unwanted materials • Radioactive materials or flammable materials, including wood • Harmful gas or fluids • Salt • Direct sunlight Keep wood and other flammable materials away from the bypass. |
| Altitude | 1000 m (3281 ft) maximum Note: Derate the output current by 1% for each 100 m (328 ft) to install the bypass in altitudes between 1000 m to 4000 m (3281 ft to 13123 ft). It is not necessary to derate the rated voltage in these conditions: <ul style="list-style-type: none"> • When you install the bypass at 2000 m (6562 ft) or lower • When you install the bypass between 2000 m to 4000 m (6562 ft to 13123 ft) and ground the neutral point on the power supply. |
| Vibration | <ul style="list-style-type: none"> • 10 Hz to 20 Hz: 1 G (9.8 m/s², 32.15 ft/s²) • 20 Hz to 55 Hz: H6BPD002 to D030, H6BPB1P1, B001 to B034: 0.6 G (5.9 m/s², 19.36 ft/s²) H6BPD046 to H6BPD074, H6BPB040 to B077: 0.2 G (1.96 m/s², 6.43 ft/s²) • 20 Hz to 55 Hz: H6B1D002 to D030, H6B1A002 to A028, H6B1B1P1, B001 to B034: 0.6 G (5.9 m/s², 19.36 ft/s²) H6B1D046 to D273, H6B1A042 to A248, H6B1B040 to B302: 0.2 G (1.96 m/s², 6.43 ft/s²) |
| Installation Orientation | Install the bypass vertically for sufficient cooling airflow. |

NOTICE: Do not let unwanted objects, for example metal shavings or wire clippings, fall into the bypass during installation. Put a temporary cover over the bypass during installation. Remove the temporary cover before start-up. Unwanted objects inside of the bypass can cause damage to the bypass.

Note:

Do not put peripheral devices, transformers, or other electronics near the bypass. Shield the bypass from electrical interference if components must be near the bypass. The bypass or the devices around the bypass may malfunction due to electrical interference.

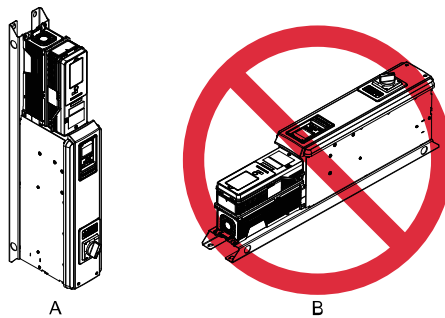
2.3 Narrow Bypass Installation Position and Clearances

◆ Installation Dimensions

Refer to the Dimension Drawing (DD.HB.x.xx.xx) packaged with the bypass for exterior and mounting dimensions for your model.

◆ Installation Position

Install the bypass vertically for sufficient cooling airflow.



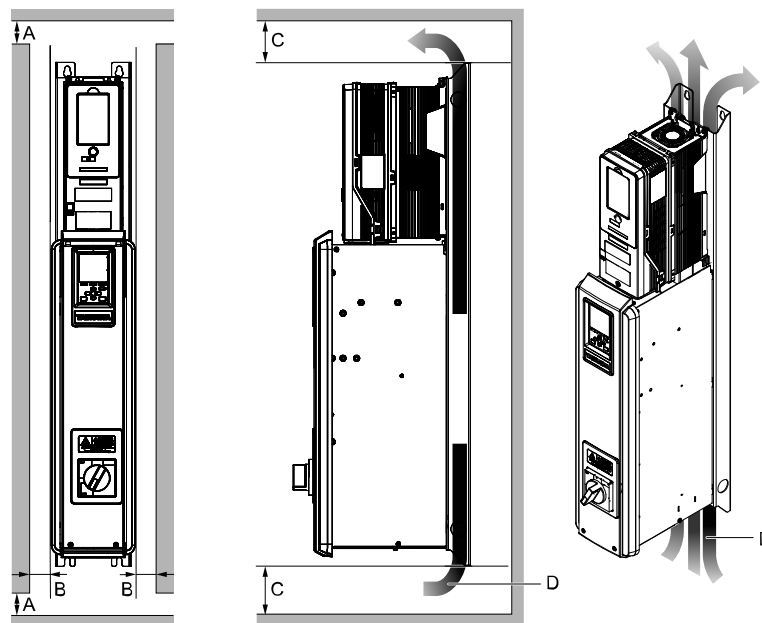
A - Vertical installation

B - Horizontal installation

Figure 2.1 Installation Position

◆ Single Narrow Bypass Installation Clearances

Use the clearances specified in Figure 2.2 to install the bypass. Make sure that there is sufficient space for wiring and airflow.



A - 50 mm (2 in) minimum
B - 30 mm (1.2 in) minimum

C - 120 mm (4.7 in) minimum *1
D - Airflow direction

Figure 2.2 Single Bypass Installation

*1 This is the distance from a component or mounting bracket that has the maximum height. The highest component is different for different models.

2.4 Bypass Components

◆ Input Disconnect Switch

Electrically located on the input power side of the bypass, the door mounted rotary input disconnect switch provides a way to disconnect bypass from line power for equipment maintenance. Put the disconnect in the OFF position to open the bypass enclosure door. When open, you can use a padlock to lock the handle in the OFF position. The customer must supply branch short circuit protection for the bypass.

◆ Contactors

The bypass is a 2-contactor or 3-contactor bypass circuit employing IEC rated contactors in an electrically interlocked arrangement to allow mutually exclusive operation in Drive or Bypass modes.

The control logic and “soft start” characteristic of the drive limit the drive input and output contactors to motor FLA current or less. For this reason, the drive output contactor has a lower current rating than the bypass contactor. The bypass contactor is exposed to motor inrush current (LRA) when starting the motor across-the-line and therefore requires a higher current rating.

◆ Overload Relay

Electronic overload relay consists of bypass relay board and two pass-through current transformers. Overload relay functions, settings, adjustments and reset operations are done through the keypad. The bypass three-phase output power connection to the motor is made to terminal block TB3.

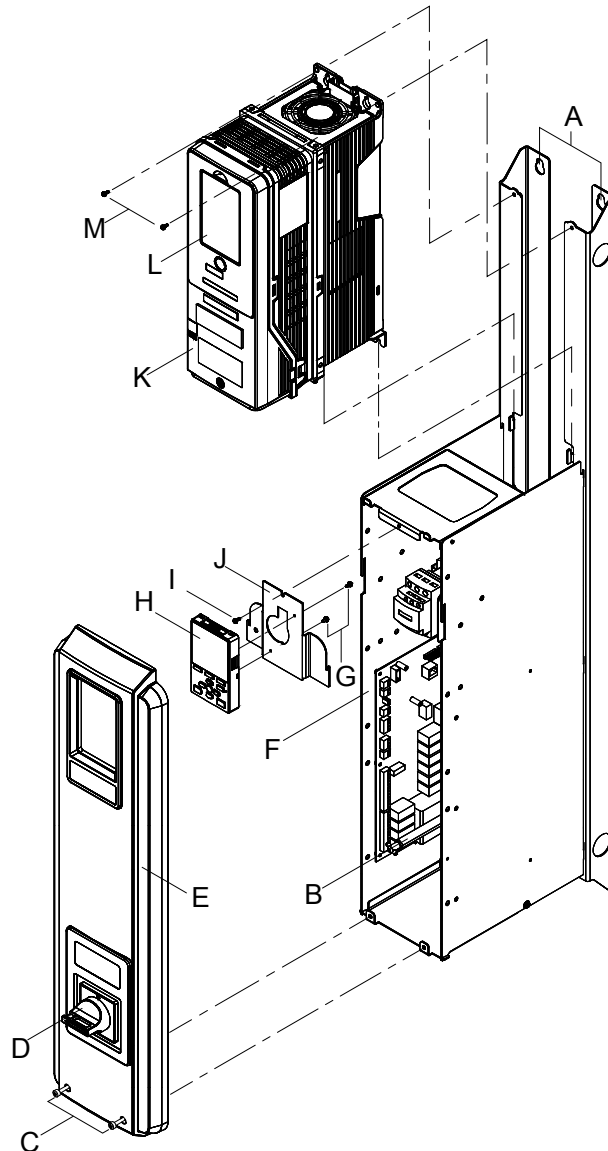
◆ Control Power Transformer

A Control Power Transformer (CPT) is provided to power the bypass 120 Vac control circuit. The VA capacity is determined by the control circuit and optional functions specified for the unit. The CPT primary is fused in both legs, the secondary is fused when required by NEC (transformer VA and wire size dependent). One side of the transformer secondary is grounded to the bypass enclosure.

2.5 Narrow Bypass Component Names

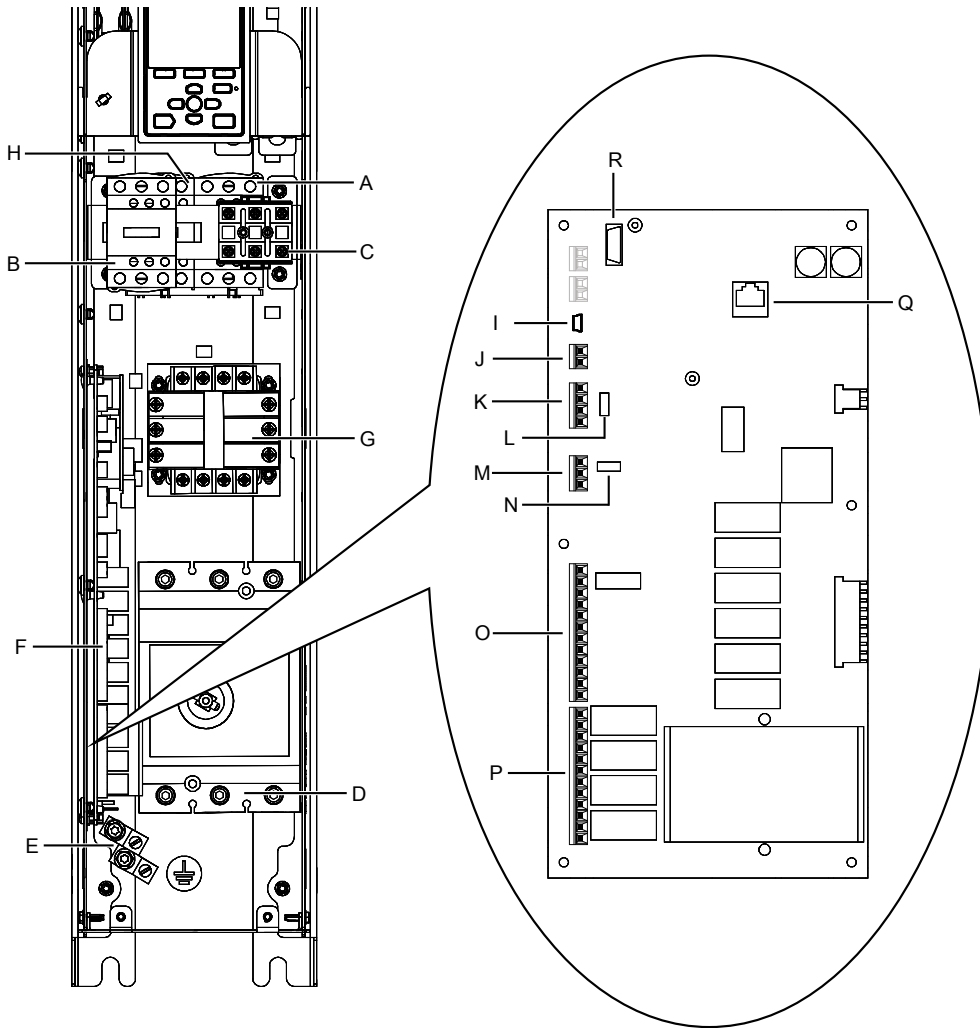
This section gives an overview of the Narrow Bypass components described in this manual.

- ◆ 208 V Narrow Models: H6BPD002 to D074
- 480 V Narrow Models: H6BPB1P1, B001 to B077



- | | |
|---------------------------------------|-----------------------------------|
| A - Bypass bracket mounting hole | H - Keypad |
| B - Disconnect shaft | I - Keypad mounting bracket screw |
| C - Bypass front cover captive screws | J - Keypad mounting bracket |
| D - Disconnect handle | K - Drive |
| E - Bypass front cover | L - Blank keypad |
| F - Bypass enclosure | M - Drive mounting screw |
| G - Keypad mounting screw | |

Figure 2.3 Exploded View of Components (Example Narrow Model D024)



- | | |
|--------------------------------------|---|
| A - Output contactor K2 | J - Terminal TB6 (Ground) |
| B - Input contactor K1 | K - Terminal TB3 (Serial Comms) |
| C - Motor connections | L - RS-485 terminator switch S1 |
| D - Input power terminals | M - Terminal TB4 (Analog Input) |
| E - Ground terminals | N - Analog input V or I switch S2 |
| F - A2 bypass control board | O - Terminal TB2 (Digital Inputs) |
| G - 120 V control transformer | P - Terminal TB1 (Digital Outputs) |
| H - Bypass contactor K3 | Q - Digital operator port CN2 |
| I - USB port CN1 | R - Option card connector CN5 |

Figure 2.4 Front View of Narrow Components

2.6 Moving the Bypass

Obey local laws and regulations when you move and install this product.

CAUTION! *Crush Hazard. Tighten terminal cover screws and hold the case safely when you move the bypass. If the bypass or covers fall, it can cause moderate injury.*

| Bypass Weight | Persons Necessary to Move the Bypass |
|-------------------|---|
| < 15 kg (33 lbs.) | 1 |
| ≥ 15 kg (33 lbs.) | 2 + using appropriate lifting equipment |

Refer to [Using the Mounting Rails to Move the Bypass on page 29](#) for information about how to use suspension systems, wires, or hanging metal brackets to move the bypass.

◆ Using the Mounting Rails to Move the Bypass

Use the holes in the mounting rails attached to the bypass to temporarily lift the bypass when you install it. Do not let the bypass stay vertically or horizontally suspended or move the bypass over a long distance while it is suspended.

Before you install the bypass, make sure that you read these precautions:

WARNING! *Crush Hazard. Before you hang the bypass vertically, use screws to correctly attach the front cover and other components. If you do not secure the front cover, it can fall and cause minor injury.*

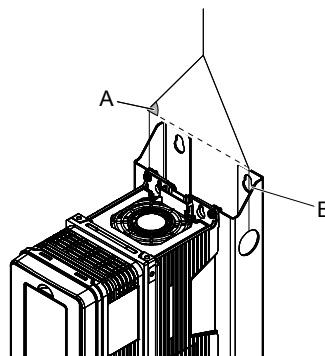
WARNING! *Crush Hazard. When you use a crane or hoist to lift the bypass during installation or removal, prevent more than 1.96 m/s² (0.2 G) vibration or impact. Too much vibration or impact can cause serious injury or death from falling equipment.*

WARNING! *Crush Hazard. When you lift the bypass during installation or removal, do not try to turn it over and do not ignore a hanging bypass. If you move a hanging bypass too much or if you ignore it, it can fall and cause serious injury or death.*

■ Vertical Suspension

To use the hanging brackets to vertically suspend the drive, lift the drive with this procedure:

1. Put wire through the two holes in the hanging brackets.



A - Suspension angle of at least 50 degrees B - Hanging bracket (2)

Figure 2.5 Vertical Suspension

2. Use a crane to gradually wind up the wire. Visually make sure that there is sufficient tension in the wire, then lift the drive to its correct location.
3. Prepare the control panel for installation, then lower the drive.

Note:

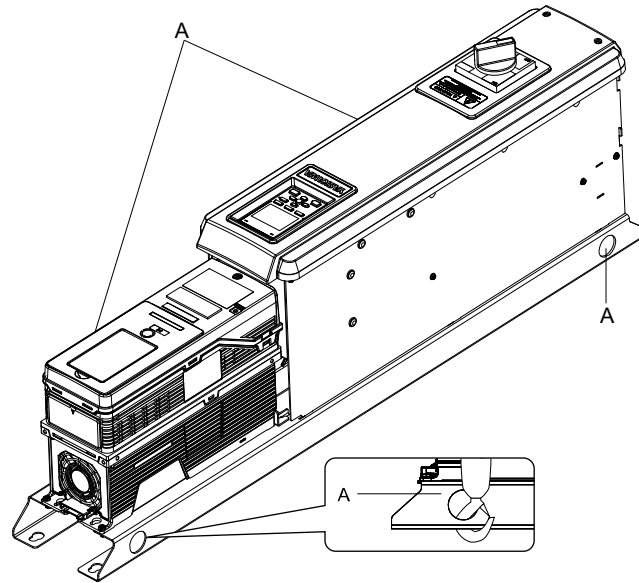
When you lower the drive, stop before the drive touches the floor, then slowly lower it the remaining distance.

■ Horizontal Suspension

When horizontal suspension is necessary, use this procedure to hang the bypass:

1. Put the bypass on the ground horizontally.

NOTICE: *When you attach a horizontal lifting cable or chain to the bypass, use a jig or pad between the wire and the bypass. The wire can scratch the drive and cause damage to the bypass.*



A - Hanging bracket (4)

Figure 2.6 Horizontal Suspension

2. Connect wires to the four hanging brackets.
3. Use a crane to lift the bypass.

2.7 Removing/Reattaching Covers

This section gives information about how to remove and reattach the bypass front cover and drive front cover and terminal cover for wiring and inspection.

Refer to [Table 2.1](#) for more information.

Table 2.1 Procedures to Remove Covers by Model

| Bypass Model H6BP | Bypass Cover Removal Procedure | Drive Cover Removal Procedure |
|----------------------------|-----------------------------------|-----------------------------------|
| D002 - D074 B1P1 - B077 | Procedure 1 31 | Procedure A 32 |

◆ Removing/Reattaching the Bypass Cover Using Procedure 1

DANGER! Electrical Shock Hazard. Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe. If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

1. Turn the disconnect handle to the “OFF” position.

DANGER! Electrical Shock Hazard. Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe. If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

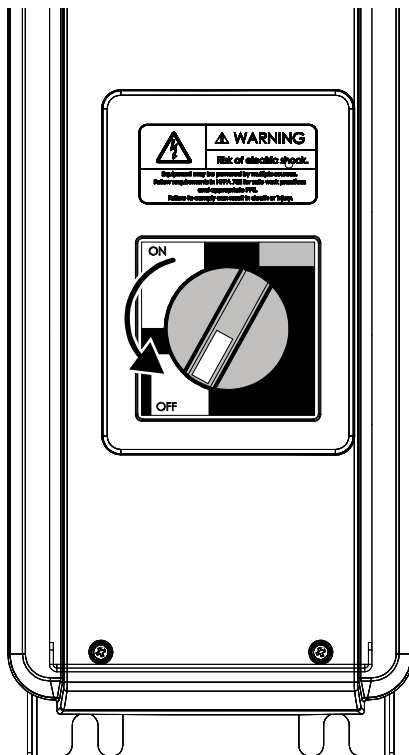


Figure 2.7 Disconnect Power

2. Loosen the captive front cover screws.

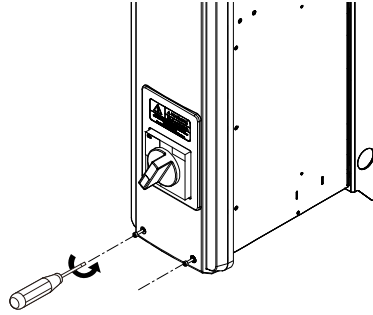


Figure 2.8 Loosen the Front Cover Screws

3. Lift up the cover and gently pull forward to remove the front cover.

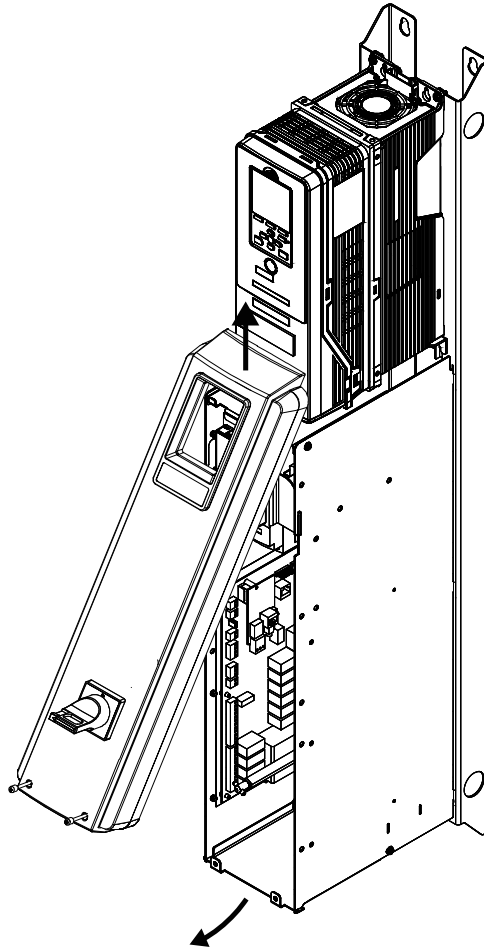


Figure 2.9 Remove the Front Cover

4. Reverse the steps to reattach the cover.

◆ Removing/Reattaching the Drive Cover Using Procedure A

DANGER! *Electrical Shock Hazard. Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe. If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.*

■ Remove the Front Cover

1. Remove the bypass front cover in Procedure A
2. Loosen the front cover screw.

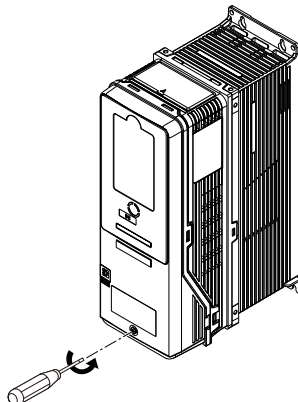


Figure 2.10 Loosen the Front Cover Screw

3. Push on the tabs in the sides of the front cover then pull the front cover forward to remove it from the drive.

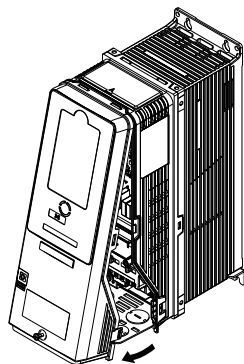


Figure 2.11 Remove the Front Cover

■ Reattach the Front Cover

1. Wire the drive and other peripheral devices.
2. Reverse the steps to reattach the cover.

Note:

- Make sure that you did not pinch wires or signal lines between the front cover and the drive before you reattach the cover.
- Make sure that the tabs on the sides of the front cover correctly click into the hook.
- Tighten the screws to a tightening torque of 0.98 N·m to 1.33 N·m (8.67 in·lb to 11.77 in·lb).

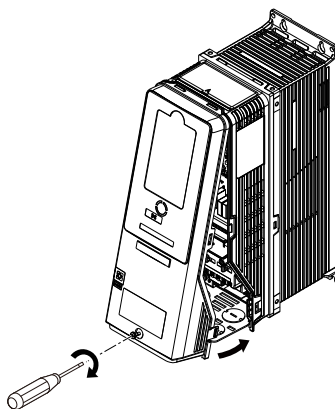


Figure 2.12 Reattach the Front Cover

Electrical Installation

This chapter explains how to wire the control circuit terminals, motor, and power supply.

| | | |
|------------|---|-----------|
| 3.1 | Section Safety | 36 |
| 3.2 | Wiring Diagram | 38 |
| 3.3 | Main Circuit Wiring | 42 |
| 3.4 | Main Circuit Terminal Wiring Procedure | 46 |
| 3.5 | Bypass Controller | 48 |
| 3.6 | Drive Control Circuit..... | 54 |
| 3.7 | Control I/O Connections | 62 |
| 3.8 | Connect the Bypass to a PC | 64 |
| 3.9 | Motor Application Precautions | 65 |

3.1 Section Safety

DANGER

Electrical Shock Hazard

Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe.

If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

WARNING

Electrical Shock Hazard

Do not operate the bypass when covers are missing. Replace covers and shields before you operate the bypass. Use the bypass only as specified by the instructions.

Some figures in this section include bypasses without covers or safety shields to more clearly show the inside of the bypass. If covers or safety shields are missing from the bypass, it can cause serious injury or death.

Ground the neutral point on the power supply of the bypass to comply with the EMC Directive before you turn on the EMC filter.

If you turn ON the EMC filter, but you do not ground the neutral point, it can cause serious injury or death.

Make sure that the protective ground wire conforms to technical standards and local safety regulations. The IEC/EN 61800-5-1:2007 standard specifies that you must wire the power supply to automatically de-energize when the protective ground wire disconnects. You can also connect a protective ground wire that has a minimum cross-sectional area of 10 mm² (copper wire) or 16 mm² (aluminum wire).

If you do not obey the standards and regulations, it can cause serious injury or death. The leakage current of the bypass will be more than 3.5 mA.

The bypass can cause a residual current with a DC component in the protective earthing conductor. When a residual current operated protective or monitoring device prevents direct or indirect contact, always use a type B Ground Fault Circuit Interrupter (GFCI) as specified by IEC/EN 60755.

If you do not use the correct GFCI, it can cause serious injury or death.

Do not wear loose clothing or jewelry when you do work on the bypass. Tighten loose clothing and remove all metal objects, for example watches or rings.

Loose clothing can catch on the bypass and jewelry can conduct electricity and cause serious injury or death.

Do not remove covers or touch circuit boards while the bypass is energized.

If you touch the internal components of an energized bypass, it can cause serious injury or death.

Only let approved personnel install, wire, maintain, examine, replace parts, and repair the bypass.

If personnel are not approved, it can cause serious injury or death.

Do not modify the bypass body, drive body, bypass circuitry, or drive circuitry.

Modifications to bypass and drive body and circuitry can cause serious injury or death, will cause damage to the bypass and drive, and will void the warranty. Yaskawa is not responsible for modifications of the product made by the user.

Fire Hazard

Tighten all terminal screws to the correct tightening torque.

Connections that are too loose or too tight can cause incorrect operation and damage to the bypass. Incorrect connections can also cause death or serious injury from fire.

⚠ WARNING

Tighten screws at an angle in the specified range shown in this manual.

If you tighten the screws at an angle not in the specified range, you can have loose connections that can cause damage to the terminal block or start a fire and cause serious injury or death.

Damage to Equipment

Do not apply incorrect voltage to the main circuit of the bypass. Operate the bypass in the specified range of the input voltage on the nameplate.

Voltages that are higher than the permitted nameplate tolerance can cause damage to the bypass.

NOTICE

Do not let unwanted objects, for example metal shavings or wire clippings, fall into the bypass during installation. Put a temporary cover over the bypass during installation. Remove the temporary cover before start-up.

Unwanted objects inside of the bypass can cause damage to the bypass.

Damage to Equipment

When you touch the bypass, drive, and circuit boards, make sure that you observe correct electrostatic discharge (ESD) procedures.

If you do not follow procedures, it can cause ESD damage to the drive and bypass circuitry.

Select a motor that is compatible with the load torque and speed range. When 100% continuous torque is necessary at low speed, use an inverter-duty motor. When you use a standard fan-cooled motor, decrease the motor torque in the low-speed range.

If you operate a standard fan-cooled motor at low speed and high torque, it will decrease the cooling effects and can cause heat damage.

Obey the speed range specification of the motor as specified by the manufacturer. When you must operate the motor outside of its specifications, contact the motor manufacturer.

If you continuously operate oil-lubricated motors outside of the manufacturer specifications, it can cause damage to the motor bearings.

When the input voltage is 440 V or higher or the wiring distance is longer than 100 m (328 ft), make sure that the motor insulation voltage is sufficient or use an inverter-duty motor with reinforced insulation.

Motor winding and insulation failure can occur.

Make sure that all connections are correct after you install the bypass and connect peripheral devices.

Incorrect connections can cause damage to the bypass.

Note:

- Torque characteristics are different than when you operate the motor directly from line power. Make sure that you understand the load torque characteristics for the application.
- The current rating of submersible motors is usually higher than the current rating of standard motors for a given motor power. Make sure that the rated output current of the bypass is equal to or more than the current rating of the motor. If the motor wire length is longer than 100 m (328 ft), select the correct wire gauge to adjust for a loss in voltage and prevent a loss of motor torque.
- Do not use unshielded wire for control wiring. Use shielded, twisted-pair wires and ground the shield to the ground terminal of the bypass. Unshielded wire can cause electrical interference and unsatisfactory system performance.

3.2 Wiring Diagram

DANGER! *Electrical Shock Hazard. Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe. If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.*

WARNING! *Electrical Shock Hazard. De-energize the bypass and wait 5 minutes minimum until the Charge LED turns off. Remove the front cover and terminal cover to do work on wiring, circuit boards, and other parts. Use terminals for their correct function only. Incorrect wiring, incorrect ground connections, and incorrect repair of protective covers can cause death or serious injury.*

WARNING! *Electrical Shock Hazard. Correctly ground the drive before you turn on the EMC filter switch. If you touch electrical equipment that is not grounded, it can cause serious injury or death.*

WARNING! *Electrical Shock Hazard. Use the terminals for the drive only for their intended purpose. Refer to the technical manual for more information about the I/O terminals. Wiring and grounding incorrectly or modifying the cover may damage the equipment or cause injury.*

◆ Standard Connection Diagram

Wire the bypass as specified by [Figure 3.1](#).

WARNING! *Sudden Movement Hazard. Set the MFDI parameters before you close control circuit switches. Incorrect Run/Stop circuit sequence settings can cause serious injury or death from moving equipment.*

WARNING! *Sudden Movement Hazard. Check the I/O signals and the external sequences for the drive before you set the Application Preset function. When you set the Application Preset function (A1-06 ≠ 0), it changes the I/O terminal functions for the drive and it can cause equipment to operate unusually. This can cause serious injury or death.*

WARNING! *Fire Hazard. Install sufficient branch circuit short circuit protection as specified by applicable codes and this manual. The bypass is suitable for circuits that supply not more than 100,000 RMS symmetrical amperes, 240 Vac maximum (208/240 V), 480 Vac maximum (480 V). Incorrect branch circuit short circuit protection can cause serious injury or death.*

NOTICE: *When the input voltage is 440 V or higher or the wiring distance is longer than 100 m (328 ft), make sure that the motor insulation voltage is sufficient or use an inverter-duty motor with reinforced insulation. Motor winding and insulation failure can occur.*

Note:

Do not connect the AC control circuit ground to the drive enclosure. Incorrect ground wiring can cause the control circuit to operate incorrectly.

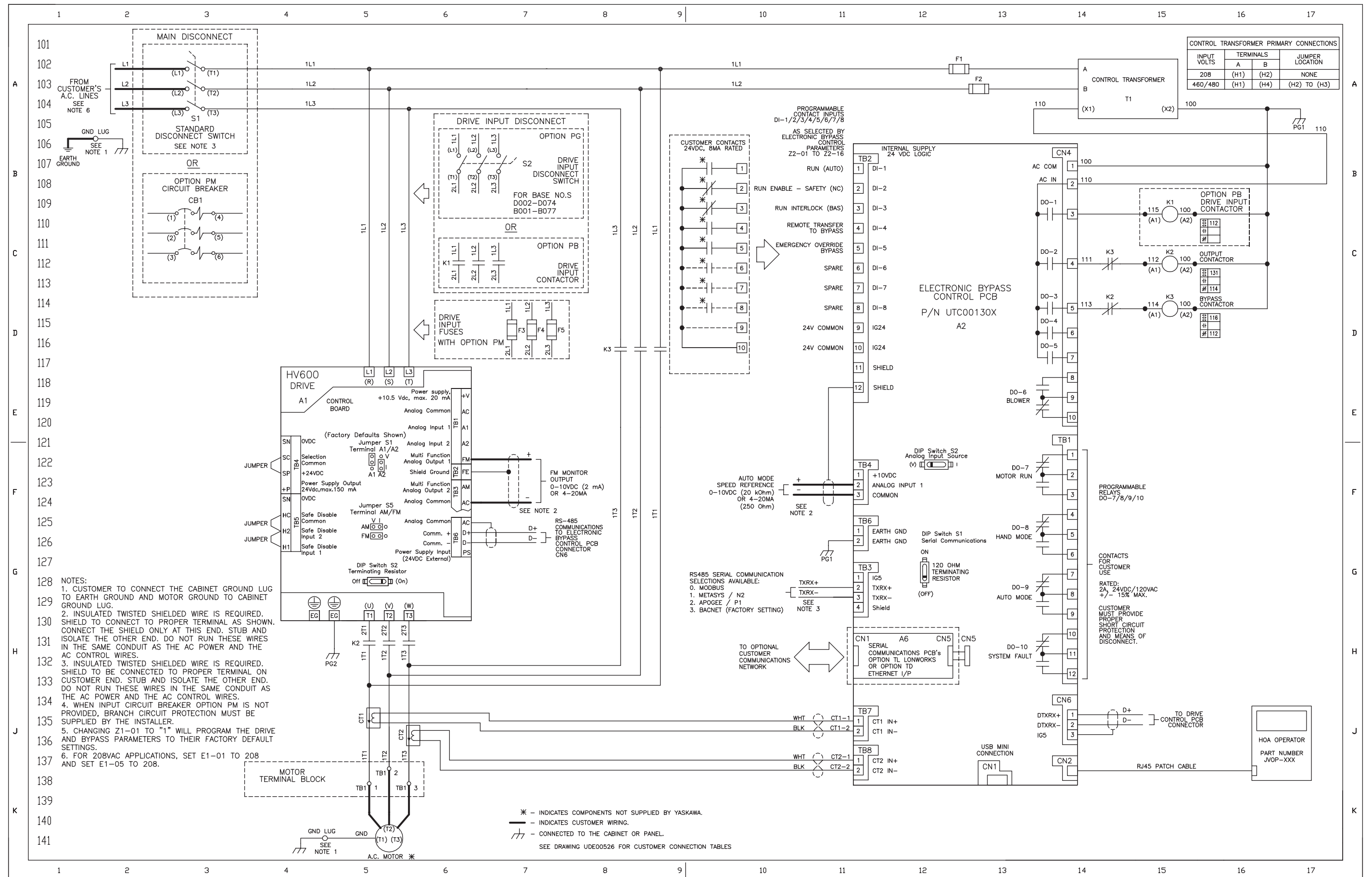


Figure 3.1 Standard Narrow Bypass Connection Diagram

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3.3 Main Circuit Wiring

This section gives information about the functions, specifications, and procedures necessary to safely and correctly wire the main circuit in the bypass.

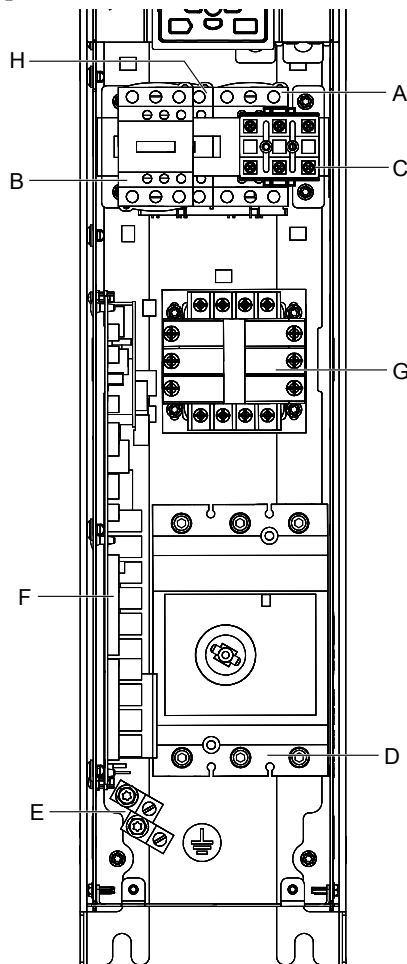
NOTICE: Damage to Equipment. Do not energize and de-energize the bypass more frequently than one time each 30 minutes. If you frequently energize and de-energize the bypass, it can cause failure.

Note:

Soldered wire connections can become loose over time and cause unsatisfactory performance.

◆ Narrow Bypass Input and Output Power Wiring Connections

The input disconnect switch is located in the upper right hand side of the bypass. The three-phase input power connection is made to the input terminals of the disconnect. Refer to [Figure 3.2](#) for a representative example. Motor Terminal Block TB1 is mounted to the contactor assembly or back panel (depending on rating), just above the bypass contactor. The bypass three-phase output power connection to the motor is made to Terminal Block TB1.



Note:

The location of components are different for different bypass models.

- | | |
|--------------------------------------|--------------------------------------|
| A - Drive output contactor K2 | E - Ground screw |
| B - Input contactor K1 | F - Bypass PCB A2 |
| C - Motor connections | G - 120 V control transformer |
| D - Input power terminals | H - Bypass contactor K3 |

Figure 3.2 Narrow Bypass Circuit Components Example

◆ Factory Recommended Branch Circuit Protection

WARNING! Fire Hazard. Branch Circuit protection is required to be installed according to applicable local codes and the requirements listed on the bypass nameplate. The bypass is suitable for use on a circuit capable of delivering not more than 100,000 RMS symmetrical amperes, 208/240 Vac and 480 Vac with the circuit breaker option or when protected by class J or class L fuses as specified on the bypass nameplate. Failure to obey can cause fire and damage to the bypass and drive or injury to personnel.

Yaskawa recommends installing branch circuit protection according to maintain compliance with UL508C. Semiconductor protective type fuses are preferred. Alternate branch circuit protection devices are also listed in this manual.

◆ Wire Selection

Select the correct wires for main circuit wiring.

■ Wire Selection Precautions

WARNING! Electrical Shock Hazard. Make sure that the protective ground wire conforms to technical standards and local safety regulations. The IEC/EN 61800-5-1:2007 standard specifies that you must wire the power supply to automatically de-energize when the protective ground wire disconnects. You can also connect a protective ground wire that has a minimum cross-sectional area of 10 mm² (copper wire) or 16 mm² (aluminum wire). If you do not obey the standards and regulations, it can cause serious injury or death. The leakage current of the bypass will be more than 3.5 mA.

Think about line voltage drop before you select wire gauges. Select wire gauges that drop the voltage by 2% or less of the rated voltage. Increase the wire gauge and the cable length when the risk of voltage drop increases. Calculate line voltage drop with this formula:

Line voltage drop (V) = $\sqrt{3} \times$ wire resistance (Ω/km) \times wiring distance (m) \times motor rated current (A) $\times 10^{-3}$.

■ Wire Gauge and Torque Specifications for UL Listing

WARNING! Electrical Shock Hazard. Make sure that the protective ground wire conforms to technical standards and local safety regulations. The IEC/EN 61800-5-1:2007 standard specifies that you must wire the power supply to automatically de-energize when the protective ground wire disconnects. You can also connect a protective ground wire that has a minimum cross-sectional area of 10 mm² (copper wire) or 16 mm² (aluminum wire). If you do not obey the standards and regulations, it can cause serious injury or death. The leakage current of the bypass will be more than 3.5 mA.

Refer to the following tables for the recommended wire gauges and tightening torques of the main circuit terminals.

Note:

The recommended wire gauges are based on drive continuous current ratings with 75 °C (167 °F) 600 V class copper wire. Assume these conditions:

- Ambient temperature: 40 °C (104 °F) or lower
- Wiring distance: 100 m (3281 ft) or shorter
- Normal Duty Rated current value

■ Bypass Control Circuit Wire Gauges and Torques

For input and output wire gauges and torques, refer to the Customer Connection Drawing (UDE00xxx) packaged with the bypass.

Table 3.1 Bypass Control Wiring

| A1 Terminal Blocks TB1, TB3-TB6 | | A1 Terminal Block TB2 (FE) | | A2 Terminal Blocks TB1-TB4 and TB6 | | Panel Terminal Block TB4 | |
|---------------------------------------|------------------------------|----------------------------------|------------------------------|--|------------------------------|--------------------------------|------------------------------|
| AWG, kcmil | Tightening Torque (in lb) | AWG, kcmil | Tightening Torque (in lb) | AWG, kcmil | Tightening Torque (in lb) | AWG, kcmil | Tightening Torque (in lb) |
| 24-16 | 4.4 to 5.3 | 24-18 *1 | 8.85 to 10.62 | 26-14 | 4 | 26-10 | 5.3 to 7.1 |

*1 24-16 is acceptable for solid wire or ferrule use only.

■ Bypass Input and Output Wire Gauges and Torques

For input and output wire gauges and torques, refer to the Customer Connection Drawing (UDE00xxx) packaged with the bypass.

◆ Main Circuit Terminal and Motor Wiring

This section outlines the various steps, precautions, and checkpoints to wire the main circuit terminals and motor terminals.

WARNING! Sudden Movement Hazard. Make sure that you align the phase order for the bypass and motor when you connect the motor to output terminals U/T1, V/T2, and W/T3. If the phase order is incorrect, it can cause the motor to run in reverse. If the motor accidentally runs in reverse, it can cause serious injury or death.

NOTICE: Do not connect phase-advancing capacitors, LC/RC noise filters, or leakage breakers (GFCI) to the motor circuit. If you connect these devices to the output circuits, it can cause damage to the bypass and connected equipment.

■ Cable Length Between Bypass and Motor

When the wiring between the bypass and the motor is too long, voltage drop along the motor cable can decrease motor torque, usually at low frequency output. If you use a long motor cable to connect motors in parallel, this is also a problem. Output current increases when the leakage current from the cable increases. An increase in leakage current can cause overcurrent and decrease the precision of current detection.

If the system configuration makes the motor wiring distance more than 100 m (328 ft), do not use metal conduits or use isolated cables for each phase to decrease stray capacitance.

Table 3.2 Carrier Frequency against Cable Length Between Drive and Motor

| Wiring Distance between the Bypass and Motor | 100 m (328 ft) Maximum |
|--|------------------------|
| Carrier Frequency | 2 kHz or less |

Note:

- For bypass models D004 to D016, A002 to A015, and B1P1, B001 to B014:
 - Shorter than 10 m: No carrier frequency derating from default setting (5 kHz) is necessary.
 - 10 m to 50 m: 5 kHz to 2 kHz is necessary.
 - 50 m and longer: 2 kHz
- To set the carrier frequency in a bypass that is operating more than one motor, calculate the cable length as the total distance of wiring to all connected motors.

■ Ground Wiring

Follow these precautions to wire the ground for one bypass or a series of bypasses.

WARNING! Electrical Shock Hazard. Make sure that the protective ground wire conforms to technical standards and local safety regulations. The IEC/EN 61800-5-1:2007 standard specifies that you must wire the power supply to automatically de-energize when the protective ground wire disconnects. You can also connect a protective ground wire that has a minimum cross-sectional area of 10 mm² (copper wire) or 16 mm² (aluminum wire). If you do not obey the standards and regulations, it can cause serious injury or death. The leakage current of the bypass will be more than 3.5 mA.

WARNING! Electrical Shock Hazard. Ground the neutral point on the power supply of the bypass to comply with the EMC Directive before you turn on the EMC filter. If you turn ON the EMC filter, but you do not ground the neutral point, it can cause serious injury or death.

WARNING! Electrical Shock Hazard. Use a ground wire that complies with technical standards on electrical equipment and use the minimum length of ground wire. Incorrect equipment grounding can cause serious injury or death from dangerous electrical potentials on the equipment chassis.

Note:

- Only use the bypass grounding wire to ground the bypass. Do not share the ground wire with other devices, for example, welding machines or large-current electrical equipment. Incorrect equipment grounding can cause incorrect operation of equipment.
- To connect more than one bypass to the same grounding circuit, use the instructions in the manual. Incorrect equipment grounding can cause incorrect operation of equipment.

When you install more than one bypass, refer to [Figure 3.3](#). Do not loop the grounding wire.

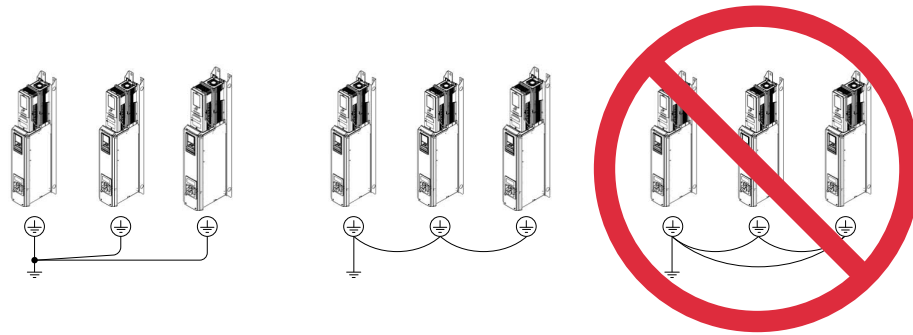


Figure 3.3 Wiring More than One Bypass

■ Wiring the Main Circuit Terminal Block

WARNING! *Electrical Shock Hazard. Before you wire the main circuit terminals, make sure that MCCB and MC are OFF. If you touch electrical equipment when MCCB and MC are ON, it can cause serious injury or death.*

◆ Protection of Main Circuit Terminals

When you wire the main circuit terminals, do not let cable ends go near terminals or the drive. If you use crimped terminals, make sure that you also use insulation caps.

3.4 Main Circuit Terminal Wiring Procedure

DANGER! Electrical Shock Hazard. Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe. If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

◆ Notes on Wiring the Main Circuit Terminal

Read these safety messages and notes before you wire the main circuit terminal.

WARNING! Fire Hazard. Do not use bent or crushed wires. Remove the damaged end of the wire before you use it. Incorrect connections can cause death or serious injury from fire.

WARNING! Fire Hazard. If you use stranded wire, make sure that all of the wire strands are in the connection. Also, do not twist the stranded wire too much. Incorrect connections can cause death or serious injury from fire.

NOTICE: Do not solder stranded wire. Soldered wire connections can become loose over time and cause unsatisfactory drive performance.

NOTICE: If you use power tools to tighten the terminal screws, use a low speed setting (300 min⁻¹ (r/min) to 400 min⁻¹ (r/min)). High speeds can cause damage to the terminal screws.

Note:

- Use UL Listed vinyl-coated insulated copper wires for operation with a continuous maximum permitted temperature of 75 °C at 600 V.
- Remove all unwanted objects that are near the terminal block connections.
- Remove the insulation from the connection wires to the wire stripping lengths shown in the manual.
- Put the wire all the way into the terminal block. Remove the insulation from the wire to the recommended wire stripping length to fit the wire with insulation in the plastic housing.
- Use a torque driver, torque ratchet, or torque wrench for the screws. A slotted driver or a hex tool will be necessary to wire the screw clamp terminal. Use applicable tools as specified by the recommended conditions in the product manual.
- Put the bit all the way into the hex socket to tighten the hex socket cap screw.
- When tightening slotted screws, hold the straight-edge screwdriver perpendicularly to the screw. Take care to ensure that the tip of the straight-edge screwdriver is aligned with the screw groove.

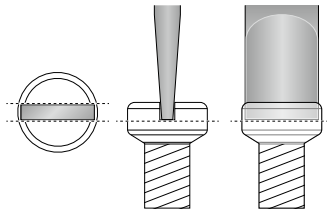
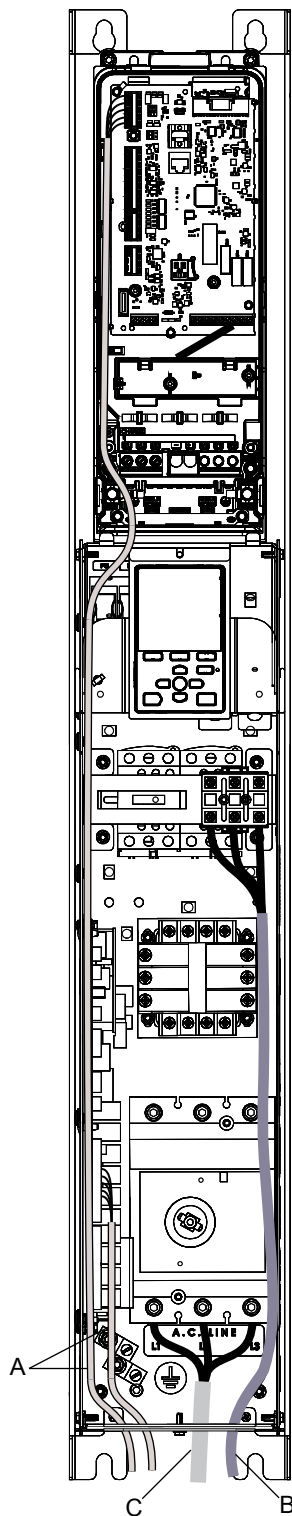


Figure 3.4 Tightening Slotted Screws

- After connecting the wires to the terminal block, lightly pull on the wires to make sure that they do not come out of the terminals.

◆ Narrow Bypass Main Circuit Terminal Block Wiring Procedure

1. Correctly ground the bypass terminal board.
2. Route the main circuit wiring. [Figure 3.5](#) shows suggested wire entry and bending areas for the enclosure.



- A - Optional drive control wiring
- B - Motor output circuit
- C - Main input circuit

Figure 3.5 Narrow Bypass Wire Routing Example (Models H6BPD002 to D074 and B1P1, B001 to B077)

3.5 Bypass Controller

Note:

When possible, use these control terminal connections on the bypass controller. There are additional control I/O terminals available on the drive, however those terminals are active in Drive Mode ONLY and may not report correctly in Bypass Mode.

◆ Control Circuit Terminal Arrangement

The bypass control circuit terminals are in the positions shown in [Figure 3.6](#).

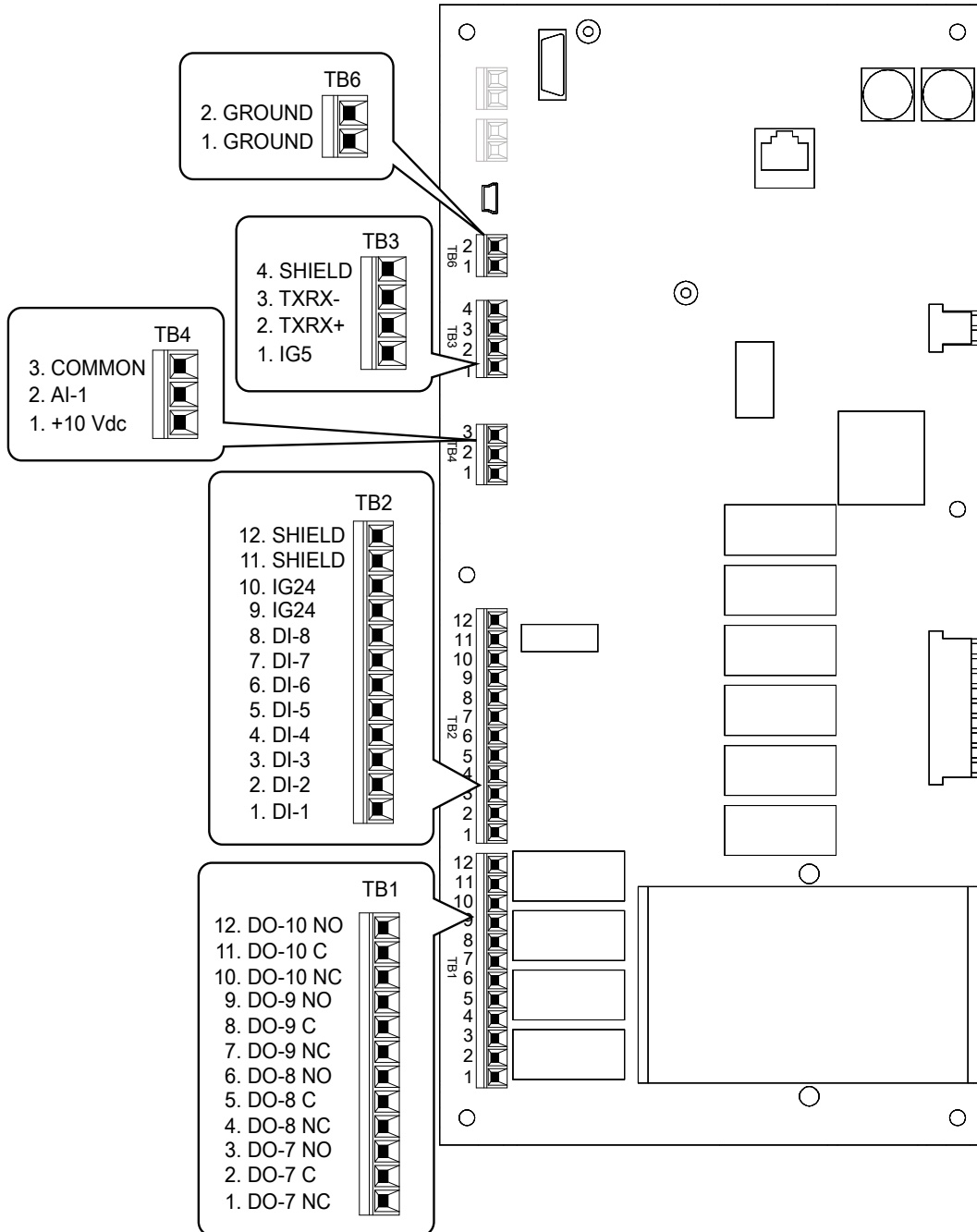


Figure 3.6 Bypass Control Circuit Terminal Arrangement

◆ Bypass Control Circuit Wire Gauges and Tightening Torques

Use the tables in this section to select the correct wires. Use shielded wire to wire the control circuit terminal block. Use crimp ferrules on the wire ends to make the wiring procedure easier and more reliable.

Table 3.3 Bypass Control Circuit Wire Gauges and Tightening Torques

| Bypass Terminal Block | Terminal | Tightening Torque in-lb | Recommended Gauge AWG | Applicable Gauge AWG |
|-----------------------|---------------------------|----------------------------|--------------------------|-------------------------|
| TB1 | DO-7 - DO-10 | 4 | 18 | 26-14 |
| TB2 | DI-1 - DI-8, IG24, SHIELD | | | |
| TB3 | SHEILD, TXRX-, TXRX+, IG5 | | | |
| TB4 | +10 Vdc, AI-1, COMMON | | | |
| TB6 | GROUND, GROUND | | | |

◆ Crimp Ferrules

Attach an insulated sleeve when you use crimp ferrules. Refer to [Table 3.4](#) for the recommended external dimensions and model numbers of the crimp ferrules.

Use the CRIMPFOX 6, a crimping tool made by PHOENIX CONTACT.

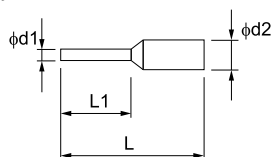


Figure 3.7 External Dimensions of Crimp Ferrules

Table 3.4 Crimp Ferrule Models and Sizes

| Wire Gauge mm ² (AWG) | Model | L (mm) | L1 (mm) | φd1 (mm) | φd2 (mm) |
|-------------------------------------|--------------------------|--------|---------|----------|----------|
| 0.25 (24) | AI 0.25-8YE | 12.5 | 8 | 0.8 | 2.0 |
| 0.34 (22) | AI 0.34-8TQ | 12.5 | 8 | 0.8 | 2.0 |
| 0.5 (20) | AI 0.5-8WH AI 0.5-8OG | 14 | 8 | 1.1 | 2.5 |
| 0.75 (18) | AI 0.75-8 GY | 14 | 8 | 1.3 | 2.8 |

◆ Bypass Control Circuit Terminal Block Input Functions

WARNING! Sudden Movement Hazard. Correctly wire and test all control circuits to make sure that the control circuits operate correctly. If you use a drive that has incorrect control circuit wiring or operation, it can cause death or serious injury.

WARNING! Sudden Movement Hazard. Check the I/O signals and the external sequences for the drive before you set the Application Preset function. When you set the Application Preset function (A1-06 ≠ 0), it changes the I/O terminal functions for the drive and it can cause equipment to operate unusually. This can cause serious injury or death.

NOTICE: Damage to Equipment. Do not energize and de-energize the bypass more frequently than one time each 30 minutes. If you frequently energize and de-energize the bypass, it can cause failure.

Table 3.5 Bypass Digital Input Terminals (TB2)

| Type | Terminal | Name (Default) | Function (Signal Level) |
|----------------|------------------|--|---|
| Digital Inputs | TB2-1 DI-1 | Digital Input 1 (Run (AUTO)) | Dry contact rated, photocoupler sinking input to IG24, 24 Vdc 8 mA, Ground fault protected |
| | TB2-2 DI-2 | Digital Input 2 (Run Enable - Safety (NC)) | |
| | TB2-3 DI-3 | Digital Input 3 (Run Interlock (BAS)) | |
| | TB2-4 DI-4 | Digital Input 4 (Remote Transfer to Bypass) | |
| | TB2-5 DI-5 | Digital Input 5 (Emergency Override Bypass) | |
| | TB2-6 DI-6 | Digital Input 6 (Not used) | |
| | TB2-7 DI-7 | Digital Input 7 (Not used) | |
| | TB2-8 DI-8 | Digital Input 8 (Not used) | |
| | TB2-9/10 IG24 | Isolated Ground | Digital input common |

Table 3.6 Bypass Analog Input Terminals (TB4)

| Type | Terminal | Name (Default) | Function (Signal Level) |
|--------------|------------------|------------------------------|---|
| Analog Input | TB4-1 +10 Vdc | Analog Input Power Supply | AUTO Mode Speed Reference 0 to 10 Vdc (20 kΩ) or 4 to 20 mA (250 Ω) |
| | TB4-2 AI | Analog Input Speed Reference | |
| | TB4-3 COMMON | Analog Input Common | |

◆ Bypass Control Circuit Terminal Block Output Functions

Table 3.7 Bypass Digital Output Terminals (TB1)

| Type | Terminal | Name (Default) | Function (Signal Level) |
|-----------------|---------------------------|--|--|
| Digital Outputs | TB1-1/2/3 DO-7 | Digital Output 7 (Run Active) | Relay, dry contact form C, 30 Vdc or 120 Vac, DO-7 to DO-10 for customer use, 2 Amp |
| | TB1-4/5/6 DO-8 | Digital Output 8 (HAND mode Active) | |
| | TB1-7/8/9 DO-9 | Digital Output 9 (AUTO mode Active) | |
| | TB1-10/11/ 12 DO-10 | Digital Output 10 (Fault Active) | |

Table 3.8 Control Circuit Ground Terminals (TB6)

| Type | Terminal | Name (Default) | Function (Signal Level) |
|--------|-------------------|----------------|-------------------------|
| Ground | TB6-1/2 GROUND | Chassis Ground | - |

◆ Bypass Serial Communication Terminals

Table 3.9 Bypass Serial Communication Terminals (TB3)

| Type | Terminal | Terminal Name | Function (Signal Level) |
|----------------------|-----------------|---------------------------------------|---|
| Serial Communication | TB3-1 IG5 | Isolated ground | Ground reference for RS-485 signals. This is an isolated ground used only for communications and may be used in certain circumstances to connect the floating ground references of other communication devices. |
| | TB3-2 TXRX+ | (+) Differential communication signal | <ul style="list-style-type: none"> BACnet communications APOGEE FLN communications MEMOBUS/ Modbus communications Metasys N2 communications Use an RS-485 cable to connect the drive. Note: Make sure that DIP switch S1 is ON to enable the termination resistor in the last drive in a BACnet, APOGEE FLN, MEMOBUS/ Modbus, or Metasys N2 network. |
| | TB3-3 TXRX- | (-) Differential communication signal | |
| | TB3-4 SHIELD | Shield tie point | Capacitively coupled to chassis ground. |

◆ Switches on the Bypass Controller

The bypass controller has switches to adapt the bypass I/Os to the external control signals as shown in [Figure 3.8](#). Set the switches to select the functions for each terminal.

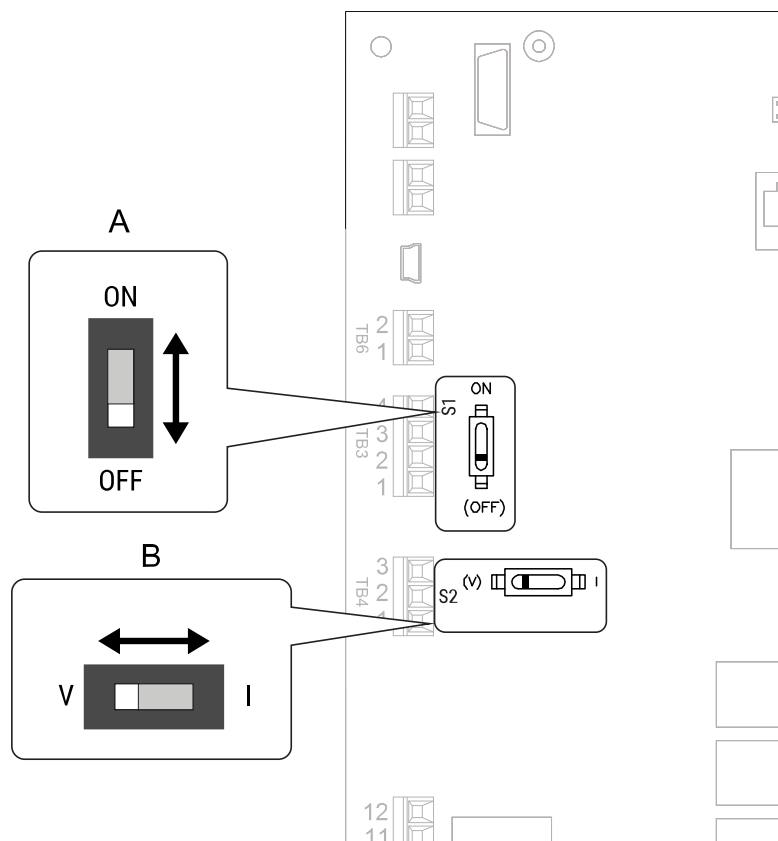


Figure 3.8 Locations of Switches

Table 3.10 I/O Switch Functions

| Position | Switch | Function | Default Setting |
|----------|---------------|---|--|
| A | DIP switch S1 | RS-485 Terminating Resistor (120 Ω) enables and disables the termination resistor of these communications: <ul style="list-style-type: none"> • BACnet (MSTP) • APOGEE FLN • MEMOBUS/Modbus • Metasys N2 | OFF |
| B | DIP switch S2 | V/I switch for analog input. | V (voltage input) I (current input) |

◆ Wiring the Bypass Control Circuit Terminal

WARNING! Electrical Shock Hazard. Do not remove covers or touch circuit boards while the bypass is energized. If you touch the internal components of an energized bypass, it can cause serious injury or death.

NOTICE: Do not let wire shields touch other signal lines or equipment. Insulate the wire shields with electrical tape or shrink tubing. If you do not insulate the wire shields, it can cause a short circuit and damage the drive.

Note:

- Isolate control circuit wiring from main circuit wiring and other high-power wiring. If the control circuit wires are adjacent to the main circuit wires, electrical interference can cause the bypass or the devices around the bypass to malfunction.
- Isolate TB1 contact output terminals from other control circuit wiring. If the output terminal wires are adjacent to other control circuit wires, electrical interference can cause the bypass or devices around the bypass to malfunction.
- Use a UL Listed Class 2 Power Supply to connect external power to the TB1 contact output control terminals. If the power supply for peripheral devices is incorrect, it can cause a decrease in bypass performance.
- Connect the shield of shielded cable to the applicable ground or shield terminal. If the shield connections are not correct, electrical interference can cause the bypass or devices around the bypass to malfunction.

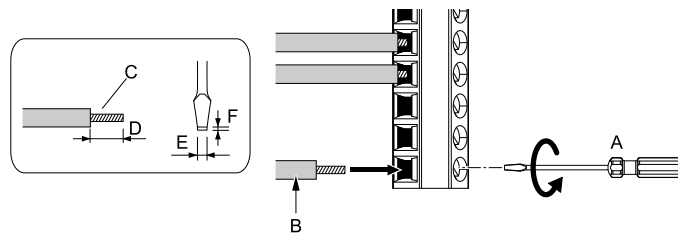
Correctly ground the bypass terminals and complete main circuit wiring before you wire the control circuit. Remove the front cover.

1. Refer to Figure 3.9 and wire the control circuit.

WARNING! Fire Hazard. Tighten all terminal screws to the correct tightening torque. Connections that are too loose or too tight can cause incorrect operation and damage to the bypass. Incorrect connections can also cause death or serious injury from fire.

Note:

- Use shielded wires and shielded twisted-pair wires for the control circuit terminal wiring. If the grounding is not correct, electrical interference can cause the drive or devices around it to malfunction.
- Do not use control circuit wiring that is longer than 50 m (164 ft) to supply the frequency reference with an analog signal from a remote source. Wiring that is too long can cause unsatisfactory system performance.



- A - Loosen the screws and put the wire into the opening on the terminal block.**
- B - Wire with a crimp ferrule attached, or use wire that is not soldered with the core wires lightly twisted.**
- C - Pull back the shielding and lightly twist the end with your fingers to keep the ends from fraying.**

- D - If you do not use crimp ferrules, remove approximately 5.5 mm (0.21 in) of the covering at the end of the wire.**
- E - Blade width of 2.5 mm (0.1 in) or less**
- F - Blade depth of 0.4 mm (0.01 in) or less**

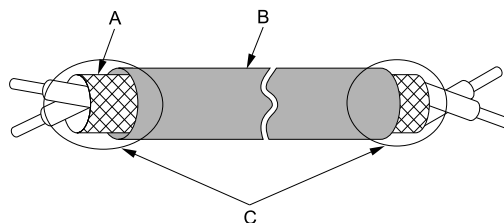
Figure 3.9 Wiring Procedure for the Control Circuit

WARNING! Fire Hazard. Tighten all terminal screws to the correct tightening torque. Connections that are too loose or too tight can cause incorrect operation and damage to the bypass. Incorrect connections can also cause death or serious injury from fire.

NOTICE: Do not tin stranded wire with solder. Soldered wire connections can become loose over time and cause unsatisfactory system performance.

Note:

- Refer to [Figure 3.10](#) for information to prepare terminal ends of the shielded wire.
- Prepare the wire ends of shielded twisted-pair wires as shown in [Figure 3.10](#) to use an analog reference from an external frequency setting potentiometer to set the frequency. Connect the shield to TB2-11 or TB2-12 on the bypass control board or terminal FE on the drive.



A - Connect the shield to TB2-11 or TB2-12.

B - Sheath

C - Insulate with electrical tape or shrink tubing.

Figure 3.10 Prepare the Ends of Shielded Wire

2. Install the front cover to its initial position.

3.6 Drive Control Circuit

Note:

When possible, use the control terminal connections on the Bypass PCB A2. The additional control I/O terminals available on the Drive Control circuit, are active in Drive Mode ONLY and may not report correctly in Bypass Mode. Typically, the Drive Control circuit wiring is used with a PID feedback signal or an analog monitor (output). In most applications, you should not connect to the drive control circuit digital inputs (S1 to S7) because it can cause unintended operation.

◆ Drive Control Circuit Terminal Arrangement

The drive control circuit terminals are in the positions shown in [Figure 3.11](#).

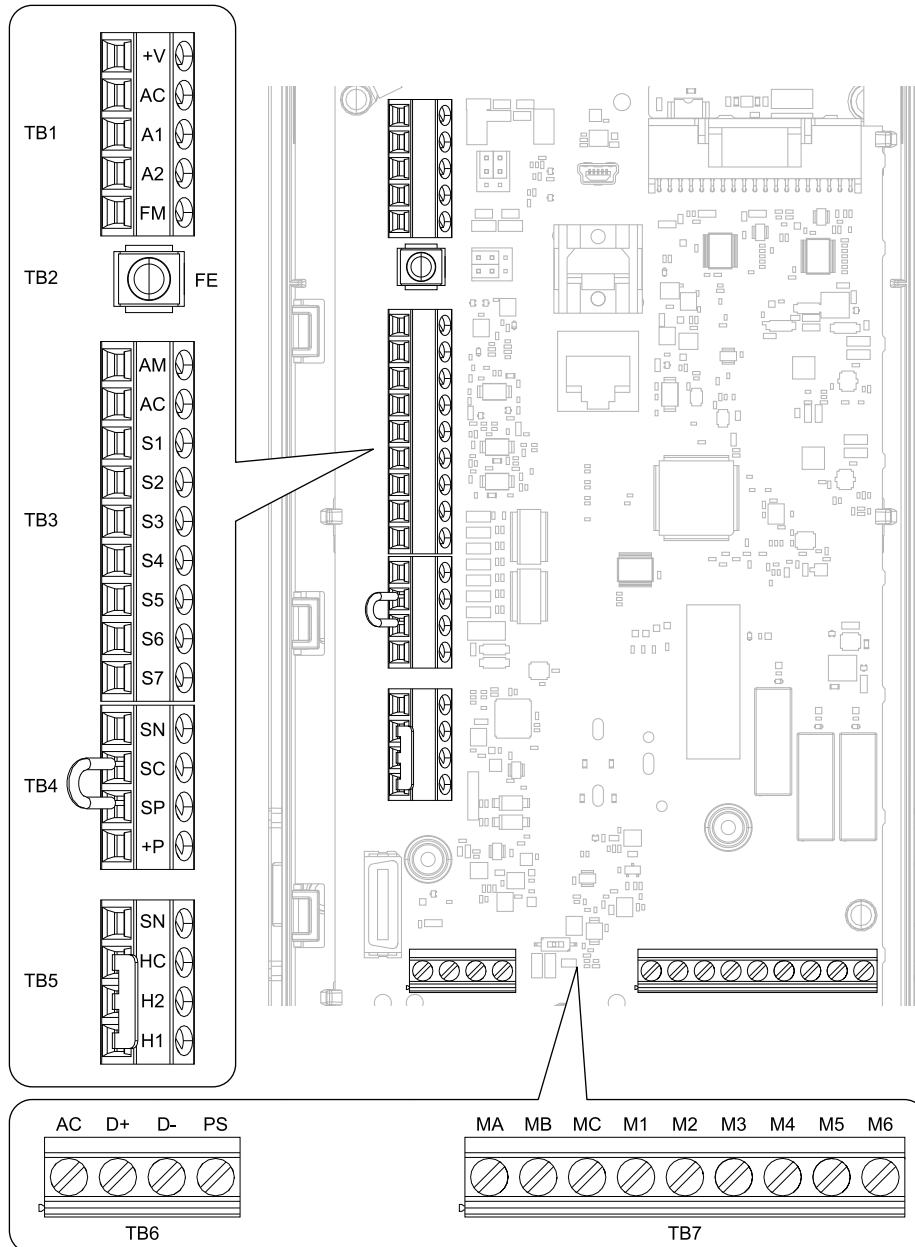


Figure 3.11 Drive Control Circuit Terminal Arrangement

The tightening torque for the drive terminal screws is shown on the reverse side or the lower front side of the drive front cover.

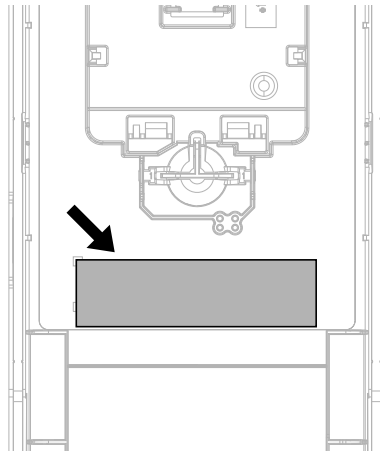


Figure 3.12 Tightening Torque Display Location (Reverse Side of Drive Front Cover)

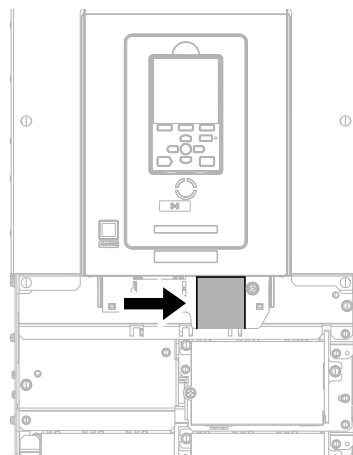


Figure 3.13 Tightening Torque Display Location (Lower Front Side of Drive Front Cover)

◆ Drive Control Circuit Wire Gauges and Tightening Torques

Use the tables in this section to select the correct wires. Use shielded wire to wire the control circuit terminal block. Use crimp ferrules on the wire ends to make the wiring procedure easier and more reliable.

Table 3.11 Drive Control Circuit Wire Gauges and Tightening Torques

| Drive Terminal Block | Terminal | Screw Size | Tightening Torque N·m (in·lb) | Bare Wire | | Crimp Ferrule | |
|----------------------|---------------------|------------|----------------------------------|--|---|--|---|
| | | | | Recommended Gauge mm ² (AWG) | Applicable Gauge mm ² (AWG) | Recommended Gauge mm ² (AWG) | Applicable Gauge mm ² (AWG) |
| TB1 | +V, AC, A1, A2, FM | M3 | 0.5 - 0.6 (4.4 - 5.3) | 0.75 (18) | Stranded wire: 0.25 - 1.5 (24 - 16) Solid wire: 0.25 - 1.5 (24 - 16) | 0.75 (18) | 0.25 - 1.5 (24 - 16) |
| TB3 | AM, AC, S1 - S7 | | | | | | |
| TB4 | SN, SC, SP, +P | | | | | | |
| TB5 | SN, HC, H1, H2 | | | | | | |
| TB6 | AC, D+, D-, PS | | | | | | |
| TB7 | MA, MB, MC, M1 - M6 | | | | | | |
| TB2 | FE | | 1.0 - 1.2 (8.85 - 10.62) | 0.75 (18) | Stranded wire: 0.12 - 0.75 (26 - 18) Solid wire: 0.2 - 1.5 (26 - 16) | 0.75 (18) | 0.25 - 1.5 (24 - 16) |

◆ Crimp Ferrules

Attach an insulated sleeve when you use crimp ferrules. Refer to [Table 3.12](#) for the recommended external dimensions and model numbers of the crimp ferrules.

Use the CRIMPFOX 6, a crimping tool made by PHOENIX CONTACT.

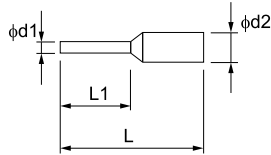


Figure 3.14 External Dimensions of Crimp Ferrules

Table 3.12 Crimp Ferrule Models and Sizes

| Wire Gauge mm ² (AWG) | Model | L (mm) | L1 (mm) | φd1 (mm) | φd2 (mm) |
|-------------------------------------|--------------------------|--------|---------|----------|----------|
| 0.25 (24) | AI 0.25-8YE | 12.5 | 8 | 0.8 | 2.0 |
| 0.34 (22) | AI 0.34-8TQ | 12.5 | 8 | 0.8 | 2.0 |
| 0.5 (20) | AI 0.5-8WH AI 0.5-8OG | 14 | 8 | 1.1 | 2.5 |
| 0.75 (18) | AI 0.75-8 GY | 14 | 8 | 1.3 | 2.8 |

◆ Drive Control Circuit Terminal Block Input Functions

Hx-xx parameters set functions for the multi-function input and output terminals.

WARNING! Sudden Movement Hazard. Correctly wire and test all control circuits to make sure that the control circuits operate correctly. If you use a drive that has incorrect control circuit wiring or operation, it can cause death or serious injury.

WARNING! Sudden Movement Hazard. Check the I/O signals and the external sequences for the drive before you set the Application Preset function. When you set the Application Preset function (A1-06 ≠ 0), it changes the I/O terminal functions for the drive and it can cause equipment to operate unusually. This can cause serious injury or death.

NOTICE: Damage to Equipment. Do not energize and de-energize the bypass more frequently than one time each 30 minutes. If you frequently energize and de-energize the bypass, it can cause failure.

Refer to [Table 3.13](#) for a list of input terminals and functions on the drive.

Table 3.13 Drive Multi-function Input Terminals

| Type | Terminal | Name (Default) | Function (Signal Level) |
|---------------------------------|---------------------------|--|---|
| MFDI | S1 | MFDI selection 1 (Not used) | <p>Note: Connections to these inputs can cause unintended operation. Use the Bypass PCB digital inputs.</p> <p>Multi-Function Digital Input</p> <ul style="list-style-type: none"> • Photocoupler • 24 V, 6 mA <p>Note: Install the wire jumpers between terminals SC-SP and SC-SN to set the MFDI power supply (sinking/sourcing mode or internal/external power supply).</p> <ul style="list-style-type: none"> • Sinking Mode: Install a jumper between terminals SC and SP. <p>NOTICE: Damage to Equipment. Do not close the circuit between terminals SC-SN. If you close the circuits between terminals SC-SP and terminals SC-SN at the same time, it will cause damage to the drive.</p> <ul style="list-style-type: none"> • Sourcing Mode: Install a jumper between terminals SC and SN. <p>NOTICE: Damage to Equipment. Do not close the circuit between terminals SC-SP. If you close the circuits between terminals SC-SP and terminals SC-SN at the same time, it will cause damage to the drive.</p> <ul style="list-style-type: none"> • External power supply: No jumper necessary between terminals SC-SN and terminals SC-SP. |
| | S2 | MFDI selection 2 (Not Used) | |
| | S3 | MFDI selection 3 (External Fault (NO-Always-Coast)) | |
| | S4 | MFDI selection 4 (Not used) | |
| | S5 | MFDI selection 5 (Multi-Step Speed Reference 1) | |
| | S6 | MFDI selection 6 (Multi-Step Speed Reference 2) | |
| | S7 | MFDI selection 7 (Jog Reference Selection) | |
| | SN | MFDI power supply 0 V | |
| | SC | MFDI selection common | |
| SP | MFDI power supply +24 Vdc | | |
| Safe Disable Input | H1 | Safe Disable input 1 | <p>Note: Active during Drive Mode only. Safe Disable Input</p> <p>Remove the jumper between terminals H1-HC and H2-HC to use the Safe Disable input.</p> <ul style="list-style-type: none"> • 24 V, 6 mA • ON: Normal operation • OFF: Coasting motor • Internal impedance 4.7 kΩ • OFF Minimum OFF time of 2 ms. <p>Note: Safe disable inputs are only effective in Drive Mode. They will not function in Bypass Mode.</p> |
| | H2 | Safe Disable input 2 | |
| | HC | Safe Disable function common | |
| Analog Inputs (Drive Mode only) | +V | Power supply for frequency setting | Power Supply for Multi-Function Analog Input <ul style="list-style-type: none"> • 10.5 V (allowable current 20 mA maximum) |
| | A1 | MFAI 1 (Not used) | Voltage input or current input Select terminal A1 with Jumper switch S1 and H3-01 [Terminal A1 Signal Level Select]. <ul style="list-style-type: none"> • 0 V to 10 V/100% (input impedance: 20 kΩ) • 4 mA to 20 mA/100%, 0 mA to 20 mA/100% (input impedance: 250 Ω) |
| | A2 | MFAI 2 (Not used) | Voltage input or current input Select terminal A2 with Jumper switch S1 and H3-09 [Terminal A2 Signal Level Select] <ul style="list-style-type: none"> • 0 V to 10 V/100% (input impedance: 20 kΩ) • 4 mA to 20 mA/100%, 0 mA to 20 mA/100% (input impedance: 250 Ω) |
| | AC | Analog input common | Signal Ground for Multi-Function Analog Input <ul style="list-style-type: none"> • 0 V |
| | FE | Connecting shielded cable | Frame Earth |

◆ Drive Control Circuit Terminal Block Output Functions

Refer to [Table 3.14](#) and [Table 3.15](#) for a list of output terminals and functions.

Table 3.14 Drive Control Circuit Output Terminals

| Type | Terminal | Name (Default) | Function (Signal Level) |
|--------------------|----------|-----------------------|---|
| Fault Relay Output | MA | N.O. output (Fault) | Drive Fault Signal Output <ul style="list-style-type: none"> Relay output 30 Vdc, 10 mA to 2 A 250 Vac, 10 mA to 2 A Minimum load: 5 V, 10 mA (Reference value) Note: <ul style="list-style-type: none"> Active during Drive Mode only. This will signal drive-based faults only. Note: |
| | MB | N.C. output (Fault) | |
| | MC | Digital output common | |
| MFDO | M1 | MFDO (During Run) | Multi Function Digital Output <ul style="list-style-type: none"> Relay output 30 Vdc, 10 mA to 2 A 250 Vac, 10 mA to 2 A Minimum load: 5 V, 10 mA (Reference value) Note: <ul style="list-style-type: none"> Active during Drive Mode only. These are active for drive-based conditions only. Do not set functions that frequently switch ON/OFF to MFDO (M1 to M6) because this will decrease the performance life of the relay contacts. Yaskawa estimates switching life at 200,000 times (assumes 1 A, resistive load). |
| | M2 | | |
| | M3 | MFDO (Zero Speed) | |
| | M4 | | |
| | M5 | MFDO (Speed Agree 1) | |
| | M6 | | |

Table 3.15 Drive Control Circuit Monitor Output Terminals

| Type | Terminal | Name (Default) | Function (Signal Level) |
|---|----------|---------------------------|---|
| Monitor Output | FM | MFAO 1 (Output frequency) | Multi Function Analog Output Select voltage or current output. <ul style="list-style-type: none"> 0 V to 10 V/0% to 100% 4 mA to 20 mA (receiver recommended impedance: 250 Ω) Note: <ul style="list-style-type: none"> This functions in Drive Mode only. Select with jumper switch S5 and H4-07 [Terminal FM Signal Level Select] or H4-08 [Terminal AM Signal Level Select]. |
| | AM | MFAO 2 (Output current) | |
| | AC | Monitor common | |
| External Power Supply Output (Not used) | +P | External power supply | Power supply for external devices. <ul style="list-style-type: none"> 24 V (150 mA maximum) |

◆ Switches and Jumpers on the Drive Control Circuit

The terminal board has switches to adapt the drive I/Os to the external control signals as shown in [Figure 3.15](#). Set the switches to select the functions for each terminal.

Note:

Active during Drive Mode only.

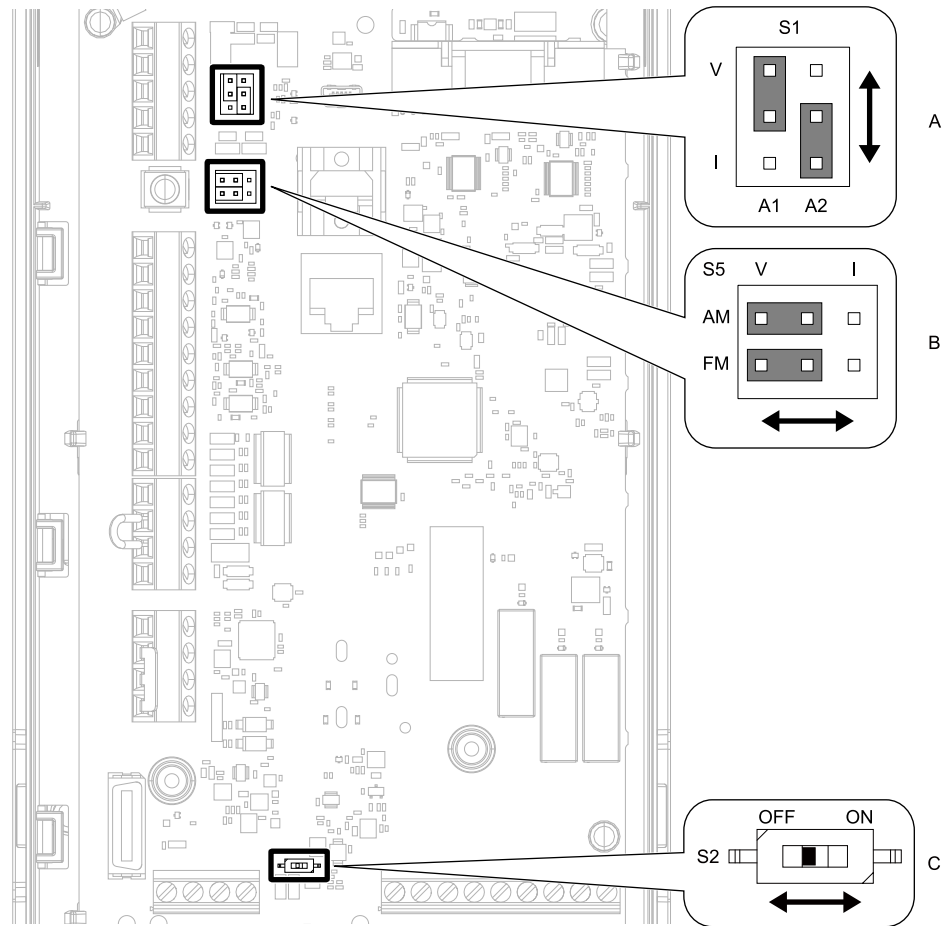


Figure 3.15 Locations of Switches

Table 3.16 I/O Terminals and Switches Functions

| Position | Switch | Terminal | Function | Default Setting |
|----------|------------------|----------|--|---|
| A | Jumper switch S1 | A1, A2 | Sets terminals A1 and A2 to voltage or current output. | A1: V (voltage input) A2: I (current input) |
| B | Jumper switch S5 | FM, AM | Sets terminals FM and AM to voltage or current output. | FM: V (voltage output) AM: V (voltage output) |
| C | DIP switch S2 | - | Enables and disables the termination resistor of embedded communications protocols. This switch should always be in the ON position. | ON Note: This switch should always be ON when the drive is part of a bypass package. |

◆ Wiring the Drive Control Circuit Terminal

WARNING! *Electrical Shock Hazard. Do not remove covers or touch circuit boards while the bypass is energized. If you touch the internal components of an energized bypass, it can cause serious injury or death.*

NOTICE: *Do not let wire shields touch other signal lines or equipment. Insulate the wire shields with electrical tape or shrink tubing. If you do not insulate the wire shields, it can cause a short circuit and damage the drive.*

3.6 Drive Control Circuit

Note:

- Isolate control circuit wiring from main circuit wiring (terminals R/L1, S/L2, T/L3, U/T1, V/T2, W/T3, -, +1) and other high-power wiring. If the control circuit wires are adjacent to the main circuit wires, electrical interference can cause the drive or the devices around the drive to malfunction.
- Isolate contact output terminals MA, MB, MC and M1-M6 from other control circuit wiring. If the output terminal wires are adjacent to other control circuit wires, electrical interference can cause the drive or devices around the drive to malfunction.
- Use a UL Listed Class 2 Power Supply to connect external power to the contact output terminals. If the power supply for peripheral devices is incorrect, it can cause a decrease in drive performance.
- Connect the shield of shielded cable to the applicable ground terminal. If the grounding is not correct, electrical interference can cause the drive or devices around the drive to malfunction.

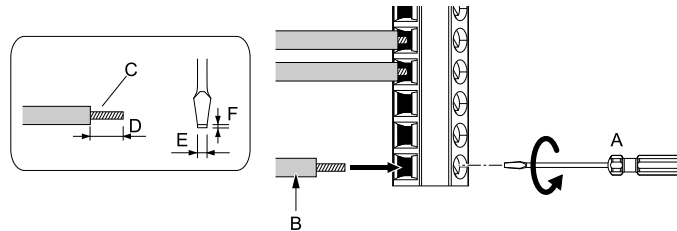
Correctly ground the drive terminals and complete main circuit wiring before you wire the control circuit. Remove the keypad and front cover.

1. Refer to [Figure 3.16](#) and wire the control circuit.

WARNING! Fire Hazard. Tighten all terminal screws to the correct tightening torque. Connections that are too loose or too tight can cause incorrect operation and damage to the bypass. Incorrect connections can also cause death or serious injury from fire.

Note:

- Use shielded wires and shielded twisted-pair wires for the control circuit terminal wiring. If the grounding is not correct, electrical interference can cause the drive or devices around it to malfunction.
- Do not use control circuit wiring that is longer than 50 m (164 ft) to supply the frequency reference with an analog signal from a remote source. Wiring that is too long can cause unsatisfactory system performance.



- A - Loosen the screws and put the wire into the opening on the terminal block.**
- B - Wire with a crimp ferrule attached, or use wire that is not soldered with the core wires lightly twisted.**
- C - Pull back the shielding and lightly twist the end with your fingers to keep the ends from fraying.**

- D - If you do not use crimp ferrules, remove approximately 5.5 mm (0.21 in) of the covering at the end of the wire.**
- E - Blade width of 2.5 mm (0.1 in) or less**
- F - Blade depth of 0.4 mm (0.01 in) or less**

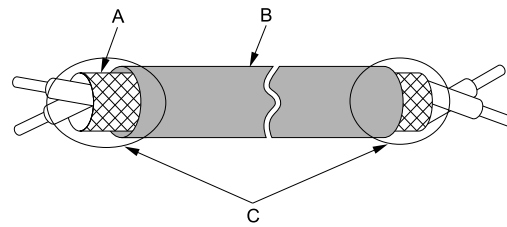
Figure 3.16 Wiring Procedure for the Control Circuit

WARNING! Fire Hazard. Tighten all terminal screws to the correct tightening torque. Connections that are too loose or too tight can cause incorrect operation and damage to the bypass. Incorrect connections can also cause death or serious injury from fire.

NOTICE: Do not tin stranded wire with solder. Soldered wire connections can become loose over time and cause unsatisfactory system performance.

Note:

- Refer to [Figure 3.17](#) for information to prepare terminal ends of the shielded wire.
- Prepare the wire ends of shielded twisted-pair wires as shown in [Figure 3.17](#) to use an analog reference from an external frequency setting potentiometer to set the frequency. Connect the shield to terminal FE of the drive.



**A - Connect the shield to terminal
FE of the drive.**

B - Sheath

**C - Insulate with electrical tape or
shrink tubing.**

Figure 3.17 Prepare the Ends of Shielded Wire

2. Install the front cover to its initial position.

3.7 Control I/O Connections

This section gives information about the settings for the listed control circuit I/O signals.

- MFDI (terminals S1 to S7)
- MFDO (terminals M1 to M6)
- MFAI (terminals A1, A2)
- MFAO (terminals FM, AM)
- RS-485 communications (terminals D+, D-, AC)

◆ Set Input Signals for MFAI Terminals A1 and A2

Use terminals A1 and A2 to input a voltage or a current signal. Set the signal type as shown in [Table 3.17](#).

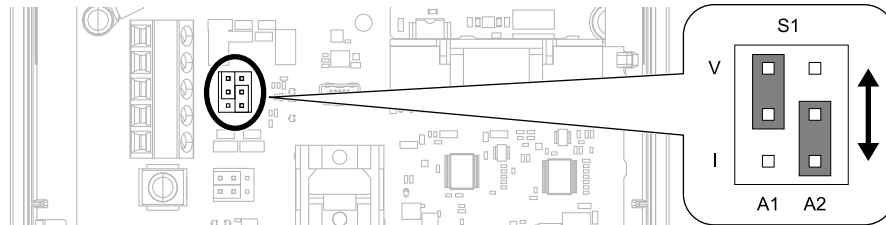






Figure 3.18 Location of Jumper Switch S1

Table 3.17 MFAI Terminals A1 and A2 Signal Settings

| Terminal | Types of Input Signals | Jumper Switch S1 | Parameter | |
|----------|-------------------------|---|-----------|--|
| | | | No. | Signal Level |
| A1 | Voltage input (Default) |  | H3-01 | 0: 0 V to 10 V/0% to 100% (input impedance: 20 kΩ) |
| | Current input |  | | 2: 4 mA to 20 mA/0% to 100% (input impedance: 250 Ω) 3: 0 mA to 20 mA/0% to 100% (input impedance: 250 Ω) |
| A2 | Voltage input |  | H3-09 | 0: 0 V to 10 V/0% to 100% (input impedance: 20 kΩ) |
| | Current input (Default) |  | | 2: 4 mA to 20 mA/0% to 100% (input impedance: 250 Ω) 3: 0 mA to 20 mA/0% to 100% (input impedance: 250 Ω) |

Note:

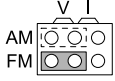
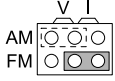
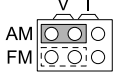
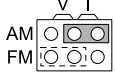
Set H3-02, H3-10 = 0 [Terminal A1 Function Selection, Terminal A2 Function Selection = Frequency Reference] to set A1 and A2 to frequency reference. The drive will add the analog input values together to make the frequency reference.

◆ Set Output Signals for MFAO Terminals FM, AM

Set the signal type for terminals AM and FM to voltage or current output. Use jumper switch S5 and H4-07, H4-08 [Terminal FM Signal Level Select, Terminal AM Signal Level Select] to set the signal type.



Figure 3.19 Location of Jumper Switch S5

| Terminal | Types of Output Signals | Jumper Switch S5 | Parameter | |
|----------|--------------------------|---|-----------|------------------|
| | | | No. | Signal Level |
| FM | Voltage output (Default) |  | H4-07 | 0: 0 V to 10 V |
| | Current output |  | | 2: 4 mA to 20 mA |
| AM | Voltage output (Default) |  | H4-08 | 0: 0 V to 10 V |
| | Current output |  | | 2: 4 mA to 20 mA |

3.8 Connect the Bypass to a PC

The bypass control board has a mini-B type USB port.

You can use a USB cable (USB 2.0, type: A - mini-B) to connect the bypass to a type-A USB port on a PC. Open the front door of the bypass cabinet to connect the USB cable to the CN1 port on the bypass PCB. After you connect the bypass PCB to the PC, you can use Yaskawa DriveWizard HVAC software to monitor drive performance and manage parameter settings. Visit the Yaskawa website to download the DriveWizard HVAC software:

<https://www.yaskawa.com/products/drives/hvac-drives/software-tools/drivewizard-hvac>

Note:

Do not connect to the USB port on the drive. Always use the CN1 port on the bypass PCB to communicate with a bypass.

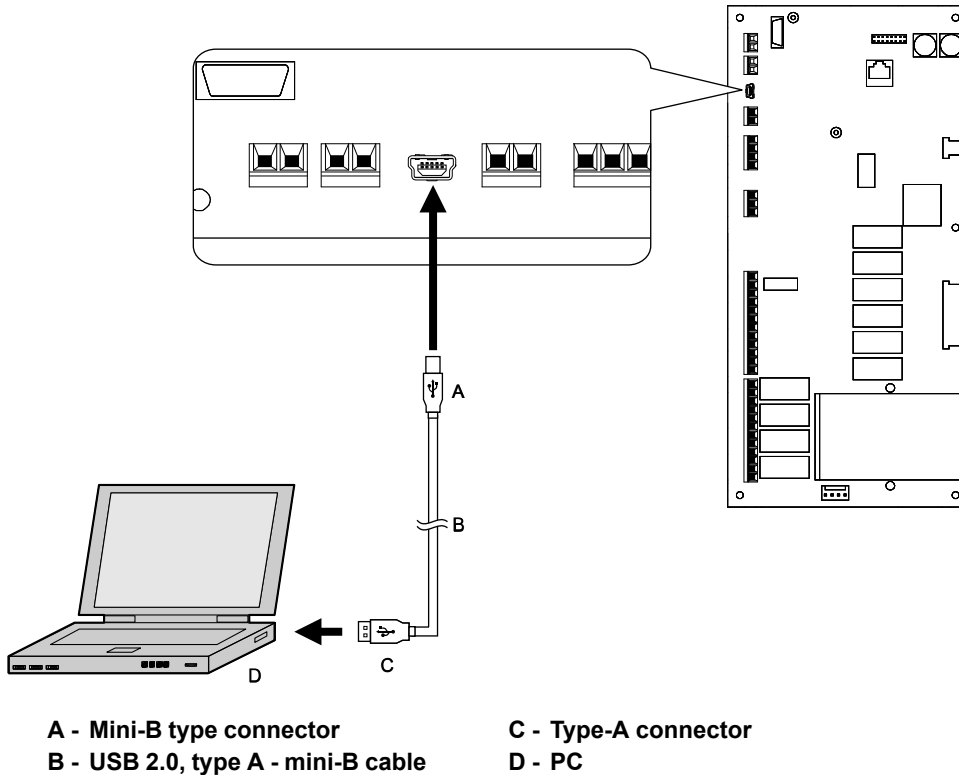


Figure 3.20 Connect to a PC (USB)

Yaskawa recommends that you use a USB cable with connectors connected with shielded wires.

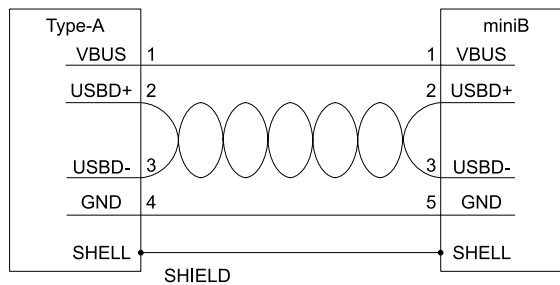


Figure 3.21 Recommended USB Cable

3.9 Motor Application Precautions

◆ Precautions for Existing Standard Motors

■ Insulation Withstand Voltage

Consider motor voltage tolerance levels and motor insulation in applications with an input voltage of over 440 V or particularly long wiring distances. Use an insulated drive motor.

NOTICE: Use an inverter-duty motor with reinforced insulation and windings applicable for use with an AC drive. If the motor does not have the correct insulation, it can cause a short circuit or ground fault from insulation deterioration.

■ Vibration

Vibrations can occur in the these conditions:

- Resonance with the natural frequency of machinery
Use caution if you add a variable-speed drive to applications that operate the motor from line power at a constant speed. If resonance occurs, install shock-absorbing rubber around the base of the motor and enable the Jump frequency control.
- The motor is not balanced
Use caution if the motor speed is higher than the rated motor speed.
- Subsynchronous resonance
Subsynchronous resonance can occur with long motor shafts and in applications such as turbines, blowers, and fans with high inertia loads.

■ Audible Noise

The audible noise of the motor changes when the carrier frequency setting changes. When you use a high carrier frequency, audible noise from the motor is equivalent to the motor noise generated when you operate from line power. If you operate at speeds that are more than the rated rotation speed, the unwanted motor noise increases.

◆ Precautions for Specialized Motors

■ Pole Change Motors

The rated current of pole change motors is different than standard motors. Check the maximum current of the motor before you select a drive. Always stop the motor before you switch between the number of motor poles. If you change the number of poles while the motor is rotating, the overvoltage from regeneration or the overcurrent protection circuitry will make the motor coast to stop.

■ Submersible Motors

The rated current of a submersible motor is more than the rated current of a standard motor. Use a sufficiently large motor cable that will not let voltage drop decrease the maximum torque level.

■ Explosion-Proof Motors

You must test the motor and the drive together for explosion-proof certification. You must also test existing installations of explosion-proof motors. The drive is not designed for explosion-proof areas. Install the drive in a safe location.

The encoder used with pressure-resistant explosion-proof motors is intrinsically safe. When wiring between the drive and encoder, always connect through a specialized pulse coupler.

■ Geared Motors

The continuous speed range is different for different lubricating methods and manufacturers. For oil lubrication, continuous operation in the low-speed range can cause burnout. Contact the manufacturer for more information about applications where operating at more than the rated frequency is necessary.

■ Single-Phase Motors

Variable speed drives are not designed to operate with single-phase motors. The drive is for use with three-phase motors only. If you use capacitors to start the motor, it can cause a high frequency current to flow to the capacitors and can damage the capacitors. A split-phase start or a repulsion start can burn out the starter coils because the internal centrifugal switch is not activated.

◆ Notes on the Power Transmission Mechanism

For power transmission machinery that uses oil to lubricate gearboxes, transmissions, or reduction gears, make sure that you use precaution if you operate the machinery continuously at low speed. Oil does not lubricate the system as well at low speeds. If you operate at frequencies higher than the rated frequency, it can cause problems with the power transmission mechanism. These problems include audible noise, decreased service life, and decreased durability.

Startup Procedure and Test Run

| | | |
|------------|--|-----------|
| 4.1 | Section Safety | 68 |
| 4.2 | Keypad: Names and Functions..... | 69 |
| 4.3 | Start-up, Test Operation, and Rotation Check..... | 75 |
| 4.4 | Auto-Tuning | 81 |
| 4.5 | Fine Tuning during Test Runs (Adjust the Control Function)..... | 83 |

4.1 Section Safety

DANGER

Electrical Shock Hazard

Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe.

If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

WARNING

Electrical Shock Hazard

Do not operate the bypass when covers are missing. Replace covers and shields before you operate the bypass. Use the bypass only as specified by the instructions.

Some figures in this section include bypasses without covers or safety shields to more clearly show the inside of the bypass. If covers or safety shields are missing from the bypass, it can cause serious injury or death.

Do not remove covers or touch circuit boards while the bypass is energized.

If you touch the internal components of an energized bypass, it can cause serious injury or death.

NOTICE

Sudden Movement Hazard

Deactivate the Run command before you switch from Programming Mode to Drive Mode.

If you switch from Programming Mode to Drive Mode and there is an active Run command, the motor will rotate and the equipment can suddenly start.

4.2 Keypad: Names and Functions

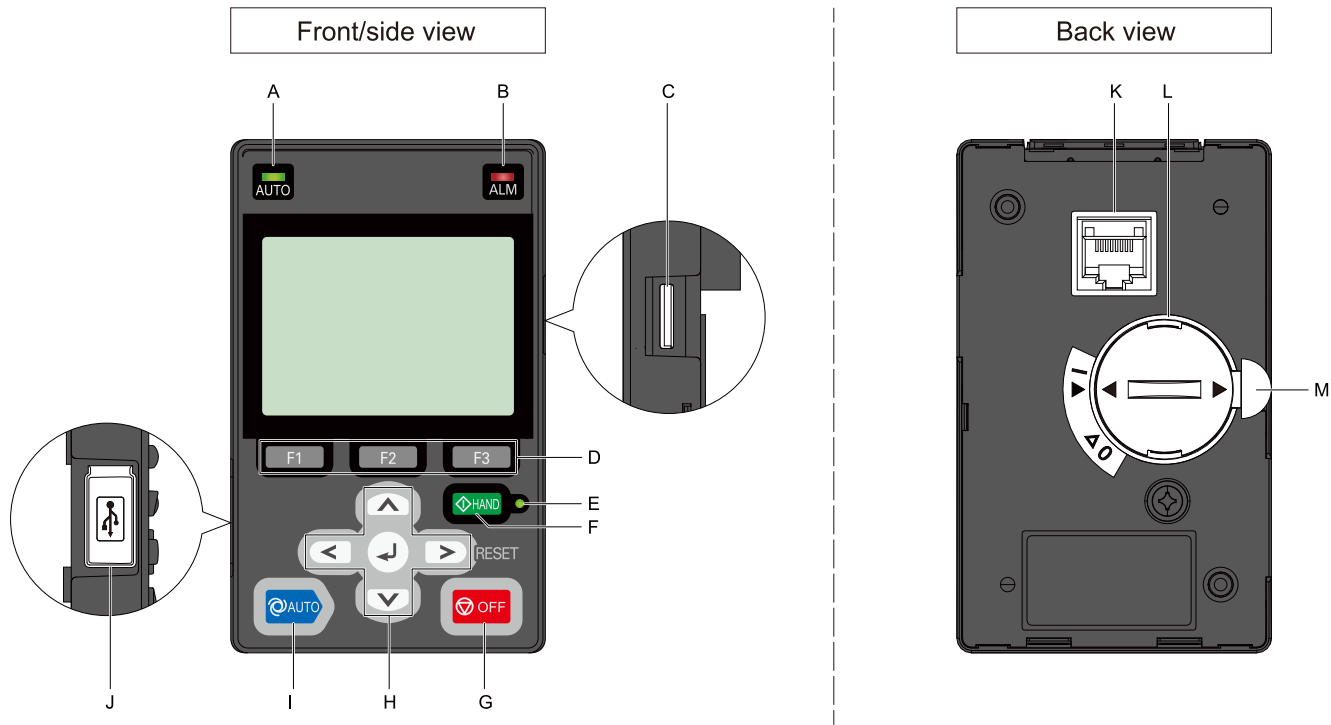








Figure 4.1 Keypad

Table 4.1 Keypad: Names and Functions

| No. | Name | Function |
|-----|--------------------------------|--|
| A | AUTO LED ^{*/} | Illuminates to show that the drive is in AUTO Mode. |
| B | ALM LED | Illuminates when the drive detects a fault. Flashes when the drive detects: <ul style="list-style-type: none"> An alarm An oPE parameter setting error A fault or alarm during Auto-Tuning The LED turns off when there are no drive faults or alarms. |
| C | microSD Card Insertion Slot | The insertion point for a microSD card. |
| D | Function Keys (F1, F2, F3) | The menu shown on the keypad sets the functions for function keys. The name of each function is in the lower half of the display window. |
| E | HAND LED ^{*/} | Illuminates to show that the drive is in HAND Mode. |
| F | HAND Key | Sets drive operation to HAND Mode. The drive uses the S5-01 [HAND Frequency Reference Selection] setting. |
| G | OFF Key | Stops drive operation. Note: The OFF key has highest priority. Push to stop the motor even when a Run command is active at an external Run command source. Set o2-02 = 0 [STOP Key Function Selection = Disabled] to disable priority. |

4.2 Keypad: Names and Functions

| No. | Name | Function |
|-----|--|---|
| H | Left Arrow Key  | Moves the cursor to the left. |
| | Up Arrow Key/Down Arrow Key  | <ul style="list-style-type: none"> Scrolls up or down to display the next item or the previous item. Selects parameter numbers, and increments or decrements setting values. |
| | Right Arrow Key (RESET)  | <ul style="list-style-type: none"> Moves the cursor to the right. Continues to the next screen. Clears drive faults. |
| | ENTER Key  | <ul style="list-style-type: none"> Enters parameter values and settings. Selects menu items to move the user between keypad displays. Selects each mode, parameter, and set value. |
| I | AUTO Key  | <p>Sets drive operation to AUTO Mode. The drive uses the b1-01 [Frequency Reference Selection 1] and b1-02 [Run Command Selection 1] settings.</p> <p>Note: Push  on the keypad to set the drive to HAND Mode before you use the keypad to operate the motor.</p> |
| J | USB Terminal | Insertion point for a mini USB cable. Uses a USB cable (USB standard 2.0, type A - mini-B) to connect the keypad to a PC. |
| K | RJ-45 Connector | Uses an RJ-45 8-pin straight through UTP CAT5e extension cable or keypad connector to connect to the drive. |
| L | Clock Battery Cover | <p>Cover for the clock battery.</p> <p>Note:</p> <ul style="list-style-type: none"> The battery included with the keypad is for operation check. It may be exhausted earlier than the expected battery life described in the manual. Refer to "Maintenance & Troubleshooting Manual (TOEPYAIHV6001)" for more information about replacement procedure. <p>To replace the battery, use a Hitachi Maxell "CR2016 Lithium Manganese Dioxide Lithium Battery" or an equivalent battery with these properties:</p> <ul style="list-style-type: none"> Nominal voltage: 3 V Operating temperature range: -20 °C to +85 °C (-4 °F to +185 °F) |
| M | Insulation Sheet | An insulating sheet is attached to the keypad battery to prevent battery drain. Remove the insulation sheet before you use the keypad for the first time. |

*1 Refer to [AUTO LED and HAND LED Indications on page 71](#) for more information about AUTO LED and HAND LED indications.

◆ LCD Display

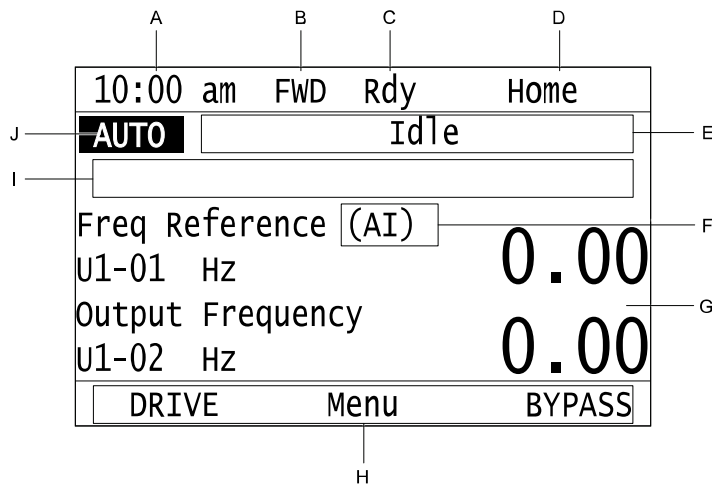


Figure 4.2 LCD Display Indications



Table 4.2 LCD Display Indications and Meanings

| Symbol | Name | Description |
|--------|--------------------------------|---|
| A | Time display area | Shows the current time. Set the time on the default settings screen. |
| B | Forward/Reverse run indication | Shows direction of motor rotation. <ul style="list-style-type: none"> FWD: Shown when set to Forward run. REV: Shown when set to Reverse run. |
| C | Ready | The screen will show Rdy when the drive is ready for operation or when the drive is running. |

| Symbol | Name | Description |
|--------|---|--|
| D | Mode display area | Shows the name of the current mode or screen. |
| E | Alarm codes and status messages display area | Shows an alarm code or message about bypass status. Refer to page 146 for more information about status messages. |
| F | Frequency reference source indication | Shows the current frequency reference source. <ul style="list-style-type: none"> • KPD: keypad • AI: analog input terminal (Bypass PCB Terminal TB4-2) • COM: serial communications • OPT: option card |
| G | Data display area | Shows parameter values, monitor values, and details of the results of operations. |
| H | Function keys 1 to 3 (F1 to F3) | The function names shown in this area will change when the selected screen changes. Push one of the function keys F1 to F3 on the keypad to do the function. |
| I | Alarm and message texts display area | Shows a fault, minor fault, alarm, or error name and message text. Note: When the drive must show an alarm and a message on the keypad at the same time, the keypad will switch between the alarm code and message text in 2-second intervals. |
| J | HOA mode or alternative Run command source indication | <ul style="list-style-type: none"> • OFF: The bypass is operating in OFF Mode. • AUTO: The bypass is operating in AUTO Mode. • HAND: The bypass is operating in HAND Mode. • EMOV: The bypass is operating in Emergency Override Mode. |

◆ AUTO LED and HAND LED Indications

Table 4.3 AUTO LED and HAND LED Indications

|  |  | Status |
|---|---|---|
| OFF | OFF | OFF Mode |
| OFF | ON | HAND Mode |
| OFF | Long blink (50% duty) | HAND Mode <ul style="list-style-type: none"> • When the Frequency Reference is 0 or during deceleration • During PI Sleep |
| OFF | Double blink | HAND Mode When you clear the Run command and enter the Run command again during the time set in C1-02 [Deceleration Time 1] |
| ON | OFF | AUTO Mode |
| Long blink (50% duty) | OFF | AUTO Mode <ul style="list-style-type: none"> • When the Frequency Reference is 0 or during deceleration • During PI Sleep |
| Double blink | OFF | AUTO Mode When an MFDI sends a Fast Stop signal to stop the drive |

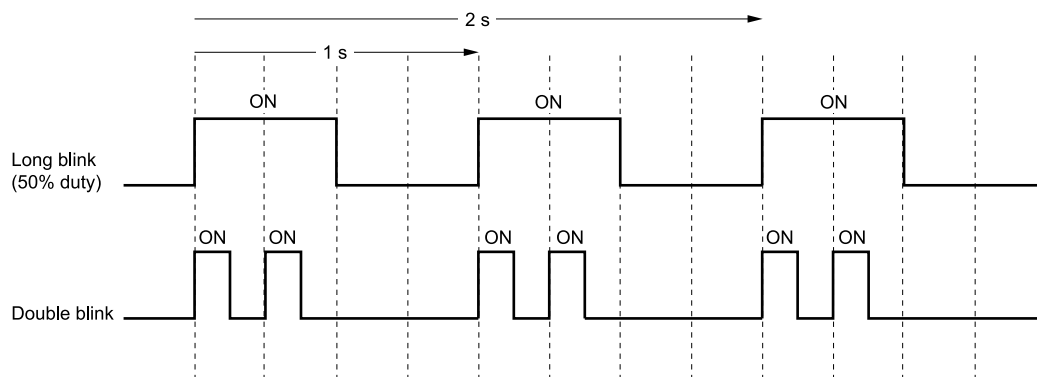


Figure 4.3 AUTO LED and HAND LED Timing Status

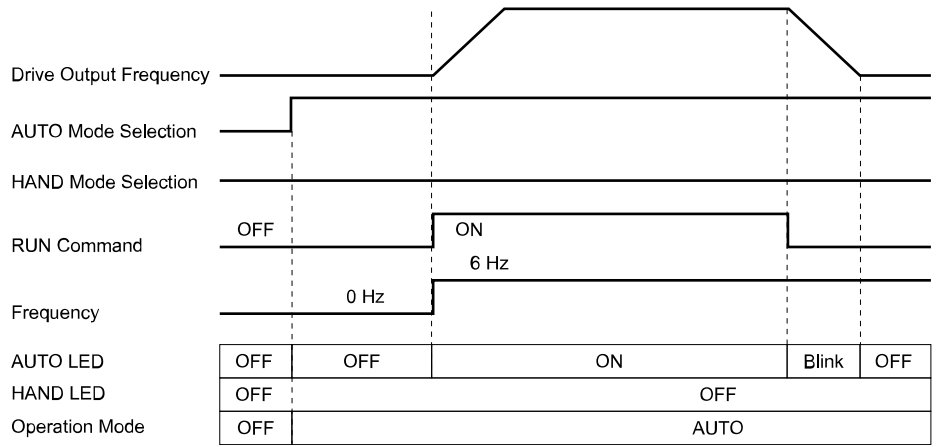


Figure 4.4 LEDs and Drive Operation in AUTO and HAND Modes

◆ Keypad Mode and Menu Displays

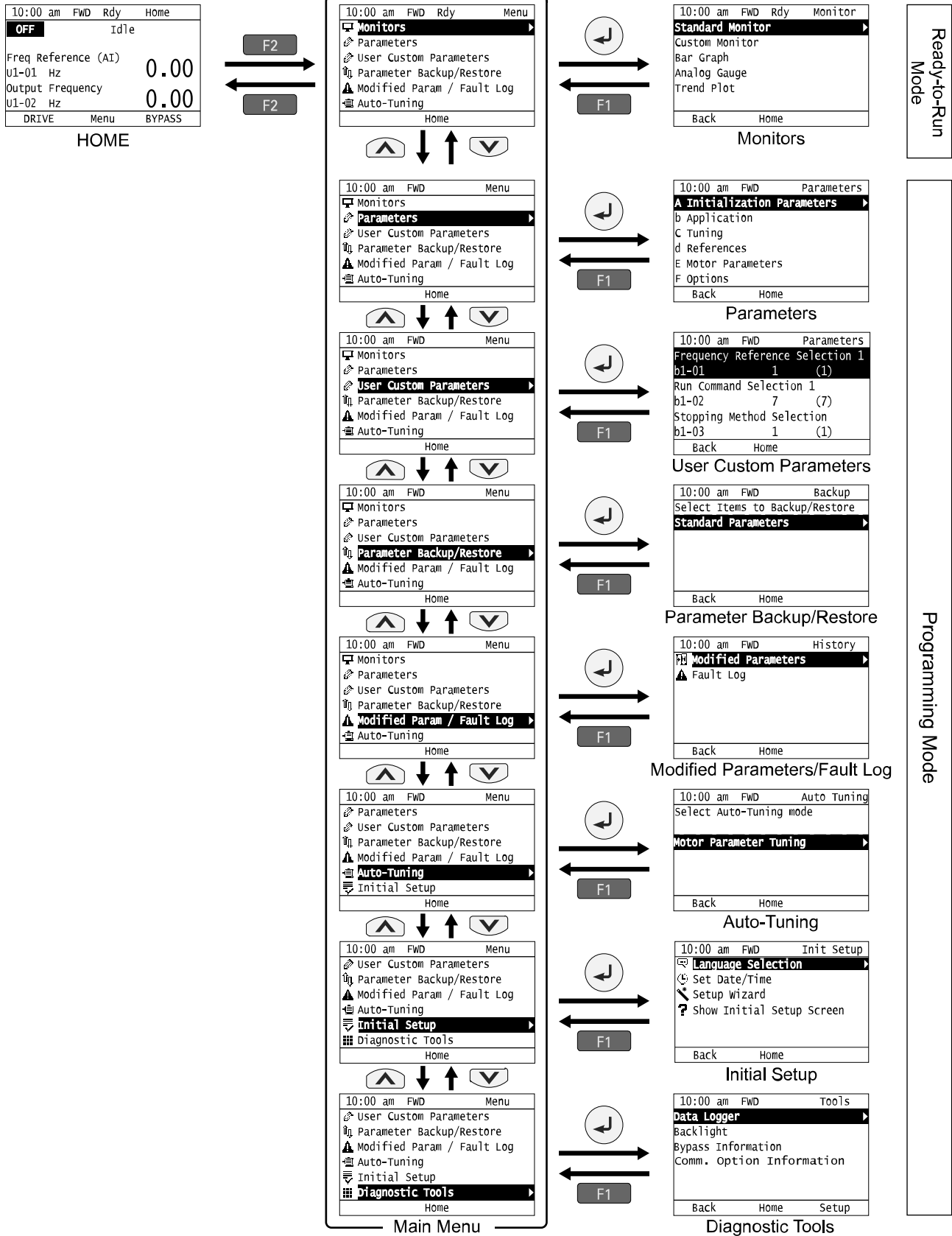


Figure 4.5 Keypad Functions and Display Levels

4.2 Keypad: Names and Functions

Note:



- Push  from the Home screen to show monitors.
- Push  to set *d1-01 [Reference 1]* when you set *b1-01 = 0 [Frequency Reference Selection 1 = Keypad]* and the Home screen shows *U1-01 [Frequency Reference]*.
- The keypad will show [Rdy] when the drive is in Ready-to-Run Mode. The drive is prepared to accept a Run command.
- The bypass will not accept a Run command in Programming Mode in the default setting. Set *b1-08 [Run Command Select in PRG Mode]* to accept or reject a Run command from an external source while in Programming Mode.
 - Set *b1-08 = 0 [Disregard RUN while Programming]* to reject the Run command from an external source while in Programming Mode (default).
 - Set *b1-08 = 1 [Accept RUN while Programming]* to accept the Run command from an external source while in Programming Mode.
 - Set *b1-08 = 2 [Allow Programming Only at Stop]* to prevent changes from Drive Mode to Programming Mode while the drive is operating.

Table 4.4 Drive Mode Screens and Functions

| Mode | Keypad Screen | Function |
|-------------------|-------------------------------|---|
| Ready-to-Run Mode | Monitors | Sets monitor items to display. |
| Programming Mode | Parameters | Changes parameter settings. |
| | User Custom Parameters | Shows the User Parameters. |
| | Parameter Backup/Restore | Saves parameters to the keypad as backup. |
| | Modified Parameters/Fault Log | Shows modified parameters and fault history. |
| | Auto-Tuning | Auto-Tunes the drive. |
| | Initial Setup | Changes initial settings. |
| | Diagnostic Tools | Sets data logs and backlight. Will also show bypass and communications option information (if installed). |

4.3 Start-up, Test Operation, and Rotation Check

This section gives the basic steps necessary to get the bypass started and make sure the motor spins in the correct direction. This section gives information about only the most basic settings.

◆ Items to Check before You Energize the Bypass

1. Make sure there is no power to the bypass. Use a properly rated and functioning multimeter to make sure that it is safe and do all appropriate lockout/tagout procedures.

WARNING! Electrical Shock Hazard. Do not operate the bypass when covers are missing. Replace covers and shields before you operate the bypass. Use the bypass only as specified by the instructions. Some figures in this section include bypasses without covers or safety shields to more clearly show the inside of the bypass. If covers or safety shields are missing from the bypass, it can cause serious injury or death.

2. Record the motor nameplate information and make sure that the input voltage aligns with the bypass rating. Make sure that the motor rated FLA is not more than the output current rating of the bypass as shown on the bypass nameplate. Make sure that the motor rated FLA is in range of the specifications.
3. The bypass will have one of two types of main input disconnect:

A non-fusible disconnect switch

The standard bypass includes a non-fusible disconnect switch that does not provide branch circuit protection. If you will be installing the bypass according to applicable local codes and the requirements shown on the bypass nameplate, you must install appropriate branch circuit protection. Yaskawa recommends semiconductor fusing to ensure 100 kAIC SCCR panel rating. This fusing is specified on the bypass nameplate.

WARNING! Fire Hazard. You must install branch circuit protection according to applicable local codes and the requirements listed on the bypass nameplate. The bypass is suitable for use on a circuit capable of delivering not more than 100,000 RMS symmetrical amperes, 208 Vac and 480 Vac with the circuit breaker option or when protected by class J or class L fuses as specified on the bypass nameplate. Consult factory with questions. Failure to comply could result in fire and damage to the bypass unit or injury to personnel

An input circuit breaker

Bypass Option M includes an input circuit breaker. You must use the two dials on the circuit breaker to set the adjustable trip level. The dial marked "FLA" sets the breaker to match the motor FLA. Use a small straight-edge screwdriver and adjust to the appropriate current level. The other dial sets the inrush level. Make sure this dial is set to "Auto 1" (factory setting).

4. Make sure that the available three-phase line power is the correct voltage. Connect line power to the input disconnect device.
5. Connect the bypass grounding terminal to the appropriate building ground circuit.
6. If you are using a dual voltage motor, make sure that the motor is wired for the application voltage.
7. Connect the motor to the output terminal block in the bypass or to the motor overload (if provided).
8. Connect the motor ground to the bypass drive ground terminal.
9. If you have an external motor overload, set the correct FLA from Step 2 there.
10. Use the connection diagram or the schematic packaged with the bypass to make sure that you correctly terminate wiring connections and connected to appropriate circuits at Bypass PCB A2. Please note the following with respect to the safety circuit (DI-2, terminal TB2-2) and the BAS interlock circuit (DI-3, terminal TB2-3):

Safety Interlock Circuit

DI-2 (terminal TB2-2) is provided to connect safety devices in a normally-closed series circuit, such as: freeze up thermostats, smoke/fire sensors, high pressure limits, temperature limits, or vibration detectors.

The keypad will display the status "Safety Open" if a N.C. safety circuit is not closed between DI-2 and IG24 (TB2-10) on Bypass PCB A2. An open circuit between DI-2 and IG24 will prevent drive or bypass operation.

Take ONE of these steps to ensure proper operation prior to startup:

- Install normally-closed (N.C.) safety circuit between DI-2 and IG24 on Bypass PCB A2.
- Install a jumper between DI-2 and IG24 on Bypass PCB A2.

Building Automation System Interlock Circuit (Drive and Bypass Enable Input)

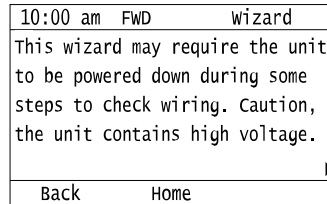
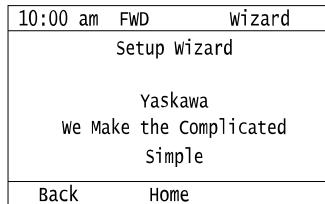
The keypad will display an AL02 - Interlock Open alarm or FB-02 - Wait For Interlock Timeout fault if a N.C. safety circuit is not closed between DI-3 (TB2-3 by default setting of Z2-03) and IG24 on Bypass PCB A2 when there is an active Run command in either HAND or AUTO Mode. An open circuit between TB2-3 and IG24 (TB2-10) will prevent drive or bypass operation.

Take ONE of these steps to ensure proper operation prior to startup:

- Install a normally-closed (N.C.) BAS Interlock Circuit/Damper Interlock between DI-3 and IG24 on Bypass PCB A2.
 - Install a jumper between DI-3 and IG24 on Bypass PCB A2.
11. Record all other connections to the bypass by terminal number to determine if special programming of any of the following is required:
 - Multi-function Digital Inputs – Bypass control board TB2 (A2)
 - Multi-function Digital Outputs – Bypass control board TB1 (A2)
 - Analog Speed Reference - Bypass control board TB4 (A2)
 - Other Analog Inputs – Drive control board (A1)
 - Analog Outputs – Drive control board (A1)
 - Differential PI control – Drive control board (A1)
 - Serial Communications – Bypass control board TB3 (A2)
 12. Run all control wiring in separate conduit from motor or line power. Route digital output wiring exceeding 24 V in conduit separate from other control wiring.
 13. Make sure that the building automation system logic is ready for the start, stop, and speed command functions.

◆ **Bypass Start-Up Procedure**

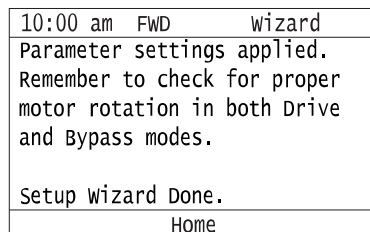
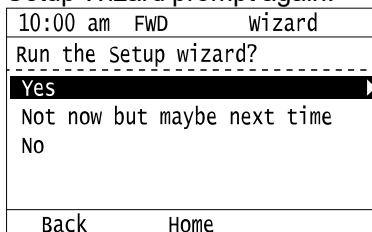
1. Replace all bypass and drive covers.
2. Before you apply power to the bypass, use a properly rated multimeter to check all three-phases of input power for proper levels and balance. Record these levels for future reference.
3. Turn the main input disconnect handle (if equipped) clockwise to energize the bypass.
4. When you energize the bypass for the first time, the keypad will show the Setup Wizard prompt screen.



The Setup Wizard will quickly configure and adjust commonly used parameters related to:

- Clock
- Motor FLA
- Frequency Reference
- Run Command
- Accel/Decel Times
- Safety Interlocks
- Speed Search

5. Select [Yes] to run the Setup Wizard. After you complete the Setup Wizard, the bypass will not show the Setup Wizard prompt again.



Note:

If you select [Not now but maybe next time] from the Setup Wizard prompt, the keypad will show the Setup Wizard prompt each time you energize the bypass.

If you select [No], the keypad will not show the Setup Wizard prompt nor the Initial Setup screen when you energize the bypass. You can set the date and time or run the Setup Wizard from the Initial Setup screen.

6. Check for correct motor rotation in Drive Mode and Bypass Mode. Refer to [Test Run and Rotation Check on page 77](#) for more information about checking and changing motor rotation.

◆ Test Run and Rotation Check

■ Test Run (No Load)

When possible, Yaskawa recommends that you do a test run in Drive Mode and Bypass Mode to check rotation in both modes before you mechanically connect the motor to the rest of the machine. This is critically important if running the machine at full speed and/or running the machine in the wrong direction could cause damage or injury.

■ Rotation Check in Drive Mode and Bypass Mode

You must check the rotation in both Drive Mode and Bypass Mode. If the rotation direction is incorrect in Drive Mode, you must change the output (motor) wiring. If the rotation direction is incorrect in Bypass Mode, you must change the input power wiring.

Note:

Do the Drive Mode rotation check first. If there are any problems, make sure that you correct them before you do the Bypass Mode rotation check.

■ Precautions before You Do a Test Run

Before you rotate the motor, check these items:

- Check for safety issues near the bypass system, motor, and machine.
- Make sure that all safety, interlock, emergency stop circuits and safety mechanisms are operating correctly.

■ Test Run and Rotation Check - Drive Mode (HAND)

Note:


Yaskawa strongly recommends that you do the items in [Start-up, Test Operation, and Rotation Check on page 75](#), including completing the Setup Wizard before you do this procedure.

1. Energize the bypass. If the HOME screen is not shown, push **F2**.
2. Push **OFF** to make sure that the bypass does not respond to an Auto-Run command.
3. Check the lower-left corner of the keypad screen to make sure that the bypass is in Drive Mode. "DRIVE" will flash when the bypass is in Drive Mode.

| | | | |
|---------------------|------|--------|------|
| 10:00 am | FWD | Rdy | Home |
| OFF | | | |
| Freq Reference (AI) | | 0.00 | |
| U1-01 Hz | | 0.00 | |
| Output Frequency | | 0.00 | |
| U1-02 Hz | | 0.00 | |
| DRIVE | Menu | BYPASS | |



WARNING! Sudden Movement Hazard. Before you do the next step, remove all personnel and objects from the area around the bypass and motor. The motor will rotate in the next step and can cause serious injury or death.

4. Push **HAND** to give the bypass a Run command from HAND Mode.
5. Push **↶** to show *S5-05 [HAND Frequency Reference]*, and set it to 6.00 Hz.

6. Push  to save the value and the motor will start to run.

| | | |
|--------------------------|---------|------------|
| 10:00 am | FWD Rdy | Parameters |
| HAND Frequency Reference | | |
| S5-05 | | |
| 006.00 Hz | | |
| Default : 0.00Hz | | |
| Range : 0.00~400.00 | | |
| Home | | Min/Max |

If the system does not run, check the keypad for a “Safety Open” message or an “AL02 – Interlock Open” alarm.

- If there is a “Safety Open” message, check the safety circuit (or jumper) connected at TB2-2.
 - If there is an “AL02 – Interlock Open” alarm, check the BAS Interlock circuit (or jumper) connected at TB2-3.
7. Push  to return to the HOME screen, then push  until you can see the Output Current display on the keypad screen.

| | | |
|---------------------|---------|---------|
| 10:00 am | FWD Rdy | Monitor |
| Freq Reference (AI) | | |
| U1-01 Hz | 6.00 | |
| Output Frequency | | |
| U1-02 Hz | 6.00 | |
| Output Current | | |
| U1-03 A | 12.34 | |
| DRIVE | Menu | BYPASS |


Output current should typically be between 20% and 100% of motor full load amps (FLA).

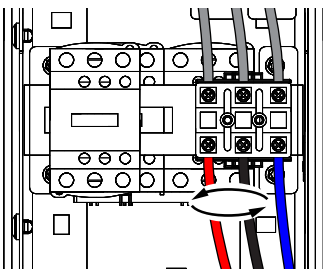
If the output current is **not** in this range:

- Make sure that there are no mechanical issues or binding in the machinery.
 - Make sure that the motor is correctly wired to the motor terminal block (or motor overload, if equipped).
 - Make sure that a multi-voltage motor is correctly wired in the motor junction box.
8. Look at the motor (or load) to make sure that the rotation direction is correct (Drive Mode).

If the motor direction in Drive Mode is **CORRECT**, do steps 15 to 18.

If the motor direction in Drive Mode is **INCORRECT**, do steps 9 to 14.

9. Push  to stop the motor.
10. De-energize the system at the power source. Observe correct lockout/tagout safety procedures and wait for the CHARGE light to completely go out on the HV600. The CHARGE light will be visible after you open the cabinet door.
11. Remove lower cover (or open cabinet door) to access motor wiring.
12. Switch any two phases on the **customer wiring side of the motor terminal block or motor overload**.






Note:

DO NOT change the wiring connected directly to the HV600 drive unit.

13. Replace lower cover (or close cabinet door).
14. Repeat Steps 1 to 8 of this procedure to confirm correct rotation in Drive Mode.

WARNING! Sudden Movement Hazard. Before you do this step, remove all personnel and objects from the area around the bypass and motor. The motor will rotate at full speed in this step and can cause serious injury or death.

15. Push  to give the bypass a Run command from HAND Mode.
16. Push  to show S5-05 [HAND Frequency Reference].

17. Push  to increase the frequency reference value.


Change the setting value in increments of 10 Hz if necessary and examine the response.

Each time you increase the setting value, use *U1-03 [Output Current]* to check the drive output current. Watch and listen for unusual conditions or noises.

When the output current of the drive is not more than the motor rated current, the status is correct.




Example: 6 Hz → 20 Hz → 30 Hz → 40 Hz → 50 Hz → 60 Hz



| | | | |
|---------------------|------|--------|------|
| 10:00 am | FWD | Rdy | Home |
| Freq Reference (AI) | | | |
| U1-01 | Hz | 60.00 | |
| Output Frequency | | | |
| U1-02 | Hz | 60.00 | |
| Output Current | | | |
| U1-03 | A | 29.48 | |
| DRIVE | Menu | BYPASS | |

18. Set the HAND frequency reference back to the desired value, then push . The Drive Mode test run and rotation check is complete.


■ Test Run and Rotation Check - Bypass Mode (HAND)


Before you do this procedure, Yaskawa strongly recommends that you do the items in *Start-up, Test Operation, and Rotation Check on page 75* (including the Setup Wizard), and do the steps in *Test Run and Rotation Check - Drive Mode (HAND) on page 77*.



- Energize the bypass. If the HOME screen is not shown, push .
- Push  to make sure that the bypass does not respond to an Auto-Run command.
- Check the lower-right corner of the keypad screen to make sure that the bypass is in Bypass Mode. "BYPASS" will flash when the bypass is in Bypass Mode. If it is NOT in Bypass Mode, push  to put the system into Bypass Mode

| | | | |
|--|-------|---|------|
| 10:00 am | FWD | Rdy | Home |
|  Idle | | | |
| Motor Current | | | |
| Ub-01 | 0.00A | | |
| DRIVE | Menu |  | |

WARNING! Sudden Movement Hazard. Before you do the next step, remove all personnel and objects from the area around the bypass and motor. The motor will immediately rotate at full speed in the next step and can cause serious injury or death.

- Push  to give the bypass a Run command from HAND Mode. Make sure that *Ub-01 [Motor Current]* is not more than the nameplate FLA. It is normal for the current be more than full load amps temporarily at start. Watch and listen for unusual conditions or noises.

| | | | |
|---|--------|--------|------|
| 10:00 am | FWD | Rdy | Home |
|  Running in Bypass | | | |
| Motor Current | | | |
| Ub-01 | 29.48A | | |
| DRIVE | Menu | BYPASS | |

- Look at the motor (or load) to make sure that the rotation direction is correct (Bypass Mode). If you cannot determine the rotation direction, push  and watch the motor as it coasts to stop. If the motor direction in Bypass Mode is **CORRECT**, the test is complete. If the motor direction in Bypass Mode is **INCORRECT**, do steps 6 to 11.
- Push  to stop the motor.
- De-energize the system at the power source. Observe correct lockout/tagout safety procedures and wait for the CHARGE light to completely go out on the HV600. The CHARGE light will be visible after you open the cabinet door.

4.3 Start-up, Test Operation, and Rotation Check

8. Remove lower cover (or open cabinet door) to access motor wiring.
9. Switch any two phases on the **customer connection side of incoming power**.

Note:

- DO NOT change the motor (output) wiring.
- DO NOT change the wiring connected directly to the HV600 drive unit.

10. Replace lower cover (or close cabinet door).
11. Repeat Steps 1 to 5 of this procedure to confirm correct rotation in Bypass Mode.

4.4 Auto-Tuning

Auto-Tuning uses motor characteristics to automatically set parameters. Think about the type of motor and the motor installation environment and select the best Auto-Tuning method.

The keypad will show the messages with prompts to input the necessary parameter information.

◆ Auto-Tuning for Induction Motors

This section gives information about Auto-Tuning for induction motors. Auto-Tuning sets motor parameters *E1-xx*, *E2-xx*.

Note:

Do Stationary Auto-Tuning if you cannot do Rotational Auto-Tuning. There can be large differences between the measured results and the motor characteristics when Auto-Tuning is complete. Examine the parameters for the measured motor characteristics after you do Stationary Auto-Tuning.

Table 4.5 Types of Auto-Tuning for Induction Motors

| Mode | Application Conditions and Benefits |
|-------------------------|---|
| Rotational Auto-Tuning | <ul style="list-style-type: none"> When you can decouple the motor and load the motor can rotate freely while Auto-Tuning. When operating motors that have fixed output characteristics. When it is necessary to use motors that have high-precision control. When you cannot decouple the motor and load, but the motor load is less than 30%. |
| Line-to-Line Resistance | <ul style="list-style-type: none"> After Auto-Tuning, the wiring distance between the drive and motor changed by 50 m or more. When the wiring distance is 50 m or more in the V/f Control mode. When the motor output and drive capacity are different. |

■ Input Data for Induction Motor Auto-Tuning

To do Auto-Tuning, input data for the items in [Table 4.6](#) that have an "x". Before starting Auto-Tuning, prepare the motor test report or record the information on the motor nameplate as a reference.

Table 4.6 Input Data for Induction Motor Auto-Tuning

| Input Data | Unit | Auto-Tuning Mode | |
|-----------------------|--------------------------|------------------------|-------------------------|
| | | Rotational Auto-Tuning | Line-to-Line Resistance |
| Motor Rated Power | HP | x | x |
| Motor Rated Voltage | V | x | - |
| Motor Rated Current | A | x | x |
| Motor Base Frequency | Hz | x | - |
| Number of Motor Poles | - | x | - |
| Motor Base Speed | RPM (min ⁻¹) | x | - |
| Motor Iron Loss | W | x | - |

◆ Precautions before Auto-Tuning

Examine the topics in this section before you start Auto-Tuning.

■ Prepare for Basic Auto-Tuning


- You must input data from the motor nameplate or motor test report to do Auto-Tuning. Make sure that this data is available before Auto-Tuning.
- For best performance, make sure that the input supply voltage is equal to or more than the motor rated voltage.
- Push  on the keypad to cancel Auto-Tuning.
- [Table 4.7](#) shows the status of input/output terminals during Auto-Tuning.

Table 4.7 Status of Drive Unit Input/Output Terminals during Auto-Tuning

| Auto-Tuning Type | Mode | | Multi-Function Inputs | Multi-Function Outputs ^{*1} |
|-----------------------------|------------|-------------------------|-----------------------|---|
| Induction Motor Auto-Tuning | Rotational | Rotational Auto-Tuning | Disabled | Functions the same as during usual operation. |
| | Stationary | Line-to-Line Resistance | Disabled | Keeps the status at the start of Auto-Tuning. |

*1 A terminal to which H2-xx = E [MFDO Function Selection = Fault] is assigned functions the same as during usual operation.

WARNING! Sudden Movement Hazard. Before you do Rotational Auto-Tuning, disconnect the load from the motor. The load can move suddenly and cause serious injury or death.

WARNING! Injury to Personnel. Rotational Auto-Tuning rotates the motor at 50% or more of the motor rated frequency. Make sure that there are no issues related to safety in the area around the drive and motor. Increased motor frequency can cause serious injury or death.

WARNING! Electrical Shock Hazard. During Auto-Tuning, the motor will receive high voltage when the motor is stopped. Do not touch the motor until Auto-Tuning is complete. If you touch a motor that is energized, it can cause serious injury or death.

■ Precautions before Rotational Auto-Tuning

WARNING! Electrical Shock Hazard. During Auto-Tuning, the motor will receive high voltage when the motor is stopped. Do not touch the motor until Auto-Tuning is complete. If you touch a motor that is energized, it can cause serious injury or death.

- Before you do Rotational Auto-Tuning, to prevent drive malfunction, uncouple the motor from the load. If you do Rotational Auto-Tuning with the motor connected to a load that is more than 30% of the motor duty rating, the bypass will not correctly calculate the motor parameters and the motor can operate incorrectly.
- When the load is 30% or less of the motor duty rating, you can do Auto-Tuning with the motor connected to a load.
- Make sure that external force from the machine will not cause the motor to rotate.

■ Precautions before Stationary Auto-Tuning

- Make sure that external force from the machine will not cause the motor to rotate.

WARNING! Electrical Shock Hazard. During Auto-Tuning, the motor will receive high voltage when the motor is stopped. Do not touch the motor until Auto-Tuning is complete. If you touch a motor that is energized, it can cause serious injury or death.

■ Precautions before Stationary Auto-Tuning for Line-to-Line Resistance and Stator Resistance Auto-Tuning

In V/f control, when the motor cable is 50 meters (164 feet) or longer, do Stationary Auto-Tuning for Line-to-Line Resistance.

WARNING! Electrical Shock Hazard. During Auto-Tuning, the motor will receive high voltage when the motor is stopped. Do not touch the motor until Auto-Tuning is complete. If you touch a motor that is energized, it can cause serious injury or death.

4.5 Fine Tuning during Test Runs (Adjust the Control Function)

This section gives information about the adjustment procedures to stop hunting or oscillation errors caused by control function during a test run. Adjust the applicable parameters as specified by your status.

Note:

This section only lists frequently adjusted parameters. If you must adjust parameters that have a higher degree of precision, contact Yaskawa.

◆ V/f Control

Table 4.8 Parameters for Fine Tuning the Drive (V/f)

| Issue | Parameter Number | Possible Solutions | Default | Recommended Setting |
|---|---|---|---|----------------------------|
| Hunting or oscillation at mid-range speeds (10 Hz to 40 Hz) | n1-02 [Hunting Prevention Gain Setting] | <ul style="list-style-type: none"> If torque is not sufficient with heavy loads, decrease the setting value. If hunting or oscillation occur with light loads, increase the setting value. If hunting occurs with a low-inductance motor, for example a motor with a larger frame size or a high-frequency motor, lower the setting value. | 1.00 | 0.10 - 2.00 |
| <ul style="list-style-type: none"> The volume of the motor excitation sound is too high. Hunting or oscillation at low speeds (10 Hz or lower), or at mid-range speeds (10 Hz to 40 Hz) | C6-02 [Carrier Frequency Selection] | <ul style="list-style-type: none"> If the volume of the motor excitation sound is too high, increase the carrier frequency. If hunting or oscillation occur at low or mid-range speeds, decrease the carrier frequency. | 1 (2 kHz) *1 | 1 to upper limit value |
| <ul style="list-style-type: none"> Unsatisfactory motor torque and speed response Hunting or oscillation | C4-02 [Torque Compensation Delay Time] | <ul style="list-style-type: none"> If torque or speed response are slow, decrease the setting value. If hunting or oscillation occur, increase the setting value. | 200 ms *1 | 100 - 1000 ms |
| <ul style="list-style-type: none"> Torque at low speeds (10 Hz or lower) is not sufficient. Hunting or oscillation | C4-01 [Torque Compensation Gain] | <ul style="list-style-type: none"> If torque at low speeds (10 Hz or lower) is not sufficient, increase the setting value. If hunting or oscillation occur with light loads, decrease the setting value. | 1.00 | 0.50 - 1.50 |
| <ul style="list-style-type: none"> Torque at low speeds (10 Hz or lower) is not sufficient. Large initial vibration at start up. | <ul style="list-style-type: none"> E1-08 [Mid Point A Voltage] E1-10 [Minimum Output Voltage] | <ul style="list-style-type: none"> If torque at low speeds (10 Hz or lower) is not sufficient, increase the setting value. If there is large initial vibration at start up, decrease the setting value | <ul style="list-style-type: none"> E1-08: 15.0 V *2 E1-10: 9.0 V *2 | Default setting +/- 5 V *3 |
| Speed precision is unsatisfactory. (V/f Control) | C3-01 [Slip Compensation Gain] | Set E2-01 [Motor Rated Current], E2-02 [Motor Rated Slip], and E2-03 [Motor No-Load Current], then adjust C3-01. | 0.0 (no slip compensation) | 0.5 - 1.5 |

*1 The default setting changes when the setting for o2-04 [Drive Model (KVA) Selection] changes.

*2 The default setting changes when the setting for E1-03 [V/f Pattern Selection] changes.

*3 Recommended settings are for 208/240 V. Multiply the voltage by 2 for 480 V.

Troubleshooting

| | | |
|-------------|---|------------|
| 5.1 | Section Safety | 86 |
| 5.2 | Types of Faults, Minor Faults, Alarms, and Errors | 88 |
| 5.3 | Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically..... | 89 |
| 5.4 | Faults, Minor Faults, Alarms, and Error Codes Listed by Decimal Value for Use with BACnet/Modbus | 96 |
| 5.5 | Faults | 102 |
| 5.6 | Minor Faults/Alarms | 126 |
| 5.7 | Parameter Setting Errors..... | 139 |
| 5.8 | Auto-Tuning Errors | 142 |
| 5.9 | Backup Function Operating Mode Display and Errors..... | 145 |
| 5.10 | Bypass Status Messages | 146 |
| 5.11 | Diagnosing and Resetting Faults..... | 147 |

5.1 Section Safety

DANGER

Electrical Shock Hazard

Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe.

If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

WARNING

Electrical Shock Hazard

Do not operate the bypass when covers are missing. Replace covers and shields before you operate the bypass. Use the bypass only as specified by the instructions.

Some figures in this section include bypasses without covers or safety shields to more clearly show the inside of the bypass. If covers or safety shields are missing from the bypass, it can cause serious injury or death.

Always ground the motor-side grounding terminal.

If you do not ground the equipment correctly, it can cause serious injury or death if you touch the motor case.

After the bypass blows a fuse or trips a GFCI, do not immediately energize the bypass or operate peripheral devices. Wait for the time specified on the warning label at a minimum and make sure that all indicators are OFF. Then check the wiring and peripheral device ratings to find the cause of the problem. If you do not know the cause of the problem, contact Yaskawa before you energize the bypass or peripheral devices.

If you do not fix the problem before you operate the bypass or peripheral devices, it can cause serious injury or death.

Only let approved personnel install, wire, maintain, examine, replace parts, and repair the bypass.

If personnel are not approved, it can cause serious injury or death.

Do not wear loose clothing or jewelry when you do work on the bypass. Tighten loose clothing and remove all metal objects, for example watches or rings.

Loose clothing can catch on the bypass and jewelry can conduct electricity and cause serious injury or death.

Do not remove covers or touch circuit boards while the bypass is energized.

If you touch the internal components of an energized bypass, it can cause serious injury or death.

Do not modify the bypass body, drive body, bypass circuitry, or drive circuitry.

Modifications to bypass and drive body and circuitry can cause serious injury or death, will cause damage to the bypass and drive, and will void the warranty. Yaskawa is not responsible for modifications of the product made by the user.

Fire Hazard

Tighten all terminal screws to the correct tightening torque.

Connections that are too loose or too tight can cause incorrect operation and damage to the bypass. Incorrect connections can also cause death or serious injury from fire.

Tighten screws at an angle in the specified range shown in this manual.

If you tighten the screws at an angle not in the specified range, you can have loose connections that can cause damage to the terminal block or start a fire and cause serious injury or death.

⚠ WARNING**Damage to Equipment**

Do not apply incorrect voltage to the main circuit of the bypass. Operate the bypass in the specified range of the input voltage on the nameplate.

Voltages that are higher than the permitted nameplate tolerance can cause damage to the bypass.

Fire Hazard

Do not put flammable or combustible materials on top of the bypass and do not install the bypass near flammable or combustible materials. Attach the bypass to metal or other noncombustible material.

Flammable and combustible materials can start a fire and cause serious injury or death.

Crush Hazard

Wear eye protection when you do work on the bypass.

If you do not use correct safety equipment, it can cause serious injury or death.

Use a crane or hoist to move large bypasses when necessary.

If you try to move a large bypass without a crane or hoist, it can cause serious injury or death.

NOTICE**Damage to Equipment**

When you touch the bypass, drive, and circuit boards, make sure that you observe correct electrostatic discharge (ESD) procedures.

If you do not follow procedures, it can cause ESD damage to the drive and bypass circuitry.

Do not break the electrical connection between the bypass and the motor when the bypass is outputting voltage.

Incorrect equipment sequencing can cause damage to the bypass.

Make sure that all connections are correct after you install the bypass and connect peripheral devices.

Incorrect connections can cause damage to the bypass.

Note:

Do not use unshielded wire for control wiring. Use shielded, twisted-pair wires and ground the shield to the ground terminal of the bypass. Unshielded wire can cause electrical interference and unsatisfactory system performance.

5.2 Types of Faults, Minor Faults, Alarms, and Errors

If the bypass or motor do not operate correctly, check the keypad for a code or message.




If problems occur that are not identified in this manual, contact the nearest Yaskawa representative with this information:

- Bypass model
- Bypass software version
- Date of purchase
- Description of the problem (such as failure conditions)

Table 5.1 contains descriptions of the different types of faults, minor faults, alarms, and errors that can occur during operation.

Contact Yaskawa if there is damage to the bypass. Contact information is on the back cover of the manual.

Table 5.1 Types of Faults, Minor Faults, Alarms, and Errors

| Type | Response |
|----------------------|---|
| Faults | <p>Drive faults thrown by the HV600 drive will stop the bypass from running the drive, but will not stop it from running in Bypass Mode.</p> <p>If $Z1-05 = 1$ [Auto Transfer To Bypass = Enabled], a drive fault will cause the unit to start running in Bypass Mode.</p> <p>System faults (FB0x) will stop the drive and also stop the bypass from running in Bypass Mode.</p> <p>When the bypass detects a fault, it will cause these conditions:</p> <ul style="list-style-type: none"> • The keypad shows the fault code and  and ALM/ERR of the LED Status Ring illuminate continuously. • The keypad shows the fault code and  and ALM/ERR on the LED Status Ring illuminate continuously when $o2-24 = 0$ or 1 [LED Light Function Selection = Enable Status Ring & Keypad LED or LED Status Ring Disable]. • The bypass shuts off output, and the motor coasts to a stop. Some faults let the user select a motor stopping method. • On the bypass control board (A2), fault output contacts TB1-11 and TB1-12 will turn ON, and TB1-10 and TB1-11 will turn OFF. This requires that $Z2-26 = 15$ [Digital Output 10 (TB110-12) = Fault Active], which is the default setting. <p>The bypass will not operate until you clear the fault with a Fault Reset and the bypass goes back to usual status.</p> |
| Minor Faults/Alarms | <p>When the bypass detects a minor fault or an alarm, it will cause these conditions:</p> <ul style="list-style-type: none"> • The keypad shows the alarm code and  and ALM/ERR on the LED Status Ring flash when $o2-24 = 0$ or 1. • The bypass will continue to operate the motor. Some alarms let the user select a motor stopping method. • If the bypass detects a minor fault, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Select = Alarm] will switch ON. If you do not set parameters $H2-01$ to $H2-03$, the bypass will not trigger MFDO terminals when it detects a minor fault. • The bypass will not output a minor fault signal when it detects an alarm. <p>It is not necessary to do Fault Reset.</p> |
| Operation Errors | <p>An error occurs when parameter settings do not agree or a parameter combination is incorrect. The bypass will not operate until you set the parameters correctly.</p> <p>When the bypass detects an operation error, these conditions will result:</p> <ul style="list-style-type: none"> • The keypad shows the error code. • Multi-function outputs do not output an alarm signal. <p>Find the parameters that caused the error and correct the settings.</p> |
| Auto-Tuning Errors | <p>An error occurs during Auto-Tuning.</p> <p>When the bypass detects a tuning error, it will cause these conditions:</p> <ul style="list-style-type: none"> • The keypad shows the error code. • Multi-function outputs do not output an alarm signal. • The motor coasts to stop. <p>Remove the cause of the error and do Auto-Tuning again.</p> |
| Copy Function Errors | <p>An error occurs when you use the keypad for a backup, restore, or verify operation.</p> <p>When the bypass detects a copy function error, it will cause these conditions:</p> <ul style="list-style-type: none"> • The keypad shows the error code. • Multi-function outputs do not output an alarm signal. <p>Push a key on the keypad to clear the error. Remove the cause of the error and try the backup, restore, or verify operation again.</p> |

5.3 Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically

Table 5.2 shows the possible fault, minor fault, alarm, and error codes.

The display codes are in alphabetical order. Search the table for the code shown on the keypad, and identify its causes and possible solutions.

Drive Faults thrown by the HV600 drive will stop the bypass from running the drive but will not stop it from running in Bypass Mode.

System Faults will stop the drive and also keep it from running in Bypass Mode.

Note:

The number in parentheses adjacent to the code in the table identifies the fault code or minor fault code (hex. number) that was read during serial communications.

Example: AFBL (00A2)

Table 5.2 List of Fault, Minor Fault, Alarm, and Error Codes

| Display (Hex.) | Name | ALM LED | Type | Ref. |
|----------------|----------------------------------|-------------|---------------|------|
| AFBL (00A2) | Analog Fbk Lost, Switched to Net | Flashing | Alarm | 126 |
| AL02 (00B2) | Interlock Open | Flashing | Alarm | 126 |
| AL03 (00B3) | Emergency Override Bypass | Flashing | Alarm | 126 |
| AL09 (00B9) | Restart Delay Active | Flashing | Alarm | 126 |
| AL13 (00BD) | Loss of Load Detected | Flashing | Alarm | 126 |
| AL16 (00C0) | Input Phase Rotation | Flashing | Alarm | 126 |
| AL17 (00C1) | Remote Xfer disabled in Reverse | Flashing | Alarm | 126 |
| AL18 (00C2) | Auto Xfer disabled in Reverse | Flashing | Alarm | 126 |
| AuDis (00A3) | Low PI Aux Fdbk Drive Disabled | Flashing | Alarm | 126 |
| AuFbl (00A5) | PI Aux Fdbk Lost Switched to Net | Flashing | Alarm | 126 |
| AUXFB (00A4) | PI Aux Feedback Level Loss | Flashing | Alarm | 126 |
| AUXFB (0420) | PI Aux Feedback Level Loss | Illuminated | Drive Fault | 102 |
| bAT (0085) | Keypad Battery Low Voltage | Flashing | Alarm | 127 |
| bAT (0402) | Keypad Battery Low Voltage | Illuminated | Drive Fault | 102 |
| bb (0008) | Baseblock | Flashing | Alarm | 127 |
| bCE (0416) | Bluetooth Communication Fault | Illuminated | Drive Fault | 102 |
| bCE (008A) | Bluetooth Communication Error | Flashing | Alarm | 127 |
| BuDif (00A6) | Main Fdbk Lost, Using Diff Fdbk | Flashing | Alarm | 127 |
| Bu-Fb (0090) | Main Fdbk Lost Using Backup Fdbk | Flashing | Alarm | 127 |
| BuFbl (0091) | Backup Fdbk Lost Chk/Repl Xducer | Flashing | Alarm | 127 |
| bUS (0015) | Option Communication Error | Flashing | Alarm | 127 |
| bUS (0022) | Option Communication Error | Illuminated | Drive Fault | 102 |
| bUSy | Busy | - | Not an alarm. | 128 |
| CALL (001D) | Serial Comm Transmission Error | Flashing | Alarm | 128 |
| CE (0092) | Run at H5-34 (CE Go-To-Freq) | Flashing | Alarm | 129 |
| CE (0014) | Serial Communication Error | Flashing | Alarm | 128 |
| CE (0021) | Serial Communication Error | Illuminated | Drive Fault | 102 |
| CoF (0046) | Current Offset Fault | Illuminated | Drive Fault | 103 |
| CPF00 (0081) | Control Circuit Error | Illuminated | Drive Fault | 103 |
| CPF01 (0082) | Control Circuit Error | Illuminated | Drive Fault | 103 |

5.3 Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically

| Display (Hex.) | Name | ALM LED | Type | Ref. |
|----------------|---------------------------------|-------------|-------------------------------|------|
| CPF02 (0083) | A/D Conversion Error | Illuminated | Drive Fault | 103 |
| CPF03 (0084) | Control Board Connection Error | Illuminated | Drive Fault | 103 |
| CPF06 (0087) | EEPROM Memory Data Error | Illuminated | Drive Fault | 104 |
| CPF07 (0088) | Terminal Board Connection Error | Illuminated | Drive Fault | 104 |
| CPF08 (0089) | Terminal Board Connection Error | Illuminated | Drive Fault | 104 |
| CPF11 (008C) | RAM Fault | Illuminated | Drive Fault | 104 |
| CPF12 (008D) | FLASH Memory Fault | Illuminated | Drive Fault | 104 |
| CPF13 (008E) | Watchdog Circuit Exception | Illuminated | Drive Fault | 104 |
| CPF14 (008F) | Control Circuit Fault | Illuminated | Drive Fault | 104 |
| CPF16 (0091) | Clock Fault | Illuminated | Drive Fault | 105 |
| CPF17 (0092) | Timing Fault | Illuminated | Drive Fault | 105 |
| CPF18 (0093) | Control Circuit Fault | Illuminated | Drive Fault | 105 |
| CPF19 (0094) | Control Circuit Fault | Illuminated | Drive Fault | 105 |
| CPF20 (0095) | Control Circuit Error | Illuminated | Drive Fault | 105 |
| CPF21 (0096) | Control Circuit Error | Illuminated | Drive Fault | 105 |
| CPF22 (0097) | Hybrid IC Error | Illuminated | Drive Fault | 105 |
| CPF23 (0098) | Control Board Connection Error | Illuminated | Drive Fault | 105 |
| CPF24 (0099) | Drive Unit Signal Fault | Illuminated | Drive Fault | 106 |
| CPF26 (009B) | BB Circuit Error | Illuminated | Drive Fault | 106 |
| CPF27 (009C) | PWM Set Reg Error | Illuminated | Drive Fault | 106 |
| CPF28 (009D) | PWM Pattern Error | Illuminated | Drive Fault | 106 |
| CPF29 (009E) | On-Delay Error | Illuminated | Drive Fault | 106 |
| CPF30 (009F) | BB On Error | Illuminated | Drive Fault | 106 |
| CPF31 (00A0) | ASIC Code Error | Illuminated | Drive Fault | 106 |
| CPF32 (00A1) | ASIC Startup Error | Illuminated | Drive Fault | 106 |
| CPF33 (00A2) | Watch-dog Error | Illuminated | Drive Fault | 107 |
| CPF34 (00A3) | Power/Clock Error | Illuminated | Drive Fault | 107 |
| CPF35 (00A4) | Ext A/D Conv Error | Illuminated | Drive Fault | 107 |
| CPF36 (00A5) | ASIC COM Error | Illuminated | Drive Fault | 107 |
| CPF37 (00A6) | ASIC COM Error | Illuminated | Drive Fault | 107 |
| CPF38 (00A7) | EEPROM Data Error | Illuminated | Drive Fault | 107 |
| CPF39 (00A8) | CPU-ASIC Communication Error | Illuminated | Drive Fault | 107 |
| CPyE | Error Writing Data | - | Backup Function Runtime Error | 145 |
| CrST | Cannot Reset | Flashing | Not an alarm. | 129 |
| CSEr | Control Mode Mismatch | - | Backup Function Runtime Error | 145 |
| CyPo (0029) | Cycle Power to Accept Changes | Flashing | Alarm | 129 |
| dFPS | Drive Model Mismatch | - | Backup Function Runtime Error | 145 |
| DIFF (0093) | Differential Feedback Exceeded | Flashing | Alarm | 129 |
| DIFF (0421) | Differential Feedback Exceeded | Illuminated | Drive Fault | 108 |
| dnE (002A) | Drive Disabled | Flashing | Alarm | 129 |
| dv7 (005B) | Polarity Judge Timeout | Illuminated | Drive Fault | 108 |
| EF (0007) | FWD/REV Run Command Input Error | Flashing | Alarm | 130 |
| EF0 (001A) | Option Card External Fault | Flashing | Alarm | 130 |

5.3 Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically

| Display (Hex.) | Name | ALM LED | Type | Ref. |
|----------------|----------------------------------|-------------|----------------------|------|
| EF0 (0027) | Option Card External Fault | Illuminated | Drive Fault | 108 |
| EF1 (0039) | External Fault (Terminal S1) | Flashing | Alarm | 130 |
| EF1 (0042) | External Fault (Terminal S1) | Illuminated | Drive Fault | 108 |
| EF2 (003A) | External Fault (Terminal S2) | Flashing | Alarm | 130 |
| EF2 (0043) | External Fault (Terminal S2) | Illuminated | Drive Fault | 108 |
| EF3 (0009) | External Fault (Terminal S3) | Flashing | Alarm | 130 |
| EF3 (0011) | External Fault (Terminal S3) | Illuminated | Drive Fault | 108 |
| EF4 (000A) | External Fault (Terminal S4) | Flashing | Alarm | 130 |
| EF4 (0012) | External Fault (Terminal S4) | Illuminated | Drive Fault | 109 |
| EF5 (000B) | External Fault (Terminal S5) | Flashing | Alarm | 130 |
| EF5 (0013) | External Fault (Terminal S5) | Illuminated | Drive Fault | 109 |
| EF6 (000C) | External Fault (Terminal S6) | Flashing | Alarm | 130 |
| EF6 (0014) | External Fault (Terminal S6) | Illuminated | Drive Fault | 109 |
| EF7 (000D) | External Fault (Terminal S7) | Flashing | Alarm | 131 |
| EF7 (0015) | External Fault (Terminal S7) | Illuminated | Drive Fault | 109 |
| End1 | Excessive Rated Voltage Setting | Flashing | An Auto-Tuning Error | 142 |
| End2 | Iron Core Saturation Coefficient | Flashing | An Auto-Tuning Error | 142 |
| End3 | Rated Current Setting Alarm | Flashing | An Auto-Tuning Error | 142 |
| End4 | Adjusted Slip Calculation Error | Flashing | An Auto-Tuning Error | 142 |
| End5 | Resistance Tuning Error | Flashing | An Auto-Tuning Error | 142 |
| End6 | Leakage Inductance Alarm | Flashing | An Auto-Tuning Error | 142 |
| End7 | No-Load Current Alarm | Flashing | An Auto-Tuning Error | 142 |
| EOF (0067) | Emergency Override FWD | Flashing | Alarm | 131 |
| EOR (0068) | Emergency Override REV | Flashing | Alarm | 131 |
| EP24v (0081) | External Power 24V Supply | Flashing | Alarm | 131 |
| Er-01 | Motor Data Error | Flashing | An Auto-Tuning Error | 142 |
| Er-02 | Drive in an Alarm State | Flashing | An Auto-Tuning Error | 143 |
| Er-03 | STOP Button was Pressed | Flashing | An Auto-Tuning Error | 143 |
| Er-04 | Line-to-Line Resistance Error | Flashing | An Auto-Tuning Error | 143 |
| Er-05 | No-Load Current Error | Flashing | An Auto-Tuning Error | 143 |
| Er-08 | Rated Slip Error | Flashing | An Auto-Tuning Error | 143 |
| Er-09 | Acceleration Error | Flashing | An Auto-Tuning Error | 144 |
| Er-12 | Current Detection Error | Flashing | An Auto-Tuning Error | 144 |
| Er-13 | Leakage Inductance Error | Flashing | An Auto-Tuning Error | 144 |
| Er-18 | Back EMF Error | Flashing | An Auto-Tuning Error | 144 |
| Er-25 | HighFreq Inject Param Tuning Err | Flashing | An Auto-Tuning Error | 144 |
| Err (001F) | EEPROM Write Error | Illuminated | Drive Fault | 109 |
| FAn1 (0413) | Drive Cooling Fan Fault | Illuminated | Drive Fault | 109 |
| FB02 (043A) | Wait For Interlock Timeout | Illuminated | System Fault | 110 |
| FB03 (043B) | External Fault Bypass (EFB) | Illuminated | System Fault | 110 |
| FB05 (043D) | Motor Overload | Illuminated | System Fault | 110 |
| FB06 (043E) | External Overload 1 | Illuminated | System Fault | 111 |
| FB07 (043F) | External Overload 2 | Illuminated | System Fault | 111 |

5.3 Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically

| Display (Hex.) | Name | ALM LED | Type | Ref. |
|-----------------|----------------------------------|-------------|-------------------------------|------|
| FB08 (0440) | Brownout Detected | Illuminated | System Fault | 111 |
| FB09 (0441) | Blackout Detected | Illuminated | System Fault | 111 |
| FB10 (0442) | Loss of Drive Communications | Illuminated | Drive Fault | 111 |
| FB13 (0445) | Loss of Load | Illuminated | System Fault | 111 |
| FB15 (0447) | Input Phase Loss | Illuminated | System Fault | 112 |
| FB16 (0448) | Input Phase Rotation | Illuminated | System Fault | 112 |
| FB17 (0449) | Load Verify Fault | Illuminated | System Fault | 112 |
| FB18 (044A) | Welded Bypass Contactor Detected | Illuminated | System Fault | 112 |
| FB26 (0452) | Option on Drive Detected | Illuminated | Drive Fault | 112 |
| FB27 (0453) | Drive Hardware Fault (CPFx ofX) | Illuminated | Drive Fault | 112 |
| FB28 (0454) | Drive Faulted | Illuminated | System Fault | 112 |
| FB30 (0456) | Conflicting SW Check UB-99 | Illuminated | Drive Fault | 113 |
| FDBKL (0094) | Feedback Loss Wire Break | Flashing | Alarm | 131 |
| FDBKL (0422) | WIRE Break | Illuminated | Drive Fault | 113 |
| FIRE_ST (00CA) | Fire Stat Open | Flashing | Alarm | 131 |
| FREEZ_ST (00CB) | Freeze Stat Open | Flashing | Alarm | 132 |
| FLGT (0095) | Feedback Loss, Go To Freq b5-83 | Flashing | Alarm | 131 |
| FR<MS (009E) | Freq Ref < Minimum Speed (Y1-06) | Flashing | Alarm | 132 |
| FR<TH (009F) | Freq. Reference < Thrust (Y4-12) | Flashing | Alarm | 132 |
| GF (0006) | Ground Fault | Illuminated | Drive Fault | 113 |
| HCA (0034) | High Current Alarm | Flashing | Alarm | 132 |
| HFB (0423) | High Feedback Sensed | Illuminated | Drive Fault | 114 |
| HIAUX (0096) | High PI Aux Feedback Level | Flashing | Alarm | 132 |
| HIAUX (0424) | High PI Aux Feedback Level | Illuminated | Drive Fault | 114 |
| HIFB (0097) | High Feedback Sensed | Flashing | Alarm | 132 |
| iFEr | Communication Err | - | Backup Function Runtime Error | 145 |
| INTLK (0069) | BAS Interlock | Flashing | Alarm | 133 |
| LCP (00A7) | Low City Pressure | Flashing | Alarm | 133 |
| LF (001C) | Output Phase Loss | Illuminated | Drive Fault | 114 |
| LF2 (0036) | Output Current Imbalance | Illuminated | Drive Fault | 114 |
| LFB (0425) | Low Feedback Sensed | Illuminated | Drive Fault | 114 |
| LOAUX (0099) | Low PI Aux Feedback Level | Flashing | Alarm | 133 |
| LOAUX (0426) | Low PI Aux Feedback Level | Illuminated | Drive Fault | 114 |
| LoG | Com Error / Abnormal SD Card | Flashing | Alarm | 133 |
| LOFB (009A) | Low Feedback Sensed | Flashing | Alarm | 133 |
| LOP (009B) | Loss of Prime | Flashing | Alarm | 133 |
| LOP (0427) | Loss of Prime | Illuminated | Drive Fault | 115 |
| LOW_SUCT (00CE) | Low Suction Detected | Flashing | Alarm | 134 |
| LSP (00A8) | Low Suction Pressure | Flashing | Alarm | 134 |
| LT-1 (0035) | Cooling Fan Maintenance Time | Flashing | Alarm | 134 |
| LT-2 (0036) | Capacitor Maintenance Time | Flashing | Alarm | 134 |
| LT-3 (0043) | SoftChargeBypassRelay MainteTime | Flashing | Alarm | 134 |
| LT-4 (0044) | IGBT Maintenance Time (50%) | Flashing | Alarm | 134 |

5.3 Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically

| Display (Hex.) | Name | ALM LED | Type | Ref. |
|----------------|----------------------------------|-------------|-------------------------------|------|
| LWT (00A9) | Low Water In Tank | Flashing | Alarm | 134 |
| ndAT | Model,VolClass,Capacity Mismatch | - | Backup Function Runtime Error | 145 |
| NMS (009C) | Setpoint Not Met | Flashing | Alarm | 134 |
| NMS (0429) | Setpoint Not Met | Illuminated | Drive Fault | 115 |
| oC (0007) | Overcurrent | Illuminated | Drive Fault | 115 |
| OD (009D) | Output Disconnect | Flashing | Alarm | 135 |
| OD (042A) | Output Disconnect | Illuminated | Drive Fault | 116 |
| oFA00 (0101) | Option Not Compatible with Port | Illuminated | Drive Fault | 116 |
| oFA01 (0102) | Option Fault/Connection Error | Illuminated | Drive Fault | 116 |
| oFA05 (0106) | Option A/D Error | Illuminated | Drive Fault | 116 |
| oFA06 (0107) | Option Communication Error | Illuminated | Drive Fault | 116 |
| oFA10 (0111) | Option RAM Error | Illuminated | Drive Fault | 116 |
| oFA11 (0112) | Option Ope Mode Error | Illuminated | Drive Fault | 116 |
| oFA12 (0113) | Drive Receive CRC Error | Illuminated | Drive Fault | 117 |
| oFA13 (0114) | Drive Receive Frame Error | Illuminated | Drive Fault | 117 |
| oFA14 (0115) | Drive Receive Abort Error | Illuminated | Drive Fault | 117 |
| oFA15 (0116) | Option Receive CRC Error | Illuminated | Drive Fault | 117 |
| oFA16 (0117) | Option Receive Frame Error | Illuminated | Drive Fault | 117 |
| oFA17 (0118) | Option Receive Abort Error | Illuminated | Drive Fault | 117 |
| oFA30 (0131) | COM ID Error | Illuminated | Drive Fault | 117 |
| oFA31 (0132) | Type Code Error | Illuminated | Drive Fault | 117 |
| oFA32 (0133) | SUM Check Error | Illuminated | Drive Fault | 118 |
| oFA33 (0134) | Option Receive Time Over | Illuminated | Drive Fault | 118 |
| oFA34 (0135) | Memobus Time Over | Illuminated | Drive Fault | 118 |
| oFA35 (0136) | Drive Receive Time Over 1 | Illuminated | Drive Fault | 118 |
| oFA36 (0137) | CI Check Error | Illuminated | Drive Fault | 118 |
| oFA37 (0138) | Drive Receive Time Over 2 | Illuminated | Drive Fault | 118 |
| oFA38 (0139) | Control Reference Error | Illuminated | Drive Fault | 118 |
| oFA39 (013A) | Drive Receive Time Over 3 | Illuminated | Drive Fault | 118 |
| oFA40 (013B) | CtrlResSel 1Err | Illuminated | Drive Fault | 119 |
| oFA41 (013C) | Drive Receive Time Over 4 | Illuminated | Drive Fault | 119 |
| oFA42 (013D) | CtrlResSel 2Err | Illuminated | Drive Fault | 119 |
| oFA43 (013E) | Drive Receive Time Over 5 | Illuminated | Drive Fault | 119 |
| oH (0003) | Heatsink Overheat | Flashing | Alarm | 135 |
| oH (0009) | Heatsink Overheat | Illuminated | Drive Fault | 119 |
| oH1 (000A) | Heatsink Overheat | Illuminated | Drive Fault | 119 |
| oH2 (0004) | External Overheat (H1-XX=B) | Flashing | Alarm | 135 |
| oH3 (001D) | Motor Overheat (PTC Input) | Illuminated | Drive Fault | 119 |
| oH3 (0022) | Motor Overheat (PTC Input) | Flashing | Alarm | 135 |
| oH4 (0020) | Motor Overheat Fault (PTC Input) | Illuminated | Drive Fault | 120 |
| oL1 (000B) | Motor Overload | Illuminated | Drive Fault | 120 |
| oL2 (000C) | Drive Overload | Illuminated | Drive Fault | 121 |
| oL3 (0005) | Overtorque 1 | Flashing | Alarm | 136 |

5.3 Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically

| Display (Hex.) | Name | ALM LED | Type | Ref. |
|--------------------------|-----------------------------------|-------------|-------------------------------|---------------------|
| oL3 (000D) | Overtorque Detection 1 | Illuminated | Drive Fault | 122 |
| oL4 (0006) | Overtorque 2 | Flashing | Alarm | 136 |
| oL4 (000E) | Overtorque Detection 2 | Illuminated | Drive Fault | 122 |
| oL7 (002B) | High Slip Braking Overload | Illuminated | Drive Fault | 122 |
| oPE01 | Drive Capacity Setting Fault | Flashing | Parameter Setting Error | 139 |
| oPE02 | Parameter Range Setting Error | Flashing | Parameter Setting Error | 139 |
| oPE03 | Multi-Function Input Setting Err | Flashing | Parameter Setting Error | 139 |
| oPE05 | Run Cmd/Freq Ref Source Sel Err | Flashing | Parameter Setting Error | 140 |
| oPE07 | Analog Input Selection Error | Flashing | Parameter Setting Error | 140 |
| oPE08 | Parameter Selection Error | Flashing | Parameter Setting Error | 140 |
| oPE09 | PID Control Selection Fault | Flashing | Parameter Setting Error | 140 |
| oPE10 | V/f Data Setting Error | Flashing | Parameter Setting Error | 140 |
| oPE11 | Carrier Frequency Setting Error | Flashing | Parameter Setting Error | 141 |
| oPE16 | Energy Saving Constants Error | Flashing | Parameter Setting Error | 141 |
| oPE20 | No Motor Overload Set | Flashing | Parameter Setting Error | 141 |
| oPE29 | Baud Rate Setting Error | Flashing | Parameter Setting Error | 141 |
| oPE34 | HAND/OFF/AUTO Input Setting | Flashing | Parameter Setting Error | 141 |
| oPE36 | Bypass Energy Savings Setting Err | Flashing | Parameter Setting Error | 141 |
| oPr (001E) | Keypad Connection Fault | Illuminated | Drive Fault | 122 |
| ov (0002) | DC Bus Overvoltage | Flashing | Alarm | 136 |
| ov (0008) | Overvoltage | Illuminated | Drive Fault | 122 |
| ov2 (0405) | DC Bus Overvoltage 2 | Illuminated | Drive Fault | 123 |
| ovEr | Too Many Parameters Changed | - | Not an alarm. | 136 |
| OV_PRESS (00CD) | Over Pressure Detected | Flashing | Alarm | 136 |
| PA1 (003F) | PLC Error 1 | Flashing | Alarm | 136 |
| PASS | Serial Communication Test | Flashing | Not an alarm. | 136 |
| PE1 (0047) PE2 (0048) | PLC Faults | Illuminated | Drive Fault | 123 |
| PF (0047) | Input Phase Loss | Flashing | Alarm | 136 |
| PF (001B) | Input Phase Loss | Illuminated | Drive Fault | 123 |
| PSE (0437) | JOHB-SMP3 Protocol set Error | Illuminated | Drive Fault | 123 |
| rdEr | Error Reading Data | - | Backup Function Runtime Error | 145 |
| SAFE (00C9) | Safety Open | Flashing | Alarm | 137 |
| SC (0005) | Short Circuit/IGBT Failure | Illuminated | Drive Fault | 124 |
| SCF (040F) | Safety Circuit Fault | Illuminated | Drive Fault | 124 |
| SE (0020) | Modbus Test Mode Error | Flashing | Alarm | 137 |
| SEr (003B) | Speed Search Retries Exceeded | Illuminated | Drive Fault | 124 |
| SMK_ALARM (00CC) | Smoke Alarm Active | Flashing | Alarm | 137 |
| STo (003C) | Safe Torque OFF | - | Alarm | 137 |
| SToF (003B) | Safe Torque OFF | Flashing | Alarm | 137 |
| TiM (0089) | Keypad Time Not Set | Flashing | Alarm | 137 |
| TiM (0401) | Keypad Time Not Set | Illuminated | Drive Fault | 124 |
| TrPC (0042) | IGBT Maintenance Time (90%) | Flashing | Alarm | 137 |

5.3 Faults, Minor Faults, Alarms, and Error Codes Listed Alphabetically

| Display (Hex.) | Name | ALM LED | Type | Ref. |
|-----------------|----------------------------------|-------------|-------------------------------|---------------------|
| UL3 (001E) | Undertorque Detection 1 | Flashing | Alarm | 138 |
| UL3 (0029) | Undertorque Detection 1 | Illuminated | Drive Fault | 124 |
| UL4 (001F) | Undertorque Detection 2 | Flashing | Alarm | 138 |
| UL4 (002A) | Undertorque Detection 2 | Illuminated | Drive Fault | 124 |
| UL6 (004E) | Underload or Belt Break Detected | Flashing | Alarm | 138 |
| UL6 (005A) | Underload or Belt Break Detected | Illuminated | Drive Fault | 124 |
| Uv (0001) | DC Bus Undervoltage | Flashing | Alarm | 138 |
| Uv1 (0002) | DC Bus Undervoltage | Illuminated | Drive Fault | 125 |
| Uv2 (0003) | Control Power Undervoltage | Illuminated | Drive Fault | 125 |
| Uv3 (0004) | Soft Charge Answerback Fault | Illuminated | Drive Fault | 125 |
| vAEr | Voltage Class, Capacity Mismatch | - | Backup Function Runtime Error | 145 |
| VBRATION (00CF) | Vibration Detected | Flashing | Alarm | 138 |
| vFyE | Parameters do not Match | - | Backup Function Runtime Error | 145 |
| VLTS (042B) | Thermostat Fault | Illuminated | Drive Fault | 125 |

5.4 Faults, Minor Faults, Alarms, and Error Codes Listed by Decimal Value for Use with BACnet/Modbus

Table 5.3 shows the list of faults by decimal number. Faults are read in Modbus register 0080 or BACnet AV42.

Table 5.4 shows the list of minor faults and alarms by decimal number. Minor fault and alarm decimal numbers are read in Modbus register 007F.

The display codes are in decimal order. Search the tables for the decimal code, and identify its causes and possible solutions.

Drive Faults thrown by the HV600 drive will stop the bypass from running the drive but will not stop it from running in Bypass Mode.

System Faults will stop the drive and also stop it from running in Bypass Mode.

Note:

The number in parentheses adjacent to the code in the table identifies the fault code or minor fault code (hex. number) that was read during serial communications.

Example: AFBL (00A2)

Table 5.3 List of Faults by Decimal

| Decimal Value | Display (Hex.) | Name | ALM LED | Type | Ref. |
|---------------|----------------|----------------------------------|-------------|-------------|------|
| 2 | Uv1 (0002) | DC Bus Undervoltage | Illuminated | Drive Fault | 125 |
| 3 | Uv2 (0003) | Control Power Undervoltage | Illuminated | Drive Fault | 125 |
| 4 | Uv3 (0004) | Soft Charge Answerback Fault | Illuminated | Drive Fault | 125 |
| 5 | SC (0005) | Short Circuit/IGBT Failure | Illuminated | Drive Fault | 124 |
| 6 | GF (0006) | Ground Fault | Illuminated | Drive Fault | 113 |
| 7 | oC (0007) | Overcurrent | Illuminated | Drive Fault | 115 |
| 8 | ov (0008) | Overvoltage | Illuminated | Drive Fault | 122 |
| 9 | oH (0009) | Heatsink Overheat | Illuminated | Drive Fault | 119 |
| 10 | oH1 (000A) | Heatsink Overheat | Illuminated | Drive Fault | 119 |
| 11 | oL1 (000B) | Motor Overload | Illuminated | Drive Fault | 120 |
| 12 | oL2 (000C) | Drive Overload | Illuminated | Drive Fault | 121 |
| 13 | oL3 (000D) | Overtorque Detection 1 | Illuminated | Drive Fault | 122 |
| 14 | oL4 (000E) | Overtorque Detection 2 | Illuminated | Drive Fault | 122 |
| 17 | EF3 (0011) | External Fault (Terminal S3) | Illuminated | Drive Fault | 108 |
| 18 | EF4 (0012) | External Fault (Terminal S4) | Illuminated | Drive Fault | 109 |
| 19 | EF5 (0013) | External Fault (Terminal S5) | Illuminated | Drive Fault | 109 |
| 20 | EF6 (0014) | External Fault (Terminal S6) | Illuminated | Drive Fault | 109 |
| 21 | EF7 (0015) | External Fault (Terminal S7) | Illuminated | Drive Fault | 109 |
| 25 | dEv (0019) | Speed Deviation | Illuminated | Drive Fault | 107 |
| 27 | PF (001B) | Input Phase Loss | Illuminated | Drive Fault | 123 |
| 28 | LF (001C) | Output Phase Loss | Illuminated | Drive Fault | 114 |
| 29 | oH3 (001D) | Motor Overheat (PTC Input) | Illuminated | Drive Fault | 119 |
| 30 | oPr (001E) | Keypad Connection Fault | Illuminated | Drive Fault | 122 |
| 31 | Err (001F) | EEPROM Write Error | Illuminated | Drive Fault | 109 |
| 32 | oH4 (0020) | Motor Overheat Fault (PTC Input) | Illuminated | Drive Fault | 120 |
| 33 | CE (0021) | Serial Communication Error | Illuminated | Drive Fault | 102 |
| 34 | bUS (0022) | Option Communication Error | Illuminated | Drive Fault | 102 |
| 39 | EF0 (0027) | Option Card External Fault | Illuminated | Drive Fault | 108 |

5.4 Faults, Minor Faults, Alarms, and Error Codes Listed by Decimal Value for Use with BACnet/Modbus

| Decimal Value | Display (Hex.) | Name | ALM LED | Type | Ref. |
|---------------|----------------|----------------------------------|-------------|-------------|------|
| 41 | UL3 (0029) | Undertorque Detection 1 | Illuminated | Drive Fault | 124 |
| 42 | UL4 (002A) | Undertorque Detection 2 | Illuminated | Drive Fault | 124 |
| 43 | oL7 (002B) | High Slip Braking Overload | Illuminated | Drive Fault | 122 |
| 54 | LF2 (0036) | Output Current Imbalance | Illuminated | Drive Fault | 114 |
| 59 | SEr (003B) | Speed Search Retries Exceeded | Illuminated | Drive Fault | 124 |
| 66 | EF1 (0042) | External Fault (Terminal S1) | Illuminated | Drive Fault | 108 |
| 67 | EF2 (0043) | External Fault (Terminal S2) | Illuminated | Drive Fault | 108 |
| 70 | CoF (0046) | Current Offset Fault | Illuminated | Drive Fault | 103 |
| 71 | PE1 (0047) | PLC Faults | Illuminated | Drive Fault | 123 |
| 72 | PE2 (0048) | PLC Faults | Illuminated | Drive Fault | 123 |
| 90 | UL6 (005A) | Underload or Belt Break Detected | Illuminated | Drive Fault | 124 |
| 91 | dv7 (005B) | Polarity Judge Timeout | Illuminated | Drive Fault | 108 |
| 129 | CPF00 (0081) | Control Circuit Error | Illuminated | Drive Fault | 103 |
| 130 | CPF01 (0082) | Control Circuit Error | Illuminated | Drive Fault | 103 |
| 131 | CPF02 (0083) | A/D Conversion Error | Illuminated | Drive Fault | 103 |
| 132 | CPF03 (0084) | Control Board Connection Error | Illuminated | Drive Fault | 103 |
| 135 | CPF06 (0087) | EEPROM Memory Data Error | Illuminated | Drive Fault | 104 |
| 136 | CPF07 (0088) | Terminal Board Connection Error | Illuminated | Drive Fault | 104 |
| 137 | CPF08 (0089) | Terminal Board Connection Error | Illuminated | Drive Fault | 104 |
| 140 | CPF11 (008C) | RAM Fault | Illuminated | Drive Fault | 104 |
| 141 | CPF12 (008D) | FLASH Memory Fault | Illuminated | Drive Fault | 104 |
| 142 | CPF13 (008E) | Watchdog Circuit Exception | Illuminated | Drive Fault | 104 |
| 143 | CPF14 (008F) | Control Circuit Fault | Illuminated | Drive Fault | 104 |
| 145 | CPF16 (0091) | Clock Fault | Illuminated | Drive Fault | 105 |
| 146 | CPF17 (0092) | Timing Fault | Illuminated | Drive Fault | 105 |
| 147 | CPF18 (0093) | Control Circuit Fault | Illuminated | Drive Fault | 105 |
| 148 | CPF19 (0094) | Control Circuit Fault | Illuminated | Drive Fault | 105 |
| 149 | CPF20 (0095) | Control Circuit Error | Illuminated | Drive Fault | 105 |
| 150 | CPF21 (0096) | Control Circuit Error | Illuminated | Drive Fault | 105 |
| 151 | CPF22 (0097) | Hybrid IC Error | Illuminated | Drive Fault | 105 |
| 152 | CPF23 (0098) | Control Board Connection Error | Illuminated | Drive Fault | 105 |
| 153 | CPF24 (0099) | Drive Unit Signal Fault | Illuminated | Drive Fault | 106 |
| 155 | CPF26 (009B) | BB Circuit Error | Illuminated | Drive Fault | 106 |
| 156 | CPF27 (009C) | PWM Set Reg Error | Illuminated | Drive Fault | 106 |
| 157 | CPF28 (009D) | PWM Pattern Error | Illuminated | Drive Fault | 106 |
| 158 | CPF29 (009E) | On-Delay Error | Illuminated | Drive Fault | 106 |
| 159 | CPF30 (009F) | BB On Error | Illuminated | Drive Fault | 106 |
| 160 | CPF31 (00A0) | ASIC Code Error | Illuminated | Drive Fault | 106 |
| 161 | CPF32 (00A1) | ASIC Startup Error | Illuminated | Drive Fault | 106 |
| 162 | CPF33 (00A2) | Watch-dog Error | Illuminated | Drive Fault | 107 |
| 163 | CPF34 (00A3) | Power/Clock Error | Illuminated | Drive Fault | 107 |
| 164 | CPF35 (00A4) | Ext A/D Conv Error | Illuminated | Drive Fault | 107 |
| 165 | CPF36 (00A5) | ASIC COM Error | Illuminated | Drive Fault | 107 |

5.4 Faults, Minor Faults, Alarms, and Error Codes Listed by Decimal Value for Use with BACnet/Modbus

| Decimal Value | Display (Hex.) | Name | ALM LED | Type | Ref. |
|---------------|----------------|---------------------------------|-------------|-------------|------|
| 166 | CPF37 (00A6) | ASIC COM Error | Illuminated | Drive Fault | 107 |
| 167 | CPF38 (00A7) | EEPROM Data Error | Illuminated | Drive Fault | 107 |
| 168 | CPF39 (00A8) | CPU-ASIC Communication Error | Illuminated | Drive Fault | 107 |
| 257 | oFA00 (0101) | Option Not Compatible with Port | Illuminated | Drive Fault | 116 |
| 258 | oFA01 (0102) | Option Fault/Connection Error | Illuminated | Drive Fault | 116 |
| 262 | oFA05 (0106) | Option A/D Error | Illuminated | Drive Fault | 116 |
| 263 | oFA06 (0107) | Option Communication Error | Illuminated | Drive Fault | 116 |
| 273 | oFA10 (0111) | Option RAM Error | Illuminated | Drive Fault | 116 |
| 274 | oFA11 (0112) | Option Ope Mode Error | Illuminated | Drive Fault | 116 |
| 275 | oFA12 (0113) | Drive Receive CRC Error | Illuminated | Drive Fault | 117 |
| 276 | oFA13 (0114) | Drive Receive Frame Error | Illuminated | Drive Fault | 117 |
| 277 | oFA14 (0115) | Drive Receive Abort Error | Illuminated | Drive Fault | 117 |
| 278 | oFA15 (0116) | Option Receive CRC Error | Illuminated | Drive Fault | 117 |
| 279 | oFA16 (0117) | Option Receive Frame Error | Illuminated | Drive Fault | 117 |
| 280 | oFA17 (0118) | Option Receive Abort Error | Illuminated | Drive Fault | 117 |
| 305 | oFA30 (0131) | COM ID Error | Illuminated | Drive Fault | 117 |
| 306 | oFA31 (0132) | Type Code Error | Illuminated | Drive Fault | 117 |
| 307 | oFA32 (0133) | SUM Check Error | Illuminated | Drive Fault | 118 |
| 308 | oFA33 (0134) | Option Receive Time Over | Illuminated | Drive Fault | 118 |
| 309 | oFA34 (0135) | Memobus Time Over | Illuminated | Drive Fault | 118 |
| 310 | oFA35 (0136) | Drive Receive Time Over 1 | Illuminated | Drive Fault | 118 |
| 311 | oFA36 (0137) | CI Check Error | Illuminated | Drive Fault | 118 |
| 312 | oFA37 (0138) | Drive Receive Time Over 2 | Illuminated | Drive Fault | 118 |
| 313 | oFA38 (0139) | Control Reference Error | Illuminated | Drive Fault | 118 |
| 314 | oFA39 (013A) | Drive Receive Time Over 3 | Illuminated | Drive Fault | 118 |
| 315 | oFA40 (013B) | CtrlResSel 1Err | Illuminated | Drive Fault | 119 |
| 316 | oFA41 (013C) | Drive Receive Time Over 4 | Illuminated | Drive Fault | 119 |
| 317 | oFA42 (013D) | CtrlResSel 2Err | Illuminated | Drive Fault | 119 |
| 318 | oFA43 (013E) | Drive Receive Time Over 5 | Illuminated | Drive Fault | 119 |
| 1025 | TiM (0401) | Keypad Time Not Set | Illuminated | Drive Fault | 124 |
| 1026 | bAT (0402) | Keypad Battery Low Voltage | Illuminated | Drive Fault | 102 |
| 1029 | ov2 (0405) | DC Bus Overvoltage 2 | Illuminated | Drive Fault | 123 |
| 1039 | SCF (040F) | Safety Circuit Fault | Illuminated | Drive Fault | 124 |
| 1043 | FAn1 (0413) | Drive Cooling Fan Fault | Illuminated | Drive Fault | 109 |
| 1046 | bCE (0416) | Bluetooth Communication Fault | Illuminated | Drive Fault | 102 |
| 1056 | AUXFB (0420) | PI Aux Feedback Level Loss | Illuminated | Drive Fault | 102 |
| 1057 | DIFF (0421) | Differential Feedback Exceeded | Illuminated | Drive Fault | 108 |
| 1058 | FDBKL (0422) | WIRE Break | Illuminated | Drive Fault | 113 |
| 1059 | HFB (0423) | High Feedback Sensed | Illuminated | Drive Fault | 114 |
| 1060 | HIAUX (0424) | High PI Aux Feedback Level | Illuminated | Drive Fault | 114 |
| 1061 | LFB (0425) | Low Feedback Sensed | Illuminated | Drive Fault | 114 |
| 1062 | LOAUX (0426) | Low PI Aux Feedback Level | Illuminated | Drive Fault | 114 |
| 1063 | LOP (0427) | Loss of Prime | Illuminated | Drive Fault | 115 |

5.4 Faults, Minor Faults, Alarms, and Error Codes Listed by Decimal Value for Use with BACnet/Modbus

| Decimal Value | Display (Hex.) | Name | ALM LED | Type | Ref. |
|---------------|----------------|----------------------------------|-------------|--------------|------|
| 1065 | NMS (0429) | Setpoint Not Met | Illuminated | Drive Fault | 115 |
| 1066 | OD (042A) | Output Disconnect | Illuminated | Drive Fault | 116 |
| 1067 | VLTS (042B) | Thermostat Fault | Illuminated | Drive Fault | 125 |
| 1079 | PSE (0437) | JOHB-SMP3 Protocol set Error | Illuminated | Drive Fault | 123 |
| 1082 | FB02 (043A) | Wait For Interlock Timeout | Illuminated | System Fault | 110 |
| 1083 | FB03 (043B) | External Fault Bypass (EFB) | Illuminated | System Fault | 110 |
| 1085 | FB05 (043D) | Motor Overload | Illuminated | System Fault | 110 |
| 1086 | FB06 (043E) | External Overload 1 | Illuminated | System Fault | 111 |
| 1087 | FB07 (043F) | External Overload 2 | Illuminated | System Fault | 111 |
| 1088 | FB08 (0440) | Brownout Detected | Illuminated | System Fault | 111 |
| 1089 | FB09 (0441) | Blackout Detected | Illuminated | System Fault | 111 |
| 1090 | FB10 (0442) | Loss of Drive Communications | Illuminated | Drive Fault | 111 |
| 1093 | FB13 (0445) | Loss of Load | Illuminated | System Fault | 111 |
| 1095 | FB15 (0447) | Input Phase Loss | Illuminated | System Fault | 112 |
| 1096 | FB16 (0448) | Input Phase Rotation | Illuminated | System Fault | 112 |
| 1097 | FB17 (0449) | Load Verify Fault | Illuminated | System Fault | 112 |
| 1098 | FB18 (044A) | Welded Bypass Contactor Detected | Illuminated | System Fault | 112 |
| 1106 | FB26 (0452) | Option on Drive Detected | Illuminated | Drive Fault | 112 |
| 1107 | FB27 (0453) | Drive Hardware Fault (CPFx oFx) | Illuminated | Drive Fault | 112 |
| 1108 | FB28 (0454) | Drive Faulted | Illuminated | System Fault | 112 |
| 1110 | FB30 (0456) | Conflicting SW Check UB-99 | Illuminated | Drive Fault | 113 |

Table 5.4 List of Minor Faults and Alarms by Decimal

Minor fault and alarm decimal numbers are read in Modbus register 007F.

| Decimal Value | Display (Hex.) | Name | ALM LED | Type | Ref. |
|---------------|----------------|---------------------------------|----------|-------|------|
| 1 | Uv (0001) | DC Bus Undervoltage | Flashing | Alarm | 138 |
| 2 | ov (0002) | DC Bus Overvoltage | Flashing | Alarm | 136 |
| 3 | oH (0003) | Heatsink Overheat | Flashing | Alarm | 135 |
| 4 | oH2 (0004) | External Overheat (H1-XX=B) | Flashing | Alarm | 135 |
| 5 | oL3 (0005) | Overtorque 1 | Flashing | Alarm | 136 |
| 6 | oL4 (0006) | Overtorque 2 | Flashing | Alarm | 136 |
| 7 | EF (0007) | FWD/REV Run Command Input Error | Flashing | Alarm | 130 |
| 8 | bb (0008) | Baseblock | Flashing | Alarm | 127 |
| 9 | EF3 (0009) | External Fault (Terminal S3) | Flashing | Alarm | 130 |
| 10 | EF4 (000A) | External Fault (Terminal S4) | Flashing | Alarm | 130 |
| 11 | EF5 (000B) | External Fault (Terminal S5) | Flashing | Alarm | 130 |
| 12 | EF6 (000C) | External Fault (Terminal S6) | Flashing | Alarm | 130 |
| 13 | EF7 (000D) | External Fault (Terminal S7) | Flashing | Alarm | 131 |
| 20 | CE (0014) | Serial Communication Error | Flashing | Alarm | 128 |
| 21 | bUS (0015) | Option Communication Error | Flashing | Alarm | 127 |
| 26 | EF0 (001A) | Option Card External Fault | Flashing | Alarm | 130 |
| 29 | CALL (001D) | Serial Comm Transmission Error | Flashing | Alarm | 128 |
| 30 | UL3 (001E) | Undertorque Detection 1 | Flashing | Alarm | 138 |
| 31 | UL4 (001F) | Undertorque Detection 2 | Flashing | Alarm | 138 |

5.4 Faults, Minor Faults, Alarms, and Error Codes Listed by Decimal Value for Use with BACnet/Modbus

| Decimal Value | Display (Hex.) | Name | ALM LED | Type | Ref. |
|---------------|----------------|----------------------------------|----------|-------|------|
| 32 | SE (0020) | Modbus Test Mode Error | Flashing | Alarm | 137 |
| 34 | oH3 (0022) | Motor Overheat (PTC Input) | Flashing | Alarm | 135 |
| 41 | CyPo (0029) | Cycle Power to Accept Changes | Flashing | Alarm | 129 |
| 42 | dnE (002A) | Drive Disabled | Flashing | Alarm | 129 |
| 52 | HCA (0034) | High Current Alarm | Flashing | Alarm | 132 |
| 53 | LT-1 (0035) | Cooling Fan Maintenance Time | Flashing | Alarm | 134 |
| 54 | LT-2 (0036) | Capacitor Maintenance Time | Flashing | Alarm | 134 |
| 57 | EF1 (0039) | External Fault (Terminal S1) | Flashing | Alarm | 130 |
| 58 | EF2 (003A) | External Fault (Terminal S2) | Flashing | Alarm | 130 |
| 59 | SToF (003B) | Safe Torque OFF | Flashing | Alarm | 137 |
| 60 | STo (003C) | Safe Torque OFF | - | Alarm | 137 |
| 63 | PA1 (003F) | PLC Error 1 | Flashing | Alarm | 137 |
| 66 | TrPC (0042) | IGBT Maintenance Time (90%) | Flashing | Alarm | 137 |
| 67 | LT-3 (0043) | SoftChargeBypassRelay MainteTime | Flashing | Alarm | 134 |
| 68 | LT-4 (0044) | IGBT Maintenance Time (50%) | Flashing | Alarm | 134 |
| 71 | PF (0047) | Input Phase Loss | Flashing | Alarm | 136 |
| 78 | UL6 (004E) | Underload or Belt Break Detected | Flashing | Alarm | 138 |
| 103 | EOF (0067) | Emergency Override FWD | Flashing | Alarm | 131 |
| 104 | EOR (0068) | Emergency Override REV | Flashing | Alarm | 131 |
| 105 | INTLK (0069) | BAS Interlock | Flashing | Alarm | 133 |
| 129 | EP24v (0081) | External Power 24V Supply | Flashing | Alarm | 131 |
| 133 | bAT (0085) | Keypad Battery Low Voltage | Flashing | Alarm | 127 |
| 137 | TiM (0089) | Keypad Time Not Set | Flashing | Alarm | 137 |
| 138 | bCE (008A) | Bluetooth Communication Error | Flashing | Alarm | 127 |
| 144 | Bu-Fb (0090) | Main Fdbk Lost Using Backup Fdbk | Flashing | Alarm | 127 |
| 145 | BuFbl (0091) | Backup Fdbk Lost Chk/Repl Xducer | Flashing | Alarm | 127 |
| 146 | CE (0092) | Run at H5-34 (CE Go-To-Freq) | Flashing | Alarm | 129 |
| 147 | DIFF (0093) | Differential Feedback Exceeded | Flashing | Alarm | 129 |
| 148 | FDBKL (0094) | Feedback Loss Wire Break | Flashing | Alarm | 131 |
| 149 | FLGT (0095) | Feedback Loss, Go To Freq b5-83 | Flashing | Alarm | 131 |
| 150 | HIAUX (0096) | High PI Aux Feedback Level | Flashing | Alarm | 132 |
| 151 | HIFB (0097) | High Feedback Sensed | Flashing | Alarm | 132 |
| 153 | LOAUX (0099) | Low PI Aux Feedback Level | Flashing | Alarm | 133 |
| 154 | LOFB (009A) | Low Feedback Sensed | Flashing | Alarm | 133 |
| 155 | LOP (009B) | Loss of Prime | Flashing | Alarm | 133 |
| 156 | NMS (009C) | Setpoint Not Met | Flashing | Alarm | 134 |
| 157 | OD (009D) | Output Disconnect | Flashing | Alarm | 135 |
| 158 | FR<MS (009E) | Freq Ref < Minimum Speed (Y1-06) | Flashing | Alarm | 132 |
| 159 | FR<TH (009F) | Freq. Reference < Thrust (Y4-12) | Flashing | Alarm | 132 |
| 162 | AFBL (00A2) | Analog Fbk Lost, Switched to Net | Flashing | Alarm | 126 |
| 163 | AuDis (00A3) | Low PI Aux Fdbk Drive Disabled | Flashing | Alarm | 126 |
| 164 | AUXFB (00A4) | PI Aux Feedback Level Loss | Flashing | Alarm | 126 |
| 165 | AuFbl (00A5) | PI Aux Fdbk Lost Switched to Net | Flashing | Alarm | 126 |

5.4 Faults, Minor Faults, Alarms, and Error Codes Listed by Decimal Value for Use with BACnet/Modbus

| Decimal Value | Display (Hex.) | Name | ALM LED | Type | Ref. |
|---------------|-----------------|---------------------------------|----------|-------|---------------------|
| 166 | BuDif (00A6) | Main Fdbk Lost, Using Diff Fdbk | Flashing | Alarm | 127 |
| 167 | LCP (00A7) | Low City Pressure | Flashing | Alarm | 133 |
| 168 | LSP (00A8) | Low Suction Pressure | Flashing | Alarm | 134 |
| 169 | LWT (00A9) | Low Water In Tank | Flashing | Alarm | 134 |
| 178 | AL02 (00B2) | Interlock Open | Flashing | Alarm | 126 |
| 179 | AL03 (00B3) | Emergency Override Bypass | Flashing | Alarm | 126 |
| 185 | AL09 (00B9) | Restart Delay Active | Flashing | Alarm | 126 |
| 189 | AL13 (00BD) | Loss of Load Detected | Flashing | Alarm | 126 |
| 192 | AL16 (00C0) | Input Phase Rotation | Flashing | Alarm | 126 |
| 193 | AL17 (00C1) | Remote Xfer disabled in Reverse | Flashing | Alarm | 126 |
| 194 | AL18 (00C2) | Auto Xfer disabled in Reverse | Flashing | Alarm | 126 |
| 201 | SAFE (00C9) | Safety Open | Flashing | Alarm | 137 |
| 202 | FIRE_ST (00CA) | Fire Stat Open | Flashing | Alarm | 131 |
| 203 | FREEZ_ST (00CB) | Freeze Stat Open | Flashing | Alarm | 132 |
| 204 | SMK_ALRM (00CC) | Smoke Alarm Active | Flashing | Alarm | 137 |
| 205 | OV_PRESS (00CD) | Over Pressure Detected | Flashing | Alarm | 136 |
| 206 | LOW_SUCT (00CE) | Low Suction Detected | Flashing | Alarm | 134 |
| 207 | VBRATION (00CF) | Vibration Detected | Flashing | Alarm | 138 |

5.5 Faults

This section gives information about some of the causes and possible solutions of faults. You must use the Fault Reset operation to remove the fault before you can operate the drive. Use the information in this table to remove the cause of the fault.

| Code | Name | Causes | Possible Solutions |
|--|-------------------------------|--|--|
| AUXFB | PI Aux Feedback Level Loss | The analog input from the terminal set for <i>PI Auxiliary Control Feedback Level</i> [H3-xx = 27] is more than 21 mA or less than 3 mA for longer than 1 s. | Repair transducer or wiring. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| bAT | Keypad Battery Low Voltage | The keypad battery voltage is low. | Replace the keypad battery. |
| Note: Use o4-24 [bAT Detection Selection] to enable/disable bAT detection. | | | |
| Code | Name | Causes | Possible Solutions |
| bCE | Bluetooth Communication Fault | The smartphone or tablet with DriveWizard Mobile installed is too far from the keypad. | Use the smartphone or tablet 10 m (32.8 ft) or nearer to the keypad. Note: bCE can occur when the smartphone or tablet is 10 m (32.8 ft) or nearer to the keypad depending on the specifications of the smartphone or tablet. |
| | | Radio waves from a different device are causing interference with communications between the smartphone or tablet and keypad. | Make sure that no device around the keypad uses the same radio bandwidth (2400 MHz to 2480 MHz), and prevent radio interference. |
| Note: <ul style="list-style-type: none"> The drive detects this error when you use the Bluetooth LCD keypad and operate the drive with a smartphone or tablet. Do a Fault Reset to clear the fault. Set the stopping method for this fault in o2-27 [bCE Detection Selection]. | | | |
| Code | Name | Causes | Possible Solutions |
| bUS | Option Communication Error | The drive did not receive a signal from the controller. | Correct wiring errors. |
| | | The communications cable wiring is incorrect. | |
| | | There is a short-circuit in the communications cable or the communications cable is not connected. | <ul style="list-style-type: none"> Repair short circuits and connect cables. Replace the defective communications cable. |
| | | Electrical interference caused a communication data error. | <ul style="list-style-type: none"> Examine the control circuit lines, main circuit lines, and ground wiring, and decrease the effects of electrical interference. Make sure that a magnetic contactor is not the source of the electrical interference, then use a Surge Protective Device if necessary. Use only the recommended cables or other shielded line. Ground the shield on the controller side or the drive input power side. Separate the communication wiring from drive power lines, and install a noise filter to the input side of the power supply for communication. Decrease the effects of electrical interference from the controller. |
| | | The option is incorrectly installed to the bypass control board A2. | Correctly install the option to the bypass control board A2. |
| | | The option is damaged. | If the fault continues and the wiring is correct, replace the option. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the Run command or frequency reference is assigned to the option card. Do a Fault Reset to clear the fault. If the drive detects this error, the drive will operate the motor as specified by the stopping method set in F6-01 [Communication Error Selection]. | | | |
| Code | Name | Causes | Possible Solutions |
| CE | Serial Communication Error | The communications cable wiring is incorrect. | Correct wiring errors. |
| | | There is a short circuit in the communications cable or the communications cable is not connected. | <ul style="list-style-type: none"> Repair short circuits and connect cables. Replace the defective communications cable. |

| Code | Name | Causes | Possible Solutions |
|---|--------------------------------|---|--|
| | | Electrical interference caused a communication data error. | <ul style="list-style-type: none"> Examine the control circuit lines, main circuit lines, and ground wiring, and decrease the effects of electrical interference. Make sure that a magnetic contactor is not the source of the electrical interference, then use a Surge Protective Device if necessary. Use only the recommended cables or other shielded line. Ground the shield on the controller side or the drive input power side. Separate the communication wiring from drive power lines, and install a noise filter to the input side of the power supply for communication. Decrease the effects of electrical interference from the controller. |
| Note: <ul style="list-style-type: none"> The drive detects this error if it does not correctly receive control data for the <i>CE</i> detection time set to <i>H5-09 [CE Detection Time]</i>. Do a Fault Reset to clear the fault. If the drive detects this error, the drive will operate the motor as specified by the stopping method set in <i>H5-04 [Communication Error Stop Method]</i>. | | | |
| Code | Name | Causes | Possible Solutions |
| CoF | Current Offset Fault | The drive starts operation while the induced voltage stays in the motor (during coasting to a stop or after fast deceleration). | <ul style="list-style-type: none"> Make a sequence that does not restart operation when induced voltage stays in the motor. Set <i>b3-01 = 1 [Speed Search at Start Selection = Enabled]</i>. Use <i>Speed Search from Fmax or Fref [H1-xx = 61, 62]</i> to do a speed search through one of the external terminals. |
| | | A drive hardware problem occurred. | Replace the drive. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the current offset value is more than the permitted setting range while the drive automatically adjusts the current offset. Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF00 | Control Circuit Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF01 | Control Circuit Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF02 | A/D Conversion Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF03 | Control Board Connection Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|--|---------------------------------|--|--|
| CPF06 | EEPROM Memory Data Error | The drive power supply was de-energized while a communication option card entered a parameter Write command. | Set <i>A1-03 = 2220</i> [<i>Initialize Parameters = 2-Wire Initialization</i>] and initialize the drive. |
| | | An EEPROM peripheral circuit error occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> The drive detects this error if there is an error in the data written to the EEPROM of the drive. Do a Fault Reset to clear the fault. Fault trace is not available for this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF07 | Terminal Board Connection Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF08 | Terminal Board Connection Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF11 | RAM Fault | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF12 | FLASH Memory Fault | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF13 | Watchdog Circuit Exception | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF14 | Control Circuit Fault | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |

| Code | Name | Causes | Possible Solutions |
|---|--------------------------------|------------------------------------|--|
| CPF16 | Clock Fault | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF17 | Timing Fault | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF18 | Control Circuit Fault | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF19 | Control Circuit Fault | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive and check if the fault still remains. Replace the control board or the entire drive if the fault continues. Contact Yaskawa or your nearest sales representative for instructions on replacing the control board. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF20 | Control Circuit Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF21 | Control Circuit Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF22 | Hybrid IC Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF23 | Control Board Connection Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|---|-------------------------|------------------------------------|--|
| CPF24 | Drive Unit Signal Fault | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF26 | BB Circuit Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF27 | PWM Set Reg Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF28 | PWM Pattern Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF29 | On-Delay Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF30 | BB On Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF31 | ASIC Code Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF32 | ASIC Startup Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |

| Code | Name | Causes | Possible Solutions |
|---|------------------------------|--|--|
| CPF33 | Watch-dog Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF34 | Power/Clock Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF35 | Ext A/D Conv Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF36 | ASIC COM Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF37 | ASIC COM Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF38 | EEPROM Memory Data Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| CPF39 | CPU-ASIC Communication Error | A drive hardware problem occurred. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for these faults. | | | |
| Code | Name | Causes | Possible Solutions |
| dEv | Speed Deviation | The load is too heavy. | Decrease the load. |
| | | Acceleration and deceleration times are set too short. | Increase the values set in <i>C1-01</i> to <i>C1-04</i> [<i>Acceleration/Deceleration Time</i>]. |
| | | The <i>dEv</i> detection level settings are incorrect. | Adjust <i>F1-10</i> [<i>Speed Deviation Detection Level</i>] and <i>F1-11</i> [<i>Speed Deviation Detect DelayTime</i>]. |
| | | The load is locked up. | Examine the machine. |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|---|--------------------------------|--|---|
| | | The holding brake is stopping the motor. | Release the holding brake. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the difference between the detected speed and the speed reference is more than the setting of <i>F1-10</i> for longer than <i>F1-11</i>. Do a Fault Reset to clear the fault. If the drive detects this error, the drive will operate the motor as specified by the stopping method set in <i>F1-04</i> [<i>Speed Deviation Detection Select</i>]. | | | |
| Code | Name | Causes | Possible Solutions |
| DIFF | Differential Feedback Exceeded | The difference between the PID Feedback and <i>Differential Level Source</i> [<i>H3-xx = 2D</i>] is more than the level set in <i>Y4-18</i> [<i>Differential Level</i>] for the time set in <i>Y4-19</i> [<i>Differential Lvl Detection Time</i>]. | <ul style="list-style-type: none"> Replace the feedback transducer or transducers. Make sure that the settings of <i>Y4-18</i> [<i>Differential Level</i>] to <i>Y4-20</i> [<i>Differential Level Detection Sel</i>] are correct. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| dv7 | Polarity Judge Timeout | There is a disconnection in the motor coil winding. | Measure the motor line-to-line resistance and replace the motor if a coil is disconnected. |
| | | The screws on the drive output terminals are loose. | Tighten the terminal screws to the correct tightening torque. |
| Note: <ul style="list-style-type: none"> The drive detects this error if it cannot detect polarity in a pre-set length of time. Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| EF0 | Option Card External Fault | The communication option received an external fault from the controller. | <ol style="list-style-type: none"> Find the device that caused the external fault and remove the cause. Clear the external fault input from the controller. |
| | | A programming error occurred on the controller side. | Examine the operation of the controller program. |
| Note: <ul style="list-style-type: none"> The drive detects this fault if the alarm function on the external device side is operating. Do a Fault Reset to clear the fault. If the drive detects this fault, it will operate the motor as specified by the stop method set in <i>F6-03</i> [<i>Comm External Fault (EF0) Select</i>]. | | | |
| Code | Name | Causes | Possible Solutions |
| EF1 | External Fault (Terminal S1) | MFDI terminal S1 caused an external fault through an external device. | <ol style="list-style-type: none"> Find the device that caused the external fault and remove the cause. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S1. |
| | | <i>External Fault</i> [<i>H1-01 = 20 to 2B</i>] is set to MFDI terminal S1, but the terminal is not in use. | Correctly set the MFDI. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| EF2 | External Fault (Terminal S2) | MFDI terminal S2 caused an external fault through an external device. | <ol style="list-style-type: none"> Find the device that caused the external fault and remove the cause. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S2. |
| | | <i>External Fault</i> [<i>H1-02 = 20 to 2B</i>] is set to MFDI terminal S2, but the terminal is not in use. | Correctly set the MFDI. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| EF3 | External Fault (Terminal S3) | MFDI terminal S3 caused an external fault through an external device. | <ol style="list-style-type: none"> Find the device that caused the external fault and remove the cause. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S3. |
| | | <i>External Fault</i> [<i>H1-03 = 20 to 2B</i>] is set to MFDI terminal S3, but the terminal is not in use. | Correctly set the MFDI. |
| Note: Do a Fault Reset to clear the fault. | | | |

| Code | Name | Causes | Possible Solutions |
|--|------------------------------|--|---|
| EF4 | External Fault (Terminal S4) | MFDI terminal S4 caused an external fault through an external device. | <ol style="list-style-type: none"> Find the device that caused the external fault and remove the cause. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S4. |
| | | <i>External Fault [H1-04 = 20 to 2B]</i> is set to MFDI terminal S4, but the terminal is not in use. | Correctly set the MFDI. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| EF5 | External Fault (Terminal S5) | MFDI terminal S5 caused an external fault through an external device. | <ol style="list-style-type: none"> Find the device that caused the external fault and remove the cause. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S5. |
| | | <i>External Fault [H1-05 = 20 to 2B]</i> is set to MFDI terminal S5, but the terminal is not in use. | Correctly set the MFDI. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| EF6 | External Fault (Terminal S6) | MFDI terminal S6 caused an external fault through an external device. | <ol style="list-style-type: none"> Find the device that caused the external fault and remove the cause. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S6. |
| | | <i>External Fault [H1-06 = 20 to 2B]</i> is set to MFDI terminal S6, but the terminal is not in use. | Correctly set the MFDI. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| EF7 | External Fault (Terminal S7) | MFDI terminal S7 caused an external fault through an external device. | <ol style="list-style-type: none"> Find the device that caused the external fault and remove the cause. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S7. |
| | | <i>External Fault [H1-07 = 20 to 2B]</i> is set to MFDI terminal S7, but the terminal is not in use. | Correctly set the MFDI. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| Err | EEPROM Write Error | There was a problem with the EEPROM hardware. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. Contact Yaskawa or your nearest sales representative to replace the board. |
| | | Electrical interference corrupted the data while it was writing to the EEPROM of the drive. | <ul style="list-style-type: none"> Push ENTER Key. Set the parameters again. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FAnI | Drive Cooling Fan Fault | The cooling fan stopped operating correctly. | <ul style="list-style-type: none"> Examine cooling fan operation. Re-energize the drive. Examine U4-03 [Cooling Fan Ope Time] and U4-04 [Cool Fan Maintenance]. If the performance life of the cooling fan is expired or if there is damage to the fan, replace the fan. |
| | | The circulation fan is damaged. | <ul style="list-style-type: none"> Examine circulation fan operation. Re-energize the drive. Examine U4-03 [Cooling Fan Ope Time] and U4-04 [Cool Fan Maintenance]. If there is damage to the circulation fan or if the performance life of the fan is expired, replace the fan. |
| Note: Do a Fault Reset to clear the fault. | | | |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|---|--|---|---|
| FB02 | Wait For Interlock Timeout | The digital input set to Run Interlock is open. This will usually be Terminal TB2-3 on bypass control PCB A2. | <ul style="list-style-type: none"> Install a NC BAS Interlock Circuit/Damper Interlock between TB2-3 and TB2-9 on the bypass control board A2. Install a jumper between TB2-3 and TB2-9 on the bypass control board A2.. Use this method when you will add a BAS (Building Automation System) Interlock circuit in the future or if you will not use a Building Automation System interlock circuit. Make sure that the input assigned for the Interlock is active in the timeout period set in Z1-15. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB03 | External Fault Bypass (EFB) | An digital input set for external fault (EFB) was activated. | Remove the cause of the external fault. |
| | | An external fault (EFB) was received from the serial communications network. | <ul style="list-style-type: none"> Remove the cause of the external fault. Remove the external fault input from the controller. Make sure that the controller program is correct. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB05 | Motor Overload | The load is too heavy. | Decrease the load. Note: You can only reset FB05 when U4-16 [Motor oL1 Level] < 100. |
| | | The acceleration/deceleration times or cycle times are too short. | <ul style="list-style-type: none"> Examine the acceleration/deceleration times and the motor start/stop frequencies (cycle times). Increase the values set in C1-01 to C1-04 [Acceleration/Deceleration Times]. |
| | | Overload occurred while running at low speed. | <ul style="list-style-type: none"> Decrease the load when running at low speed. Increase the motor speed. If the motor is run frequently at low speeds, replace the motor with a larger motor or use a drive-dedicated motor. Note: For general-purpose motors, overload can occur while running at low speed when operating at below the rated current. |
| | | Starting the motor too often in Bypass Mode. | Decrease the number of times the motor is started in Bypass Mode. |
| | | The V/f pattern does not fit the motor qualities. | <ul style="list-style-type: none"> Examine the ratios between the V/f pattern frequency and voltage. Decrease the voltage if it is too high compared to the frequency. Adjust E1-04 to E1-10 [V/f Pattern Parameters]. Decrease the values set in E1-08 [Mid Point A Voltage] and E1-10 [Minimum Output Voltage]. Note: If the values set in E1-08 and E1-10 are too low, the overload tolerance will decrease at low speeds. |
| | | E1-06 [Base Frequency] is set incorrectly. | Set E1-06 to the rated frequency shown on the motor nameplate. |
| | | One drive is operating more than one motor. | Set L1-01 = 0 [Motor Overload (oL1) Protection = Disabled], connect thermal overload relay to each motor to prevent damage to the motors. |
| | | The electronic thermal protector is operating at an incorrect level. | <ul style="list-style-type: none"> Set E2-01 [Motor Rated Current (FLA)] correctly to the value specified by the motor nameplate. Check that L1-08 = 0.0 A [oL1 Current Level = 0.0] or the correct value specified by the motor nameplate. |
| | | There is increased motor loss from overexcitation operation. | <ul style="list-style-type: none"> Lower the value set in n3-13 [OverexcitationBraking (OEB) Gain]. Set L3-04 ≠ 4 [Stall Prevention during Decel ≠ Overexcitation/High Flux]. Set n3-23 = 0 [Overexcitation Braking Operation = Disabled]. |
| The speed search-related parameters are set incorrectly. | <ul style="list-style-type: none"> Examine the settings for all speed search related parameters. Adjust b3-03 [Speed Search Deceleration Time]. Set b3-24 = 1 [Speed Search Method Selection = Speed Estimation] after Auto-Tuning. | | |
| Phase loss in the input power supply is causing the output current to change. | Make sure that there is no phase loss, and repair problems. | | |

| Code | Name | Causes | Possible Solutions |
|--|------------------------------|---|---|
| | | Overload occurred during overexcitation deceleration. | <ul style="list-style-type: none"> Decrease the value set in n3-13 [OverexcitationBraking (OEB) Gain]. Decrease the value set in n3-21 [HSB Current Suppression Level]. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB06 | External Overload 1 | The load is too heavy. | Decrease the load. |
| | | The cycle times for acceleration and deceleration are too short. | Increase the acceleration and deceleration times in C1-01 and C1-02. |
| | | The external motor overload is set incorrectly. | Adjust the dial on the external motor overload to align with the motor nameplate rating. |
| | | External motor overload wiring error. | Make sure that the wiring is correct between the normally-closed control contacts on the external motor overload and the digital input [Z2-0x] programmed to 29 [External Overload Motor 1 (NC)]. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB07 | External Overload 2 | The load is too heavy. | Decrease the load. |
| | | The cycle times for acceleration and deceleration are too short. | Increase the acceleration and deceleration times in C1-01 and C1-02. |
| | | The external motor overload is set incorrectly. | Adjust the dial on the external motor overload to align with the motor nameplate rating. |
| | | External motor overload wiring error. | Make sure that the wiring is correct between the normally-closed control contacts on the external motor overload and the digital input [Z2-0x] programmed to 30 [External Overload Motor 2 (NC)]. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB08 | Brownout Detected | Input power is too low. | Make sure that the input power is sufficient to power the bypass. |
| | | The brownout settings are incorrect. | Make sure that Z1-27 [Brownout Voltage Level] and Z1-28 [Brownout Time] are correct. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB09 | Blackout Detected | Input power is too low. | Make sure that the input power is sufficient to power the bypass. |
| | | The blackout settings are incorrect. | <ul style="list-style-type: none"> Make sure that Z1-29 [Blackout Voltage Level] is correct. Set Z1-60 ≠0 [Blackout Operation Select ≠Fault]. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB10 | Loss of Drive Communications | The cable between the bypass controller and the drive is disconnected or damaged. | Make sure that the cable between the bypass controller board (A2) connector CN6 to drive terminal CN6 is connected at both ends and is not damaged. |
| | | The drive does not have power (look at the CHARGE LED to verify). | <ul style="list-style-type: none"> If equipped, check the drive input disconnect switch, the drive input fuses, and/or correct operation of the K1 input contactor. Switch the system into Bypass Mode. |
| | | The bypass controller circuit is defective. | Replace the bypass control board. |
| | | The drive circuitry is defective. | Replace the drive. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB13 | Loss of Load | The motor is disconnected from the drive | Check the continuity between the drive/bypass and the motor. |
| | | The load is disconnected from the motor. | Check the belt/coupling between the motor and the load. |
| | | The Loss of Load settings are incorrect. | Make sure that the settings in Z1-31 to Z1-36 are correct. |
| Note: Do a Fault Reset to clear the fault. | | | |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|--|----------------------------------|--|---|
| FB15 | Input Phase Loss | Bypass Mode current unbalance condition is more than the unbalance level limit in Z1-50 for the length of time in Z1-51. | <ul style="list-style-type: none"> Make sure that the input wiring including fuses, breakers, and connections upstream from the bypass is correct. Make sure that the motor wiring and connections are correct. To disable this fault, set Z1-51 [Bypass Input Phase Loss Delay] to 0.0 sec. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB16 | Input Phase Rotation | Incorrect phase rotation while Z1-52 = 2 in Bypass Mode. | <ul style="list-style-type: none"> Make sure that the sequence (phase rotation) of the input wiring to the bypass package is correct. To disable this fault, set Z1-52 [Input Phase Rotation Detection] to 0 or 1 |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB17 | Load Verify Fault | The drive or bypass output current is less than 5% of E2-01, Motor Rated Current for longer than 10 seconds. | <ul style="list-style-type: none"> Close all external output disconnects. Make sure that the frequency reference or PID output > 0. Check motor wiring. Set d2-02 > 0.0% To disable this fault, set Z1-53 = 0 [Load Verify Detection = Disabled]. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB18 | Welded Bypass Contactor Detected | The bypass detected a welded contactor condition. | Inspect the K3 bypass contactor. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB26 | Option on Drive Detected | There is a communications option PCB connected to the CN5 port on the drive. | Remove the option PCB from the drive and install it in the CN5 port of the bypass controller. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB27 | Drive Hardware Fault (CPFx oFx) | There is a CPFxx or oFA fault on the drive. | Remove the cause of the fault on the drive. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| FB28 | Drive Faulted | Generic fault code to identify a drive fault that was duplicated or not detected by the bypass. | Investigate and remove the cause of the drive fault. |
| Note: Do a Fault Reset to clear the fault. | | | |

| Code | Name | Causes | Possible Solutions | | | | | | | | | | | | | | | | |
|--|---|--|---|--|---|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------|-------------------|
| FB30 | Conflicting SW Check UB-99 | <p>The bypass controller software version does not align with the drive software version.</p> <p>The bypass controller firmware is for a different drive series than HV600. You can see the drive series on the keypad during a power-up sequence (splash screen).</p> | <p>Do ONE of these solutions:</p> <ol style="list-style-type: none"> Update the firmware in the HV600 drive to align with what is displayed in bypass monitor <i>Ub-99</i> (set <i>A1-01</i> = 3 to be able to view this monitor). Update the firmware in the bypass controller to one that aligns with the firmware in the HV600 drive as listed in the table below: <table border="1"> <thead> <tr> <th>HV600 Drive Software (Read from U1-25)</th> <th>Update Bypass Controller Firmware Version to:</th> </tr> </thead> <tbody> <tr> <td>01011</td> <td>00442</td> </tr> <tr> <td>01012</td> <td>00442</td> </tr> <tr> <td>01013</td> <td>00444</td> </tr> <tr> <td>01014</td> <td>00444</td> </tr> <tr> <td>01015</td> <td>00445</td> </tr> <tr> <td>01016</td> <td>00446</td> </tr> <tr> <td>01017</td> <td>00447 or 00448 *1</td> </tr> </tbody> </table> <p>*1 If your bypass controller has firmware version 00448 or later, do not downgrade to an older version of firmware.</p> <ol style="list-style-type: none"> Disable firmware version checking. Set <i>Z1-98</i> or <i>Z1-99</i> so that $Z1-98 \leq U1-25 \leq Z1-99$. (set <i>A1-01</i> = 3 to be able to change these parameters). Refer to the <i>Z1-99</i> [Maximum Drive SW Ver] Parameter Details description in the Technical Reference for more information. | HV600 Drive Software (Read from U1-25) | Update Bypass Controller Firmware Version to: | 01011 | 00442 | 01012 | 00442 | 01013 | 00444 | 01014 | 00444 | 01015 | 00445 | 01016 | 00446 | 01017 | 00447 or 00448 *1 |
| HV600 Drive Software (Read from U1-25) | Update Bypass Controller Firmware Version to: | | | | | | | | | | | | | | | | | | |
| 01011 | 00442 | | | | | | | | | | | | | | | | | | |
| 01012 | 00442 | | | | | | | | | | | | | | | | | | |
| 01013 | 00444 | | | | | | | | | | | | | | | | | | |
| 01014 | 00444 | | | | | | | | | | | | | | | | | | |
| 01015 | 00445 | | | | | | | | | | | | | | | | | | |
| 01016 | 00446 | | | | | | | | | | | | | | | | | | |
| 01017 | 00447 or 00448 *1 | | | | | | | | | | | | | | | | | | |

Note:

- Do a Fault Reset to clear the fault.
- If this fault is detected, the bypass will still function in Bypass Mode. Only operation in Drive Mode is prohibited.
- The HV600 drive firmware number is shown in bypass monitor *U1-25*.
- The bypass controller firmware version is shown in bypass monitor *Ub-18*.

| Code | Name | Causes | Possible Solutions |
|-------|------------|---|---|
| FDBKL | WIRE Break | <p>The analog input from the terminal set for <i>PID Feedback</i> [<i>H3-xx = B</i>] is more than 21mA or less than 3mA for longer than 1 s in these conditions:</p> <ul style="list-style-type: none"> <i>b5-82</i> = 2 [<i>Feedback Loss 4 ~ 20mA Detect Sel = Fault</i>] <i>b5-01</i> ≠ 0 [<i>PID Mode Setting ≠ Disabled</i>] <i>H3-01</i> or <i>H3-09</i> = 2 [<i>Terminal A1/A2 Signal Level Selection = 4 to 20 mA</i>] | Make sure that you install the PID feedback source and it operates correctly. |

Note:

- Do a Fault Reset to clear the fault.
- If the drive detects this fault, it will operate the motor as specified by the settings of *b5-82*.
- Parameter *L5-42* [*Feedback Loss Fault Retry Select*] sets the Auto Restart function of this fault.

| Code | Name | Causes | Possible Solutions |
|------|--------------|--|---|
| GF | Ground Fault | Overheating caused damage to the motor or the motor insulation is not satisfactory. | Measure the motor insulation resistance, and replace the motor if there is electrical conduction or unserviceable insulation. |
| | | The motor main circuit cable is contacting ground to make a short circuit. | <ul style="list-style-type: none"> Examine the motor main circuit cable for damage, and repair short circuits. Measure the resistance between the motor main circuit cable and the ground terminal. If there is electrical conduction, replace the cable. |
| | | An increase in the stray capacitance of the cable and the ground terminal caused an increase in the leakage current. | <ul style="list-style-type: none"> If the wiring length of the cable is more than 100 m, decrease the carrier frequency. Decrease the stray capacitance. |
| | | There was a problem with the drive hardware. | Replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |

Note:

- The drive detects this fault if a current short to ground was more than 50% of rated current on the output side of the drive.
- Do a Fault Reset to clear the fault.
- L5-08* [*Fault Reset Enable Select Grp2*] disables the Auto Restart function.

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|--|----------------------------|---|--|
| HFB | High Feedback Sensed | The feedback level is more than the level set in <i>Y1-11 [High Feedback Level]</i> for the time set in <i>Y1-12 [High Feedback Lvl Fault Dly Time]</i> . | <ul style="list-style-type: none"> Decrease the feedback level less than <i>Y1-11</i>. Set <i>Y1-11</i> and <i>Y1-12</i> correctly. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. If the drive detects this fault, it will respond as specified by the setting of <i>Y1-13 [High Feedback Selection]</i>. Parameter <i>L5-41 [Hi Feedback Flt Retry Selection]</i> sets the Auto Restart function of this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| HIAUX | High PI Aux Feedback Level | PI Auxiliary Feedback is more than the level set in <i>YF-12 [PI Aux Control High Level Detect]</i> for the time set in <i>YF-13 [PI Aux High Level Detection Time]</i> in these conditions: <ul style="list-style-type: none"> The drive operates in AUTO Mode. The output frequency > 0. | <ul style="list-style-type: none"> Decrease the PI Auxiliary Feedback level less than <i>YF-12</i>. Set <i>YF-12</i> and <i>YF-13</i> correctly. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Parameter <i>YF-14 [PI Aux Hi Level Detection Select]</i> sets the Auto Restart function of this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| LF | Output Phase Loss | The motor main circuit cable is disconnected. | Connect motor main circuit cable wiring. Correct wiring errors in the main circuit drive input power. |
| | | There is a disconnection in the motor coil winding. | If a coil is disconnected, measure the motor Line-to-Line Resistance and replace the motor. |
| | | The screws on the drive output terminals are loose. | Tighten the terminal screws to the correct tightening torque. |
| | | The rated current of the motor is less than 5% of the drive rated output current. | Examine the drive capacity or the motor output to be applied. |
| | | You are trying to use a single-phase motor. | The drive cannot operate a single-phase motor. |
| | | The output transistor in the drive is damaged. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| | | One of the output contactors K2 (K4 or K5 if equipped) is defective. | Contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> The drive detects this fault if phase loss occurs on the output side of the drive. Do a Fault Reset to clear the fault. Set <i>L8-07 [Output Phase Loss Protection Sel]</i> to enable and disable <i>LF</i> detection. | | | |
| Code | Name | Causes | Possible Solutions |
| LF2 | Output Current Imbalance | Phase loss occurred in the wiring on the output side of the drive. | Examine for wiring errors or disconnected wires on the output side of the drive, and repair problems. |
| | | The output terminal screws of the drive are loose. | Tighten the terminal screws to the correct tightening torque. |
| | | The drive output circuit is broken. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Code | Name | Causes | Possible Solutions |
| LFB | Low Feedback Sensed | The feedback level is less than the level set in <i>Y1-08 [Low Feedback Level]</i> for the time set in <i>Y1-09 [Low Feedback Lvl Fault Dly Time]</i> . | <ul style="list-style-type: none"> Increase the feedback level to more than <i>Y1-08</i>. Set <i>Y1-08</i> and <i>Y1-09</i> correctly. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. If the drive detects this fault, it will respond as specified by the setting of <i>Y1-10 [Low Feedback Selection]</i>. Parameter <i>L5-40 [Low Feedback Flt Retry Selection]</i> sets the Auto Restart function of this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| LOAUX | Low PI Aux Feedback Level | When the drive operates in AUTO Mode or HAND Mode, PI Auxiliary Feedback is less than the level set in <i>YF-09 [PI Aux Control Low Lvl Detection]</i> for the time set in <i>YF-10 [PI Aux Control Low Lvl Det Time]</i> and the drive is running. | <ul style="list-style-type: none"> Increase the PI Auxiliary Feedback level to be more than <i>YF-09</i>. Set <i>YF-09</i> and <i>YF-10</i> correctly. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Parameter <i>YF-11 [PI Aux Control Low Level Det Sel]</i> sets the Auto Restart function of this fault. | | | |

| Code | Name | Causes | Possible Solutions |
|---|---|---|---|
| LOP | Loss of Prime | The drive used the <i>Y1-18 [Prime Loss Detection Method]</i> setting and measured a pump load that is less than the level set in <i>Y1-19 [Prime Loss Level]</i> for the time set in <i>Y1-20 [Prime Loss Time]</i> , and the output frequency is <i>Y1-21 [Prime Loss Activation Freq]</i> or more. | <ul style="list-style-type: none"> Examine for a dry well, air in the system, or no water in the system. Use preferred priming method suggested by the pump manufacturer to restart the pump. When there is resistance in the pump, let the system pump water again. Set <i>Y1-18</i> to <i>Y1-21</i> correctly. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. If the drive detects this fault, it will respond as specified by the setting of <i>Y1-22 [Prime Loss Selection]</i>. Parameters <i>L5-51 [Loss of Prime Fault Retry Select]</i> and <i>Y1-23 [Prime Loss Max Restart Time]</i> set the Auto Restart function of this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| NMS | Setpoint Not Met | The feedback deviates from the setpoint at a level more than <i>Y1-15 [Maximum Setpoint Difference]</i> for the time set in <i>Y1-16 [Not Maintaining Setpoint Time]</i> . | <ul style="list-style-type: none"> Examine for a blocked impeller, over cycling, or broken pipe. Set <i>Y1-15</i> and <i>Y1-16</i> correctly. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. If the drive detects this fault, it will respond as specified by the setting of <i>Y1-17 [Not Maintaining Setpoint Sel]</i>. Parameter <i>L5-50 [Setpoint Not Met Fault Retry Sel]</i> sets the Auto Restart function of this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oC | Overcurrent | The load is too large. | <ul style="list-style-type: none"> Measure the current flowing into the motor. Replace the drive with a larger capacity model if the current value is more than the drive rated current. Decrease the load or replace with a larger drive to prevent sudden changes in the current level. |
| | | Overheating caused damage to the motor or the motor insulation is not satisfactory. | Measure the motor insulation resistance, and replace the motor if there is electrical conduction or unserviceable insulation. |
| | | The motor main circuit cable is contacting ground to make a short circuit. | <ul style="list-style-type: none"> Examine the motor main circuit cable for damage, and repair short circuits. Measure the resistance between the motor main circuit cable and the ground terminal. If there is electrical conduction, replace the cable. |
| | | A short circuit or ground fault on the drive output side caused damage to the output transistor of the drive. | <ul style="list-style-type: none"> Make sure that there is not a short circuit in terminals - and terminals U/T1, V/T2, and W/T3. If there is a short circuit, contact Yaskawa or your nearest sales representative. |
| | | The acceleration time is too short. | <ul style="list-style-type: none"> Calculate the torque necessary during acceleration related to the load inertia and the specified acceleration time. Increase the values set in <i>C1-01</i> or <i>C1-03 [Acceleration Times]</i> to get the necessary torque. Increase the values set in <i>C2-01</i> to <i>C2-04 [S-Curve Characteristics]</i> to get the necessary torque. Replace the drive with a larger capacity model. |
| | | The drive is trying to operate a specialized motor or a motor that is larger than the maximum applicable motor output of the drive. | <ul style="list-style-type: none"> Examine the motor nameplate, the motor, and the drive to make sure that the drive rated current is larger than the motor rated current. Replace the drive with a larger capacity model. |
| | | A magnetic contactor was switched at the output. | Set the operation sequence to not turn ON or OFF the magnetic contactor while the drive is outputting voltage. |
| | | The V/f pattern settings are incorrect. | <ul style="list-style-type: none"> Examine the ratios between the V/f pattern frequency and voltage. Decrease the voltage if it is too high compared to the frequency. Adjust <i>E1-04</i> to <i>E1-10 [V/f Pattern Parameters]</i>. |
| | | The torque compensation gain is too large. | Decrease the value set in <i>C4-01 [Torque Compensation Gain]</i> to make sure that the motor does not stall. |
| | | Electrical interference caused a problem. | Examine the control circuit lines, main circuit lines, and ground wiring, and decrease the effects of electrical interference. |
| | | The gain during overexcitation operation is too large. | <ul style="list-style-type: none"> Find the time when the fault occurs. If the fault occurs at the same time as overexcitation operation, decrease the value set in <i>n3-13 [OverexcitationBraking (OEB) Gain]</i> and consider the motor flux saturation. |
| The drive received a Run command while the motor was coasting. | <ul style="list-style-type: none"> Examine the sequence and input the Run command after the motor fully stops. Set <i>b3-01 = 1 [Speed Search at Start Selection = Enabled]</i> or set <i>H1-xx = 61, 62 [Speed Search from Fmax or Fref]</i> to input speed search commands from the MFDI terminals. | | |
| The motor main circuit cable is too long. | Replace the drive with a larger capacity model. | | |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|--|---------------------------------|--|--|
| | | The relay or contactor on the soft-charge bypass relay is damaged. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. |
| | | An overcurrent condition occurred during overexcitation deceleration. | <ul style="list-style-type: none"> Decrease the value set in <i>n3-13 [OverexcitationBraking (OEB) Gain]</i>. Decrease the value set in <i>n3-21 [HSB Current Suppression Level]</i>. |
| Note: <ul style="list-style-type: none"> This fault occurs if the drive sensors detect a drive output current more than the specified overcurrent detection level. Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| OD | Output Disconnect | The output circuit between the drive and the motor is open, and the drive output current is less than 5% of <i>E2-01 [Motor Rated Current (FLA)]</i> . | <ul style="list-style-type: none"> Close the disconnected output circuit between the drive and the motor. You can adjust <i>Y4-42 [Output Disconnect Detection Sel]</i> to disable this fault. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. If the drive detects this fault, it will respond as specified by the setting of <i>Y4-42 [Output Disconnect Detection Sel]</i>. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA00 | Option Not Compatible with Port | The option card connected to connector CN5 is not compatible or it is not functioning correctly. | Remove the option PCB connected to CN5 on the bypass controller. |
| | | The DIP switches on a JOHB-SMP3 Multi-Protocol Ethernet card are set incorrectly for your protocol. | Check the DIP switch settings for your protocol. Refer to the instructions packaged with the JOHB-SMP3 card for more information. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA01 | Option Fault/Connection Error | The option card connected to connector CN5 is not compatible. | <ol style="list-style-type: none"> De-energize the drive. Refer to the option card manual and correctly connect the option card to the connector on the bypass controller. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA05 | Option A/D Error | A fault occurred in the option card. | <ol style="list-style-type: none"> De-energize the drive. Make sure that the option card is correctly connected to the connector. If the problem continues, replace the option card. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA06 | Option Communication Error | A fault occurred in the option card. | <ol style="list-style-type: none"> De-energize the drive. Make sure that the option card is correctly connected to the connector. If the problem continues, replace the option card. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA10 | Option RAM Error | A fault occurred in the option card. | <ol style="list-style-type: none"> De-energize the drive. Make sure that the option card is correctly connected to the connector. If the problem continues, replace the option card. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA11 | Option Ope Mode Error | A fault occurred in the option card. | <ol style="list-style-type: none"> De-energize the drive. Make sure that the option card is correctly connected to the connector. If the problem continues, replace the option card. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. | | | |

| Code | Name | Causes | Possible Solutions |
|--|----------------------------|--------------------------------------|--|
| oFA12 | Drive Receive CRC Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA13 | Drive Receive Frame Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA14 | Drive Receive Abort Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA15 | Option Receive CRC Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA16 | Option Receive Frame Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA17 | Option Receive Abort Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA30 | COM ID Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA31 | Type Code Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|--|---------------------------|--------------------------------------|--|
| oFA32 | SUM Check Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA33 | Option Receive Time Over | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA34 | Memobus Time Over | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA35 | Drive Receive Time Over 1 | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA36 | CI Check Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA37 | Drive Receive Time Over 2 | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA38 | Control Reference Error | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA39 | Drive Receive Time Over 3 | A fault occurred in the option card. | <ol style="list-style-type: none"> 1. De-energize the drive. 2. Make sure that the option card is correctly connected to the connector. 3. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |

| Code | Name | Causes | Possible Solutions |
|--|----------------------------|---|--|
| oFA40 | CtrlResSel 1Err | A fault occurred in the option card. | <ol style="list-style-type: none"> De-energize the drive. Make sure that the option card is correctly connected to the connector. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA41 | Drive Receive Time Over 4 | A fault occurred in the option card. | <ol style="list-style-type: none"> De-energize the drive. Make sure that the option card is correctly connected to the connector. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA42 | CtrlResSel 2Err | A fault occurred in the option card. | <ol style="list-style-type: none"> De-energize the drive. Make sure that the option card is correctly connected to the connector. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oFA43 | Drive Receive Time Over 5 | A fault occurred in the option card. | <ol style="list-style-type: none"> De-energize the drive. Make sure that the option card is correctly connected to the connector. If the problem continues, replace the option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oH | Heatsink Overheat | The ambient temperature is high and the heatsink temperature of the drive is more than the value set in L8-02 [Overheat Alarm Level]. | <ul style="list-style-type: none"> Measure the ambient temperature. Increase the airflow in the control panel. Install a cooling device (cooling fan or air conditioner) to lower the ambient temperature. Remove objects near the drive that are producing too much heat. |
| | | The load is too heavy. | <ul style="list-style-type: none"> Measure the output current. Decrease the load. Decrease the value set in C6-02 [Carrier Frequency Selection]. |
| | | The internal cooling fan of the drive stopped. | <ol style="list-style-type: none"> Use the procedures in this manual to replace the cooling fan. Set o4-03 = 0 [Fan Operation Time Setting = 0 h]. |
| Note: <ul style="list-style-type: none"> The drive detects this fault if the heatsink temperature of the drive is more than the value set in L8-02. Do a Fault Reset to clear the fault. If the drive detects this fault, it will operate the motor as specified by the Stopping Method set in L8-03 [Overheat Pre-Alarm Selection]. | | | |
| Code | Name | Causes | Possible Solutions |
| oH1 | Heatsink Overheat | The ambient temperature is high and the heatsink temperature of the drive is more than the oH1 detection level. | <ul style="list-style-type: none"> Measure the ambient temperature. Increase the airflow in the control panel. Install a cooling device (cooling fan or air conditioner) to lower the ambient temperature. Remove objects near the drive that are producing too much heat. |
| | | The load is too heavy. | <ul style="list-style-type: none"> Measure the output current. Decrease the load. Decrease the value set in C6-02 [Carrier Frequency Selection]. |
| Note: <ul style="list-style-type: none"> The drive detects this fault if the heatsink temperature of the drive is more than the oH1 detection level. o2-04 [Drive Model (KVA) Selection] determines the oH1 detection level. Do a Fault Reset to clear the fault. L5-08 [Fault Reset Enable Select Grp2] disables the Auto Restart function. | | | |
| Code | Name | Causes | Possible Solutions |
| oH3 | Motor Overheat (PTC Input) | The thermistor wiring that detects motor temperature is defective. | Correct wiring errors. |
| | | A fault occurred on the machine. Example: The machine is locked. | Examine the machine and remove the cause of the fault |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|---|----------------------------------|--|---|
| | | The motor has overheated. | <ul style="list-style-type: none"> Check the load level, acceleration/deceleration time, and motor start/stop frequency (cycle time). Decrease the load. Increase the values set in <i>C1-01 to C1-04 [Acceleration/Deceleration Times]</i>. Set <i>E2-01 [Motor Rated Current (FLA)]</i> correctly to the value specified by the motor nameplate. Make sure that the motor cooling system is operating correctly, and repair or replace it if it is damaged. Adjust <i>E1-04 to E1-10 [V/f Pattern Parameters]</i>. Decrease the values set in <i>E1-08 [Mid Point A Voltage]</i> and <i>E1-10 [Minimum Output Voltage]</i>. <p>Note: If the values set in <i>E1-08</i> and <i>E1-10</i> are too low, the overload tolerance will decrease at low speeds.</p> |
| <p>Note:</p> <ul style="list-style-type: none"> When <i>H3-02</i> or <i>H3-10 = E [MFAI Function Selection = Motor Temperature (PTC Input)]</i>, the drive detects this fault if the motor overheat signal entered to analog input terminals A1 or A2 is more than the alarm detection level. Do a Fault Reset to clear the fault. If the drive detects this fault, it will operate the motor as specified by the Stopping Method set in <i>L1-03 [Motor Thermistor oH Alarm Select]</i>. | | | |
| Code | Name | Causes | Possible Solutions |
| oH4 | Motor Overheat Fault (PTC Input) | The motor has overheated. | <ul style="list-style-type: none"> Check the load level, acceleration/deceleration time, and motor start/stop frequency (cycle time). Decrease the load. Increase the values set in <i>C1-01 to C1-04 [Acceleration/Deceleration Times]</i>. Set <i>E2-01 [Motor Rated Current (FLA)]</i> correctly to the value specified by the motor nameplate. Make sure that the motor cooling system is operating correctly, and repair or replace it if it is damaged. Adjust <i>E1-04 to E1-10 [V/f Pattern Parameters]</i>. Decrease the values set in <i>E1-08 [Mid Point A Voltage]</i> and <i>E1-10 [Minimum Output Voltage]</i>. <p>Note: If <i>E1-08</i> and <i>E1-10</i> are set too low, the overload tolerance will decrease at low speeds.</p> |
| <p>Note:</p> <ul style="list-style-type: none"> The drive detects this fault if the motor overheat signal that was entered to an analog input terminals A1 or A2 is more than the alarm detection level. (If <i>H3-02</i> or <i>H3-10 = E [MFAI Function Select = Motor Temperature (PTC Input)]</i> was set.) Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oL1 | Motor Overload | The load is too heavy. | Decrease the load. Note: Reset <i>oL1</i> when <i>U4-16 [Motor oL1 Level] < 100</i> . |
| | | The acceleration/deceleration times or cycle times are too short. | <ul style="list-style-type: none"> Examine the acceleration/deceleration times and the motor start/stop frequencies (cycle times). Increase the values set in <i>C1-01 to C1-04 [Acceleration/Deceleration Times]</i>. |
| | | Overload occurred while running at low speed. | <ul style="list-style-type: none"> Decrease the load when running at low speed. Increase the motor speed. If the motor is run frequently at low speeds, replace the motor with a larger motor or use a drive-dedicated motor. <p>Note: For general-purpose motors, overload can occur while running at low speed when operating at below the rated current.</p> |
| | | The V/f pattern does not fit the motor qualities. | <ul style="list-style-type: none"> Examine the ratios between the V/f pattern frequency and voltage. Decrease the voltage if it is too high compared to the frequency. Adjust <i>E1-04 to E1-10 [V/f Pattern Parameters]</i>. Decrease the values set in <i>E1-08 [Mid Point A Voltage]</i> and <i>E1-10 [Minimum Output Voltage]</i>. <p>Note: If the values set in <i>E1-08</i> and <i>E1-10</i> are too low, the overload tolerance will decrease at low speeds.</p> |
| | | <i>E1-06 [Base Frequency]</i> is set incorrectly. | Set <i>E1-06</i> to the rated frequency shown on the motor nameplate. |
| | | One drive is operating more than one motor. | Set <i>L1-01 = 0 [Motor Overload (oL1) Protection = Disabled]</i> , connect thermal overload relay to each motor to prevent damage to the motor. |
| | | The electronic thermal protector qualities and the motor overload properties do not align. | Connect a thermal overload relay to the motor. |

| Code | Name | Causes | Possible Solutions |
|--|----------------|---|--|
| | | The electronic thermal protector is operating at an incorrect level. | Set <i>E2-01 [Motor Rated Current (FLA)]</i> correctly to the value specified by the motor nameplate. |
| | | There is increased motor loss from overexcitation operation. | <ul style="list-style-type: none"> Lower the value set in <i>n3-13 [OverexcitationBraking (OEB) Gain]</i>. Set <i>L3-04 ≠ 4 [Stall Prevention during Decel ≠ Overexcitation/ High Flux]</i>. Set <i>n3-23 = 0 [Overexcitation Braking Operation = Disabled]</i>. |
| | | The speed search-related parameters are set incorrectly. | <ul style="list-style-type: none"> Examine the settings for all speed search related parameters. Adjust <i>b3-03 [Speed Search Deceleration Time]</i>. Set <i>b3-24 = 1 [Speed Search Method Selection = Speed Estimation]</i> after Auto-Tuning. |
| | | Phase loss in the input power supply is causing the output current to change. | Make sure that there is no phase loss, and repair problems. |
| | | Overload occurred during overexcitation deceleration. | <ul style="list-style-type: none"> Decrease the value set in <i>n3-13 [OverexcitationBraking (OEB) Gain]</i>. Decrease the value set in <i>n3-21 [HSB Current Suppression Level]</i>. |
| <p>Note:</p> <ul style="list-style-type: none"> Parameter <i>E2-01</i> normally sets the motor overload level. In special applications, for example motors with a service factor of greater than 1, you can use <i>L1-08 [oL1 Current Level for Motor 1]</i>. Do a Fault Reset to clear the fault. <i>L5-07 [Fault Reset Enable Select Grp1]</i> disables the Auto Restart function. | | | |
| Code | Name | Causes | Possible Solutions |
| oL2 | Drive Overload | The load is too large. | Decrease the load. |
| | | The acceleration/deceleration times or cycle times are too short. | <ul style="list-style-type: none"> Examine the acceleration/deceleration times and the motor start/ stop frequencies (cycle times). Increase the values set in <i>C1-01 to C1-04 [Acceleration/ Deceleration Times]</i>. |
| | | The V/f pattern does not fit the motor qualities. | <ul style="list-style-type: none"> Examine the ratios between the V/f pattern frequency and voltage. Decrease the voltage if it is too high compared to the frequency. Adjust <i>E1-04 to E1-10 [V/f Pattern Parameters]</i>. Decrease the values set in <i>E1-08 [Mid Point A Voltage]</i> and <i>E1-10 [Minimum Output Voltage]</i>. <p>Note: If the values set in <i>E1-08</i> and <i>E1-10</i> are too low, the overload tolerance will decrease at low speeds.</p> |
| | | The drive capacity is too small. | Replace the drive with a larger capacity model. |
| | | Overload occurred while running at low speed. | <ul style="list-style-type: none"> Decrease the load when running at low speed. Replace the drive with a larger capacity model. Decrease the value set in <i>C6-02 [Carrier Frequency Selection]</i>. |
| | | The torque compensation gain is too large. | Decrease the value set in <i>C4-01 [Torque Compensation Gain]</i> to make sure that the motor does not stall. |
| | | The speed search-related parameters are set incorrectly. | <ul style="list-style-type: none"> Examine the settings for all speed search-related parameters. Adjust <i>b3-03 [Speed Search Deceleration Time]</i>. Set <i>b3-24 = 1 [Speed Search Method Selection = Speed Estimation]</i> after Auto-Tuning. |
| | | Phase loss in the input power supply is causing the output current to change. | <ul style="list-style-type: none"> Correct errors with the wiring for main circuit drive input power. Make sure that there is no phase loss, and repair problems. |
| | | Overload occurred during overexcitation deceleration. | <ul style="list-style-type: none"> Decrease the value set in <i>n3-13 [OverexcitationBraking (OEB) Gain]</i>. Decrease the value set in <i>n3-21 [HSB Current Suppression Level]</i>. |
| <p>Note:</p> <ul style="list-style-type: none"> The drive detects this fault if the electronic thermal protector of the drive started the drive overload protection. Do a Fault Reset to clear the fault. <i>L5-07 [Fault Reset Enable Select Grp1]</i> disables the Auto Restart function. | | | |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|---|----------------------------|--|--|
| oL3 | Overtorque Detection 1 | A fault occurred on the machine. Example: The machine is locked. | Examine the machine and remove the cause of the fault. |
| | | The parameters are incorrect for the load. | Adjust L6-02 [Torque Detection Level 1] and L6-03 [Torque Detection Time 1] settings. |
| Note: <ul style="list-style-type: none"> The drive detects this fault if the drive output current is more than the level set in L6-02 for longer than L6-03. Do a Fault Reset to clear the fault. If the drive detects this fault, it will operate the motor as specified by the Stopping Method set in L6-01 [Torque Detection Selection 1]. L5-07 [Fault Reset Enable Select Grp1] disables the Auto Restart function. | | | |
| Code | Name | Causes | Possible Solutions |
| oL4 | Overtorque Detection 2 | A fault occurred on the machine. Example: The machine is locked. | Examine the machine and remove the cause of the fault. |
| | | The parameters are incorrect for the load. | Adjust L6-05 [Torque Detection Level 2] and L6-06 [Torque Detection Time 2] settings. |
| Note: <ul style="list-style-type: none"> The drive detects this fault if the drive output current is more than the level set in L6-05 for longer than L6-06. Do a Fault Reset to clear the fault. If the drive detects this fault, it will operate the motor as specified by the Stopping Method set in L6-04 [Torque Detection Selection 2]. L5-07 [Fault Reset Enable Select Grp1] disables the Auto Restart function. | | | |
| Code | Name | Causes | Possible Solutions |
| oL7 | High Slip Braking Overload | The load inertia is too large. | Decrease deceleration times in C1-02 and C1-04 [Deceleration Times] for applications that do not use High Slip Braking. |
| | | An external force on the load side rotated the motor. | |
| | | Something is preventing deceleration on the load side. | |
| | | The value set in n3-04 [HSB Overload Time] is too small. | <ul style="list-style-type: none"> Increase the value set in n3-04. Connect a thermal overload relay to the motor, and set n3-04 = 1200 s (maximum value). |
| Note: <ul style="list-style-type: none"> The drive detects this fault if the output frequency is constant for longer than n3-04. Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oPr | Keypad Connection Fault | The keypad is not securely connected to the connector on the bypass controller. | Examine the connection between the keypad and the bypass controller. |
| | | The connection cable between the bypass controller and the keypad is disconnected. | <ul style="list-style-type: none"> Remove the keypad and connect it again. If the cable is damaged, replace it. |
| Note: <ul style="list-style-type: none"> The bypass controller detects this fault if these conditions are correct: <ul style="list-style-type: none"> -o2-06 = 1 [Keypad Disconnect Detection = Enabled]. -b1-02 = 0 [Run Command Selection 1 = Keypad], or the bypass controller is operating in HAND Mode with the keypad. -Z1-39 = 0 [Drive/Bypass Source Select = Keypad] Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| ov | Overvoltage | Deceleration time is too short and regenerative energy is flowing from the motor into the drive. | <ul style="list-style-type: none"> Set L3-04 = 1 [Stall Prevention during Decel = General Purpose]. Increase the values set in C1-02 or C1-04 [Deceleration Times]. Do Deceleration Rate Auto-Tuning. |
| | | The acceleration time is too short. | <ul style="list-style-type: none"> Make sure that sudden drive acceleration does not cause the fault. Increase the values set in C1-01 or C1-03 [Acceleration Times]. Increase the value set in C2-02 [S-Curve Time @ End of Accel]. Set L3-11 = 1 [Overvoltage Suppression Select = Enabled]. |
| | | The drive output cable or motor is shorted to ground (the current short to ground is charging the main circuit capacitor of the drive through the power supply). | <ol style="list-style-type: none"> Examine the motor main circuit cable, terminals, and motor terminal box, and then remove ground faults. Re-energize the drive. |
| | | If the drive detects ov in these conditions, the speed search-related parameters are incorrect: <ul style="list-style-type: none"> During speed search During momentary power loss recovery When the drive starts again automatically When you do rotational Auto-Tuning | <ul style="list-style-type: none"> Examine the settings for all speed search related parameters. Set b3-19 ≠ 0 [Speed Search Restart Attempts ≠ 0 times]. Adjust b3-03 [Speed Search Deceleration Time] setting. Do Stationary Auto-Tuning for Line-to-Line Resistance and then set b3-24 = 1 [Speed Search Method Selection = Speed Estimation]. Increase the value set in L2-04 [Powerloss V/f Recovery Ramp Time]. |

| Code | Name | Causes | Possible Solutions |
|--|------------------------------|---|---|
| | | The power supply voltage is too high. | Decrease the power supply voltage to align with the drive rated voltage. |
| | | Electrical interference caused a drive malfunction. | <ul style="list-style-type: none"> Examine the control circuit lines, main circuit lines, and ground wiring, and decrease the effects of electrical interference. Make sure that a magnetic contactor is not the source of the electrical interference, then use a Surge Protective Device if necessary. |
| | | The load inertia is set incorrectly. | <ul style="list-style-type: none"> Examine the load inertia settings with overvoltage suppression or stall prevention during deceleration. Adjust <i>L3-25 [Load Inertia Ratio]</i> to align with the qualities of the machine. |
| | | There is motor hunting. | Adjust <i>n1-02 [Hunting Prevention Gain Setting]</i> settings. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the DC bus voltage is more than the <i>ov</i> detection level while the drive is running. The <i>ov</i> detection level is approximately 410 V for 208/240 V bypasses. The detection level is approximately 820 V for 480 V bypasses. Do a Fault Reset to clear the fault. Parameter <i>L5-08 [Fault Reset Enable Select Grp2]</i> disables the Auto Restart function. | | | |
| Code | Name | Causes | Possible Solutions |
| ov2 | DC Bus Overvoltage 2 | The wiring is too long and DC bus voltage is too large. | <ul style="list-style-type: none"> Shorten the shielded motor cable. Decrease the carrier frequency. If the power supply has a neutral ground, switch on the internal EMC filter. |
| Note: <ul style="list-style-type: none"> The drive detects this fault when the DC bus voltage increases to more than the Stall Prevention Level during Deceleration for the time set in <i>S6-23 [OV2 Detect Time]</i>. Do a Fault Reset to clear the fault. This fault is resettable, but will not auto-restart. | | | |
| Code | Name | Causes | Possible Solutions |
| PE1, PE2 | PLC Faults | The communication option detected a fault. | Refer to the manual for the communication option card. |
| Note: Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| PF | Input Phase Loss | There is a phase loss in the drive input power. | Correct errors with the wiring for main circuit drive input power. |
| | | There is loose wiring in the drive input power terminals. | Tighten the terminal screws to the correct tightening torque. |
| | | The drive input power voltage is changing too much. | <ul style="list-style-type: none"> Examine the input power for problems. Make the drive input power stable. If the input power supply is good, examine the magnetic contactor on the main circuit side for problems. |
| | | There is unsatisfactory balance between voltage phases. | <ul style="list-style-type: none"> Examine the input power for problems. Make the drive input power stable. Set <i>L8-05 = 0 [Input Phase Loss Protection Sel = Disabled]</i>. |
| | | The main circuit capacitors have become unserviceable. | <ul style="list-style-type: none"> Examine the capacitor maintenance time in monitor <i>U4-05 [Capacitor Maintenance]</i>. If <i>U4-05</i> is more than 90%, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. If drive input power is correct and the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the DC bus voltage changes irregularly without regeneration. Do a Fault Reset to clear the fault. Use <i>L8-05</i> to enable and disable <i>PF</i> detection. | | | |
| Code | Name | Causes | Possible Solutions |
| PSE | JOHB-SMP3 Protocol Set Error | <ul style="list-style-type: none"> The DIP switches on the JOHB-SMP3 Multi-Protocol Ethernet Card are at factory default settings. The DIP switches on the JOHB-SMP3 are not set to a valid protocol. | Remove power from the drive, wait for the charge light to go out, then set the DIP switches on the JOHB-SMP3 to the desired protocol. Note: Refer to the instructions packaged with the JOHB-SMP3 for more information about DIP switch settings. |
| Note: Do a Fault Reset to clear the fault. | | | |

5.5 Faults

| Code | Name | Causes | Possible Solutions |
|---|----------------------------------|---|---|
| SC | Short Circuit/IGBT Failure | Overheating caused damage to the motor or the motor insulation is not satisfactory. | Measure the motor insulation resistance, and replace the motor if there is electrical conduction or unserviceable insulation. |
| | | The motor main circuit cable is contacting ground to make a short circuit. | <ul style="list-style-type: none"> Examine the motor main circuit cable for damage, and repair short circuits. Measure the resistance between the motor main circuit cable and the ground terminal. If there is electrical conduction, replace the cable. |
| | | A short circuit or ground fault on the drive output side caused damage to the output transistor of the drive. | <ul style="list-style-type: none"> Make sure that there is not a short circuit in terminal B1 and terminals U/T1, V/T2, and W/T3. Make sure that there is not a short circuit in terminals - and terminals U/T1, V/T2, and W/T3. If there is a short circuit, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> The drive detects this error if there is a short circuit or ground fault on the drive output side, or an IGBT failure. Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| SCF | Safety Circuit Fault | The safety circuit is broken. | Replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| SEr | Speed Search Retries Exceeded | The speed search-related parameters are set incorrectly. | <ul style="list-style-type: none"> Decrease <i>b3-10</i> [<i>Speed Estimation Detection Gain</i>]. Increase <i>b3-17</i> [<i>Speed Est Retry Current Level</i>]. Increase <i>b3-18</i> [<i>Speed Est Retry Detection Time</i>]. Do Auto-Tuning again. |
| | | The motor is coasting in the opposite direction of the Run command. | Set <i>b3-14</i> = 1 [<i>Bi-directional Speed Search = Enabled</i>]. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the number of speed search restarts is more than <i>b3-19</i> [<i>Speed Search Restart Attempts</i>]. Do a Fault Reset to clear the fault. | | | |
| Code | Name | Causes | Possible Solutions |
| TiM | Keypad Time Not Set | There is a battery in the keypad, but the date and time are not set. | Use the keypad to set the date and time. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Parameter <i>o4-24</i> [<i>bAT Detection Selection</i>] enables and disables <i>TiM</i> detection. | | | |
| Code | Name | Causes | Possible Solutions |
| UL3 | Undertorque Detection 1 | A fault occurred on the machine. Example: There is a broken pulley belt. | Examine the machine and remove the cause of the fault. |
| | | The parameters are incorrect for the load. | Adjust <i>L6-02</i> [<i>Torque Detection Level 1</i>] and <i>L6-03</i> [<i>Torque Detection Time 1</i>] settings. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the drive output current is less than the level set in <i>L6-02</i> for longer than <i>L6-03</i>. Do a Fault Reset to clear the fault. If the drive detects this error, it will operate the motor as specified by the Stopping Method set in <i>L6-01</i> [<i>Torque Detection Selection 1</i>]. | | | |
| Code | Name | Causes | Possible Solutions |
| UL4 | Undertorque Detection 2 | A fault occurred on the machine. Example: There is a broken pulley belt. | Examine the machine and remove the cause of the fault. |
| | | The parameters are incorrect for the load. | Adjust <i>L6-05</i> [<i>Torque Detection Level 2</i>] and <i>L6-06</i> [<i>Torque Detection Time 2</i>] settings. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the drive output current is less than the level set in <i>L6-05</i> for longer than <i>L6-06</i>. Do a Fault Reset to clear the fault. If the drive detects this error, it will operate the motor as specified by the Stopping Method set in <i>L6-04</i> [<i>Torque Detection Selection 2</i>]. | | | |
| Code | Name | Causes | Possible Solutions |
| UL6 | Underload or Belt Break Detected | The output current decreased less than the motor underload curve set in <i>L6-14</i> [<i>Motor Underload Level @ Min Freq</i>] for longer than the time set in <i>L6-03</i> [<i>Torque Detection Time 1</i>]. | Adjust the <i>L6-14</i> setting to set the output current to stay the level more than the motor underload curve during usual operations. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. | | | |

| Code | Name | Causes | Possible Solutions |
|--|------------------------------|--|--|
| Uv1 | DC Bus Undervoltage | There is a phase loss in the drive input power. | Correct errors with the wiring for main circuit drive input power. |
| | | There is loose wiring in the drive input power terminals. | Tighten the terminal screws to the correct tightening torque. |
| | | The drive input power voltage is changing too much. | <ul style="list-style-type: none"> Examine the input power for problems. Make the drive input power stable. If the input power supply is good, examine the magnetic contactor on the main circuit side for problems. |
| | | There was a loss of power. | Use a better power supply. |
| | | The main circuit capacitors have become unserviceable. | Examine the capacitor maintenance time in monitor <i>U4-05 [CapacitorMaintenance]</i> . If <i>U4-05</i> is more than 90%, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| | | The relay or contactor on the soft-charge bypass relay is damaged. | <i>U4-06 [PreChargeRelayMainte]</i> shows the performance life of the soft-charge bypass relay. If <i>U4-06</i> is more than 90%, replace the board or the drive. For information about replacing the board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the DC bus voltage decreases below the level set in <i>L2-05 [Undervoltage Detection Lvl (Uv1)]</i> while the drive is running. The <i>Uv1</i> detection level is approximately 190 V for 208/240 V bypasses. The detection level is approximately 380 V for 480 V bypasses. The detection level is approximately 350 V when <i>E1-01 [Input AC Supply Voltage] < 400</i>. Do a Fault Reset to clear the fault. Fault trace is not available for this fault. <i>L5-08 [Fault Reset Enable Select Grp2]</i> disables the Auto Restart function. | | | |
| Code | Name | Causes | Possible Solutions |
| Uv2 | Control Power Undervoltage | The value set in <i>L2-02 [Power Loss Ride Through Time]</i> increased and the momentary power loss recovery unit is not connected to the drive. | Connect the momentary power loss recovery unit to the drive. |
| | | There was a problem with the drive hardware. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the control power supply voltage decreases. Do a Fault Reset to clear the fault. Fault trace is not available for this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| Uv3 | Soft Charge Answerback Fault | The relay or contactor on the soft-charge bypass relay is damaged. | <ul style="list-style-type: none"> Re-energize the drive. If the fault stays, replace the control board or the drive. Check monitor <i>U4-06 [PreChargeRelayMainte]</i>, which shows the performance life of the soft-charge bypass relay. If <i>U4-06</i> is more than 90%, replace the board or the drive. For information about replacing the board, contact Yaskawa or your nearest sales representative. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Fault trace is not available for this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| VLTS | Thermostat Fault | The digital input from the terminal set for <i>Thermostat Fault [HI-xx = 88]</i> is active. | Examine the wiring or wait for the motor to cool. |
| Note: <ul style="list-style-type: none"> Do a Fault Reset to clear the fault. Parameter <i>L5-53 [Thermostat Fault Retry Selection]</i> sets the Auto Restart function of this fault. | | | |

5.6 Minor Faults/Alarms

This section gives information about the causes and possible solutions when a minor fault or alarm occurs. Use the information in this table to remove the cause of the minor fault or alarm.

| Code | Name | Causes | Possible Solutions |
|--|----------------------------------|---|---|
| AFBL | Analog Fbk Lost, Switched to Net | The analog input source is defective or broken. | Make sure that you install the PID Feedback source and it operates correctly. |
| | | The parameter setting is $H3\text{-}xx \neq B$ [<i>MFAI Function Selection \neq PID Feedback</i>]. | Set $H3\text{-}xx = B$ to use the analog input source for PID Feedback. |
| Note: If the drive detects this error, the terminal set to $H2\text{-}01$ to $H2\text{-}03 = 10$ [<i>MFDO Function Selection = Alarm</i>] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| AuDis | Low PI Aux Fdbk Drive Disabled | <ul style="list-style-type: none"> PI Auxiliary Feedback is less than the $YF\text{-}06$ [<i>PI Aux Control Wake-up Level</i>] setting, and the drive is stopped or running as a Lag drive. | <ul style="list-style-type: none"> Make sure that the $YF\text{-}06$ setting is correct. Wait for the PI Auxiliary Feedback to recover. |
| Note: If the drive detects this error, the terminal set to $H2\text{-}01$ to $H2\text{-}03 = 10$ [<i>MFDO Function Selection = Alarm</i>] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| AL02 | Interlock Open | The digital input set to interlock is open | Make sure that the damper is functioning correctly. The damper could be opening and the switch could be open. |
| Code | Name | Causes | Possible Solutions |
| AL03 | Emergency Override Bypass | The digital input terminal set to $H2\text{-}0x = 25$ [<i>Digital input function selection = Emergency Override Bypass</i>] activated. | When the emergency condition is gone, deactivate the digital input set to <i>Emergency Override Bypass</i> . |
| Code | Name | Causes | Possible Solutions |
| AL09 | Restart Delay Active | The restart delay is active and the drive received a Run command. | <ul style="list-style-type: none"> This is not an alarm. It is information to show that the drive is not running. When you remove the Run command to the drive, the $AL09$ alarm will go away. Parameters $Z1\text{-}60$ [<i>Blackout Operation Select</i>] and $Z1\text{-}61$ [<i>Power Loss Restart Delay Time</i>] set restart delay. |
| Code | Name | Causes | Possible Solutions |
| AL13 | Loss of Load Detected | The motor is disconnected from the load. | Replace the belt or coupling between the motor and the load. If the bypass detected this alarm incorrectly, make sure that parameters $Z1\text{-}31$ to $Z1\text{-}36$ are correct for your application. |
| Code | Name | Causes | Possible Solutions |
| AL16 | Input Phase Rotation | The phase rotation is incorrect while $Z1\text{-}52 = 1$ in Bypass Mode. | Make sure that the sequence (phase rotation) of the input wiring to the bypass package is correct. |
| Code | Name | Causes | Possible Solutions |
| AL17 | Remote Xfer disabled in Reverse | The drive is running in reverse and it received a Remote Transfer command. | This is not an alarm. It is information to show that the bypass cannot remote transfer when the drive is running in reverse. |
| Code | Name | Causes | Possible Solutions |
| AL18 | Auto Xfer disabled in Reverse | When auto transfer is enabled, the drive detects a fault and it cannot transfer while it is running in reverse. | This is not an alarm. It is information to show that the drive cannot auto transfer when reverse run is active. |
| Code | Name | Causes | Possible Solutions |
| AuFbl | PI Aux Fdbk Lost Switched to Net | The analog input source is defective or broken. | Make sure that you install the Auxiliary PI Feedback source and it operates correctly. |
| Note: <ul style="list-style-type: none"> The drive detects this error if it detected a wire-break with the <i>PI Auxiliary Control Feedback</i> [$H3\text{-}xx = 27$] analog signal and it uses PI Auxiliary Feedback. If the drive detects this error, the terminal set to $H2\text{-}01$ to $H2\text{-}03 = 10$ [<i>MFDO Function Selection = Alarm</i>] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| AUXFB | PI Aux Feedback Level Loss | The analog input from the terminal set to $H3\text{-}xx = 27$ [<i>MFAI Function Selection = PI Auxiliary Control Feedback Level</i>] is more than 21 mA or less than 3 mA for longer than 1 s. | Repair transducer or wiring. |
| Note: If the drive detects this error, the terminal set to $H2\text{-}01$ to $H2\text{-}03 = 10$ [<i>MFDO Function Selection = Alarm</i>] will activate. | | | |

| Code | Name | Causes | Possible Solutions |
|--|----------------------------------|--|--|
| bAT | Keypad Battery Low Voltage | The keypad battery voltage is low. | Replace the keypad battery. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Selection = Alarm] will activate. Set $o4-24$ [bAT Detection Selection] to enable/disable bAT detection. | | | |
| Code | Name | Causes | Possible Solutions |
| bb | Baseblock | An external baseblock command was entered through one of the drive MFDI terminals Sx, and the drive output stopped as shown by an external baseblock command. | Examine the external sequence and timing of the baseblock command input. |
| Note: The drive will not output a minor fault signal for this alarm. | | | |
| Code | Name | Causes | Possible Solutions |
| bCE | Bluetooth Communication Error | The smartphone or tablet with DriveWizard Mobile is too far from the keypad. | Move to 10 m (32.8 ft) or less from the keypad. Note: bCE can occur when the smartphone or tablet is 10 m (32.8 ft) or nearer to the keypad for different smartphone and tablet specifications. |
| | | Radio waves from a different device are causing interference with communications between the smartphone or tablet and keypad. | Make sure that no device around the keypad uses the same radio bandwidth (2400 MHz to 2480 MHz), and prevent radio interference. |
| Note: <ul style="list-style-type: none"> The drive detects this error when you use a smartphone or tablet and a Bluetooth LCD keypad to operate the drive. If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Selection = Alarm] will activate. Use $o2-27$ [bCE Detection selection] to enable and disable bCE detection. | | | |
| Code | Name | Causes | Possible Solutions |
| BuDif | Main Fdbk Lost, Using Diff Fdbk | Parameter $Y4-41 = 1$ [Diff Lvl Src Fdbk Backup Select = Enabled] and the drive detected a wire-break on the analog input terminal set for PID Feedback [H3-xx = B]. | Examine the connection of the Main PID Feedback Transducer. |
| | | Main PID Feedback Transducer is broken. | Replace Main PID Feedback Transducer. |
| Note: <ul style="list-style-type: none"> The drive detects this error if it does not receive the PID Feedback signal and it uses Differential Feedback [H3-xx = 2D] as backup. If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| Bu-Fb | Main Fdbk Lost Using Backup Fdbk | The drive detected wire-break on the analog input terminal set to $H3-xx = B$ [MFAI Function Selection = PID Feedback]. | Examine the connection of the Main PID Feedback Transducer. |
| | | Main PID Feedback Transducer is broken. | Replace Main PID Feedback Transducer. |
| Note: If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| BuFbl | Backup Fdbk Lost Chk/Repl Xducer | The drive detected wire-break on the analog input terminal set for PID Feedback Backup [H3-xx = 24]. | Examine the connection of the Differential PID Feedback transducer. |
| | | Backup PID Feedback Transducer is broken. | Replace Backup PID Feedback Transducer. |
| | | Parameter $Y4-41 = 1$ [Diff Lvl Src Fdbk Backup Select = Enabled] and the drive detected a wire-break on the analog input terminal set for Differential Level Source [H3-xx = 2D]. | Examine the connection of the Differential PID Feedback transducer. |
| | | Parameter $Y4-41 = 1$ and the Differential PID Feedback Transducer is broken. | <ul style="list-style-type: none"> Replace the Differential PID Feedback Transducer. Set $Y4-41 = 0$ [Disabled]. |
| Note: <ul style="list-style-type: none"> The drive detects this error if it does not receive the PID Feedback Backup signal. If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| bUS | Option Communication Error | The communications cable wiring is incorrect. | Correct wiring errors. |
| | | There is a short-circuit in the communications cable or the communications cable is not connected. | <ul style="list-style-type: none"> Repair short circuits and connect cables. Replace the defective communications cable. |

5.6 Minor Faults/Alarms

| Code | Name | Causes | Possible Solutions |
|--|--------------------------------|--|--|
| | | Electrical interference caused a communication data error. | <ul style="list-style-type: none"> Examine the control circuit lines, main circuit lines, and ground wiring, and decrease the effects of electrical interference. Make sure that a magnetic contactor is not the source of the electrical interference, then use a Surge Protective Device if necessary. Use only the recommended cables or other shielded line. Ground the shield on the controller side or the drive input power side. Separate the communication wiring from drive power lines, and install a noise filter to the input side of the power supply for communication. Decrease the effects of electrical interference from the controller. |
| | | The option card is incorrectly installed to the bypass controller. | Correctly install the option card to the bypass controller. |
| | | The option card is damaged. | If the alarm continues and the wiring is correct, replace the option card. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the Run command or frequency reference is assigned to the option card. If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. If the drive detects this error, it will operate the motor as specified by the stopping method set in <i>F6-01 [Communication Error Selection]</i>. | | | |
| Code | Name | Causes | Possible Solutions |
| bUSy | Busy | You set the bypass controller to use serial communications to change parameters, but you used the keypad to change parameters. | Use serial communications to enter the enter command, then use the keypad to change the parameter. |
| | | You tried to change a parameter while the bypass controller was changing a setting. | Wait until the process is complete. |
| Code | Name | Causes | Possible Solutions |
| CALL | Serial Comm Transmission Error | The communications cable wiring is incorrect. | Correct wiring errors. |
| | | There is a short circuit in the communications cable or the communications cable is not connected. | <ul style="list-style-type: none"> Repair the short-circuited or disconnected portion of the cable. Replace the defective communications cable. |
| | | A programming error occurred on the controller side. | Examine communications at start-up and correct programming errors. |
| | | There is damage to the communications circuitry. | <ul style="list-style-type: none"> Do a self-diagnostics check. If the problem continues, replace the control board or the drive. Contact Yaskawa or your nearest sales representative to replace the control board. |
| | | The termination resistor setting for RS-485 based communications is incorrect. | On the last drive of an RS-485 based network, set DIP switch S2 to the ON position to enable the termination resistor. |
| Note: <ul style="list-style-type: none"> The drive detects this error if it does not correctly receive communications from the controller when the drive is first energized. Parameter <i>H5-33 [Power-up CALL Alarm]</i> enables or disables the detection of this alarm at power-up. In bypass controller software versions 00444 and later, HAND operation is available during a <i>CALL</i> alarm. | | | |
| Code | Name | Causes | Possible Solutions |
| CE | Serial Communication Error | The communications cable wiring is incorrect. | Correct wiring errors. |
| | | There is a short circuit in the communications cable or the communications cable is not connected. | <ul style="list-style-type: none"> Repair short circuits and connect cables. Replace the defective communications cable. |
| | | Electrical interference caused a communication data error. | <ul style="list-style-type: none"> Examine the control circuit lines, main circuit lines, and ground wiring, and decrease the effects of electrical interference. Make sure that a magnetic contactor is not the source of the electrical interference, then use a Surge Protective Device if necessary. Use only the recommended cables or other shielded line. Ground the shield on the controller side or the drive input power side. Separate the communication wiring from drive power lines, and install a noise filter to the input side of the power supply for communication. Decrease the effects of electrical interference from the controller. |
| | | The communication protocol is not compatible. | <ul style="list-style-type: none"> Examine the values set in <i>H5-xx</i>. Examine the settings on the controller side and correct the difference in communication conditions. |
| | | The value set in <i>H5-09 [CE Detection Time]</i> is too small for the communications cycle. | <ul style="list-style-type: none"> Change the controller software settings. Increase the value set in <i>H5-09</i>. |

| Code | Name | Causes | Possible Solutions |
|--|---------------------------------|--|---|
| | | The controller software or hardware is causing a communication problem. | Examine the controller and remove the cause of the problem. |
| Note: <ul style="list-style-type: none"> This alarm is a different alarm from <i>CE [Run at H5-34 (CE Go-To-Freq)]</i>. The keypad will show this alarm when: <ul style="list-style-type: none"> –H5-04 ≠ 4 [Communication Error Stop Method ≠ Run at H5-34 (CE Go-To-Freq)] –H5-04 = 4 but the drive cannot operate at the selected frequency The drive detects this error if it does not correctly receive control data for the <i>CE</i> detection time set to H5-09. If the drive detects this error, it will operate the motor as specified by the stopping method set in H5-04. | | | |
| Code | Name | Causes | Possible Solutions |
| CE | Run at H5-34 (CE Go-To-Freq) | The communications cable wiring is incorrect. | Correct wiring errors. |
| | | There is a short circuit in the communications cable or the communications cable is not connected. | <ul style="list-style-type: none"> Repair short circuits and connect cables. Replace the defective communications cable. |
| | | Electrical interference caused a communication data error. | <ul style="list-style-type: none"> Examine the control circuit lines, main circuit lines, and ground wiring, and decrease the effects of electrical interference. Make sure that a magnetic contactor is not the source of the electrical interference, then use a Surge Protective Device if necessary. Use only recommended shielded line. Ground the shield on the controller side or on the drive input power side. Separate the communication wiring from drive power lines, and install a noise filter to the input side of the power supply for communication. Decrease the effects of electrical interference from the controller. |
| | | The communication protocol is not compatible. | <ul style="list-style-type: none"> Examine the values set in H5-xx. Examine the settings on the controller side and correct the difference in communication conditions. |
| | | The value set in H5-09 [CE Detection Time] is too small for the communications cycle. | <ul style="list-style-type: none"> Make sure that the settings are compatible. Change the software settings in the PLC. Increase the value set in H5-09. |
| | | The controller software or hardware is causing a communication problem. | Examine the controller and remove the cause of the problem. |
| Note: <ul style="list-style-type: none"> This alarm is a different alarm from the standard <i>CE [Serial Communication Error]</i>. The keypad will show this alarm only when H5-04 = 4 [Communication Error Stop Method = Run at H5-34 (CE Go-To-Freq)]. If the drive cannot operate at the selected frequency, the keypad will show the standard <i>CE</i> alarm. The drive detects this error if it does not correctly receive control data for the <i>CE</i> detection time set to H5-09. | | | |
| Code | Name | Causes | Possible Solutions |
| CrST | Cannot Reset | The drive received a fault reset command when a Run command was active. | Turn off the Run command or switch into OFF mode, then reset the fault. |
| Code | Name | Causes | Possible Solutions |
| CyPo | Cycle Power to Accept Changes | Although F6-15 = 1 [Comm. Option Parameters Reload = Reload Now], the drive does not update the communication option parameters. | De-energize then re-energize the bypass to activate the new option communication parameters. |
| Code | Name | Causes | Possible Solutions |
| DIFF | Differential Feedback Exceeded | The difference between the PID Feedback and Differential Level Source [H3-xx = 2D] is more than the level set in Y4-18 [Pre-Charge Loss of Prime Level 2] for the time set in Y4-19 [Differential Lvl Detection Time]. | <ul style="list-style-type: none"> Replace the feedback transducer or transducers. Set Y4-18 and Y4-19 correctly. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, it will respond as specified by the setting of Y4-20 [Differential Level Detection Sel]. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| dnE | Drive Disabled | A terminal set for H1-xx = 6A [MFDO Function Selection = Drive Enable] deactivated. | Examine the operation sequence. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EF | FWD/REV Run Command Input Error | The drive received a forward command and a reverse command at the same time for longer than 0.5 s. | Examine the forward and reverse command sequence and correct the problem. |
| Note: <ul style="list-style-type: none"> If the drive detects <i>EF</i>, the motor will ramp to stop. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |


5.6 Minor Faults/Alarms

| Code | Name | Causes | Possible Solutions |
|---|------------------------------|---|---|
| EF0 | Option Card External Fault | The communication option card received an external fault from the controller. | 1. Find the device that caused the external fault and remove the cause. 2. Clear the external fault input from the controller. |
| | | Programming error occurred on the controller side. | Examine the operation of the controller program. |
| Note: • The drive detects this error if the alarm function on the external device side is operating. • Use F6-03 [Comm External Fault (EF0) Select] to set the stopping method for this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| EF1 | External Fault (Terminal S1) | MFDI terminal S1 caused an external fault through an external device. | 1. Find the device that caused the external fault and remove the cause. 2. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S1. |
| | | External Fault [HI-01 = 2C to 2F] is set to MFDI terminal S1, but the terminal is not in use. | Correctly set the MFDI. |
| Note: If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EF2 | External Fault (Terminal S2) | MFDI terminal S2 caused an external fault through an external device. | 1. Find the device that caused the external fault and remove the cause. 2. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S2. |
| | | External Fault [HI-02 = 2C to 2F] is set to MFDI terminal S2, but the terminal is not in use. | Correctly set the MFDI. |
| Note: If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EF3 | External Fault (Terminal S3) | MFDI terminal S3 caused an external fault through an external device. | 1. Find the device that caused the external fault and remove the cause. 2. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S3. |
| | | External Fault [HI-03 = 2C to 2F] is set to MFDI terminal S3, but the terminal is not in use. | Correctly set the MFDI. |
| Note: If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EF4 | External Fault (Terminal S4) | MFDI terminal S4 caused an external fault through an external device. | 1. Find the device that caused the external fault and remove the cause. 2. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S4. |
| | | External Fault [HI-04 = 2C to 2F] is set to MFDI terminal S4, but the terminal is not in use. | Correctly set the MFDI. |
| Note: If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EF5 | External Fault (Terminal S5) | MFDI terminal S5 caused an external fault through an external device. | 1. Find the device that caused the external fault and remove the cause. 2. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S5. |
| | | External Fault [HI-05 = 2C to 2F] is set to MFDI terminal S5, but the terminal is not in use. | Correctly set the MFDI. |
| Note: If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EF6 | External Fault (Terminal S6) | MFDI terminal S6 caused an external fault through an external device. | 1. Find the device that caused the external fault and remove the cause. 2. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S6. |

| Code | Name | Causes | Possible Solutions |
|--|---------------------------------|--|--|
| | | <i>External Fault [H1-06 = 2C to 2F]</i> is set to MFDI terminal S6, but the terminal is not in use. | Correctly set the MFDI. |
| Note: If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EF7 | External Fault (Terminal S7) | MFDI terminal S7 caused an external fault through an external device. | 1. Find the device that caused the external fault and remove the cause. 2. Clear the external fault input in the MFDI. |
| | | The wiring is incorrect. | Correctly connect the signal line to MFDI terminal S7. |
| | | <i>External Fault [H1-07 = 2C to 2F]</i> is set to MFDI terminal S7, but the terminal is not in use. | Correctly set the MFDI. |
| Note: If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EOF | Emergency Override FWD | The digital input terminal set to <i>H1-xx = AF [MFDI Function Selection = Emergency Override FWD]</i> activated. | When the emergency condition is gone, deactivate the digital input set to <i>Emergency Override FWD</i> . |
| Note: If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EOR | Emergency Override REV | The digital input terminal set to <i>H1-xx = B0 [MFDI Function Selection = Emergency Override REV]</i> activated. | When the emergency condition is gone, deactivate the digital input set to <i>Emergency Override REV</i> . |
| Note: If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| EP24v | External Power 24V Supply | The voltage of the main circuit power supply decreased, and the 24 V power supply is supplying power to the drive. | <ul style="list-style-type: none"> Examine the main circuit power supply. Turn ON the main circuit power supply to run the drive. |
| Note: <ul style="list-style-type: none"> Set <i>o2-26 [Ext. Power 24V Supply Display]</i> to enable or disable <i>EP24v</i> detection. The drive will not output an alarm signal for this alarm. | | | |
| Code | Name | Causes | Possible Solutions |
| FDBKL | Feedback Loss Wire Break | <p>The analog input from the terminal set to <i>H3-xx = B [MFAI Function Selection = PID Feedback]</i> is more than 21 mA or less than 3 mA for longer than 1 s in these conditions:</p> <ul style="list-style-type: none"> <i>b5-82 = 1 [Feedback Loss 4 ~ 20mA Detect Sel = Alarm Only]</i> <i>b5-01 ≠ 0 [PID Mode Setting ≠ Disabled]</i> <i>H3-01 or H3-09 = 2 [Terminal A1/A2 Signal Level Selection = 4 to 20 mA]</i> | Make sure that you install the PID feedback source and it operates correctly. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. If the drive detects this error, it will operate the motor as specified by the settings of <i>b5-82</i>. Parameter <i>L5-42 [Feedback Loss Fault Retry Select]</i> sets the Auto Restart function of this error. | | | |
| Code | Name | Causes | Possible Solutions |
| FLGT | Feedback Loss, Go To Freq b5-83 | <p>The analog input from the terminal set to <i>H3-xx = B [MFAI Function Selection = PID Feedback]</i> is more than 21 mA or less than 3 mA for longer than 1 s in these conditions:</p> <ul style="list-style-type: none"> <i>b5-82 = 3 [Feedback Loss 4 ~ 20mA Detect Sel = Run At b5-83]</i> <i>b5-01 ≠ 0 [PID Mode Setting ≠ Disabled]</i> <i>H3-01 or H3-09 = 2 [Terminal A1/A2 Signal Level Selection = 4 to 20 mA]</i> | Make sure that you install the PID feedback source and it operates correctly. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. If the drive detects this error, it will operate the motor at the speed set in <i>b5-83 [Feedback Loss Goto Frequency]</i> as specified by the setting of <i>b5-82</i>. | | | |
| Code | Name | Causes | Possible Solutions |
| FIRE_ST | Fire Stat Open | The bypass detected a Fire Stat condition. | <ul style="list-style-type: none"> Check the digital input programmed for Fire Stat Switch (<i>Z2-0x = 38</i>). Check the connected device for continuity. Check Bypass Digital Input Invert Settings in <i>Z2-09 to Z2-16</i>. |

5.6 Minor Faults/Alarms

| Code | Name | Causes | Possible Solutions |
|---|----------------------------------|---|---|
| FREEZ_ST | Freeze Stat Open | The bypass detected a Freeze Stat condition. | <ul style="list-style-type: none"> Check the digital input programmed for Freeze Stat Switch (Z2-0x = 39). Check the connected device for continuity. Check Bypass Digital Input Invert Settings in Z2-09 to Z2-16. |
| Code | Name | Causes | Possible Solutions |
| FR<MS | Freq Ref < Minimum Speed (Y1-06) | <p>The drive frequency reference setting is less than the value set in Y1-06 [Minimum Speed] in these conditions:</p> <ul style="list-style-type: none"> The drive is not in PI Mode The drive is running Minimum Speed is enabled (Y1-06 > 0.00) Y1-06 > Y4-12 [Thrust Frequency] | Increase the frequency reference to a value more than Y1-06. |
| <p>Note:</p> <ul style="list-style-type: none"> If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. If the drive detects this error, it internally sets the frequency reference to the value set in Y1-06. | | | |
| Code | Name | Causes | Possible Solutions |
| FR<TH | Freq. Reference < Thrust (Y4-12) | <p>The drive frequency reference setting is less than the value set in Y4-12 [Thrust Frequency] in these conditions:</p> <ul style="list-style-type: none"> The drive is not in PI Mode The drive is running Thrust is enabled (Y4-11 [Thrust Acceleration Time] > 0.00 and Y4-12 > Y1-06 [Minimum Speed]) | Increase the frequency reference to a value more than Y4-12. |
| <p>Note:</p> <ul style="list-style-type: none"> If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. If the drive detects this error, it internally sets the frequency reference to the value set in Y4-12. | | | |
| Code | Name | Causes | Possible Solutions |
| HCA | High Current Alarm | The load is too heavy. | <ul style="list-style-type: none"> Decrease the load for applications with repetitive starts and stops. Replace the drive with a larger capacity model. |
| | | The acceleration time is too short. | <ul style="list-style-type: none"> Calculate the torque necessary during acceleration related to the load inertia and the specified acceleration time. Increase the values set in C1-01 or C1-03 [Acceleration Times] until you get the necessary torque. Increase the values set in C2-01 to C2-04 [S-Curve Characteristics] until you get the necessary torque. Replace the drive with a larger capacity model. |
| | | The drive is trying to operate a specialized motor or a motor that is larger than the maximum applicable motor output of the drive. | <ul style="list-style-type: none"> Examine the motor nameplate, the motor, and the drive to make sure that the drive rated current is larger than the motor rated current. Replace the drive with a larger capacity model. |
| | | The current level temporarily increased because of speed search after a momentary power loss or while trying to Auto Restart. | If speed search or Auto Restart cause an increase in current, the drive can temporarily show this alarm. The time that the drive shows the alarm is short. No more steps are necessary to clear the alarm. |
| <p>Note:</p> <ul style="list-style-type: none"> The drive detects this error if the drive output current is more than the overcurrent alarm level (150% of the rated current). If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| HIAUX | High PI Aux Feedback Level | <p>PI Auxiliary Feedback is more than the level set in YF-12 [PI Aux Control High Level Detect] for the time set in YF-13 [PI Aux High Level Detection Time] in these conditions:</p> <ul style="list-style-type: none"> The drive operates in AUTO Mode. The output frequency > 0. | <ul style="list-style-type: none"> Decrease the PI Auxiliary Feedback level to less than YF-12. Set YF-12 and YF-13 correctly. |
| <p>Note:</p> <p>If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate.</p> | | | |
| Code | Name | Causes | Possible Solutions |
| HIFB | High Feedback Sensed | The feedback level is more than the level set in Y1-11 [High Feedback Level]. | <ul style="list-style-type: none"> Decrease the feedback level to less than Y1-11 - Y1-14 [Hysteresis Level]. Set Y1-11 and Y1-12 correctly. |
| <p>Note:</p> <ul style="list-style-type: none"> If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. If the drive detects this error, it will respond as specified by the setting of Y1-13 [High Feedback Selection]. | | | |

| Code | Name | Causes | Possible Solutions |
|--|----------------------------------|---|--|
| INTLK | BAS Interlock | The digital input terminal set to $H1-xx = B2$ [MFDI Function Selection = BAS Interlock] deactivates. | Make sure the cause of interlock. |
| Note:  will only flash when there is a Run command. | | | |
| Code | Name | Causes | Possible Solutions |
| L24v | Loss of External Power 24 Supply | The voltage of the backup 24 V power supply has decreased. The main circuit power supply is operating correctly. | <ul style="list-style-type: none"> Examine the external 24 V power supply for disconnected wires and wiring errors and repair the problems. Examine the external 24 V power supply for problems. |
| Note: <ul style="list-style-type: none"> Set $\alpha 2-23$ [External 24V Powerloss Detection] to enable or disable L24v detection. The drive will not output an alarm signal for this alarm. | | | |
| Code | Name | Causes | Possible Solutions |
| LCP | Low City Pressure | Insufficient pressure is present on the inlet to the pump in these conditions: <ul style="list-style-type: none"> $Y4-24 = 0$ [Low City Alarm Text = Low City Pressure] The terminal set for $Z2-0x = 46$ [Bypass MFDI Function Selection - Low City Pressure] activates | <ul style="list-style-type: none"> Examine the pressure switch contact for correct operation. Make sure that control wiring to drive terminal strip from pressure switch contact. Make sure that suction pressure is present with an isolated measuring device. Set $Y4-22$ [Low City On-Delay Time] and $Y4-23$ [Low City Off-Delay Time] correctly. Deactivate the digital input terminals set to $Z2-0x = 46$ [Bypass MFDI Function Selection - Low City Pressure]. |
| Note: If the drive detects this error during run, it coasts to stop and does not operate until the digital input has deactivated for the time set in $Y4-22$. | | | |
| Code | Name | Causes | Possible Solutions |
| LOAUX | Low PI Aux Feedback Level | When the drive operates in AUTO Mode or HAND Mode, PI Auxiliary Feedback is less than the level set in $YF-09$ [PI Aux Control Low Lvl Detection] for the time set in $YF-10$ [PI Aux Control Low Lvl Det Time] and the drive is running. | <ul style="list-style-type: none"> Increase the PI Auxiliary Feedback level more than $YF-09$. Set $YF-09$ and $YF-10$ correctly. |
| Note: If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| LOFB | Low Feedback Sensed | The feedback level is less than the level set in $Y1-08$ [Low Feedback Level] for the time set in $Y1-09$ [Low Feedback Lvl Fault Dly Time]. | <ul style="list-style-type: none"> Increase the feedback level to more than $Y1-08 + Y1-14$ [High Feedback Hysteresis Level]. Set $Y1-08$ and $Y1-09$ correctly. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Selection = Alarm] will activate. If the drive detects this fault, it will respond as specified by the setting of $Y1-10$ [Low Feedback Selection]. | | | |
| Code | Name | Causes | Possible Solutions |
| LoG | Com Error / Abnormal SD Card | There is not a micro SD card in the keypad. <ul style="list-style-type: none"> The drive is connected to USB. The number of log communication files is more than 1000. The micro SD card does not have available memory space. The line number data in a log communication file was changed. A communication error between the keypad and drive occurred during a log communication. | Put a micro SD card in the keypad. Set $\alpha 5-01 = 0$ [Log Start/Stop Selection = OFF]. |
| Note: If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 6A$ [MFDO Function Selection = Data Logger Error] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| LOP | Loss of Prime | The pump load that measured based on the $Y1-18$ [Prime Loss Detection Method] setting is less than the level set in $Y1-19$ [Prime Loss Level] for the time set in $Y1-20$ [Prime Loss Time], and the output frequency is $Y1-21$ [Prime Loss Activation Freq] or more. | <ul style="list-style-type: none"> Examine a dry well, air in the system, or no water in the system. Use preferred priming method suggested by the pump manufacturer to restart the pump. When there is resistance in the pump, allow the system to pump water again. Set $Y1-18$ to $Y1-21$ correctly. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to $H2-01$ to $H2-03 = 10$ [MFDO Function Selection = Alarm] will activate. If the drive detects this fault, it will respond as specified by the setting of $Y1-22$ [Prime Loss Selection]. | | | |

5.6 Minor Faults/Alarms

| Code | Name | Causes | Possible Solutions |
|---|----------------------------------|--|--|
| LOW_SUCT | Low Suction Detected | The bypass detected a Low Suction condition. | <ul style="list-style-type: none"> Check the digital input programmed for Low Suction Switch (Z2-0x = 42). Check the connected device for continuity. Check Bypass Digital Input Invert Settings in Z2-09 to Z2-16. |
| Code | Name | Causes | Possible Solutions |
| LSP | Low Suction Pressure | An external input has indicated that an insufficient suction pressure condition exists in these conditions: <ul style="list-style-type: none"> Y4-24 = 1 [Low City Alarm Text = Low Suction Pressure] The terminal set for H1-xx = B8 or 1B8 [MFDI Function Selection = Low City Pressure or !Low City Pressure] activates | <ul style="list-style-type: none"> Examine the pressure switch contact for correct operation. Make sure that control wiring to drive terminal strip from pressure switch contact. Make sure that suction pressure is present with an isolated measuring device. Increase the system pressure. Set Y4-22 [Low City On-Delay Time] and Y4-23 [Low City Off-Delay Time] correctly. Deactivate the digital input terminals set to H1-xx = B8 or 1B8. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. If the drive detects this error during run, it coasts to stop and does not operate until the digital input has deactivated for the time set in Y4-22. | | | |
| Code | Name | Causes | Possible Solutions |
| LT-1 | Cooling Fan Maintenance Time | The cooling fan is at 90% of its performance life estimate. | <ol style="list-style-type: none"> Replace the cooling fan. Set o4-03 = 0 [Fan Operation Time Setting = 0 h] to reset the cooling fan operation time. |
| Note: When the performance life estimate is expired, the terminal set to H2-01 to H2-03 = 2F [MFDO Function Selection = Maintenance Notification] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| LT-2 | Capacitor Maintenance Time | The capacitors for the main circuit and control circuit are at 90% of their performance life estimate. | Replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: When the performance life estimate is expired, the terminal set to H2-01 to H2-03 = 2F [MFDO Function Selection = Maintenance Notification] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| LT-3 | SoftChargeBypassRelay MainteTime | The soft charge bypass relay is at 90% of its performance life estimate. | Replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Note: When the performance life estimate is expired, the terminal set to H2-01 to H2-03 = 2F [MFDO Function Selection = Maintenance Notification] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| LT-4 | IGBT Maintenance Time (50%) | The IGBT is at 50% of its performance life estimate. | Check the load, carrier frequency, and output frequency. |
| Note: When the performance life estimate is expired, the terminal set to H2-01 to H2-03 = 2F [MFDO Function Selection = Maintenance Notification] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| LWT | Low Water In Tank | An external input has indicated that the water level in the tank is too low in these conditions: <ul style="list-style-type: none"> Y4-24 = 2 [Low City Alarm Text = Low Water in Tank] The terminal set for H1-xx = B8 or 1B8 [MFDI Function Selection = Low City Pressure or !Low City Pressure] activates | <ul style="list-style-type: none"> Examine the pressure switch contact for correct operation. Make sure that control wiring to drive terminal strip from pressure switch contact. Make sure that suction pressure is present with an isolated measuring device. Increase the water level. Set Y4-22 [Low City On-Delay Time] and Y4-23 [Low City Off-Delay Time] correctly. Deactivate the digital input terminals set to H1-xx = B8 or 1B8. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. If the drive detects this error during run, it coasts to stop and does not operate until the digital input has deactivated for the time set in Y4-22. | | | |
| Code | Name | Causes | Possible Solutions |
| NMS | Setpoint Not Met | The feedback deviates from the setpoint at a level more than Y1-15 [Maximum Setpoint Difference] for the time set in Y1-16 [Not Maintaining Setpoint Time]. | <ul style="list-style-type: none"> Examine for a blocked impeller, over cycling, or broken pipe. Set Y1-15 and Y1-16 correctly. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. If the drive detects this error, it will respond as specified by the setting of Y1-17 [Not Maintaining Setpoint Sel]. | | | |

| Code | Name | Causes | Possible Solutions |
|--|-----------------------------|--|---|
| OD | Output Disconnect | The output circuit between the drive and the motor is open, and the drive output current is less than 5% of <i>E2-01 [Motor Rated Current (FLA)]</i> . | <ul style="list-style-type: none"> Close the disconnected output circuit between the drive and the motor. If you do not use a motor disconnect, set <i>Y4-42 = 0 [Disabled]</i>. |
| Note: <ul style="list-style-type: none"> If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. If the drive detects this error, it will respond as specified by the setting of <i>Y4-42 [Output Disconnect Detection Sel]</i>. | | | |
| Code | Name | Causes | Possible Solutions |
| oH | Heatsink Overheat | The ambient temperature is high and the heatsink temperature is more than the <i>L8-02 [Overheat Alarm Level]</i> . | <ul style="list-style-type: none"> Measure the ambient temperature. Increase the airflow around the drive. Install a cooling device (cooling fan or air conditioner) to decrease the ambient temperature. Remove objects near the drive that are producing too much heat. |
| | | There is not sufficient airflow around the drive. | <ul style="list-style-type: none"> Give the drive the correct installation space as shown in the manual. Make sure that there is sufficient circulation around the control panel. Examine the drive for dust or other unwanted materials that could clog the cooling fan. Remove unwanted materials that prevent air circulation. |
| | | The internal cooling fan or fans stopped. | <ol style="list-style-type: none"> Replace the cooling fan. Set <i>o4-03 = 0 [Fan Operation Time Setting = 0 h]</i> to reset the cooling fan operation time. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the heatsink temperature of the drive is more than <i>L8-02</i>. If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. Use <i>L8-03 [Overheat Pre-Alarm Selection]</i> to the stopping method for this fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oH2 | External Overheat (H1-XX=B) | An external device sent an <i>oH2</i> alarm. | <ol style="list-style-type: none"> Find the external device that output the overheat alarm. Remove the cause of the problem. Clear the <i>Overheat Alarm (oH2) [H1-xx = B]</i> in MFDI terminals S1 to S7. |
| Note: <p>If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate.</p> | | | |
| Code | Name | Causes | Possible Solutions |
| oH3 | Motor Overheat (PTC Input) | The thermistor wiring that detects motor temperature is defective. | Correct wiring errors. |
| | | A fault occurred on the machine. Example: The machine is locked. | Examine the machine and remove the cause of the fault |
| | | The motor has overheated. | <ul style="list-style-type: none"> Check the load level, acceleration/deceleration time, and motor start/stop frequency (cycle time). Decrease the load. Increase the values set in <i>C1-01 to C1-04 [Acceleration/Deceleration Times]</i>. Set <i>E2-01 [Motor Rated Current (FLA)]</i> correctly to the value specified by the motor nameplate. Make sure that the motor cooling system is operating correctly, and repair or replace it if it is damaged. Adjust <i>E1-04 to E1-10 [V/f Pattern Parameters]</i>. Decrease the values set in <i>E1-08 [Mid Point A Voltage]</i> and <i>E1-10 [Minimum Output Voltage]</i>. <p>Note: If the values set in <i>E1-08</i> and <i>E1-10</i> are too low, the overload tolerance will decrease at low speeds.</p> |
| Note: <ul style="list-style-type: none"> When <i>H3-02 or H3-10 = E [MFAI Function Selection = Motor Temperature (PTC Input)]</i>, the drive detects this fault if the motor overheat signal entered to analog input terminals A1 and A2 is more than the alarm detection level. If the drive detects this error, the terminal set to <i>H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm]</i> will activate. If the drive detects this error, it will operate the motor as specified by the stopping method set in <i>L1-03 [Motor Thermistor oH Alarm Select]</i>. | | | |

5.6 Minor Faults/Alarms

| Code | Name | Causes | Possible Solutions |
|--|-----------------------------|--|--|
| oL3 | Overtorque 1 | A fault occurred on the machine. Example: The machine is locked. | Examine the machine and remove the cause of the fault. |
| | | The parameters are incorrect for the load. | Adjust L6-02 [Torque Detection Level 1] and L6-03 [Torque Detection Time 1] settings. |
| Note: <ul style="list-style-type: none"> The drive detects this fault if the drive output current is more than the level set in L6-02 for longer than L6-03. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. Use L6-01 [Torque Detection Selection 1] to set the conditions that trigger the minor fault. | | | |
| Code | Name | Causes | Possible Solutions |
| oL4 | Overtorque 2 | A fault occurred on the machine. Example: The machine is locked. | Examine the machine and remove the cause of the fault. |
| | | The parameters are incorrect for the load. | Adjust L6-05 [Torque Detection Level 2] and L6-06 [Torque Detection Time 2] settings. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the drive output current is more than the level set in L6-05 for longer than L6-06. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. Use L6-04 [Torque Detection Selection 2] to set the conditions that trigger the minor fault. | | | |
| Code | Name | Causes | Possible Solutions |
| ov | DC Bus Overvoltage | The drive output cable or motor is shorted to ground (the current short to ground is charging the main circuit capacitor of the drive through the power supply). | <ol style="list-style-type: none"> Examine the motor main circuit cable, terminals, and motor terminal box, and then remove ground faults. Re-energize the drive. |
| | | The power supply voltage is too high. | Decrease the power supply voltage to align with the drive rated voltage. |
| | | Electrical interference caused a drive malfunction. | <ul style="list-style-type: none"> Examine the control circuit lines, main circuit lines, and ground wiring, and minimize the effects of noise. Find the source of the noise. If a magnetic contactor is the source, use Surge Protective Device if necessary. Set L5-01 ≠ 0 [Number of Auto-Restart Attempts ≠ 0 times]. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the DC bus voltage is more than the ov detection level when the Run command has not been input (while the drive is stopped). The ov detection level is approximately 410 V for 208/240 V bypasses. The detection level is approximately 820 V for 480 V bypasses. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| ovEr | Too Many Parameters Changed | You tried to change more than 150 parameters. | Make sure that parameters that do not have an effect on drive operation are at their default settings. Note: <ul style="list-style-type: none"> You can change 150 parameters maximum. If you change parameters that have dependencies, the drive can detect ovEr when the number of changed parameters is fewer than 150. |
| Code | Name | Causes | Possible Solutions |
| OV_PRESS | Over Pressure Detected | The bypass detected an Over Pressure condition. | <ul style="list-style-type: none"> Check the digital input programmed for Over Pressure Switch (Z2-0x = 41). Check the connected device for continuity. Check Bypass Digital Input Invert Settings in Z2-09 to Z2-16. |
| Code | Name | Causes | Possible Solutions |
| PA1 | PLC Error 1 | The network speed on one port does not align with the network speed on the other port. | Make sure that the network speeds on both ports are the same. |
| Code | Name | Causes | Possible Solutions |
| PASS | Serial Communication Test | The serial communications test is complete. | The PASS display will turn off after communications test mode is cleared. |
| Code | Name | Causes | Possible Solutions |
| PF | Input Phase Loss | There is a phase loss in the drive input power. | Correct errors with the wiring for main circuit drive input power. |
| | | Loose wiring in the input power terminals. | Tighten the terminal screws to the correct tightening torque. |
| | | The drive input power voltage is changing too much. | <ul style="list-style-type: none"> Examine the input power for problems. Make the drive input power stable. |
| | | Unsatisfactory balance between voltage phases. | <ul style="list-style-type: none"> Examine the input power for problems. Make the drive input power stable. If the input power supply is good, examine the magnetic contactor on the main circuit side for problems. |


| Code | Name | Causes | Possible Solutions |
|---|-----------------------------|--|---|
| | | The main circuit capacitors are unserviceable. | <ul style="list-style-type: none"> Examine the capacitor maintenance time in monitor U4-05 [CapacitorMaintenance]. If U4-05 is more than 90%, replace the capacitor. Contact Yaskawa or your nearest sales representative for more information. |
| | | | <ul style="list-style-type: none"> Examine the input power for problems. Re-energize the drive. If the alarm stays, replace the circuit board or the drive. Contact Yaskawa or your nearest sales representative for more information. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the DC bus voltage changes irregularly without regeneration. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. Use L8-05 [Input Phase Loss Protection Sel] to enable and disable PF detection. | | | |
| Code | Name | Causes | Possible Solutions |
| SAFE | Safety Open | The bypass detected a Open Safety condition. | <ul style="list-style-type: none"> Check the digital input programmed for Run Enable - Safety (NC) Z2-0x = 22. Check the connected device for continuity. Check the Bypass Digital Input Invert settings in Z2-09 to Z2-16. |
| Code | Name | Causes | Possible Solutions |
| SE | Modbus Test Mode Error | Serial Hardware communications self-diagnostics [Z2-xx = 45] was done while the drive was running. | Stop the drive and do MEMOBUS/Modbus communications self-diagnostics. |
| Note: <p>If drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate.</p> | | | |
| Code | Name | Causes | Possible Solutions |
| SMK_ALRM | Smoke Alarm Active | The bypass detected a Smoke Alarm condition. | <ul style="list-style-type: none"> Check the digital input programmed for Smoke Alarm (Z2-0x = 40). Check the connected device for continuity. Check Bypass Digital Input Invert Settings in Z2-09 to Z2-16. |
| Code | Name | Causes | Possible Solutions |
| STo | Safe Torque OFF | Safe Disable inputs H1-HC and H2-HC are open. | <ul style="list-style-type: none"> Make sure that the Safe Disable signal is input from an external source to terminal H1-HC and H2-HC. When the Safe Disable function is not in use, use a jumper to connect terminals H1-HC and H2-HC. |
| | | There is internal damage to the two Safe Disable channels. | Replace the board or the drive. Contact Yaskawa or your nearest sales representative to replace the board. |
| Note: <ul style="list-style-type: none"> The drive will not output an alarm signal for this alarm. If the drive detects this error, the terminal set to H2-01 to H2-03 = 21 [MFDO Function Selection = Safe Torque OFF] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| SToF | Safe Torque OFF Hardware | One of the two terminals H1-HC or H2-HC received the Safe Disable input signal. | <ul style="list-style-type: none"> Make sure that the Safe Disable signal is input from an external source to terminals H1-HC or H2-HC. When the Safe Disable function is not in use, use a jumper to connect terminals H1-HC and H2-HC. |
| | | The Safe Disable input signal is wired incorrectly. | |
| | | There is internal damage to one Safe Disable channel. | Replace the board or the drive. Contact Yaskawa or your nearest sales representative to replace the board. |
| Note: <p>If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate.</p> | | | |
| Code | Name | Causes | Possible Solutions |
| TiM | Keypad Time Not Set | There is a battery in the keypad, but you have not set the date and time. | Use the keypad to set the date and time. |
| Note: <ul style="list-style-type: none"> Parameter o4-24 [bAT Detection selection] enables and disables TiM detection. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| TrPC | IGBT Maintenance Time (90%) | The IGBT is at 90% of its performance life estimate. | Replace the IGBT or the drive. For more information, contact Yaskawa or your nearest sales representative. |
| Note: <p>If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate.</p> | | | |

5.6 Minor Faults/Alarms

| Code | Name | Causes | Possible Solutions |
|--|----------------------------------|---|---|
| UL3 | Undertorque Detection 1 | A fault occurred on the machine. Example: There is a broken pulley belt. | Examine the machine and remove the cause of the fault. |
| | | The parameters are incorrect for the load. | Adjust L6-02 [Torque Detection Level 1] and L6-03 [Torque Detection Time 1] settings. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the drive output current is less than the level set in L6-02 for longer than L6-03. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. If the drive detects this error, it will operate the motor as specified by the Stopping Method set in L6-01 [Torque Detection Selection 1]. | | | |
| Code | Name | Causes | Possible Solutions |
| UL4 | Undertorque Detection 2 | A fault occurred on the machine. Example: There is a broken pulley belt. | Examine the machine and remove the cause of the fault. |
| | | The parameters are incorrect for the load. | Adjust L6-05 [Torque Detection Level 2] and L6-06 [Torque Detection Time 2] settings. |
| Note: <ul style="list-style-type: none"> The drive detects this error if the drive output current is less than the level set in L6-05 for longer than L6-06. If detected, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. If the drive detects this error, it will operate the motor as specified by the Stopping Method set in L6-04 [Torque Detection Selection 2]. | | | |
| Code | Name | Causes | Possible Solutions |
| UL6 | Underload or Belt Break Detected | The output current decreased less than the motor underload curve set in L6-14 [Motor Underload Level @ Min Freq] for longer than the time set in L6-03 [Torque Detection Time 1]. | Examine parameters L6-13 [Motor Underload Curve Select] and L6-14. |
| | | The belt has broken disconnecting the motor from the load. | |
| Note: If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| Uv | Undervoltage | The drive input power voltage is changing too much. | <ul style="list-style-type: none"> Examine the input power for problems. Make the drive input power stable. If the input power supply is good, examine the magnetic contactor on the main circuit side for problems. |
| | | There is a phase loss in the drive input power. | Correct errors with the wiring for main circuit drive input power. |
| | | There is loose wiring in the drive input power terminals. | Tighten the terminal screws to the correct tightening torque. |
| | | There was a loss of power. | Use a better power supply. |
| | | The main circuit capacitors have become unserviceable. | Examine the capacitor maintenance time in monitor U4-05 [Capacitor Maintenance]. If U4-05 is more than 90%, replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| | | The drive input power transformer is too small and voltage drops when the power is switched on. | <ul style="list-style-type: none"> Check for an alarm when a molded-case circuit breaker, Leakage Breaker (ELCB or GFCI) (with overcurrent protective function), or magnetic contactor is ON. Check the capacity of the drive power supply transformer. |
| Note: <ul style="list-style-type: none"> The drive detects this error if one of these conditions is correct when the Run command has not been input (while the drive is stopped). <ul style="list-style-type: none"> The DC bus voltage < L2-05 [Undervoltage Detection Lvl (Uv1)]. The Contactor that prevents inrush current in the drive was opened. If the drive detects this error, the terminal set to H2-01 to H2-03 = 10 [MFDO Function Selection = Alarm] will activate. | | | |
| Code | Name | Causes | Possible Solutions |
| VBRATION | Vibration Detected | The bypass detected a Vibration condition. | <ul style="list-style-type: none"> Check the digital input programmed for Vibration Switch (Z2-0x = 43). Check the connected device for continuity. Check Bypass Digital Input Invert Settings in Z2-09 to Z2-16. |

5.7 Parameter Setting Errors

Parameter setting errors occur when multiple parameter settings do not agree, or when parameter setting values are not correct. Refer to the table in this section, examine the parameter setting that caused the error, and remove the cause of the error. You must first correct the parameter setting errors before you can operate the drive. The drive will not send notification signals for the faults and alarms when these parameter setting errors occur.

| Code | Name | Causes | Possible Solutions |
|-------|----------------------------------|---|--|
| oPE01 | Drive Capacity Setting Error | The value set in <i>o2-04 [Drive Model (KVA) Selection]</i> does not agree with the drive model. | Consult Yaskawa technical support. |
| Code | Name | Causes | Possible Solutions |
| oPE02 | Parameter Range Setting Error | Parameters settings are not in the applicable setting range. | <ol style="list-style-type: none"> Push  to show <i>U1-18 [oPE Fault Parameter]</i>, and find parameters that are not in the applicable setting range. Correct the parameter settings. <p>Note: If more than one error occurs at the same time, other <i>oPExx</i> errors have priority over <i>oPE02</i>.</p> |
| | | You set $E2-01 \leq E2-03$ [<i>Motor Rated Current (FLA) ≤ Motor No-Load Current</i>]. | <p>Make sure that $E2-01 > E2-03$.</p> <p>Note: If it is necessary to set $E2-01 < E2-03$, first lower the value set in <i>E2-03</i>, and then set <i>E2-01</i>.</p> |
| | | You set $S3-09 < S3-10$ [<i>PI2 Control Output Upper Limit < PI2 Control Output Lower Limit</i>]. | Make sure that $S3-09 > S3-10$ at all times. |
| | | You set $S3-13 > S3-15$ [<i>PI2 Control Low Feedback Lvl > PI2 Control High Feedback Lvl</i>]. | Make sure that $S3-13 < S3-15$ at all times. |
| Code | Name | Causes | Possible Solutions |
| oPE03 | Multi-Function Input Setting Err | The settings for these parameters do not agree: <ul style="list-style-type: none"> <i>Z2-01 to Z2-08 [Digital Input 1 Function (TB2-1) to Digital Input 8 Function (TB2-8)]</i> <i>H1-01 to H1-07 [Terminals S1 to S7 Function Selection]</i> | Correct the parameter settings. |
| | | The settings for the bypass MFDIs <i>Z2-01 to Z2-08</i> overlap and/or the setting for the drive MFDIs <i>H1-01 to H1-07</i> overlap <p>Note: This does not include $H1-xx = 20$ to $2F$ [<i>MFDI Function Selection = External Fault</i>].</p> | Check the settings and make sure that you did not program two or more MFDIs to the same value. |
| | | A minimum of two of these MFDI combinations are set to Digital Inputs (<i>H1-xx</i> and <i>H7-01 to H7-04</i>) at the same time: <ul style="list-style-type: none"> Setting value <i>1E [Reference Sample Hold]</i> Setting values <i>44 to 46 [Add Offset Frequency 1 to 3 (d7-01 to d7-03)]</i> | Remove the function settings that are not in use. |
| | | These commands are set in Digital Inputs (<i>H1-xx</i> and <i>H7-01 to H7-04</i>) at the same time: <ul style="list-style-type: none"> Setting values <i>61 [Speed Search from Fmax]</i> and <i>62 [Speed Search from Fref]</i> | Remove the function settings that are not in use. |
| | | These groups of MFDI functions are not set to Digital Inputs (<i>H1-xx</i> and <i>H7-01 to H7-04</i>) at the same time: <ul style="list-style-type: none"> Setting values <i>3E [PID Setpoint Selection 1]</i> and <i>3F [PID Setpoint Selection 2]</i> Setting values <i>83 [Dedicated Multi-Setpoint YA-02]</i>, <i>84 [Dedicated Multi-Setpoint YA-03]</i>, and <i>85 [Dedicated Multi-Setpoint YA-04]</i> | Set the MFDI groups correctly. |
| | | Settings for N.C. and N.O. input [<i>H1-xx</i>] for these functions were selected at the same time: <ul style="list-style-type: none"> Setting value <i>15 [Fast Stop (N.O.)]</i> Setting value <i>17 [Fast Stop (N.C.)]</i> | Remove one of the function settings. |
| | | These MFDI functions are set at the same time: <ul style="list-style-type: none"> $H1-xx = 6A$ [<i>Drive Enable</i>] $H1-xx = 70$ [<i>Drive Enable 2</i>] | Remove one of the function settings. |

5.7 Parameter Setting Errors

| Code | Name | Causes | Possible Solutions |
|---|---------------------------------|--|--|
| | | <p>These parameters are set at the same time:</p> <ul style="list-style-type: none"> • $H1-xx = 62$ [Speed Search from Fref] • $H5-22 = 1$ [Speed Search from MODBUS = Enabled] <p>Parameter $S3-01 \neq 0$ [PI2 Control Enable Selection ≠ Disabled] and MFDI set for $H1-xx = AD$ [Select PI2 Control PI Parameters] is ON or MFDI set for $H1-xx = 1AD$ [Select PI2 Control PI Parameters] is OFF.</p> | <p>Remove one of the function settings.</p> <ul style="list-style-type: none"> • Set $S3-01 = 0$ to use $H1-xx = AD$ or $1AD$ for the adjustments of $S3-06$ [PI2 Control Proportional Gain] and $S3-07$ [PI2 Control Integral Time] instead of the primary PI controller Proportional and Integral adjustments. • When PI2 Control is necessary, remove the MFDI function setting. |
| Code | Name | Causes | Possible Solutions |
| oPE05 | Run Cmd/Freq Ref Source Sel Err | There is an option card installed on the drive. | Remove the option card from the drive. If it is compatible, install the option card on the bypass control board. |
| | | The setting to assign the Run command or frequency reference to an option card is incorrect. | Correct the parameter settings. |
| | | $Z1-39 = 3$ [Drive/Bypass Source Select = Option PCB] is set, but there is no option card connected. | Connect an option card. |
| | | $b1-01 = 3$ [Frequency Reference Selection 1 = Option PCB] is set, but there is no option card connected. | |
| | | $b1-02 = 3$ [Run Command Selection 1 = Option PCB] is set, but there is no option card connected. | |
| Code | Name | Causes | Possible Solutions |
| oPE07 | Analog Input Selection Error | The settings for $H3-02$ and $H3-10$ [MFAI Function Selection] and $H7-30$ [Virtual Analog Input Selection] overlap. | <p>Set $H3-02$, $H3-10$, and $H7-30$ correctly to prevent overlap.</p> <p>Note: It is possible to set these functions to multiple analog input terminals at the same time:</p> <ul style="list-style-type: none"> • Setting value 0 [Frequency Reference] • Setting values F and $1F$ [Not Used] |
| Code | Name | Causes | Possible Solutions |
| oPE08 | Parameter Selection Error | <p>You set these parameters:</p> <ul style="list-style-type: none"> • $S1-01 = 1$ [Dynamic Noise Control = Enabled] • $Y4-42 \neq 0$ [Output Disconnect Detection Sel ≠ Disabled] | Set $S1-01 = 0$ or $Y4-42 = 0$. |
| | | You set $L6-02$ [Torque Detection Level 1] < $L6-14$ [Motor Underload Level @ Min Freq]. | Set parameters to be $L6-02 \geq L6-14$. |
| Code | Name | Causes | Possible Solutions |
| oPE09 | PID Control Selection Fault | <p>These parameters are set at the same time:</p> <ul style="list-style-type: none"> • $b5-01 = 1$ • $b5-11 = 1$ [PID Output Reverse Selection = Negative Output Accepted] <p>And one of these parameters is set:</p> <ul style="list-style-type: none"> • $d2-02 \neq 0.0$ [Frequency Reference Lower Limit ≠ 0.0%] • $Y1-06 \neq 0.0$ [Minimum Speed ≠ 0.0%] • $Y4-12 \neq 0.0$ [Thrust Frequency ≠ 0.0%] • $YF-01 \neq 0$ [PI Aux Control Selection ≠ Disabled] | Correct the parameter settings. |
| | | <p>Parameter $b5-01 = 3$ and one of these parameters is set at the same time:</p> <ul style="list-style-type: none"> • $d2-02 \neq 0.0$ • $Y1-06 \neq 0.0$ • $Y4-12 \neq 0.0$ • $YF-01 \neq 0$ | Correct the parameter settings. |
| <p>Note: The drive detects this error if the PID control function selection is incorrect. (When $b5-01 = 1$ or 3 [PID Mode Setting = Standard or Fref + PID Trim])</p> | | | |
| Code | Name | Causes | Possible Solutions |
| oPE10 | V/f Data Setting Error | <p>The parameters that set the V/f pattern do not satisfy these conditions:</p> <ul style="list-style-type: none"> • $E1-09 \leq E1-07 < E1-06 \leq E1-11 \leq E1-04$ [Minimum Output Frequency ≤ Mid Point A Frequency < Base Frequency ≤ Mid Point B Frequency ≤ Maximum Output Frequency] | Set the parameters correctly to satisfy the conditions. |

| Code | Name | Causes | Possible Solutions |
|-------|-----------------------------------|---|---|
| oPE11 | Carrier Frequency Setting Error | <p>These parameters are set at the same time:</p> <ul style="list-style-type: none"> • $C6-05 > 6$ [Carrier Freq Proportional Gain > 6] • $C6-04 > C6-03$ [Carrier Frequency Lower Limit > Carrier Frequency Upper Limit] <p>Note: When $C6-05 < 7$, $C6-04$ becomes disabled. $C6-03$ stays active.</p> <p>$C6-02$ to $C6-05$ settings are not in the applicable setting range.</p> | Set $C6-02$ to $C6-05$ correctly. |
| oPE16 | Energy Saving Constants Error | <p>These parameters are set at the same time:</p> <ul style="list-style-type: none"> • $b8-01 = 1$ [Energy Saving Control Selection = Enabled] • $S1-01 = 1$ [Dynamic Noise Control = Enabled] | Disable Energy Saving Control or Dynamic Noise Control. |
| oPE20 | No Motor Overload Set | <p>$L1-01 = 0$ [Motor Overload (oL1) Protection = Disabled] and $Z2-0x \neq 29$ or 30 [Digital Input x Function (TB2-x) \neq External Overload Motor 1 (NC) or External Overload Motor 1 (NC)].</p> | <ul style="list-style-type: none"> • Set $L1-01 = 1$ [Motor Overload (oL1) Protection = Enabled]. • Set one digital input to motor overload $Z2-0x = 29$ or 30 and connect a thermal motor overload relay to that input. |
| oPE29 | Baud Rate Setting Error | <p>The baud rate setting [$H5-02$] does not align with the currently selected protocol [$H5-08$].</p> <p>One of these contradictory settings is true:</p> <ul style="list-style-type: none"> • $H5-08 = 1$ and $H5-02 \neq 3$ [Communication Protocol Selection = Metasys/N2 and Communication Speed Selection \neq 9600 bps] • $H5-08 = 2$ and $H5-02 \neq 2, 3$ [Communication Protocol Selection = Apogee/P1 and Communication Speed Selection \neq 4800 bps, 9600 bps] • $H5-08 = 3$ and $H5-02 \neq 3, 4, 5, 7$ [Communication Protocol Selection = BACnet and Communication Speed Selection \neq 9600 bps, 19.2 kbps, 38.4 kbps, 76.8 kbps] | Correct the parameter settings. |
| oPE34 | HAND/OFF/AUTO Input Setting | <p>Parameter $b1-02 = 7$ to 9 and only HAND or AUTO MFDI [$Z2-0x = 31$ or 32] is programmed.</p> <p>Parameter $b1-02 = 1$ to 3 and the AUTO MFDI [$Z2-0x = 32$] is programmed</p> <p>Parameter $b1-02 = 0$ and either HAND or AUTO MFDI [$Z2-0x = 31$ or 32] are programmed.</p> | <p>Program HAND and AUTO MFDIs [$Z2-0x = 31$ and 32].</p> <p>Un-program HAND and AUTO MFDIs, so neither are selected.</p> <p>Un-program the AUTO MFDI.</p> <p>Un-program the HAND and AUTO MFDIs.</p> |
| oPE36 | Bypass Energy Savings Setting Err | <p>These parameters are set at the same time:</p> <ul style="list-style-type: none"> • $Z1-16 \neq 0$ [Energy Savings Mode \neq Disabled] • $Y4-42 \neq 0$ [Output Disconnect Detection Sel \neq Disabled] | Set $Z1-16$ or $Y4-42 = 0$. |


5.8 Auto-Tuning Errors

This table gives information about errors detected during Auto-Tuning. If the drive detects an Auto-Tuning error, the keypad will show the error and the motor will coast to stop. The drive will not send notification signals for faults and alarms when Auto-Tuning errors occur.

Two types of Auto-Tuning errors are: *Endx* and *Erx*. *Endx* identifies that Auto-Tuning has successfully completed with calculation errors. Find and repair the cause of the error and do Auto-Tuning again, or set the motor parameters manually. You can use the drive in the application if you cannot find the cause of the *Endx* error.

Erx identifies that Auto-Tuning was not successful. Find and repair the cause of the error and do Auto-Tuning again.

| Code | Name | Causes | Possible Solutions |
|-------|----------------------------------|--|---|
| End1 | Excessive Rated Voltage Setting | The torque reference was more than 20% during Auto-Tuning or the no-load current that was measured after Auto-Tuning is more than 80%. | <ul style="list-style-type: none"> Make sure that the input motor nameplate data is correct. Do Auto-Tuning again and correctly set the motor nameplate data. If you can uncouple the motor and load, remove the motor from the machine and do Rotational Auto-Tuning again. If you cannot uncouple the motor and load, use the results from Auto-Tuning. |
| Code | Name | Causes | Possible Solutions |
| End2 | Iron Core Saturation Coefficient | The motor nameplate data entered during Auto-Tuning is incorrect. | <ul style="list-style-type: none"> Make sure that the input motor nameplate data is correct. Do Auto-Tuning again and correctly set the motor nameplate data. |
| Code | Name | Causes | Possible Solutions |
| End3 | Rated Current Setting Alarm | The rated current value is incorrect. | Do Auto-Tuning again and set the correct rated current shown on the motor nameplate. |
| Code | Name | Causes | Possible Solutions |
| End4 | Adjusted Slip Calculation Error | The Auto-Tuning results were not in the applicable parameter setting range. | <ul style="list-style-type: none"> Make sure the input motor nameplate data is correct. Do Rotational Auto-Tuning again and correctly set the motor nameplate data. If you cannot uncouple the motor and load, do Stationary Auto-Tuning 2. |
| | | The motor rated slip that was measured after Stationary Auto-Tuning was 0.2 Hz or lower. | |
| | | The secondary resistor measurement results were not in the applicable range. | |
| Code | Name | Causes | Possible Solutions |
| End5 | Resistance Tuning Error | The Auto-Tuning results of the Line-to-Line Resistance were not in the applicable range. | <ul style="list-style-type: none"> Make sure that the input motor nameplate data is correct. Examine and repair damaged motor wiring. |
| Code | Name | Causes | Possible Solutions |
| End6 | Leakage Inductance Alarm | The Auto-Tuning results were not in the applicable parameter setting range. | Make sure that the input motor nameplate data is correct, and do Auto-Tuning again. |
| Code | Name | Causes | Possible Solutions |
| End7 | No-Load Current Alarm | The Auto-Tuning results of the motor no-load current value were not in the applicable range. | Examine and repair damaged motor wiring. |
| | | Auto-Tuning results were less than 5% of the motor rated current. | Make sure that the input motor nameplate data is correct, and do Auto-Tuning again. |
| Code | Name | Causes | Possible Solutions |
| Er-01 | Motor Data Error | The motor nameplate data entered during Auto-Tuning is incorrect. | <ul style="list-style-type: none"> Make sure that the motor nameplate data is correct. Do Auto-Tuning again and correctly set the motor nameplate data. |
| | | The combination of the motor rated power and motor rated current do not match. | <ul style="list-style-type: none"> Examine the combination of drive capacity and motor output. Do Auto-Tuning again, and correctly set the motor rated power and motor rated current. |
| | | The combination of the motor rated current that was entered during Auto-Tuning and <i>E2-03</i> [Motor No-Load Current] do not match. | <ul style="list-style-type: none"> Examine the motor rated current and the no-load current. Set <i>E2-03</i> correctly. Do Auto-Tuning again, and correctly set the motor rated current. |
| | | The combination of the setting values of Motor Base Frequency and Motor Base Speed do not match. | Do Auto-Tuning again, and correctly set the Motor Base Frequency and Motor Base Speed. |

| Code | Name | Causes | Possible Solutions |
|-------|-------------------------------|--|--|
| Er-02 | Drive in an Alarm State | The motor nameplate data entered during Auto-Tuning is incorrect. | <ul style="list-style-type: none"> Make sure that the motor nameplate data entered in Auto-Tuning is correct. Do Auto-Tuning again and correctly set the motor nameplate data. |
| | | You did Auto-Tuning while the drive had a minor fault or alarm. | Clear the minor fault or alarm and do Auto-Tuning again. |
| | | There is a defective motor cable or cable connection. | Examine and repair motor wiring. |
| | | The load is too large. | <ul style="list-style-type: none"> Decrease the load. Examine the machine area to see if, for example, the motor shaft is locked. |
| | | The drive detected a minor fault during Auto-Tuning. | <ol style="list-style-type: none"> Stop Auto-Tuning. Examine the minor fault code and remove the cause of the problem. Do Auto-Tuning again. |
| Code | Name | Causes | Possible Solutions |
| Er-03 | OFF Button was Pressed | You pushed  during Auto-Tuning. | Auto-Tuning did not complete correctly. Do Auto-Tuning again. |
| Code | Name | Causes | Possible Solutions |
| Er-04 | Line-to-Line Resistance Error | The Auto-Tuning results were not in the applicable parameter setting range. | <ul style="list-style-type: none"> Examine and repair motor wiring. Disconnect the machine from the motor and do Rotational Auto-Tuning again. |
| | | Auto-Tuning did not complete in a pre-set length of time. | |
| | | There is a defective motor cable or cable connection. | <ul style="list-style-type: none"> Make sure that the input motor nameplate data is correct. Do Auto-Tuning again and correctly set the motor nameplate data. |
| | | The motor nameplate data entered during Auto-Tuning is incorrect. | |
| Code | Name | Causes | Possible Solutions |
| Er-05 | No-Load Current Error | The Auto-Tuning results were not in the applicable parameter setting range. | <ul style="list-style-type: none"> Examine and repair motor wiring. Disconnect the machine from the motor and do Rotational Auto-Tuning again. |
| | | Auto-Tuning did not complete in a pre-set length of time. | |
| | | The motor nameplate data entered during Auto-Tuning is incorrect. | <ul style="list-style-type: none"> Make sure that the input motor nameplate data is correct. Do Auto-Tuning again and correctly set the motor nameplate data. |
| | | Rotational Auto-Tuning was done with a load that was more than 30% of the rating connected to the motor. | <ul style="list-style-type: none"> Disconnect the machine from the motor and do Rotational Auto-Tuning again. If you cannot uncouple the motor and load, make sure that the load is less than 30% of the motor rating. If a mechanical brake is installed in the motor, release the brake during Rotational Auto-Tuning. |
| Code | Name | Causes | Possible Solutions |
| Er-08 | Rated Slip Error | The motor nameplate data entered during Auto-Tuning is incorrect. | <ul style="list-style-type: none"> Make sure that the input motor nameplate data is correct. Do Auto-Tuning again and correctly set the motor nameplate data. |
| | | Auto-Tuning did not complete in a pre-set length of time. | <ul style="list-style-type: none"> Examine and repair the motor wiring. If the motor and machine are connected during Rotational Auto-Tuning, decouple the motor from the machinery. |
| | | The Auto-Tuning results were not in the applicable parameter setting range. | |
| | | Rotational Auto-Tuning was done with a load that was more than 30% of the rating connected to the motor. | <ul style="list-style-type: none"> Disconnect the machine from the motor and do Rotational Auto-Tuning again. If you cannot uncouple the motor and load, make sure that the load is less than 30% of the motor rating. If a mechanical brake is installed in the motor, release the brake during Rotational Auto-Tuning. |

5.8 Auto-Tuning Errors

| Code | Name | Causes | Possible Solutions |
|-------|----------------------------------|--|--|
| Er-09 | Acceleration Error | The motor did not accelerate for the specified acceleration time. | <ol style="list-style-type: none"> Increase the value set in <i>C1-01 [Acceleration Time 1]</i>. Disconnect the machine from the motor and do Rotational Auto-Tuning again. |
| | | Rotational Auto-Tuning was done with a load that was more than 30% of the rating connected to the motor. | <ul style="list-style-type: none"> Disconnect the machine from the motor and do Rotational Auto-Tuning again. If you cannot uncouple the motor and load, make sure that the load is less than 30% of the motor rating. If a mechanical brake is installed in the motor, release the brake during Rotational Auto-Tuning. |
| Code | Name | Causes | Possible Solutions |
| Er-12 | Current Detection Error | There is a phase loss in the wiring between the output terminal block (or motor overload) and the motor. | Examine and repair wiring. |
| | | The current exceeded the current rating of the drive. | <ul style="list-style-type: none"> Check the motor wiring for any short circuits between the wires. Check and turn ON any magnetic contactors used between motors. Replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| | | The output current is too low. | |
| | | You tried Auto-Tuning without a motor connected to the drive. | Connect the motor and do Auto-Tuning. |
| | | There was a current detection signal error. | Replace the control board or the drive. For information about replacing the control board, contact Yaskawa or your nearest sales representative. |
| Code | Name | Causes | Possible Solutions |
| Er-13 | Leakage Inductance Error | The motor rated current value is incorrect. | Correctly set the rated current indicated on the motor nameplate and do Auto-Tuning again. |
| | | The drive could not complete tuning for leakage inductance in fewer than 300 s. | Examine and repair motor wiring. |
| Code | Name | Causes | Possible Solutions |
| Er-18 | Back EMF Error | The result of the induced voltage tuning was not in the applicable range. | <ol style="list-style-type: none"> Make sure that the input motor nameplate data is correct. Do Auto-Tuning again and correctly set the motor nameplate data. |
| Code | Name | Causes | Possible Solutions |
| Er-25 | HighFreq Inject Param Tuning Err | The motor data is incorrect. | <p>Do Stationary Auto-Tuning again.</p> <p>Note: If the drive detects <i>Er-25</i> after you do Stationary Auto-Tuning, it is possible that the motor cannot use high frequency injection. For more information, contact Yaskawa or your nearest sales representative.</p> |

5.9 Backup Function Operating Mode Display and Errors

◆ Operating Mode Display

When the drive does backup function tasks with the HOA keypad, the keypad will show the current task. These indicators do not show that an error has occurred.

| Keypad Display | Name | Display | State |
|--|---|--------------------|---|
| Drive and Keypad mismatch. Should the parameters be restored? | Detection of inconsistency between the drive and keypad | Normally displayed | The drive detected the connection of a keypad from a different drive. Select [Yes] to copy parameters backed up in the keypad to the connected drive. |
| Restore Restore from keypad | Restoring parameters | Flashing | The parameters stored in the keypad have been restored to the drive. |
| End | Backup/restore/verify operation ended normally | Normally displayed | The parameter backup, restore, or verify operation ended normally. |
| Backup Backup from Drive | Backing up parameters | Flashing | The parameters stored in the drive are being backed up to the keypad. |
| Verify Keypad & Drive | Verifying parameters | Flashing | The parameter settings stored in the keypad and the parameter settings in the drive align or are being compared. |

◆ Backup Function Runtime Errors

When an error occurs, the keypad shows a code to identify the error.

The table in this section shows the error codes. Refer to this table to remove the cause of the errors.

Note:

Push any key on the keypad to clear an error.

| Code | Name | Causes | Possible Solutions |
|------|----------------------------------|---|--|
| CPyE | Error Writing Data | Parameter restore did not end correctly. | Restore the parameters. |
| Code | Name | Causes | Possible Solutions |
| CSEr | Control Mode Mismatch | The keypad is broken. | Replace the keypad. |
| Code | Name | Causes | Possible Solutions |
| dFPS | Drive Model Mismatch | You tried to restore parameters to a different drive model than the one that you backed up. | <ol style="list-style-type: none"> Examine the drive model that you used to back up the parameters. Restore the parameters. |
| Code | Name | Causes | Possible Solutions |
| iFEr | Keypad Communication Error | There was a communications error between the keypad and the drive. | Examine the connector or cable connection. |
| Code | Name | Causes | Possible Solutions |
| ndAT | Error Received Data | The parameter settings for model and specifications (power supply voltage and capacity) are different between the keypad and the drive. | <ol style="list-style-type: none"> Make sure that drive model and the value set in <i>o2-04 [Drive Model (KVA) Selection]</i> agree. Restore the parameters. |
| | | The parameters are not stored in the keypad. | <ol style="list-style-type: none"> Connect a keypad that has the correct parameters. Restore the parameters. |
| Code | Name | Causes | Possible Solutions |
| rdEr | Error Reading Data | You tried to back up the data when <i>o3-02 = 0 [Copy Allowed Selection = Disabled]</i> . | Set <i>o3-02 = 1 [Enabled]</i> and back up again. |
| Code | Name | Causes | Possible Solutions |
| vAEr | Voltage Class, Capacity Mismatch | The power supply specifications or drive capacity parameter settings are different between the keypad and the drive. | <ol style="list-style-type: none"> Make sure that drive model and the value set in <i>o2-04 [Drive Model (KVA) Selection]</i> agree. Restore the parameters. |
| Code | Name | Causes | Possible Solutions |
| vFyE | Parameters do not Match | The parameters that are backed up in the keypad and the parameters in the drive are not the same. | <ol style="list-style-type: none"> Restore or backup the parameter again. Verify the parameters. |

5.10 Bypass Status Messages

The bypass HOA keypad will show these status messages on line 1 of the keypad display during the conditions listed below. These are not faults or alarms.

| Keypad Display | Description |
|------------------------------|--|
| Powering Up | Shown on initial power up of the bypass system. This message goes away when the power up initialization is complete and communication is established to the drive, or when the bypass determines that the drive is not connected or energized. |
| Idle | The bypass is in an Idle state with no active Run command. There are no active faults or alarms. |
| Drive Not Ready | The drive is not in a ready state. The drive will not run if a Run command is asserted. You can run the system in Bypass Mode. |
| Safety Open | A safety programmed to a bypass digital input is not closed and there is no active Run command. This message will change to an alarm when there is an active Run command. |
| Fire Stat Open | A Fire Stat safety programmed to a bypass digital input is not closed and there is no active Run command. This message will change to an alarm when there is an active Run command. |
| Freeze Stat Open | A Freeze Stat safety programmed to a bypass digital input is not closed and there is no active Run command. This message will change to an alarm when there is an active Run command. |
| Smoke Alarm active | A Smoke Alarm safety programmed to a bypass digital input is not closed and there is no active Run command. This message will change to an alarm when there is an active Run command. |
| Over Pressure Detected | An Over Pressure safety programmed to a bypass digital input is not closed and there is no active Run command. This message will change to an alarm when there is an active Run command. |
| Low Suction Detected | A Low Suction safety programmed to a bypass digital input is not closed and there is no active Run command. This message will change to an alarm when there is an active Run command. |
| Vibration Detected | A Vibration safety programmed to a bypass digital input is not closed and there is no active Run command. This message will change to an alarm when there is an active Run command. |
| Interlock Open | Programmed BAS Interlock is not closed. The unit will not run when it receives a Run command. |
| Drive Pre Running | The drive received a Run command and the drive is entering the programmed pre-run. When the pre-run conditions are finished, the drive will enter drive run. |
| Drive Run Commanded | The bypass has commanded the drive to run, but it has not yet detected that the drive is running. |
| Restart Delay Active | There is an active Run Command, but the programmed restart delay is active and the drive cannot run. The keypad shows this display on power-up or when there is a brief power loss to the bypass unit. |
| Drive Running | The unit is running in Drive Mode. |
| Drive Stopping | The Run command to the drive was removed, and the drive is ramping to stop. |
| Running in Bypass | The unit is running in Bypass Mode. |
| Entering Energy Savings | Energy savings conditions have been detected. This functionality is programmed using parameters Z1-16 through Z1-23. When entering energy savings, the unit is running at the energy savings bump frequency and when it is finished, it will switch into the bypass run state. |
| Energy Savings Active | Energy Savings Mode is active and the unit is running in Bypass Mode. |
| Exiting Energy Savings | Energy Savings conditions are no longer present and the unit is leaving Energy Savings and returning to Drive Mode. The exit conditions are when the frequency reference changes from the programmed Energy Savings frequency reference in Z1-17. |
| Auto Transfer Active | Auto transfer was enabled in Z1-05 and the unit detected a drive fault during an active drive run. The unit will run in Bypass Mode. |
| Remote Transfer Active | A Remote Transfer was asserted and the unit is currently running in Bypass Mode. |
| Emergency Override Drive FWD | An Emergency Override Drive FWD was asserted by a bypass digital input or through serial or option board communications to the bypass board. |
| Emergency Override Drive REV | An Emergency Override Drive REV was asserted by a bypass digital input or through serial or option board communications to the bypass board. |
| Emergency Override Bypass | An Emergency Override Bypass was asserted by a bypass digital input or through serial or option board communications to the bypass board. This message also appears when Emergency Override Drive was active, there was a drive fault, and Z1-10 = 1 [Transfer to Bypass]. |
| Faulted | The unit is in Drive Mode it detected a drive fault or bypass fault, or the unit is in Bypass Mode and it detected a bypass-specific fault. |
| Soft Start On Delay | There is a Run command and the unit is waiting for the programmed on delay time in Z1-43 before asserting the soft starter run. |
| Soft Starter Ramping down | Parameter Z1-42 = 2 [Ramp to Stop] and the Run command was removed. The soft starter will ramp to stop. |

5.11 Diagnosing and Resetting Faults

When a fault occurs and the drive stops, do the procedures in this section to remove the cause of the fault, then re-energize the drive.

◆ Fault and Power Loss Occur at the Same Time

WARNING! Crush Hazard. Wear eye protection when you do work on the bypass. If you do not use correct safety equipment, it can cause serious injury or death.

WARNING! Electrical Shock Hazard. After the bypass blows a fuse or trips a GFCI, do not immediately energize the bypass or operate peripheral devices. Wait for the time specified on the warning label at a minimum and make sure that all indicators are OFF. Then check the wiring and peripheral device ratings to find the cause of the problem. If you do not know the cause of the problem, contact Yaskawa before you energize the bypass or peripheral devices. If you do not fix the problem before you operate the bypass or peripheral devices, it can cause serious injury or death.

1. Connect to the USB connector on the bypass PCB and use DriveWizard HVAC software.
2. Connect to the drive, then select “Status & Fault History” to show fault codes and operating status of the bypass immediately before the fault occurred.
3. Use the information in the Troubleshooting tables to remove the fault.

Note:

1. To find the faults that were triggered, check the fault history in U2-02 [Previous Fault]. To find information about drive status (such as frequency, current, and voltage) when the faults were triggered, check U2-03 to U2-20.
2. If the fault display stays after you re-energize the drive, remove the cause of the fault and reset.

◆ Fault Occurs Without Power Loss

1. Examine the fault code shown on the keypad.
2. Use the information in the Troubleshooting tables to remove the fault.
3. Do a fault reset.


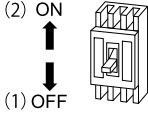
◆ Fault Reset

If a fault occurs, you must remove the cause of the fault and re-energize the drive. Table 5.5 lists the different methods to reset the drive after a fault.

Note:

You must remove the Run command or make sure that the bypass is in the OFF state before you can do a fault reset.

Table 5.5 Fault Reset Methods

| Methods | Description |
|----------|--|
| Method 1 | While the keypad is showing the fault or alarm code, push F1 (Reset) or  on the keypad. |
| Method 2 | Switch ON the MFDI Terminal set to Z2-0x = 34 [Bypass MFDI Function Select = Fault Reset]. |
| Method 3 | <ol style="list-style-type: none"> 1. De-energize the drive main circuit power supply. 2. Energize the drive again after the keypad display goes out.  |

Note:

If the drive receives a Run command from a communication option or control circuit terminal, the drive will not reset the fault. Remove the Run command then try to clear the fault. If you do a fault reset when the drive has a Run command, the keypad will show minor fault C_rST [Remove RUN Command to Reset].

Specifications

| | | |
|------------|---|------------|
| 6.1 | Section Safety | 150 |
| 6.2 | 208 V Narrow Model Specifications | 151 |
| 6.3 | 480 V Narrow Model Specifications | 153 |
| 6.4 | Common Bypass Specifications | 155 |
| 6.5 | Drive Watt Loss and Derating | 157 |
| 6.6 | Peripheral Devices and Options | 158 |
| 6.7 | Periodic Inspection and Maintenance..... | 163 |

6.1 Section Safety

 **DANGER**

Do not ignore the safety messages in this manual.

If you ignore the safety messages in this manual, it will cause serious injury or death. The manufacturer is not responsible for injuries or damage to equipment.

6.2 208 V Narrow Model Specifications

Table 6.1 208 V Narrow Ratings

| Model | | D002 | D003 | D004 | D007 | D010 | D016 |
|---|--------------------------------------|---|--------|--------|--------|---------|---------|
| Maximum Applicable Motor Output (HP) *2 | | 0.5 | 0.75 | 1 | 2 | 3 | 5 |
| Input | Rated Input Current (A) | 2.9 | 4.0 | 5.1 | 8.0 | 11.1 | 17.2 |
| | Rated Voltage Rated Frequency | Three-Phase 208 Vac 50/60 Hz | | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | | |
| Output | Rated Output Current (A) | 2.4 *3 | 3.5 *3 | 4.6 *3 | 7.5 *3 | 10.6 *3 | 16.7 *3 |
| | Minimum Applicable Motor Current (A) | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 | 3.75 |
| | Overload Tolerance | 110% of rated output current for 60 s 150% peak | | | | | |
| | Carrier Frequency | User adjustable between 1 and 12.5 kHz (Maximum Frequency varies with Rated Output Capacity) | | | | | |
| | Maximum Output Voltage (V) | Three-Phase 208 Vac | | | | | |
| | Maximum Output Frequency (Hz) | 240 Hz | | | | | |
| Harmonics Reduction | Input Power (kVA) | Built-in | | | | | |
| EMC | Filter (IEC/EN 61800-3 Category 2) | Built-in | | | | | |

- *1 The maximum applicable motor output is based on 4-pole, general-purpose 220 V motor ratings. The rated output current of the drive output amps must be equal to or more than the motor rated current.
- *2 The maximum applicable motor output complies with 208 V motor ratings as specified in NEC Table 430.250. The rated output current of the drive output amps must be equal to or more than the motor rated current.
- *3 Carrier frequency is 5 kHz. You must derate the current to increase the carrier frequency.

Table 6.2 208 V Narrow Ratings

| Model | | D024 | D030 | D046 | D059 | D074 |
|---|--------------------------------------|---|---------|---------|---------|---------|
| Maximum Applicable Motor Output (HP) *2 | | 7.5 | 10 | 15 | 20 | 25 |
| Input | Rated Input Current (A) | 24.7 | 31.3 | 46.7 | 59.9 | 75.3 |
| | Rated Voltage Rated Frequency | Three-Phase 208 Vac 50/60 Hz | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | |
| Output | Rated Output Current (A) | 24.2 *3 | 30.8 *3 | 46.2 *3 | 59.4 *3 | 74.8 *3 |
| | Minimum Applicable Motor Current (A) | 3.75 | 3.75 | 7.5 | 7.5 | 15 |
| | Overload Tolerance | 110% of rated output current for 60 s 150% peak | | | | |
| | Carrier Frequency | User adjustable between 1 and 12.5 kHz (Maximum Frequency varies with Rated Output Capacity) | | | | |
| | Maximum Output Voltage (V) | Three-Phase 208 Vac | | | | |
| | Maximum Output Frequency (Hz) | 240 Hz | | | | |
| Harmonics Reduction | Input Power (kVA) | Built-in | | | | |
| EMC | Filter (IEC/EN 61800-3 Category 2) | Built-in | | | | |

- *1 The maximum applicable motor output is based on 4-pole, general-purpose 220 V motor ratings. The rated output current of the drive output amps must be equal to or more than the motor rated current.

6.2 208 V Narrow Model Specifications

- *2 The maximum applicable motor output complies with 208 V motor ratings as specified in NEC Table 430.250. The rated output current of the drive output amps must be equal to or more than the motor rated current.
- *3 Carrier frequency is 5 kHz. You must derate the current to increase the carrier frequency.

6.3 480 V Narrow Model Specifications

Table 6.3 480 V Narrow Ratings

| Model | | B1P1 | B001 | B002 | B003 | B004 | B007 | B011 | B014 |
|---|--------------------------------------|---|--------|--------|--------|--------|--------|---------|---------|
| Maximum Applicable Motor Output (HP) *2 | | 0.5 | 0.75 | 1 | 2 | 3 | 5 | 7.5 | 10 |
| Input | Rated Input Current (A) | 1.3 | 1.8 | 2.3 | 3.6 | 5.0 | 7.8 | 11.2 | 14.2 |
| | Rated Voltage Rated Frequency | Three-Phase 480 Vac 50/60 Hz | | | | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | | | | |
| Output | Rated Output Current (A) | 1.1 *3 | 1.6 *3 | 2.1 *3 | 3.4 *3 | 4.8 *3 | 7.6 *3 | 11.0 *3 | 14.0 *3 |
| | Minimum Applicable Motor Current (A) | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 | 1.5 | 3.75 |
| | Overload Tolerance | 110% of rated output current for 60 s 150% peak | | | | | | | |
| | Carrier Frequency | User adjustable between 1 and 12.5 kHz (Maximum Frequency varies with Rated Output Capacity) | | | | | | | |
| | Maximum Output Voltage (V) | Three-Phase 480 Vac | | | | | | | |
| | Maximum Output Frequency (Hz) | 240 Hz | | | | | | | |
| Harmonics Reduction | Input Power (kVA) | Built-in | | | | | | | |
| EMC | Filter (IEC/EN 61800-3 Category 2) | Built-in | | | | | | | |

*1 The maximum applicable motor output is based on 4-pole, general-purpose 220 V motor ratings. The rated output current of the drive output amps must be equal to or more than the motor rated current.

*2 The maximum applicable motor output complies with 208 V motor ratings as specified in NEC Table 430.250. The rated output current of the drive output amps must be equal to or more than the motor rated current.

*3 Carrier frequency is 5 kHz. You must derate the current to increase the carrier frequency.

Table 6.4 480 V Narrow Ratings

| Model | | B021 | B027 | B034 | B040 | B052 | B065 | B077 | |
|---|--------------------------------------|---|---------|---------|---------|---------|---------|---------|--|
| Maximum Applicable Motor Output (HP) *2 | | 15 | 20 | 25 | 30 | 40 | 50 | 60 | |
| Input | Rated Input Current (A) | 21.2 | 27.2 | 34.2 | 40.2 | 52.2 | 65.2 | 77.2 | |
| | Rated Voltage Rated Frequency | Three-Phase 480 Vac 50/60 Hz | | | | | | | |
| | Allowable Voltage Fluctuation | -15 to 10% | | | | | | | |
| | Allowable Frequency Fluctuation | ±5% | | | | | | | |
| Output | Rated Output Current (A) | 21.0 *3 | 27.0 *3 | 34.0 *3 | 40.0 *3 | 52.0 *3 | 65.0 *3 | 77.0 *3 | |
| | Minimum Applicable Motor Current (A) | 3.75 | 3.75 | 7.5 | 7.5 | 7.5 | 7.5 | 15 | |
| | Overload Tolerance | 110% of rated output current for 60 s 150% peak | | | | | | | |
| | Carrier Frequency | User adjustable between 1 and 12.5 kHz (Maximum Frequency varies with Rated Output Capacity) | | | | | | | |
| | Maximum Output Voltage (V) | Three-Phase 480 Vac | | | | | | | |
| | Maximum Output Frequency (Hz) | 240 Hz | | | | | | | |

6.3 480 V Narrow Model Specifications

| Model | | B021 | B027 | B034 | B040 | B052 | B065 | B077 |
|---------------------|------------------------------------|----------|------|------|------|------|------|------|
| Harmonics Reduction | Input Power (kVA) | Built-in | | | | | | |
| EMC | Filter (IEC/EN 61800-3 Category 2) | Built-in | | | | | | |

- *1 The maximum applicable motor output is based on 4-pole, general-purpose 220 V motor ratings. The rated output current of the drive output amps must be equal to or more than the motor rated current.
- *2 The maximum applicable motor output complies with 208 V motor ratings as specified in NEC Table 430.250. The rated output current of the drive output amps must be equal to or more than the motor rated current.
- *3 Carrier frequency is 5 kHz. You must derate the current to increase the carrier frequency.

6.4 Common Bypass Specifications

Note:

To get the longest product life, install the bypass in an environment that meets the necessary specifications.

Table 6.5 Control Characteristics

| Item | Specification |
|--|--|
| Control Method | V/f Control (V/f) |
| Frequency Control Range | 0.01 Hz to 400 Hz |
| Frequency Accuracy (Temperature Fluctuation) | Digital inputs: Within $\pm 0.01\%$ of the maximum output frequency ($-10\text{ }^{\circ}\text{C}$ to $+40\text{ }^{\circ}\text{C}$ ($14\text{ }^{\circ}\text{F}$ to $104\text{ }^{\circ}\text{F}$)) Analog inputs: Within $\pm 0.4\%$ of the maximum output frequency ($25\text{ }^{\circ}\text{C} \pm 10\text{ }^{\circ}\text{C}$ ($77\text{ }^{\circ}\text{F} \pm 18\text{ }^{\circ}\text{F}$)) |
| Frequency Setting Resolution | Digital inputs: 0.01 Hz Analog inputs: 1/2048 of the maximum output frequency (11-bit) |
| Output Frequency Resolution | 0.001 Hz |
| Frequency Setting Signal | Main speed frequency reference: 0 Vdc to 10 Vdc (20 k Ω), 4 mA to 20 mA (250 Ω), 0 mA to 20 mA (250 Ω) |
| Starting Torque | 140%/3 Hz |
| Speed Control Range | 1:40 |
| Accel/Decel Time | 0.1 s to 6000.0 s The bypass can set two pairs of different acceleration and deceleration times. |
| V/f Characteristics | Select from 15 pre-defined V/f patterns, or a user-set V/f pattern. |
| Main Control Functions | Restart After Momentary Power Loss, Speed Search, Overtorque/Undertorque Detection, 8 Step Speed (max.), Accel/Decel Switch, S-curve Acceleration/Deceleration, Auto-Tuning (Rotational and Stationary), Cooling Fan ON/OFF Switch, Slip Compensation, Torque Compensation, Jump Frequency, Upper/Lower Limits for Frequency Reference, DC Injection Braking at Start and Stop, Overexcitation Braking, High Slip Braking, PID Control (with Sleep Function), Energy Saving Control, APOGEE FLN Communication (RS-485 4.8 or 9.6 kbps), BACnet Communication (RS-485 max. 76.8 kbps), MEMOBUS/Modbus Communication (RS-485 max. 115.2 kbps), Metasys N2 Communication (RS-485 9.6 kbps), Auto Restart, Application Presets, Overexcitation Deceleration, Overvoltage Suppression |

Table 6.6 Protection Functions

| Item | Specification |
|---|---|
| Motor Protection (Drive and Bypass Modes) | Electronic thermal overload protection |
| Momentary Overcurrent Protection (Drive Mode) | Bypass stops when the output current is more than 175% of the rated output current. |
| Overload Protection (Drive Mode) | Bypass stops when the output current is more than these overload tolerances: <ul style="list-style-type: none"> • 110% of the rated output current for 60 seconds • 140% of the rated output current for 2.5 seconds when the bypass output frequency is 3 Hz The permitted frequency of overload is one time each 10 minutes. Note: If output frequency < 6 Hz, the bypass can trigger the overload protection function when the output current is in the overload tolerance range. |
| Overvoltage Protection (Drive Mode) | 208/240 V: Stops when the DC bus voltage is more than approximately 410 V 480 V: Stops when the DC bus voltage is more than approximately 820 V |
| Undervoltage Protection (Drive Mode) | 208/240 V: Stops when the DC bus voltage decreases to less than approximately 190 V 480 V: <ul style="list-style-type: none"> • Stops when the DC bus voltage decreases to less than approximately 350 V when you use an input voltage less than 400 V • Stops when the DC bus voltage decreases to less than approximately 380 V when you use an input voltage less than 460 V • Stops when the DC bus voltage decreases to less than approximately 440 V when you use an input voltage of 460 V or more |
| Brownout Protection (Drive and Bypass Modes) | - |
| Momentary Power Loss Ride-thru (Drive and Bypass Modes) | Immediately stops when power loss is 15 ms or longer. Will automatically restart after power is restored. (depending on parameter settings) |

6.4 Common Bypass Specifications

| Item | Specification |
|---|---|
| Heatsink Overheat Protection (Drive Mode) | The bypass stops when the thermistor detects an IGBT temperature more than approximately 100 °C (212 °F). The trip temperature level is different for different models. |
| Stall Prevention (Drive Mode) | Stall prevention is available during acceleration, deceleration, and during run. |
| Ground Fault Protection (Drive Mode) | Electronic circuit protection Note: This protection detects ground faults during run. The bypass will not provide protection when: <ul style="list-style-type: none"> • There is a low-resistance ground fault for the motor cable or terminal block • Energizing the bypass when there is a ground fault. |
| DC Bus Charge LED (Drive Mode) | Charge LED illuminates when DC bus voltage is more than 50 V. |

Table 6.7 Environment

| Item | Specification |
|-----------------------------|---|
| Area of Use | Indoors |
| Ambient Temperature Setting | IP20/UL Type 1: -10 °C to +40 °C (14 °F to 104 °F) IP55/UL Type 12: -10 °C to +40 °C (14 °F to 104 °F) <ul style="list-style-type: none"> • Do not let the bypass freeze. |
| Humidity | 95% RH or less Do not let condensation form on the bypass. |
| Storage Temperature | -20 °C to +70 °C (-40 °F to +158 °F) (short-term temperature during transportation) |
| Surrounding Area | Pollution degree 2 or less Install the bypass in an area without: <ul style="list-style-type: none"> • Oil mist, corrosive or flammable gas, or dust • Metal powder, oil, water, or other unwanted materials • Radioactive materials or flammable materials, including wood • Harmful gas or fluids • Salt • Direct sunlight |
| Altitude | 1000 m (3281 ft) maximum Note: Derate the output current by 1% for each 100 m (328 ft) to install the bypass in altitudes between 1000 m to 4000 m (3281 ft to 13123 ft). It is not necessary to derate the rated voltage in these conditions: <ul style="list-style-type: none"> • When you install the bypass at 2000 m (6562 ft) or lower • When you install the bypass between 2000 m to 4000 m (6562 ft to 13123 ft) and ground the neutral point on the power supply. |
| Vibration | <ul style="list-style-type: none"> • 10 Hz to 20 Hz: 1 G (9.8 m/s², 32.15 ft/s²) • 20 Hz to 55 Hz: H6BPD002 to D030, H6BPB1P1, B001 to B034: 0.6 G (5.9 m/s², 19.36 ft/s²) H6BPD046 to H6BPD074, H6BPB040 to B077: 0.2 G (1.96 m/s², 6.43 ft/s²) • 20 Hz to 55 Hz: H6B1D002 to D030, H6B1A002 to A028, H6B1B1P1, B001 to B034: 0.6 G (5.9 m/s², 19.36 ft/s²) H6B1D046 to D273, H6B1A042 to A248, H6B1B040 to B302: 0.2 G (1.96 m/s², 6.43 ft/s²) |
| Installation Orientation | Install the bypass vertically for sufficient airflow to cool the bypass. |

Table 6.8 Certifications and Standard Compliance

| Item | Specification |
|-----------------------|--|
| c-UL-us | UL 508A |
| Seismic Certification | <ul style="list-style-type: none"> • CBC, IBC, ASCE7, ICC-ES 156 • HCAI (Special Seismic Certification Preapproval OSP-0687) |

Table 6.9 Enclosure Ratings

| Item | Specification |
|-------------------|-----------------------------------|
| Protection Design | IP20/UL Type 1 IP55/UL Type 12 |

6.5 Drive Watt Loss and Derating

For drive watt loss and drive derating data, refer to the HV600 Bypass Technical Reference (SIEPYAIHB601).

6.6 Peripheral Devices and Options

◆ Bypass Communication Options

There are many available peripheral devices and options for the bypass.

Refer to the HV600 catalog (CA.HV600.01) for information about available options, including:

- Main circuit options
- Frequency settings and monitor options
- Keypad options
- Attachment options
- Engineering tools

Contact Yaskawa or your nearest sales representative to make an order.

Refer to the instruction manual for each option for wiring information.

◆ Tools Required for Option Installation

- A Phillips screwdriver (M3 metric or #1, #2 U.S. standard) to install the option and remove the bypass front cover. Screw sizes vary by capacity. Select a screwdriver appropriate for the capacity.

Note:

Use a short-shaft, magnetic screwdriver when installing the option card into the narrow enclosure models H6BPD002 to D074 and B1P1, B001 to B077.

- A straight-edge screwdriver (blade depth: 0.4 mm, width: 2.5 mm) to wire the option terminal block when installing the SI-W3 LonWorks option.

Note:

This manual does not list the tools required to prepare the option cables for wiring.

◆ Bypass Options

These configurations are available for the bypass:

■ Option B

Three-contactor bypass: Isolates the drive circuit by adding a separate drive input contactor.

■ Option D

Ethernet/IP option.

■ Option G

Drive Input Disconnect Switch: Provides a disconnect means for the input side of the Drive, for Drive isolation capability during bypass operation. This disconnect is located inside the enclosure with an integral operating handle.

■ Option L

Serial Communication, Echelon LonWorks: An isolated circuit board provides LonTalk protocol for network communication to a BAS. This option plugs into the CN5 connection on the bypass control circuit board.

■ Option M

Lockable Circuit Breaker SCCR panel rating of 100 kA (no external customer fuses or internal fuses are necessary)

■ Option W

Custom Nameplate: Provides a custom nameplate for placement on the front of the bypass.

◆ Option Installation Procedure

■ Before You Install the Option

NOTICE: Install communications options on the bypass control PCB. Do not install communications options on the drive PCB. Improperly connected communications options will cause erroneous operation.

■ Verify Bypass Operation

Verify that the bypass functions normally without the option installed. Refer to *Electrical Installation* for information on wiring and connecting the bypass.

■ Prepare Network Cables for SI-W3 LonWorks Options

Use only LonWorks network cables.

Refer to the Echelon website for more information on network cabling (www.echelon.com). The performance cannot be guaranteed if you use non-LonWorks network cables.

Separate the LonWorks cables from the wiring to the main circuit and other lines.

Determine the length of cable required to connect from the option to a network device and attach all connectors to network cables.

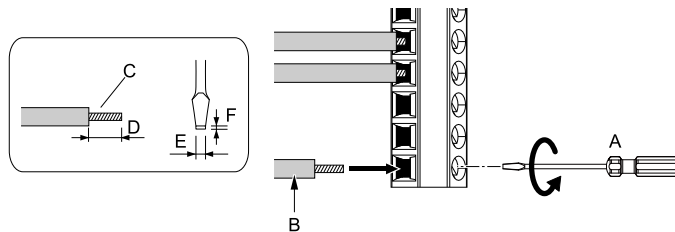
The communication terminal is a pluggable terminal block that serves as the connection point of the LonWorks network cable to the option.

| Terminal | Terminal No. | Name | Description |
|----------|--------------|------|---------------|
| 1 | 1 | A | Signal Line A |
| 2 | 2 | SLD | Shield |
| 3 | 3 | B | Signal Line B |

NOTICE: Heat shrink tubing or electrical tape may be required to ensure that cable shielding does not touch contact with other wiring. Insufficient insulation may cause a short circuit that can damage the option or the bypass.

Note:

- Use shielded wires and shielded twisted-pair wires. If the grounding is not correct, electrical interference can cause the drive or devices around it to malfunction.
- Do not use wiring that is longer than 50 m (164 ft) to supply the frequency reference with an analog signal from a remote source. Wiring that is too long can cause unsatisfactory system performance.

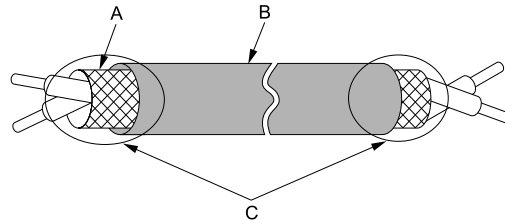


- A** - Loosen the screws and put the wire into the opening on the terminal block.
- B** - Wire with a crimp ferrule attached, or use wire that is not soldered with the core wires lightly twisted.
- C** - Pull back the shielding and lightly twist the end with your fingers to keep the ends from fraying.

- D** - If you do not use crimp ferrules, remove approximately 5.5 mm (0.21 in) of the covering at the end of the wire.
- E** - Blade width of 2.5 mm (0.1 in) or less
- F** - Blade depth of 0.4 mm (0.01 in) or less

WARNING! Fire Hazard. Tighten all terminal screws to the correct tightening torque. Connections that are too loose or too tight can cause incorrect operation and damage to the bypass. Incorrect connections can also cause death or serious injury from fire.

NOTICE: Do not tin stranded wire with solder. Soldered wire connections can become loose over time and cause unsatisfactory system performance.



A - Shield
B - Sheath

C - Insulate with electrical tape or shrink tubing.

Figure 6.1 Prepare the Ends of Shielded Wire

■ Prepare Network Cables for Ethernet-based Options

Determine the length of cable required to connect from the option to a network device and attach all connectors to network cables before you install the option.

The Ethernet-based option options will have one or two RJ45 ports available for connections. The user must supply the mating RJ45 modular connector and cable.

Table 6.10 8-Way Modular Connector (Customer-Supplied)

| Male 8-Way Modular Connector | Pin | Description |
|------------------------------|------------|--|
| | 1 (Pair 2) | Transmit data (TXD) + |
| | 2 (Pair 2) | Transmit data (TXD) - |
| | 3 (Pair 3) | Receive data (RXD) + |
| | 4 (Pair 1) | Not used for 10 Mbps and 100 Mbps networks |
| | 5 (Pair 1) | Not used for 10 Mbps and 100 Mbps networks |
| | 6 (Pair 3) | Receive data (RXD) - |
| | 7 (Pair 4) | Not used for 10 Mbps and 100 Mbps networks |
| | 8 (Pair 4) | Not used for 10 Mbps and 100 Mbps networks |

| Communication Protocol | Description |
|------------------------|---|
| EtherNet/IP | Only use cable recommended for EtherNet/Industrial Protocol (EtherNet/IP™). Using a cable not specifically recommended may cause the option or bypass to malfunction. Refer to the ODVA website for more information on network cabling (www.odva.org). |
| Modbus TCP/IP | Only use cable recommended for Modbus TCP/IP. Using a cable not specifically recommended may cause the option or bypass to malfunction. Refer to the Modbus-IDA website for more information on network cabling (www.modbus.org). |
| PROFINET | Only use cable recommended for PROFINET. Using a cable not specifically recommended may cause the option or bypass to malfunction. Refer to the PROFIBUS and PROFINET International (PI) website for more information (www.profibus.com). |
| BACnet/IP | Only use shielded Cat5e cable or better. Using a cable not specifically recommended may cause the option or bypass to malfunction. |

■ Install the Option

1. De-energize the system at the power source. Observe correct lockout/tagout safety procedures and wait for the CHARGE light to completely go out on the drive unit.
2. Remove the bypass cover or open the cabinet door to access the bypass PCB A2.
3. Install the option to bypass PCB A2.

- Use the two screws included in the option kit to fasten the option card to the metal standoffs on the bypass PCB A2. Use a short-shaft, magnetic screwdriver for narrow enclosure models H6BPxxxx. Tighten each screw to 0.5 to 0.6 N•m (4.4 to 5.3 in lbs).

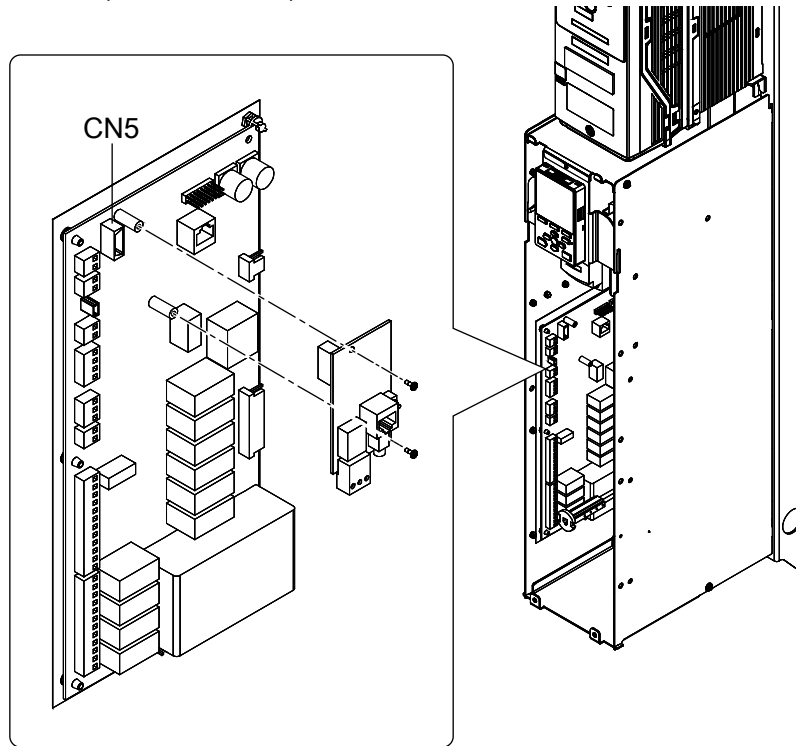


Figure 6.2 Insert Option into Bypass PCB CN5 Connector Port

- Firmly insert the end of the customer-supplied network cable into the CN1 connection port on the option board. When you have a dual-port option, connect two network cables to the two RJ45 ports. Available connection topologies are different for different options. Refer to the option manual for your communication protocol for more information.

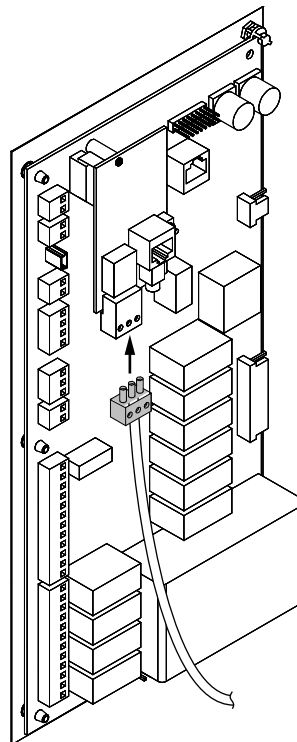


Figure 6.3 Connect Network Cable to Option (SI-W3 LonWorks Example)

6.6 Peripheral Devices and Options

NOTICE: *Separate the communication wiring from the input power, motor, and 120 Vac control wiring. Electrical interference can cause communication data errors.*

6. Make sure that you did not pinch cables between the front cover and the bypass enclosure, then replace and secure the front cover or cabinet door.
7. Set the bypass parameters for option functionality. Refer to the option manual for your communication protocol for programming information.

6.7 Periodic Inspection and Maintenance

For detailed information about:

- Recommended inspections
- Replacement of parts, including the keypad battery
- Drive cooling fan and circulation fan replacement procedures
- Storage guidelines

Refer to the HV600 Bypass Technical Reference (SIEPYAIHB601).

Parameter List

| | | |
|------|--------------------------------------|-----|
| 7.1 | How to Read the Parameter List | 166 |
| 7.2 | A: Initialization Parameters | 168 |
| 7.3 | b: Application | 171 |
| 7.4 | C: Tuning | 178 |
| 7.5 | d: Reference Settings | 180 |
| 7.6 | E: Motor Parameters | 182 |
| 7.7 | F: Options | 184 |
| 7.8 | H: Terminal Functions | 189 |
| 7.9 | L: Protection Functions | 206 |
| 7.10 | n: Special Adjustment | 213 |
| 7.11 | o: Keypad-Related Settings | 214 |
| 7.12 | S: Special Applications | 220 |
| 7.13 | Y: Application Features | 229 |
| 7.14 | Z: Bypass Parameters | 237 |
| 7.15 | U: Monitors | 245 |

7.1 How to Read the Parameter List

◆ Terms that Identify Parameters

| Icon | Description |
|--------|---|
| Hex. | Hexadecimal numbers that represent MEMOBUS addresses to change parameters over network communication. |
| RUN | You can change the parameter setting during Run. |
| Expert | The parameter is available in Expert Mode only. <i>*1</i> |

*1 Set $A1-01 = 3$ [Access Level Selection = Expert Level] to show and set Expert Mode parameters on the keypad.

◆ Parameter Groups

| Parameter Group | Name |
|-----------------|------------------------------|
| A1 | Initialization |
| A2 | User Parameters |
| b1 | Operation Mode Selection |
| b2 | DC Injection Braking |
| b3 | Speed Search |
| b4 | Timer Function |
| b5 | PID Control |
| b8 | Energy Saving |
| C1 | Accel & Decel Time |
| C2 | S-Curve Characteristics |
| C3 | Slip Compensation |
| C4 | Torque Compensation |
| C6 | Carrier Frequency |
| d1 | Frequency Reference |
| d2 | Reference Limits |
| d3 | Jump Frequency |
| d4 | Frequency Ref Up/Down & Hold |
| d6 | Field Weakening |
| d7 | Offset Frequency |
| E1 | V/f Pattern for Motor 1 |
| E2 | Motor Parameters |
| F6 | Communication Options |
| F7 | Ethernet Options |
| H1 | Digital Inputs |
| H2 | Digital Outputs |
| H3 | Analog Inputs |
| H4 | Analog Outputs |
| H5 | Serial Communication |
| H7 | Virtual Inputs / Outputs |
| L1 | Motor Protection |
| L2 | Power Loss Ride Through |

| Parameter Group | Name |
|-----------------|-------------------------------|
| L3 | Stall Prevention |
| L4 | Speed Detection |
| L5 | Fault Restart |
| L6 | Torque Detection |
| L8 | Drive Protection |
| L9 | Drive Protection 2 |
| n1 | Hunting Prevention |
| n3 | High Slip/Overexcite Braking |
| o1 | Keypad Display |
| o2 | Keypad Operation |
| o3 | Copy Keypad Function |
| o4 | Maintenance Monitors |
| o5 | Log Function |
| S1 | Dynamic Noise Control |
| S2 | Sequence Run Timers |
| S3 | PI2 Control |
| S5 | HAND/OFF/AUTO Operation |
| S6 | Protection |
| Y1 | Application Basics |
| Y2 | PID Sleep and Protection |
| Y4 | Application Advanced |
| YA | Preset Setpoint |
| YC | Foldback Features |
| YF | PI Auxiliary Control |
| Z1 | Bypass Control System |
| Z2 | Bypass Digital Inputs/Outputs |
| Z3 | Bypass Serial Communications |
| U1 | Operation Status Monitors |
| U2 | Fault Trace |
| U3 | Fault History |
| U4 | Maintenance Monitors |

| Parameter Group | Name |
|-----------------|---------------------------|
| U5 | PID Monitors |
| U6 | Operation Status Monitors |

| Parameter Group | Name |
|-----------------|----------------------------|
| Ub | Bypass Control Monitors |
| UC | BACnet Diagnostic Monitors |

7.2 A: Initialization Parameters

◆ A1: Initialization

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|------------------------|---|-----------------------|
| A1-00 (0100) RUN | Language Selection | Sets the language for the HOA keypad. Note: When you use <i>A1-03 [Initialize Parameters]</i> to initialize the drive, the drive will not reset this parameter. 0 : English 5 : Spanish | 0 (0, 5) |
| A1-01 (0101) RUN | Access Level Selection | Sets user access to parameters. The access level controls which parameters the keypad will display and which parameters you can set. 0 : Operation Only 1 : User Parameters 2 : Advanced Level 3 : Expert Level 4 : Lock Parameters | 2 (0 - 4) |
| A1-03 (0103) | Initialize Parameters | Sets parameters to default values. 0 : No Initialization 1110 : User Initialization 2220 : 2-Wire Initialization | 0 (0, 1110, 2220) |
| A1-04 (0104) | Password | Entry point for the password set in <i>A1-05 [Password Setting]</i> . The user can view the settings of parameters that are locked without entering the password. Enter the correct password in this parameter to change parameter settings. | 0000 (0000 - 9999) |
| A1-05 (0105) | Password Setting | Sets a password to lock parameters and prevent changes to parameter settings. Enter the correct password in <i>A1-04 [Password]</i> to unlock parameters and accept changes. | 0000 (0000 - 9999) |
| A1-06 (0127) | Application Preset | Sets the drive to operate in selected application conditions. 0 : No Preset Selected 1 : General Purpose Fan 2 : Fan w/ PID Control 3 : Return Fan w/ PID Control 4 : Cooling Tower Fan 5 : Cooling Tower Fan w/ PID 6 : Secondary Pump 7 : Pump w/ PID Control | 0 (0 - 7) |
| A1-11 (111D) Expert | Firmware Update Lock | Protects the drive firmware. When you enable the protection, you cannot update the bypass controller firmware. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| A1-12 (1564) | Bluetooth ID | Sets the password necessary to use Bluetooth to control the drive with a smartphone or tablet. | - (0000 - 9999) |

◆ A2: User Parameters

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|------------------|---|--------------------------|
| A2-01 (0106) | User Parameter 1 | Sets the parameter number to be shown for number 1 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters <i>A2-01</i> to <i>A2-32</i> . | b1-01 (A1-00 - Z3-16) |
| A2-02 (0107) | User Parameter 2 | Sets the parameter number to be shown for number 2 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters <i>A2-01</i> to <i>A2-32</i> . | b1-02 (A1-00 - Z3-16) |
| A2-03 (0108) | User Parameter 3 | Sets the parameter number to be shown for number 3 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters <i>A2-01</i> to <i>A2-32</i> . | b1-03 (A1-00 - Z3-16) |
| A2-04 (0109) | User Parameter 4 | Sets the parameter number to be shown for number 4 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters <i>A2-01</i> to <i>A2-32</i> . | C1-01 (A1-00 - Z3-16) |
| A2-05 (010A) | User Parameter 5 | Sets the parameter number to be shown for number 5 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters <i>A2-01</i> to <i>A2-32</i> . | C1-02 (A1-00 - Z3-16) |

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|-------------------|--|-----------------------|
| A2-06 (010B) | User Parameter 6 | Sets the parameter number to be shown for number 6 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | C6-02 (A1-00 - Z3-16) |
| A2-07 (010C) | User Parameter 7 | Sets the parameter number to be shown for number 7 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | d1-01 (A1-00 - Z3-16) |
| A2-08 (010D) | User Parameter 8 | Sets the parameter number to be shown for number 8 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | d1-02 (A1-00 - Z3-16) |
| A2-09 (010E) | User Parameter 9 | Sets the parameter number to be shown for number 9 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | d1-03 (A1-00 - Z3-16) |
| A2-10 (010F) | User Parameter 10 | Sets the parameter number to be shown for number 10 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | d1-04 (A1-00 - Z3-16) |
| A2-11 (0110) | User Parameter 11 | Sets the parameter number to be shown for number 11 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | d1-17 (A1-00 - Z3-16) |
| A2-12 (0111) | User Parameter 12 | Sets the parameter number to be shown for number 12 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | E1-01 (A1-00 - Z3-16) |
| A2-13 (0112) | User Parameter 13 | Sets the parameter number to be shown for number 13 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | E1-03 (A1-00 - Z3-16) |
| A2-14 (0113) | User Parameter 14 | Sets the parameter number to be shown for number 14 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | E1-04 (A1-00 - Z3-16) |
| A2-15 (0114) | User Parameter 15 | Sets the parameter number to be shown for number 15 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | E1-05 (A1-00 - Z3-16) |
| A2-16 (0115) | User Parameter 16 | Sets the parameter number to be shown for number 16 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. | E1-06 (A1-00 - Z3-16) |
| A2-17 (0116) | User Parameter 17 | Sets the parameter number to be shown for number 17 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | E1-09 (A1-00 - Z3-16) |
| A2-18 (0117) | User Parameter 18 | Sets the parameter number to be shown for number 18 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | E1-13 (A1-00 - Z3-16) |
| A2-19 (0118) | User Parameter 19 | Sets the parameter number to be shown for number 19 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | E2-01 (A1-00 - Z3-16) |
| A2-20 (0119) | User Parameter 20 | Sets the parameter number to be shown for number 20 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | E2-04 (A1-00 - Z3-16) |
| A2-21 (011A) | User Parameter 21 | Sets the parameter number to be shown for number 21 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | E2-11 (A1-00 - Z3-16) |
| A2-22 (011B) | User Parameter 22 | Sets the parameter number to be shown for number 22 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | H4-02 (A1-00 - Z3-16) |
| A2-23 (011C) | User Parameter 23 | Sets the parameter number to be shown for number 23 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | L1-01 (A1-00 - Z3-16) |
| A2-24 (011D) | User Parameter 24 | Sets the parameter number to be shown for number 24 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | L3-04 (A1-00 - Z3-16) |
| A2-25 (011E) | User Parameter 25 | Sets the parameter number to be shown for number 25 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | - (A1-00 - Z3-16) |

7.2 A: Initialization Parameters

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|-------------------------------|--|-------------------------------|
| A2-26 (011F) | User Parameter 26 | Sets the parameter number to be shown for number 26 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | - (A1-00 - Z3-16) |
| A2-27 (0120) | User Parameter 27 | Sets the parameter number to be shown for number 27 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | - (A1-00 - Z3-16) |
| A2-28 (0121) | User Parameter 28 | Sets the parameter number to be shown for number 28 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | - (A1-00 - Z3-16) |
| A2-29 (0122) | User Parameter 29 | Sets the parameter number to be shown for number 29 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | - (A1-00 - Z3-16) |
| A2-30 (0123) | User Parameter 30 | Sets the parameter number to be shown for number 30 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | - (A1-00 - Z3-16) |
| A2-31 (0124) | User Parameter 31 | Sets the parameter number to be shown for number 31 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | - (A1-00 - Z3-16) |
| A2-32 (0125) | User Parameter 32 | Sets the parameter number to be shown for number 32 of the [User Custom Parameters] under the main menu. You can select a maximum of 32 parameters for the drive and set them to parameters A2-01 to A2-32. You can set A2-17 to A2-32 when A2-33 = 0 [User Parameter Auto Selection = Disabled: Manual Entry Required]. | - (A1-00 - Z3-16) |
| A2-33 (0126) | User Parameter Auto Selection | Sets the automatic save feature for changes to parameters A2-17 to A2-32 [User Parameters 17 to 32]. 0 : Disabled: Manual Entry Required 1 : Enabled: Auto Save Recent Parm | Determined by A1-06 (0, 1) |

7.3 b: Application

◆ b1: Operation Mode Selection

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|---------------------------------|--|---------------------------|
| b1-01 (0180) | Frequency Reference Selection 1 | Sets the input method for the frequency reference. 0 : Keypad 1 : Analog Input 2 : Serial Communications 3 : Option PCB | 1 (0 - 3) |
| b1-02 (0181) | Run Command Selection 1 | Sets the input method for the Run command. 0 : Keypad 1 : Digital Input 2 : Serial Communications 3 : Option PCB 7 : AUTO Command + Term Run 8 : AUTO Command + Serial Run 9 : AUTO Command + Option Run | 7 (0 - 9) |
| b1-03 (0182) | Stopping Method Selection | Sets the method to stop the motor after removing a Run command or entering a Stop command. 0 : Ramp to Stop 1 : Coast to Stop 2 : DC Injection Braking to Stop 3 : Coast to Stop with Timer | 1 (0 - 3) |
| b1-04 (0183) | Reverse Operation Selection | Sets the reverse operation function. Disable reverse operation in fan or pump applications where reverse rotation is dangerous. 0 : Reverse Enabled 1 : Reverse Disabled | 1 (0, 1) |
| b1-08 (0187) | Run Command Select in PRG Mode | Sets the conditions for the drive to accept a Run command entered from an external source when using the keypad to set parameters. 0 : Disregard RUN while Programming 1 : Accept RUN while Programming 2 : Allow Programming Only at Stop | 0 (0 - 2) |
| b1-11 (01DF) | Run Delay @ Stop | Sets the amount of time that the drive will not accept the Run command again after the Run command is lost. Note: • This parameter will operate for both AUTO Mode and HAND Mode. • This parameter will operate when the drive goes to sleep then wakes up. • The time set in this parameter does not apply for faults or Auto-Restarts. • When there is an active Run command while the time set in <i>b1-11</i> is active, the keypad will show a <i>[Start Delay]</i> message as specified by the <i>o1-82 [Message Screen Display]</i> display format. | 0.0 s (0.0 - 6000.0 s) |
| b1-12 (01E0) | Run Delay Memory Selection | Sets how the drive saves the Run Delay Timer to the EEPROM during power loss. 0 : Disabled 1 : Only at Stop 2 : Running & Stop | 2 (0 - 2) |
| b1-17 (01C6) | Run Command at Power Up | Sets drive response when you apply power to drive that has an external Run command. Set this parameter in applications where energizing or de-energizing the drive enables the Run command. 0 : Disregard Existing RUN Command 1 : Accept Existing RUN Command | 1 (0, 1) |
| b1-40 (3BCF) | Deceleration Abort Time | Sets the maximum time until the drive shuts off the output to decelerate to stop. Note: Set this parameter to 0.0 s to disable this function. | 0.0 s (0.0 - 6000.0 s) |

◆ b2: DC Injection Braking

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|---|----------------------------|
| b2-01 (0189) | DC Injection/Zero SpeedThreshold | Sets the frequency to start DC Injection Braking. Note: This parameter is available when $b1-03 = 0$ [Stopping Method Selection = Ramp to Stop]. | 0.5 Hz (0.0 - 10.0 Hz) |
| b2-02 (018A) | DC Injection Braking Current | Sets the DC Injection Braking current as a percentage of the drive rated current. | 50% (0 - 100%) |
| b2-03 (018B) | DC Inject Braking Time at Start | Sets the DC Injection Braking Time at stop. | 0.00 s (0.00 - 10.00 s) |
| b2-04 (018C) | DC Inject Braking Time at Stop | Sets the DC Injection Braking Time at stop. | 0.00 s (0.00 - 10.00 s) |
| b2-09 (01E1) | Pre-heat Current 2 | Sets the percentage of motor rated output current used for the motor pre-heat function. | 5% (0 - 100%) |

◆ b3: Speed Search

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------------|---|--------------------------------------|
| b3-01 (0191) | Speed Search at Start Selection | Sets the Speed Search at Start function where the drive will perform Speed Search with each Run command. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| b3-02 (0192) | SpeedSearch Deactivation Current | Sets the current level that stops Speed Search as a percentage of the drive rated output current. Usually it is not necessary to change this setting. | 120% (0 - 200%) |
| b3-03 (0193) | Speed Search Deceleration Time | Sets the deceleration time during Speed Search operation. Set the length of time to decelerate from the maximum output frequency to the minimum output frequency. | 2.0 s (0.1 - 10.0 s) |
| b3-04 (0194) | V/f Gain during Speed Search | Sets the ratio used to reduce the V/f during searches to reduce the output current during speed searches. | Determined by o2-04 (10 - 100) |
| b3-05 (0195) | Speed Search Delay Time | Sets the Speed Search delay time to activate a magnetic contactor installed between the drive and motor. | 0.2 s (0.0 - 100.0 s) |
| b3-06 (0196) Expert | Speed Estimation Current Level 1 | Sets the level of current that flows to the motor during Speed Estimation Speed Search as a coefficient of the motor rated current. Usually it is not necessary to change this setting. | Determined by o2-04 (0.0 - 2.0) |
| b3-07 (0197) Expert | Speed Estimation Current Level 2 | Sets the level of current that flows to the motor during Speed Estimation Speed Search as a coefficient of E2-03 [Motor No-Load Current]. Usually it is not necessary to change this setting. | 1.0 (0.0 - 3.0) |
| b3-08 (0198) | Speed Estimation ACR P Gain | Sets the proportional gain for the automatic current regulator during Speed Estimation Speed Search. Also adjusts speed search responsiveness. Usually it is not necessary to change this setting. | Determined by o2-04 (0.00 - 6.00) |
| b3-09 (0199) | Speed Estimation ACR I Time | Sets the integral time for the automatic current regulator during Speed Estimation Speed Search. Also adjusts speed search responsiveness. Usually it is not necessary to change this setting. | 2.0 ms (0.0 - 1000.0 ms) |
| b3-10 (019A) Expert | Speed Estimation Detection Gain | Sets the gain to correct estimated frequencies from Speed Estimation Speed Search. | 1.05 (1.00 - 1.20) |
| b3-11 (019B) Expert | Spd Est Method Switch-over Level | Uses the quantity of voltage in the motor to automatically switch the search method within the type of speed measurement. Note: • 208/240 V at 100% = 200 V • 480 V at 100% = 400 V | 5.0% (0.5 - 100.0%) |
| b3-12 (019C) Expert | Speed Search Current Deadband | Sets the minimum current detection level during Speed Search. If the drive does not do Speed Estimation, increase this setting in 0.1-unit increments. | determined by o2-04 (2.0 - 10.0) |
| b3-14 (019E) | Bi-directional Speed Search | Sets the direction of Speed Search to the direction of the frequency reference or in the motor rotation direction as detected by the drive. 0 : Disabled 1 : Enabled | 0 (0, 1) |

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|----------------------------------|--|--------------------------------------|
| b3-17 (01F0) Expert | Speed Est Retry Current Level | Sets the current level for the search retry function in Speed Estimation Speed Search as a percentage where drive rated current is a setting value of 100%. | 110% (0 - 200%) |
| b3-18 (01F1) Expert | Speed Est Retry Detection Time | Sets the length of time that the drive will wait to retry Speed Estimation Speed Search when too much current flow stopped the Speed Search. | 0.10 s (0.00 - 1.00 s) |
| b3-19 (01F2) | Speed Search Restart Attempts | Sets the number of times to restart Speed Search if Speed Search does not complete. | 3 times (0 - 10 times) |
| b3-24 (01C0) | Speed Search Method Selection | Sets the Speed Search method when you start the motor or when you return power after a momentary power loss. Note: Set <i>b3-24 = 1</i> . If <i>b3-24 = 2</i> , the drive will detect <i>oPE08 [Parameter Selection Error]</i> . 1 : Speed Estimation 2 : Current Detection 2 | 2 (1, 2) |
| b3-25 (01C8) Expert | Speed Search Wait Time | Sets the length of time the drive will wait to start the Speed Search Retry function. | 0.5 s (0.0 - 30.0 s) |
| b3-26 (01C7) Expert | Direction Determination Level | Sets the level to find the motor rotation direction. Increase the value if the drive cannot find the direction. | 1000 (40 to 60000) |
| b3-27 (01C9) Expert | Speed Search RUN/BB Priority | Sets the conditions necessary to start Speed Search. 0 : SS Only if RUN Applied Before BB 1 : SS Regardless of RUN/BB Sequence | 0 (0, 1) |
| b3-31 (0BC0) Expert | Spd Search Current Reference Lvl | Sets the current level that decreases the output current during Current Detection Speed Search. | 1.50 (1.50 - 3.50) |
| b3-32 (0BC1) Expert | Spd Search Current Complete Lvl | Sets the current level that completes Speed Search. | 1.20 (0.00 - 1.49) |
| b3-39 (1B8F) Expert | Regen Judgement LV of Spd Search | Regen Judgement LV of Spd Search. Note: Available in HV600 Bypass software versions 00443 and later and HV600 drive software versions 1013 and later. | 15% (0 - 50%) |
| b3-56 (3126) | InverseRotationSearch WaitTime | Sets the wait time until the drive starts inverse rotation search after it completes forward search when you do inverse rotation search during Current Detection Speed Search. | Determined by o2-04 (0.1 - 5.0 s) |

◆ b4: Timer Function

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|-------------------------------|---|---------------------------|
| b4-01 (01A3) | Timer Function ON-Delay Time | Sets the ON-delay time for the timer input. | 0.0 s (0.0 - 3000.0 s) |
| b4-02 (01A4) | Timer Function OFF-Delay Time | Sets the OFF-delay time for the timer input. | 0.0 s (0.0 - 3000.0 s) |
| b4-03 (0B30) Expert | Terminal M1-M2 ON-Delay Time | Sets the delay time to activate the contact after the function set in <i>H2-01</i> activates. | 0 ms (0 - 65000 ms) |
| b4-04 (0B31) Expert | Terminal M1-M2 OFF-Delay Time | Sets the delay time to deactivate the contact after the function set in <i>H2-01</i> deactivates. | 0 ms (0 - 65000 ms) |
| b4-05 (0B32) Expert | Terminal M3-M4 ON-Delay Time | Sets the delay time to activate the contact after the function set in <i>H2-02</i> activates. | 0 ms (0 - 65000 ms) |
| b4-06 (0B33) Expert | Terminal M3-M4 OFF-Delay Time | Sets the delay time to deactivate the contact after the function set in <i>H2-02</i> deactivates. | 0 ms (0 - 65000 ms) |

7.3 b: Application

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|-------------------------------|---|------------------------|
| b4-07 (0B34) Expert | Terminal M5-M6 ON-Delay Time | Sets the delay time to activate the contact after the function set in <i>H2-03</i> activates. | 0 ms (0 - 65000 ms) |
| b4-08 (0B35) Expert | Terminal M5-M6 OFF-Delay Time | Sets the delay time to deactivate the contact after the function set in <i>H2-03</i> deactivates. | 0 ms (0 - 65000 ms) |

◆ b5: PID Control

| No. (Hex.) | Name | Description | Default (Range) |
|----------------------------------|---------------------------------|--|----------------------------|
| b5-01 (01A5) | PID Mode Setting | Sets the type of PID control. 0 : Disabled 1 : Standard 3 : Fref + PID Trim | 0 (0 - 3) |
| b5-02 (01A6) RUN | Proportional Gain (P) | Sets the proportional gain (P) that is applied to PID input. | 2.00 (0.00 - 25.00) |
| b5-03 (01A7) RUN | Integral Time (I) | Sets the integral time (I) that is applied to PID input. | 0.5 s (0.0 - 360.0 s) |
| b5-04 (01A8) RUN | Integral Limit | Sets the upper limit for integral control (I) as a percentage of the Maximum Output Frequency. | 100.0% (0.0 - 100.0%) |
| b5-05 (01A9) RUN | Derivative Time (D) | Sets the derivative time (D) for PID control. This parameter adjusts system responsiveness. | 0.00 s (0.00 - 10.00 s) |
| b5-06 (01AA) RUN | PID Output Limit | Sets the maximum possible output from the PID controller as a percentage of the Maximum Output Frequency. | 100.0% (0.0 - 100.0%) |
| b5-07 (01AB) RUN | PID Offset Adjustment | Sets the offset for the PID control output as a percentage of the Maximum Output Frequency. | 0.0% (-100.0 - +100.0%) |
| b5-08 (01AC) RUN Expert | PID Primary Delay Time Constant | Sets the primary delay time constant for the PID control output. Usually it is not necessary to change this setting. | 0.00 s (0.00 - 10.00 s) |
| b5-09 (01AD) | PID Output Level Selection | Sets the polarity of the PID output. 0 : Normal Output (Direct Acting) 1 : Reverse Output (Reverse Acting) | 0 (0, 1) |
| b5-10 (01AE) RUN | PID Output Gain Setting | Sets the amount of gain to apply to the PID output. | 1.00 (0.00 - 25.00) |
| b5-11 (01AF) | PID Output Reverse Selection | Sets the function that enables and disables reverse motor rotation for negative PID control output. 0 : Lower Limit is Zero 1 : Negative Output Accepted | 0 (0, 1) |
| b5-17 (01B5) RUN | PID Accel/Decel Time | Raises or lowers the PID setpoint using the acceleration and deceleration times set to the drive. This is a soft-starter for the PID setpoint. | 0.0 s (0.0 - 6000.0 s) |
| b5-28 (01EA) | PID Feedback Square Root Sel | Enables and disables the square root of the PID Feedback compared to the PID Setpoint to set an appropriate drive output for the correct system regulation. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| b5-29 (01EB) | PID Feedback Square Root Gain | Sets the multiplier applied to the square root of the feedback. | 0.00 (0.00 - 2.00) |
| b5-30 (01EC) | PID Feedback Offset | Sets PID feedback Offset as a percentage of maximum frequency. | 0.00% (0.00 - 100.00%) |

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|---------------------------------|--|-----------------------------|
| b5-34 (019F) RUN | PID Output Lower Limit Level | Sets the output lower limit for the PID control as a percentage of the Maximum Output Frequency. | 0.0% (-100.0 - +100.0%) |
| b5-35 (01A0) RUN | PID Input Limit Level | Sets the output upper limit for the PID control as a percentage of the Maximum Output Frequency. | 1000.0% (0.0 - 1000.0%) |
| b5-38 (01FE) | PID User Unit Display Scaling | Sets the value that the drive sets or shows as the PID setpoint when at the maximum output frequency. | 100.00% (0.01 - 600.00%) |
| b5-39 (01FF) | PID User Unit Display Digits | Sets the number of digits to set and show the PID setpoint. 0 : No Decimal Places (XXXXX) 1 : One Decimal Places (XXXX.X) 2 : Two Decimal Places (XXX.XX) 3 : Three Decimal Places (XX.XXX) | 2 (0 - 3) |
| b5-41 (0160) | PID Output 2 Unit | Sets the display units in U5-14 [PID Out2 Upr4 Digits] and U5-15 [PID Out2 Lwr4 Digits]. 0 : "WC: inches of water column 1 : PSI: pounds per square inch 2 : GPM: gallons/min 3 : °F: Fahrenheit 4 : ft³/min: cubic feet/min 5 : m³/h: cubic meters/hour 6 : L/h: liters/hour 7 : L/s: liters/sec 8 : bar: bar 9 : Pa: Pascal 10 : °C: Celsius 11 : m: meters 12 : ft: feet 13 : L/min: liters/min 14 : m³/min: cubic meters/min 15 : "Hg: Inch Mercury 16 : kPa: kilopascal 48 : %: Percent 49 : Custom(b5-68~70) 50 : None | 0 (0 - 50) |
| b5-42 (0161) RUN | PID Output 2 Calc Mode | Sets how to calculate the original PID output. 0 : Linear 1 : Square Root 2 : Quadratic 3 : Cubic Note: Used for U5-14 [PID Out2 Upr4 Digits] and U5-15 [PID Out2 Lwr4 Digits] only. | 0 (0 - 3) |
| b5-43 (0162) RUN | PID Out2 Monitor MAX Upper4 Dig | Sets the upper 4 digits of the maximum monitor value. Used with b5-44 [PID Out2 Monitor MAX Lower4 Dig] to set maximum monitor value of U5-14 [PID Out2 Upr4 Digits] and U5-15 [PID Out2 Lwr4 Digits] at maximum frequency. Note: Used for U5-14 [PID Out2 Upr4 Digits] and U5-15 [PID Out2 Lwr4 Digits] only. | 0 (0 - 9999) |
| b5-44 (0163) RUN | PID Out2 Monitor MAX Lower4 Dig | Sets the lower 4 digits of the maximum monitor value. Used with b5-43 [PID Out2 Monitor MAX Upper4 Dig] to set maximum monitor value of U5-14 [PID Out2 Upr4 Digits] and U5-15 [PID Out2 Lwr4 Digits] at maximum frequency. Note: Used for U5-14 [PID Out2 Upr4 Digits] and U5-15 [PID Out2 Lwr4 Digits] only. | 0.00 (0.00 - 99.99) |
| b5-45 (0164) RUN | PID Out2 Monitor MIN for Linear | Sets the minimum display value to show when at zero speed. Only effective when b5-42 = 0 [PID Output 2 Calc Mode = Linear]. Note: Used for U5-14 [PID Out2 Upr4 Digits] and U5-15 [PID Out2 Lwr4 Digits] only. | 0.0 (0.0 - 999.9) |

7.3 b: Application

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|-----------------------------------|--|----------------------------|
| b5-46 (0165) | PID Unit Display Selection | Sets the units-text for the PID Display. 0 : "WC: inches of water column 1 : PSI: pounds per square inch 2 : GPM: gallons/min 3 : °F: Fahrenheit 4 : ft ³ /min: cubic feet/min 5 : m ³ /h: cubic meters/hour 6 : L/h: liters/hour 7 : L/s: liters/sec 8 : bar: bar 9 : Pa: Pascal 10 : °C: Celsius 11 : m: meters 12 : ft: feet 13 : L/min: liters/min 14 : m ³ /min: cubic meters/min 15 : "Hg: Inch Mercury 16 : kPa: kilopascal 48 : %: Percent 49 : Custom(b5-68~70) 50 : None | 48 (0 - 50) |
| b5-53 (0B8F) RUN | PID Integrator Ramp Limit | Sets the responsiveness of PID control when the PID feedback changes quickly. | 0.0 Hz (0.0 - 10.0 Hz) |
| b5-61 (119A) | PID Trim Mode Lower Limit Sel | Sets the function that adjusts the PID output in relation to the frequency reference. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| b5-62 (119B) | PID Trim Mode Lower Limit Value | Sets the PID Trim Mode Lower Limit Value as a percentage of the maximum output frequency. | 0.00% (0.00 - 100.00%) |
| b5-68 (3C1F) | System Unit Custom Character 1 | Sets the first character of the custom unit display when <i>b5-46 = 49</i> [<i>PID Unit Display Selection = Custom (B5-68~70)</i>]. | 41 (20 - 7A) |
| b5-69 (3C20) | System Unit Custom Character 2 | Sets the second character of the custom unit display when <i>b5-46 = 49</i> [<i>PID Unit Display Selection = Custom (B5-68~70)</i>]. | 41 (20 - 7A) |
| b5-70 (3C21) | System Unit Custom Character 3 | Sets the third character of the custom unit display when <i>b5-46 = 49</i> [<i>PID Unit Display Selection = Custom (B5-68~70)</i>]. | 41 (20 - 7A) |
| b5-71 (3C22) | Min PID Transducer Scaling | Sets the minimum PID level corresponding to the lowest analog input signal level. Note: • To enable this parameter, you must set <i>b5-71 < b5-38</i> [<i>PID User Unit Display Scaling</i>]. If you set <i>b5-71 > b5-38</i> , the drive will disable all PID analog inputs. • Parameters <i>b5-46</i> [<i>PID Unit Display Selection</i>], <i>b5-38</i> , and <i>b5-39</i> [<i>PID User Unit Display Digits</i>] set the unit, range, and resolution. | 0.00 (-99.99 - +99.99) |
| b5-82 (31B0) | Feedback Loss 4 ~ 20mA Detect Sel | Sets the drive to do a 4 to 20 mA wire-break detection on the analog input set for PID feedback. 0 : Disabled 1 : Alarm Only 2 : Fault 3 : Run At b5-83 | 2 (0 - 3) |
| b5-83 (31B1) RUN | Feedback Loss GoTo Frequency | Sets the speed at which the drive will run if the drive detects a 4 to 20 mA wire-break on the PID Feedback and <i>b5-82 = 3</i> [<i>Feedback Loss 4 ~ 20mA Detect Sel = Run At b5-83</i>]. | 0.0 Hz (0.0 - 400.0 Hz) |
| b5-84 (31B2) RUN | Feedback Loss Loss Of Prime Lvl | Sets the level at which the drive will detect Loss of Prime in the pump. Note: • Loss of Prime condition occurs when the measured quantity set by <i>Y1-18</i> [<i>Prime Loss Detection Method</i>] decreases to this level for the time set in <i>Y1-20</i> [<i>Loss of Prime Time</i>] and the output frequency is at the <i>Y4-02</i> [<i>Pre-Charge Frequency</i>] level. The drive will respond to the Loss of Prime condition as specified by <i>Y1-22</i> [<i>Loss of Prime Selection</i>]. • Display unit and scaling are dependent on System Units. | 0.0 A (0.0 - 1000.0 A) |

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|---------------------------------|---|--------------------------|
| b5-85 (31B3) RUN | Feedback Loss GoTo Freq Timeout | When $b5-82 = 3$ [Feedback Loss 4 ~ 20mA Detect Sel = Run At b5-83] and the Feedback signal is lost, the drive will run at the $b5-83$ [Feedback Loss Goto Frequency] speed for this length of time, after which the drive will fault on <i>FDBKL</i> [WIRE Break]. Note: Set this parameter to 0.0 s to disable the function. | 0 s (0 - 6000 s) |
| b5-86 (31B4) RUN | Feedback Loss Start Delay | When you initiate an AUTO Run command, the drive will wait for this length of time before it will fault on <i>FDBKL</i> [WIRE Break] or use parameter $b5-83$ [Feedback Loss Goto Frequency]. | 0.0 s (0.0 - 120.0 s) |

◆ b8: Energy Saving

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|---------------------------------|---|--|
| b8-01 (01CC) | Energy Saving Control Selection | Sets the Energy-saving control function. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| b8-04 (01CF) Expert | Energy Saving Coefficient Value | Sets the Energy-saving control coefficient to maintain maximum motor efficiency. The default setting is for Yaskawa motors. Note: <ul style="list-style-type: none"> When you do Rotational Auto-Tuning, the drive will automatically set the energy-saving coefficient. The minimum values and the maximum values are different for different drive models: <ul style="list-style-type: none"> 2011 to 2024, 4005 to 4008: 0.0 - 2000.0 2031 to 2273, 4011 to 4302: 0.00 - 655.00 | Determined by E2-11 and o2-04 (0.00 - 655.00) |
| b8-05 (01D0) Expert | Power Detection Filter Time | Sets the time constant to measure output power. | 20 ms (0 - 2000 ms) |
| b8-06 (01D1) Expert | Search Operation Voltage Limit | Sets the voltage limit for Search Operation as a percentage of the motor rated voltage. | 0% (0 - 100%) |

7.4 C: Tuning

◆ C1: Accel & Decel Time

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|---------------------|--|----------------------------|
| C1-01 (0200) RUN | Acceleration Time 1 | Sets the length of time to accelerate from zero to maximum output frequency. | 30.0 s (0.1 - 6000.0 s) |
| C1-02 (0201) RUN | Deceleration Time 1 | Sets the length of time to decelerate from maximum output frequency to zero. | 30.0 s (0.1 - 6000.0 s) |
| C1-03 (0202) RUN | Acceleration Time 2 | Sets the length of time to accelerate from zero to maximum output frequency. | 30.0 s (0.1 - 6000.0 s) |
| C1-04 (0203) RUN | Deceleration Time 2 | Sets the length of time to decelerate from maximum output frequency to zero. | 30.0 s (0.1 - 6000.0 s) |
| C1-09 (0208) RUN | Fast Stop Time | Sets the length of time that the drive will decelerate to zero for a Fast Stop. Note: Decelerating too quickly can cause an <i>ov [Overvoltage]</i> fault that shuts off the drive while the motor to coasts to a stop. Set a Fast Stop time in <i>C1-09</i> that prevents motor coasting and makes sure that the motor stops quickly and safely. | 10.0 s (0.1 - 6000.0 s) |

◆ C2: S-Curve Characteristics

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|-------------------------------|---|----------------------------|
| C2-01 (020B) | S-Curve Time @ Start of Accel | Sets the S-curve acceleration time at start. | 0.20 s (0.00 - 10.00 s) |
| C2-02 (020C) | S-Curve Time @ End of Accel | Sets the S-curve acceleration time at completion. | 0.20 s (0.00 - 10.00 s) |
| C2-03 (020D) | S-Curve Time @ Start of Decel | Sets the S-curve deceleration time at start. | 0.20 s (0.00 - 10.00 s) |
| C2-04 (020E) | S-Curve Time @ End of Decel | Sets the S-curve deceleration time at completion. | 0.00 s (0.00 - 10.00 s) |

◆ C3: Slip Compensation

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|------------------------------|--|---------------------------|
| C3-01 (020F) RUN | Slip Compensation Gain | Sets the gain for the slip compensation function. Usually it is not necessary to change this setting. Note: Correctly set these parameters before you change the slip compensation gain: • <i>E2-01 [Motor Rated Current (FLA)]</i> • <i>E2-02 [Motor Rated Slip]</i> • <i>E2-03 [Motor No-Load Current]</i> | 0.0 (0.0 - 2.5) |
| C3-02 (0210) RUN | Slip Compensation Delay Time | Sets the slip compensation delay time when speed is unstable or when the slip compensation response is too slow. Usually it is not necessary to change this setting. | 2000 ms (0 - 10000 ms) |

◆ C4: Torque Compensation

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------------------|--|--------------------------|
| C4-01 (0215) RUN | Torque Compensation Gain | Sets the gain for the torque compensation function. Use this parameter value for motor 1 when you operate multiple motors. | 1.00 (0.00 - 2.50) |
| C4-02 (0216) RUN | Torque Compensation Delay Time | Sets the torque compensation delay time. Usually it is not necessary to change this setting. | 200 ms (0 - 60000 ms) |

◆ C6: Carrier Frequency

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|--------------------------------|---|---|
| C6-02 (0224) | Carrier Frequency Selection | <p>Sets the carrier frequency for the transistors in the drive.</p> <p>1 : 2.0 kHz 2 : 5.0 kHz 3 : 8.0 kHz 4 : 10.0 kHz 5 : 12.5 kHz 7 : Swing PWM1 (Audible Sound 1) 8 : Swing PWM2 (Audible Sound 2) 9 : Swing PWM3 (Audible Sound 3) A : Swing PWM4 (Audible Sound 4) B : Leakage Current Rejection PWM F : User Defined (C6-03 to C6-05)</p> <p>Note:</p> <ul style="list-style-type: none"> The carrier frequency for Swing PWM 1 to 4 is equivalent to 2.0 kHz. Swing PWM applies a special PWM pattern to decrease the audible noise. Setting B uses a PWM pattern that decreases the leakage current that the drive detects over long wiring distances. This can help decrease alarm detection and decrease problems with the current monitor from leakage current over long wiring distances. | Determined by o2-04 (1 - F) |
| C6-03 (0225) | Carrier Frequency Upper Limit | Sets the upper limit of the carrier frequency. Set $C6-02 = F$ [Carrier Frequency Selection = User Defined (C6-03 to C6-05)] to set this parameter. | Determined by C6-02 (1.0 - 12.5 kHz) |
| C6-04 (0226) | Carrier Frequency Lower Limit | Sets the lower limit of the carrier frequency. Set $C6-02 = F$ [Carrier Frequency Selection = User Defined (C6-03 to C6-05)] to set this parameter. | Determined by C6-02 (1.0 - 12.5 kHz) |
| C6-05 (0227) | Carrier Freq Proportional Gain | Sets the proportional gain for the carrier frequency. Set $C6-02 = F$ [Carrier Frequency Selection = User Defined (C6-03 to C6-05)] to set this parameter. | Determined by C6-02 (0 - 99) |

7.5 d: Reference Settings

◆ d1: Frequency Reference

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|---------------|--|-------------------------------|
| d1-01 (0280) RUN | Reference 1 | Sets the frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. | 0.00 Hz (0.00 - 400.00 Hz) |
| d1-02 (0281) RUN | Reference 2 | Sets the frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. | 0.00 Hz (0.00 - 400.00 Hz) |
| d1-03 (0282) RUN | Reference 3 | Sets the frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. | 0.00 Hz (0.00 - 400.00 Hz) |
| d1-04 (0283) RUN | Reference 4 | Sets the frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. | 0.00 Hz (0.00 - 400.00 Hz) |
| d1-05 (0284) RUN | Reference 5 | Sets the frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. | 0.00 Hz (0.00 - 400.00 Hz) |
| d1-06 (0285) RUN | Reference 6 | Sets the frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. | 0.00 Hz (0.00 - 400.00 Hz) |
| d1-07 (0286) RUN | Reference 7 | Sets the frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. | 0.00 Hz (0.00 - 400.00 Hz) |
| d1-08 (0287) RUN | Reference 8 | Sets the frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. | 0.00 Hz (0.00 - 400.00 Hz) |
| d1-17 (0292) RUN | Jog Reference | Sets the Jog frequency reference in the units from <i>o1-03</i> [Frequency Display Unit Selection]. Set <i>H1-xx = 6</i> [MFDI Function Selection = Jog Reference Selection] to use the Jog frequency reference. | 6.00 Hz (0.00 - 400.00 Hz) |

◆ d2: Reference Limits

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------------|--|--------------------------|
| d2-01 (0289) | Frequency Reference Upper Limit | Sets maximum limit for all frequency references. The maximum output frequency is 100%. | 100.0% (0.0 - 110.0%) |
| d2-02 (028A) | Frequency Reference Lower Limit | Sets minimum limit for all frequency references. The maximum output frequency is 100%. | 0.0% (0.0 - 110.0%) |
| d2-03 (0293) | Analog Frequency Ref Lower Limit | Sets the lower limit for the master frequency reference (the first frequency of the multi-step speed reference) as a percentage. The maximum output frequency is 100%. | 0.0% (0.0 - 110.0%) |

◆ d3: Jump Frequency

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------|--|----------------------------|
| d3-01 (0294) | Jump Frequency 1 | Sets the median value of the frequency band that the drive will avoid. | 0.0 Hz (0.0 - 400.0 Hz) |
| d3-02 (0295) | Jump Frequency 2 | Sets the median value of the frequency band that the drive will avoid. | 0.0 Hz (0.0 - 400.0 Hz) |
| d3-03 (0296) | Jump Frequency 3 | Sets the median value of the frequency band that the drive will avoid. | 0.0 Hz (0.0 - 400.0 Hz) |
| d3-04 (0297) | Jump Frequency Width | Sets the width of the frequency band that the drive will avoid. | 1.0 Hz (0.0 - 20.0 Hz) |

◆ d4: Frequency Ref Up/Down & Hold

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|---------------------------------|---|-----------------|
| d4-01 (0298) | Freq Reference Hold Selection | Sets the function that saves the frequency reference after a Stop command or when de-energizing the drive. Set <i>H1-xx</i> [MFDI Function Selection] to one of these values to enable this parameter: <ul style="list-style-type: none"> • <i>A</i> [Accel/Decel Ramp Hold] • <i>10/11</i> [Up/Down Command] 0 : Disabled 1 : Enabled | 0 (0, 1) |
| d4-10 (02B6) | Up/Down Freq Lower Limit Select | Sets the lower frequency limit for the Up/Down function. 0 : Greater of d2-02 or Analog 1 : d2-02 | 0 (0, 1) |

◆ d6: Field Weakening

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|---------------------------------|---|----------------------------|
| d6-01 (02A0) | Field Weakening Level | Sets the drive output voltage as a percentage of <i>E1-05</i> [Maximum Output Voltage] when <i>H1-xx = 63</i> [Field Weakening] is activated. | 80% (0 - 100%) |
| d6-02 (02A1) | Field Weakening Frequency Limit | Sets the minimum output frequency to start field weakening. | 0.0 Hz (0.0 - 400.0 Hz) |

◆ d7: Offset Frequency

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------|--|----------------------------|
| d7-01 (02B2) RUN | Offset Frequency 1 | Uses <i>H1-xx = 44</i> [MFDI Function Select = Add Offset Frequency 1 (d7-01)] as a percentage of the Maximum Output Frequency to add or subtract the set frequency to/from the frequency reference. | 0.0% (-100.0 - +100.0%) |
| d7-02 (02B3) RUN | Offset Frequency 2 | Uses <i>H1-xx = 45</i> [MFDI Function Select = Add Offset Frequency 2 (d7-02)] as a percentage of the Maximum Output Frequency to add or subtract the set frequency to/from the frequency reference. | 0.0% (-100.0 - +100.0%) |
| d7-03 (02B4) RUN | Offset Frequency 3 | Uses <i>H1-xx = 46</i> [MFDI Function Select = Add Offset Frequency 3 (d7-03)] as a percentage of the Maximum Output Frequency to add or subtract the set frequency to/from the frequency reference. | 0.0% (-100.0 - +100.0%) |

7.6 E: Motor Parameters

◆ E1: V/f Pattern for Motor 1

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|--------------------------|--|--|
| E1-01 (0300) | Input AC Supply Voltage | Sets the drive input voltage. | 208/240 V: 240 V, 480 V: 480 V (208/240 V: 155 - 255 V, 480 V: 310 - 510 V) |
| E1-03 (0302) | V/f Pattern Selection | Sets the V/f pattern for the drive and motor. You can use one of the preset patterns or you can make a custom pattern. 0 : Const Trq, 50Hz base, 50Hz max 1 : Const Trq, 60Hz base, 60Hz max 2 : Const Trq, 50Hz base, 60Hz max 3 : Const Trq, 60Hz base, 72Hz max 4 : VT, 50Hz, 65% Vmid reduction 5 : VT, 50Hz, 50% Vmid reduction 6 : VT, 60 Hz, 65% Vmid reduction 7 : VT, 60Hz, 50% Vmid reduction 8 : High Trq, 50Hz, 25% Vmin boost 9 : High Trq, 50Hz, 65% Vmin boost A : High Trq, 60Hz, 25% Vmin boost B : High Trq, 60Hz, 65% Vmin boost C : High Freq, 60Hz base, 90Hz max D : High Freq, 60Hz base, 120Hz max E : High Freq, 60Hz base, 180Hz max F : Custom Note: • Set the correct V/f pattern for the application and operation area. An incorrect V/f pattern can decrease motor torque and increase current from overexcitation. • Parameter A1-03 [Initialize Parameters] will not initialize the value of E1-03. | F (0 - F) |
| E1-04 (0303) | Maximum Output Frequency | Sets the maximum output frequency for the V/f pattern. | 60.0 Hz (40.0 to 400.0 Hz) |
| E1-05 (0304) | Maximum Output Voltage | Sets the maximum output voltage for the V/f pattern. | 208/240 V: 230.0 V, 480 V: 460.0 V (208/240 V: 0.0 - 255.0 V, 480 V: 0.0 - 510.0 V) |
| E1-06 (0305) | Base Frequency | Sets the base frequency for the V/f pattern. | 60.0 Hz (0.0 - E1-04) |
| E1-07 (0306) | Mid Point A Frequency | Sets a middle output frequency for the V/f pattern. | 30.0 Hz (0.0 - E1-04) |
| E1-08 (0307) | Mid Point A Voltage | Sets a middle output voltage for the V/f pattern. | Determined by o2-04 (208/240 V: 0.0 - 255.0 V, 480 V: 0.0 - 510.0 V) |
| E1-09 (0308) | Minimum Output Frequency | Sets the minimum output frequency for the V/f pattern. | 1.5 Hz (Determined by E1-04) |
| E1-10 (0309) | Minimum Output Voltage | Sets the minimum output voltage for the V/f pattern. | 10.2 V (208/240 V: 0.0 - 255.0 V, 480 V: 0.0 - 510.0 V) |
| E1-11 (030A) Expert | Mid Point B Frequency | Sets a middle output frequency for the V/f pattern. | 0.0 Hz (0.0 - E1-04) |
| E1-12 (030B) Expert | Mid Point B Voltage | Sets a middle point voltage for the V/f pattern. | 0.0 V (208/240 V: 0.0 - 255.0 V, 480 V: 0.0 - 510.0 V) |
| E1-13 (030C) Expert | Base Voltage | Sets the base voltage for the V/f pattern. | 0.0 V (208/240 V: 0.0 - 255.0 V, 480 V: 0.0 - 510.0 V) |

◆ E2: Motor Parameters

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------------|--|--|
| E2-01 (030E) | Motor Rated Current (FLA) | Sets the motor rated current in amps. | Determined by o2-04 (10% to 200% of the drive rated current) |
| E2-02 (030F) | Motor Rated Slip | Sets motor rated slip. | Determined by o2-04 (0.000 - 20.000 Hz) |
| E2-03 (0310) | Motor No-Load Current | Sets the no-load current for the motor in amps when operating at the rated frequency and the no-load voltage. | Determined by o2-04 (0 to E2-01) |
| E2-04 (0311) | Motor Pole Count | Sets the number of motor poles. | 4 (2 - 120) |
| E2-05 (0312) | Motor Line-to-Line Resistance | Sets the line-to-line resistance for the motor stator windings. | Determined by o2-04 (0.000 - 65.000 Ω) |
| E2-06 (0313) | Motor Leakage Inductance | Sets the voltage drop from motor leakage inductance when the motor is operating at the rated frequency and rated current. This value is a percentage of Motor Rated Voltage. | Determined by o2-04 (0.0 - 60.0%) |
| E2-10 (0317) | Motor Iron Loss | Sets the motor iron loss. | Determined by o2-04 (0 - 65535 W) |
| E2-11 (0318) | Motor Rated Power | Sets the motor rated output in the units from o1-58 [<i>Motor Power Unit Selection</i>]. | Determined by o2-04 (0.00 - 650.00 HP) |

7.7 F: Options

◆ F6: Communication Options

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|-----------------------------------|--|------------------------|
| F6-01 (03A2) | Communication Error Selection | Sets the method to stop the motor or let the motor continue operating when the drive detects <i>bUS</i> [Option Communication Error]. 0 : Ramp to Stop 1 : Coast to Stop 2 : Fast Stop (Use C1-09) 3 : Alarm Only 4 : Alarm (Run at d1-04) 5 : Alarm - Ramp Stop | 1 (0 - 5) |
| F6-02 (03A3) | Comm External Fault (EF0) Detect | Sets the conditions at which <i>EF0</i> [Option Card External Fault] is detected. 0 : Always Detected 1 : Detected during RUN Only | 0 (0, 1) |
| F6-03 (03A4) | Comm External Fault (EF0) Select | Sets the method to stop the motor or let the motor continue operating when the drive detects an <i>EF0</i> [Option Card External Fault]. 0 : Ramp to Stop 1 : Coast to Stop 2 : Fast Stop (Use C1-09) 3 : Alarm Only | 1 (0 - 3) |
| F6-04 (03A5) | bUS Error Detection Time | Sets the delay time for the drive to detect <i>bUS</i> [Option Communication Error]. Note: When you install an option card in the drive, the parameter value changes to 0.0 s. | 2.0 s (0.0 - 5.0 s) |
| F6-07 (03A8) | Multi-Step Ref @ NetRef/ ComRef | Sets the function that enables and disables the multi-step speed reference when the frequency reference source is NetRef or ComRef (communication option card or serial communications). 0 : Disable Multi-Step References 1 : Enable Multi-Step References | 0 (0, 1) |
| F6-08 (036A) | Comm Parameter Reset @Initialize | Sets the function to initialize <i>F6-xx</i> and <i>F7-xx</i> parameters when the drive is initialized with <i>A1-03</i> [Initialize Parameters]. 0 : No Reset - Parameters Retained 1 : Reset Back to Factory Default | 0 (0, 1) |
| F6-14 (03BB) | BUS Error Auto Reset | Sets the automatic reset function for <i>bUS</i> [Option Communication Errors]. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| F6-15 (0B5B) | Comm. Option Parameters Reload | Sets the update method when you change <i>F6-xx</i> , <i>F7-xx</i> [Communication Options]. 0 : Reload at Next Power Cycle 1 : Reload Now 2 : Cancel Reload Request | 0 (0 - 2) |
| F6-48 (02FE) | BACnet Device Object Identifier 0 | Sets the Instance Identifier of the BACnet Device Object, where the <i>F6-48</i> value is the least significant word. Available in bypass software versions 00446 and later. Note: This parameter and <i>F6-49</i> set the Instance Identifier of the BACnet Device Object. Example 1: Set the Device Object Instance Identifier to 1234. 1234 decimal is equal to 4D2H (hexadecimal). Set <i>F6-48</i> = 4D2H and <i>F6-49</i> = 0. Example 2: Set the Device Object Instance Identifier to 1234567. 1234567 decimal is equal to 12D687H. Set <i>F6-48</i> = D687H and <i>F6-49</i> = 12H. | 1 (0 - FFFFH) |
| F6-49 (02FF) | BACnet Device Object Identifier 1 | Sets the Instance Identifier of the BACnet Device Object, where the <i>F6-49</i> value is the most significant word. Available in bypass software versions 00446 and later. Note: This parameter and <i>F6-48</i> set the Instance Identifier of the BACnet Device Object. Example 1: Set the Device Object Instance Identifier to 1234. 1234 decimal is equal to 4D2H (hexadecimal). Set <i>F6-48</i> = 4D2H and <i>F6-49</i> = 0. Example 2: Set the Device Object Instance Identifier to 1234567. 1234567 decimal is equal to 12D687H. Set <i>F6-48</i> = D687H and <i>F6-49</i> = 12H. | 0 (0 - 3FH) |
| F6-54 (03C5) | Net Idle Fault Detection | Sets the function to detect <i>EF0</i> [Option Card External Fault] when the drive does not receive data from the DeviceNet or EtherNet/IP master. 0 : Enabled 1 : Disabled, No Fault Detection 2 : Vendor Specific 3 : RUN Forward 4 : RUN Reverse | 0 (0 - 4) |

◆ F7: Ethernet Options

Note:

You must cycle power or set $F6-15 = 1$ [*Comm. Option Parameters Reload = Reload Now*] for F7-xx parameters to take effect.

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|-------------------|---|------------------|
| F7-01 (03E5) | IP Address 1 | Sets the first octet of the IP Address for the device that is connecting to the network. Restart the drive after you change this parameter. Note: When $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]: • Use parameters F7-01 to F7-04 [<i>IP Address 4</i>] to set the IP Address. Be sure to set a different IP address for each drive on the network. • Also set parameters F7-01 to F7-12. | 192 (0 - 255) |
| F7-02 (03E6) | IP Address 2 | Sets the second octet of the IP Address for the device that is connecting to the network. Restart the drive after you change this parameter. Note: When $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]: • Use parameters F7-01 to F7-04 [<i>IP Address 4</i>] to set the IP Address. Be sure to set a different IP address for each drive on the network. • Also set parameters F7-01 to F7-12. | 168 (0 - 255) |
| F7-03 (03E7) | IP Address 3 | Sets the third octet of the IP Address for the device that is connecting to the network. Restart the drive after you change this parameter. Note: When $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]: • Use parameters F7-01 to F7-04 [<i>IP Address 4</i>] to set the IP Address. Be sure to set a different IP address for each drive on the network. • Also set parameters F7-01 to F7-12. | 1 (0 - 255) |
| F7-04 (03E8) | IP Address 4 | Sets the fourth octet of the IP Address for the device that is connecting to the network. Restart the drive after you change this parameter. Note: When $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]: • Use parameters F7-01 to F7-04 [<i>IP Address 4</i>] to set the IP Address. Be sure to set a different IP address for each drive on the network. • Also set parameters F7-01 to F7-12. | 20 (0 - 255) |
| F7-05 (03E9) | Subnet Mask 1 | Sets the first octet of the subnet mask of the connected network. Note: Set this parameter when $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]. | 255 (0 - 255) |
| F7-06 (03EA) | Subnet Mask 2 | Sets the second octet of the subnet mask of the connected network. Note: Set this parameter when $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]. | 255 (0 - 255) |
| F7-07 (03EB) | Subnet Mask 3 | Sets the third octet of the subnet mask of the connected network. Note: Set this parameter when $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]. | 255 (0 - 255) |
| F7-08 (03EC) | Subnet Mask 4 | Sets the fourth octet of the subnet mask of the connected network. Note: Set this parameter when $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]. | 0 (0 - 255) |
| F7-09 (03ED) | Gateway Address 1 | Sets the first octet of the gateway address of the connected network. Note: Set this parameter when $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]. | 192 (0 - 255) |
| F7-10 (03EE) | Gateway Address 2 | Sets the second octet of the gateway address of the connected network. Note: Set this parameter when $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]. | 168 (0 - 255) |
| F7-11 (03EF) | Gateway Address 3 | Sets the third octet of the gateway address of the connected network. Note: Set this parameter when $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]. | 1 (0 - 255) |
| F7-12 (03F0) | Gateway Address 4 | Sets the fourth octet of the gateway address of the connected network. Note: Set this parameter when $F7-13 = 0$ [<i>Address Mode at Startup = Static</i>]. | 1 (0 - 255) |

7.7 F: Options

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|--|-------------------------|
| F7-13 (03F1) | Address Mode at Startup | <p>Sets the method to set option card IP addresses.</p> <p>0 : Static 1 : BOOTP 2 : DHCP</p> <p>Note:</p> <ul style="list-style-type: none"> The following setting values are available when using the PROFINET communication option card (SI-EP3). <ul style="list-style-type: none"> -0: Static (It is possible for the PLC to override this setting, if so configured) -1: BOOTP (In PROFINET, this setting does NOT use BOOTP. It uses a PROFINET-specific method, DCP) (In BACnet/IP, this setting is the same as DHCP). -2: DHCP (In PROFINET, this setting does NOT use DHCP. It uses a PROFINET-specific method, DCP) When <i>F7-13 = 0</i>, set parameters <i>F7-01 to F7-12 [IP Address 1 to Gateway Address 4]</i> to set the IP Address. Be sure to set a different IP address for each drive on the network. | 2 (0 - 2) |
| F7-14 (03F2) | Duplex Mode Selection | <p>Sets the duplex mode setting method.</p> <p>0 : Half/Half 1 : Auto/Auto 2 : Full/Full 3 : Half/Auto 4 : Half/Full 5 : Auto/Half 6 : Auto/Full 7 : Full/Half 8 : Full/Auto</p> | 1 (0 - 8) |
| F7-15 (03F3) | Communication Speed Selection | <p>Sets the communications speed.</p> <p>10 : 10/10 Mbps 100 : 100/100 Mbps 101 : 10/100 Mbps 102 : 100/10 Mbps</p> <p>Note:</p> <p>You must set <i>F7-14 = 0, 2, 4, or 7</i> for this parameter to have an effect.</p> | 10 (10, 100 - 102) |
| F7-16 (03F4) | Timeout Value | <p>Sets the detection time for a communications timeout.</p> <p>Note:</p> <p>Set this parameter to 0.0 to disable the connection timeout function.</p> | 0.0 s (0.0 - 30.0 s) |
| F7-17 (03F5) | EtherNet/IP Speed Scaling Factor | Sets the scaling factor for the speed monitor in the EtherNet/IP Class ID 2AH Object. | 0 (-15 - +15) |
| F7-18 (03F6) | EtherNet/IP Current Scale Factor | Sets the scaling factor for the output current monitor in the EtherNet/IP Class ID 2AH Object. | 0 (-15 - +15) |
| F7-19 (03F7) | EtherNet/IP Torque Scale Factor | Sets the scaling factor for the torque monitor in the EtherNet/IP Class ID 2AH Object. | 0 (-15 - +15) |
| F7-20 (03F8) | EtherNet/IP Power Scaling Factor | Sets the scaling factor for the power monitor in the EtherNet/IP Class ID 2AH Object. | 0 (-15 - +15) |
| F7-21 (03F9) | EtherNet/IP Voltage Scale Factor | Sets the scaling factor for the voltage monitor in the EtherNet/IP Class ID 2AH Object. | 0 (-15 - +15) |
| F7-22 (03FA) | EtherNet/IP Time Scaling | Sets the scaling factor for the time monitor in the EtherNet/IP Class ID 2AH Object. | 0 (-15 - +15) |
| F7-23 (03FB) | Dynamic Out Param 1 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. When you use a ProfiNet option, set this parameter to set to configurable output 1. | 0 (0 - FFFF) |
| F7-24 (03FC) | Dynamic Out Param 2 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. When you use a ProfiNet option, set this parameter to set to configurable output 2. | 0 (0 - FFFF) |
| F7-25 (03FD) | Dynamic Out Param 3 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. When you use a ProfiNet option, set this parameter to set to configurable output 3. | 0 (0 - FFFF) |
| F7-26 (03FE) | Dynamic Out Param 4 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. When you use a ProfiNet option, set this parameter to set to configurable output 4. | 0 (0 - FFFF) |

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|-----------------------------------|---|--------------------|
| F7-27 (03FF) | Dynamic Out Param 5 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. When you use a ProfiNet option, set this parameter to set to configurable output 5. | 0 (0 - FFFF) |
| F7-28 (0370) | Dynamic Out Param 6 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. | 0 (0 - FFFF) |
| F7-29 (0371) | Dynamic Out Param 7 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. | 0 (0 - FFFF) |
| F7-30 (0372) | Dynamic Out Param 8 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. | 0 (0 - FFFF) |
| F7-31 (0373) | Dynamic Out Param 9 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. | 0 (0 - FFFF) |
| F7-32 (0374) | Dynamic Out Param 10 for CommCard | Sets Output Assembly 116 when you use an Ethernet/IP option. The drive writes the values from Output Assembly 116 to the MEMOBUS/Modbus address register that is stored for each parameter. The drive will not write the values from Output Assembly 116 to the registers when the MEMOBUS/Modbus address is 0. | 0 (0 - FFFF) |
| F7-33 (0375) | Dynamic In Param 1 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. When you use a ProfiNet option, set this parameter to set to configurable input 1. | 0 (0 - FFFF) |
| F7-34 (0376) | Dynamic In Param 2 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. When you use a ProfiNet option, set this parameter to set to configurable input 2. | 0 (0 - FFFF) |
| F7-35 (0377) | Dynamic In Param 3 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. When you use a ProfiNet option, set this parameter to set to configurable input 3. | 0 (0 - FFFF) |
| F7-36 (0378) | Dynamic In Param 4 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. When you use a ProfiNet option, set this parameter to set to configurable input 4. | 0 (0 - FFFF) |
| F7-37 (0379) | Dynamic In Param 5 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. When you use a ProfiNet option, set this parameter to set to configurable input 5. | 0 (0 - FFFF) |
| F7-38 (037A) | Dynamic In Param 6 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. | 0 (0 - FFFF) |
| F7-39 (037B) | Dynamic In Param 7 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. | 0 (0 - FFFF) |
| F7-40 (037C) | Dynamic In Param 8 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. | 0 (0 - FFFF) |
| F7-41 (037D) | Dynamic In Param 9 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. | 0 (0 - FFFF) |
| F7-42 (037E) | Dynamic In Param 10 for CommCard | Sets Input Assembly 166 when you use an Ethernet/IP option. The drive sends the values from the MEMOBUS/Modbus address registers stored for each parameter to Input Assembly 166. The drive returns the default register value for the option card when the MEMOBUS/Modbus address is 0 and the value sent to Input Assembly 166 is not defined. | 0 (0 - FFFF) |
| F7-43 (1BCE) | PLC CnXn Close Behavior@Run | Sets the drive response when a PLC closes a connection while the drive has an active Run command from the network. 0 : Continue 1 : Clear Run Command 2 : Fault | 0 (0 - 2) |

7.7 F: Options

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|------------------------------|--|-------------------------|
| F7-50 (1BC1) | BACnet/IP Port | Sets the UDP port on which the drive will receive incoming BACnet messages. Available in bypass software versions 00446 and later. | 47808 (1024 - 65535) |
| F7-51 (1BE9) | BBMD Foreign Register Addr 1 | Sets the first octet of the IP Address of the BACnet Broadcast Management Device (BBMD) to which the drive will register as a foreign device. Available in bypass software versions 00446 and later. | 0 (0 - 255) |
| F7-52 (1BEA) | BBMD Foreign Register Addr 2 | Sets the second octet of the IP Address of the BACnet Broadcast Management Device (BBMD) to which the drive will register as a foreign device. Available in bypass software versions 00446 and later. | 0 (0 - 255) |
| F7-53 (1BEB) | BBMD Foreign Register Addr 3 | Sets the third octet of the IP Address of the BACnet Broadcast Management Device (BBMD) to which the drive will register as a foreign device. Available in bypass software versions 00446 and later. | 0 (0 - 255) |
| F7-54 (1BEC) | BBMD Foreign Register Addr 4 | Sets the fourth octet of the IP Address of the BACnet Broadcast Management Device (BBMD) to which the drive will register as a foreign device. Available in bypass software versions 00446 and later. | 0 (0 - 255) |
| F7-55 (1BED) | BBMD Foreign Register Port | Sets the UDP port of the BBMD device to which the drive will register. Available in bypass software versions 00446 and later. | 47808 (1024 - 65535) |
| F7-56 (1BEE) | BBMD Foreign Register Time | Sets the time interval in which the drive will repeat BBMD foreign registration. Available in bypass software versions 00446 and later. | 3600 s (0 - 65535 s) |
| F7-57 (1BEF) | BACnet/IP BUS Timeout Value | Sets the length of time that the drive will wait after it receives a Run command or frequency reference command before it detects a <i>bUS</i> fault. Available in bypass software versions 00446 and later. | 3600 s (0 - 65535 s) |

7.8 H: Terminal Functions

◆ H1: Digital Inputs

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------------------|--|-----------------------------|
| H1-01 (0438) | Terminal S1 Function Selection | Sets the function for MFDI terminal S1. | 40 (3 to 1A8) |
| H1-02 (0439) | Terminal S2 Function Selection | Sets the function for MFDI terminal S2. | F (3 to 1A8) |
| H1-03 (0400) | Terminal S3 Function Selection | Sets the function for MFDI terminal S3. | 24 (3 to 1A8) |
| H1-04 (0401) | Terminal S4 Function Selection | Sets the function for MFDI terminal S4. | 14 (3 to 1A8) |
| H1-05 (0402) | Terminal S5 Function Selection | Sets the function for MFDI terminal S5. | 3 (3 to 1A8) |
| H1-06 (0403) | Terminal S6 Function Selection | Sets the function for MFDI terminal S6. | 4 (3 to 1A8) |
| H1-07 (0404) | Terminal S7 Function Selection | Sets the function for MFDI terminal S7. | 6 (3 to 1A8) |
| H1-61 (39E1) RUN | Terminal S1 On-Delay Time | Sets the length of time necessary for Terminal S1 to be closed before the drive does the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-62 (39E2) RUN | Terminal S2 On-Delay Time | Sets the length of time necessary for Terminal S2 to be closed before the drive does the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-63 (39E3) RUN | Terminal S3 On-Delay Time | Sets the length of time necessary for Terminal S3 to be closed before the drive does the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-64 (39E4) RUN | Terminal S4 On-Delay Time | Sets the length of time necessary for Terminal S4 to be closed before the drive does the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-65 (39E5) RUN | Terminal S5 On-Delay Time | Sets the length of time necessary for Terminal S5 to be closed before the drive does the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-66 (39E6) RUN | Terminal S6 On-Delay Time | Sets the length of time necessary for Terminal S6 to be closed before the drive does the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-67 (39E7) RUN | Terminal S7 On-Delay Time | Sets the length of time necessary for Terminal S7 to be closed before the drive does the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-71 (39EB) RUN | Terminal S1 Off-Delay Time | Sets the length of time necessary for Terminal S1 to be open before the drive removes the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-72 (39EC) RUN | Terminal S2 Off-Delay Time | Sets the length of time necessary for Terminal S2 to be open before the drive removes the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-73 (39ED) RUN | Terminal S3 Off-Delay Time | Sets the length of time necessary for Terminal S3 to be open before the drive removes the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-74 (39EE) RUN | Terminal S4 Off-Delay Time | Sets the length of time necessary for Terminal S4 to be open before the drive removes the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-75 (39EF) RUN | Terminal S5 Off-Delay Time | Sets the length of time necessary for Terminal S5 to be open before the drive removes the programmed function. | 0.00 s (0.00 - 300.00 s) |

7.8 H: Terminal Functions

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------|--|-----------------------------|
| H1-76 (39F0) RUN | Terminal S6 Off-Delay Time | Sets the length of time necessary for Terminal S6 to be open before the drive removes the programmed function. | 0.00 s (0.00 - 300.00 s) |
| H1-77 (39F1) RUN | Terminal S7 Off-Delay Time | Sets the length of time necessary for Terminal S7 to be open before the drive removes the programmed function. | 0.00 s (0.00 - 300.00 s) |

◆ H1-xx: MFDI Setting Values

| Setting Value | Function | Description |
|---------------|----------------------------------|---|
| 3 | Multi-Step Speed Reference 1 | Uses speed references <i>d1-01</i> to <i>d1-08</i> to set a multi-step speed reference. |
| 4 | Multi-Step Speed Reference 2 | Uses speed references <i>d1-01</i> to <i>d1-08</i> to set a multi-step speed reference. |
| 5 | Multi-Step Speed Reference 3 | Uses speed references <i>d1-01</i> to <i>d1-08</i> to set a multi-step speed reference. |
| 6 | Jog Reference Selection | Sets the drive to use the JOG Frequency Reference (JOG command) set in <i>d1-17</i> [<i>Jog Reference</i>]. The JOG Frequency Reference (JOG command) overrides the <i>d1-01</i> to <i>d1-08</i> [<i>References 1 to 8</i>] settings. |
| 7 | Accel/Decel Time Selection 1 | Sets the drive to use <i>Acceleration/Deceleration Time 1</i> [<i>C1-01, C1-02</i>] or <i>Acceleration/Deceleration Time 2</i> [<i>C1-03, C1-04</i>]. |
| 8 | Baseblock Command (N.O.) | Sets the command that stops drive output and coasts the motor to stop when the input is ON. ON : Baseblock (drive output stop) OFF : Normal operation |
| 9 | Baseblock Command (N.C.) | Sets the command that stops drive output and coasts the motor to stop when the input terminal is OFF. ON : Normal operation OFF : Baseblock (drive output stop) |
| A | Accel/Decel Ramp Hold | Momentarily pauses motor acceleration and deceleration when the terminal is turned ON, retains the output frequency that was stored in the drive at the time of the pause, and restarts motor operation. |
| B | Overheat Alarm (oH2) | Sets the drive to display an <i>oH2</i> [<i>Drive Overheat Warning</i>] alarm when the input terminal is ON. The alarm does not have an effect on drive operation. |
| C | Analog Terminal Enable Selection | Sets the command that enables or disables the terminals selected in <i>H3-14</i> [<i>Analog Input Terminal Enable Sel</i>]. ON : Input to the terminal selected with <i>H3-14</i> is enabled OFF : Input to the terminal selected with <i>H3-14</i> is disabled |
| F | Not Used | Use this setting for unused terminals or to use terminals in through mode. |
| 14 | Fault Reset | Sets the command to reset the current fault when the Run command is inactive. Note: • The drive ignores the fault reset command when the Run command is active. Remove the Run command before trying to reset a fault. • This will only reset drive-specific faults. It will not reset bypass (<i>FBxx</i>) faults. Set <i>Z2-0x = 34</i> and a bypass digital input to reset ALL faults. |
| 15 | Fast Stop (N.O.) | Sets the command to ramp to stop in the deceleration time set in <i>C1-09</i> [<i>Fast Stop Time</i>] when the input terminal is activated while the drive is operating. |
| 17 | Fast Stop (N.C.) | Sets the command to ramp to stop in the deceleration time set in <i>C1-09</i> [<i>Fast Stop Time</i>] when the input terminal is activated while the drive is operating. |
| 18 | Timer Function | Sets the command to start the timer function. Use this setting with <i>Timer Output</i> [<i>H2-xx = 12</i>]. |
| 19 | PID Disable | Sets the command to disable PID control when <i>b5-01 = 1 or 3</i> [<i>PID Mode Setting = Standard or Fref + PID Trim</i>]. ON : PID control disabled OFF : PID control enabled |
| 1B | Programming Lockout | Sets the command to prevent parameter changes when the terminal is OFF. ON : Programming Lockout OFF : Parameter Write Prohibit |
| 1E | Reference Sample Hold | Sets the command to sample the frequency reference at terminals A1 or A2 and hold the frequency reference at that frequency. |
| 20 | External Fault (NO-Always-Ramp) | When the terminal activates, the drive ramps to stop in the selected deceleration time. Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive always detects external faults whether the drive is stopped or running. |
| 21 | External Fault (NC-Always-Ramp) | When the terminal deactivates, the drive ramps to stop in the selected deceleration time. Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive always detects external faults whether the drive is stopped or running. |
| 22 | External Fault (NO-@Run-Ramp) | When the terminal activates during run, the drive ramps to stop in the selected deceleration time. Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive does not detect external faults while the drive is stopped. |

| Setting Value | Function | Description |
|---------------|----------------------------------|---|
| 23 | External Fault (NC-@Run-Ramp) | When the terminal deactivates during run, the drive ramps to stop in the selected deceleration time. Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive does not detect external faults while the drive is stopped. |
| 24 | External Fault (NO-Always-Coast) | When the terminal activates, the drive shuts off the output and the motor coasts to stop. Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive always detects external faults whether the drive is stopped or running. |
| 25 | External Fault (NC-Always-Coast) | When the terminal deactivates, the drive shuts off the output and the motor coasts to stop. Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive always detects external faults whether the drive is stopped or running. |
| 26 | External Fault (NO-@Run-Coast) | When the terminal activates during run, the drive shuts off the output and the motor coasts to stop. Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive does not detect external faults while the drive is stopped. |
| 27 | External Fault (NC-@Run-Coast) | When the terminal deactivates during run, the drive shuts off the output and the motor coasts to stop. Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive does not detect external faults while the drive is stopped. |
| 28 | External Fault (NO-Always-FStop) | When the terminal activates, the drive stops the motor in the deceleration time set to <i>C1-09 [Fast Stop Time]</i> . Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive always detects external faults whether the drive is stopped or running. |
| 29 | External Fault (NC-Always-FStop) | When the terminal deactivates, the drive stops the motor in the deceleration time set to <i>C1-09 [Fast Stop Time]</i> . Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive always detects external faults whether the drive is stopped or running. |
| 2A | External Fault (NO-@Run-FStop) | When the terminal activates during run, the drive stops the motor in the deceleration time set to <i>C1-09 [Fast Stop Time]</i> . Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive does not detect external faults while the drive is stopped. |
| 2B | External Fault (NC-@Run-FStop) | When the terminal deactivates during run, the drive stops the motor in the deceleration time set to <i>C1-09 [Fast Stop Time]</i> . Fault relay output terminal MA-MC will turn ON, and MB-MC will turn OFF. The drive does not detect external faults while the drive is stopped. |
| 2C | External Fault (NO-Always-Alarm) | When the terminal activates, the keypad shows <i>EFx [External Fault (Terminal Sx)]</i> and the output terminal set for <i>Alarm [H2-01 to H2-03 = 10]</i> activates. The drive continues operation. The drive always detects external faults whether the drive is stopped or running. |
| 2D | External Fault (NC-Always-Alarm) | When the terminal deactivates, the keypad shows <i>EFx [External Fault (Terminal Sx)]</i> and the output terminal set for <i>Alarm [H2-01 to H2-03 = 10]</i> activates. The drive continues operation. The drive always detects external faults whether the drive is stopped or running. |
| 2E | External Fault (NO-@Run-Alarm) | When the terminal activates during run, the keypad shows <i>EFx [External Fault (Terminal Sx)]</i> and the output terminal set for <i>Alarm [H2-01 to H2-03 = 10]</i> activates. The drive continues operation. The drive does not detect external faults while the drive is stopped. |
| 2F | External Fault (NC-@Run-Alarm) | When the terminal deactivates during run, the keypad shows <i>EFx [External Fault (Terminal Sx)]</i> and the output terminal set for <i>Alarm [H2-01 to H2-03 = 10]</i> activates. The drive continues operation. The drive does not detect external faults while the drive is stopped. |
| 30 | PID Integrator Reset | Sets the command to reset and hold the PID control integral to 0 when the terminal is ON. |
| 31 | PID Integrator Hold | Sets the command to hold the integral value of the PID control while the terminal is activated. |
| 34 | PID Soft Starter Disable | Sets the PID soft starter function. ON : No OFF : Yes |
| 35 | PID Input (Error) Invert | Sets the command to turn the terminal ON and OFF to switch the PID input level (polarity). |
| 3E | PID Setpoint Selection 1 | Sets the function to switch the PID setpoint to <i>YA-02 [Setpoint 2]</i> or <i>YA-04 [Setpoint 4]</i> . Set this function and <i>H1-xx = 3F [PID Setpoint Selection 2]</i> at the same time. Note: If you use this function and one of <i>H1-xx = 83 to 85 [Dedicated Multi-Setpoint YA-02 to YA-04]</i> at the same time, the drive will detect an <i>oPE03 [Multi-Function Input Setting Err]</i> . ON : <i>YA-02</i> or <i>YA-04</i> is PID setpoint. OFF : The frequency reference, <i>YA-01 [Setpoint 1]</i> , or <i>YA-03 [Setpoint 3]</i> is PID setpoint. |
| 3F | PID Setpoint Selection 2 | Sets the function to switch the PID setpoint to <i>YA-03 [Setpoint 3]</i> or <i>YA-04 [Setpoint 4]</i> . Set this function and <i>H1-xx = 3E [PID Setpoint Selection 1]</i> at the same time. Note: If you use this function and one of <i>H1-xx = 83 to 85 [Dedicated Multi-Setpoint YA-02 to YA-04]</i> at the same time, the drive will detect an <i>oPE03 [Multi-Function Input Setting Err]</i> . ON : <i>YA-03</i> or <i>YA-04</i> is PID setpoint. OFF : The frequency reference, <i>YA-01 [Setpoint 1]</i> , or <i>YA-02 [Setpoint 2]</i> is PID setpoint. |
| 40 | Forward RUN (2-Wire) | Terminals assigned to this value will have no effect. Set <i>Z2-0x = 21</i> and use a bypass digital input instead. |
| 44 | Add Offset Frequency 1 (d7-01) | Sets the function to add the offset frequency set in <i>d7-01 [Offset Frequency 1]</i> to the frequency reference when the terminal activates. |
| 45 | Add Offset Frequency 2 (d7-02) | Sets the function to add the offset frequency set in <i>d7-02 [Offset Frequency 2]</i> to the frequency reference when the terminal activates. |
| 46 | Add Offset Frequency 3 (d7-03) | Sets the function to add the offset frequency set in <i>d7-03 [Offset Frequency 3]</i> to the frequency reference when the terminal activates. |
| 51 | Sequence Timer Disable | Sets the command to disable Sequence Timers. ON : Sequence Timer is Disabled |
| 52 | Sequence Timer Cancel | Sets the command to cancel the currently active Sequence Timer. ON : Cancel Active Sequence Timer |

7.8 H: Terminal Functions

| Setting Value | Function | Description |
|---------------|----------------------------------|--|
| 61 | Speed Search from Fmax | Sets the function to start speed search using an external reference although $b3-01 = 0$ [Speed Search Selection at Start = Disabled]. Note: The drive will detect $oPE03$ [Multi-Function Input Setting Err] when $H1-xx = 61$ and 62 are set at the same time. |
| 62 | Speed Search from Fref | Sets the function to use an external reference to start speed search although $b3-01 = 0$ [Speed Search Selection at Start = Disabled]. Note: The drive will detect $oPE03$ [Multi-Function Input Setting Err] when $H1-xx = 61$ and 62 are set at the same time. |
| 63 | Field Weakening | Sets the function to send the Field Weakening Level and Field Weakening Frequency Limit commands set in $d6-01$ [Field Weakening Level] and $d6-02$ [Field Weakening Frequency Limit] when the input terminal is activated. |
| 68 | High Slip Braking (HSB) Activate | Sets the command to use high-slip braking to stop the motor. |
| 6A | Drive Enable | This will only function in Drive Mode. Sets the function to show dnE [Drive Enabled] on the keypad and ignore Run commands when the terminal is OFF. |
| 70 | Drive Enable 2 | This will only function in Drive Mode. Sets the function to show dnE [Drive Enabled] on the keypad and ignore Run commands when the terminal is OFF. ON : Run command is accepted. OFF : Run command is disabled. When the drive is running, it stops according to $b1-03$ setting. |
| 82 | PI Switch to Aux | Sets $YF-xx$ [PI Auxiliary Control] parameters as primary PI loop parameters and disables $b5-xx$ [PID Control]. Note: When this input is active, $YF-xx$ [PI Auxiliary Control] parameters will always be the primary PI loop parameters. Parameter $YF-20$ [PI Aux Main PI Speed Control] does not have an effect. |
| 83 | Dedicated Multi-Setpoint YA-02 | Sets the function to set the PID setpoint to $YA-02$ [Setpoint 2]. Note: If you use this function and one of $H1-xx = 3E$ or $3F$ [PID Setpoint Selection 1 or 2] at the same time, the drive will detect an $oPE03$ [Multi-Function Input Setting Err]. ON : $YA-02$ is PID setpoint. OFF : $YA-01$ [Setpoint 1], $YA-03$ [Setpoint 3], or $YA-04$ [Setpoint 4] is PID setpoint. |
| 84 | Dedicated Multi-Setpoint YA-03 | Sets the function to set the PID setpoint to $YA-03$ [Setpoint 3]. Set this function and $H1-xx = 83$ [Dedicated Multi-Setpoint YA-02] at the same time. Note: If you use this function and one of $H1-xx = 3E$ or $3F$ [PID Setpoint Selection 1 or 2] at the same time, the drive will detect an $oPE03$ [Multi-Function Input Setting Err]. ON : $YA-03$ is PID setpoint. OFF : $YA-01$ [Setpoint 1], $YA-02$ [Setpoint 2], or $YA-04$ [Setpoint 4] is PID setpoint. |
| 85 | Dedicated Multi-Setpoint YA-04 | Sets the function to set the PID setpoint to $YA-04$ [Setpoint 4]. Set this function, $H1-xx = 83$ [Dedicated Multi-Setpoint YA-02], and $H1-xx = 84$ [Dedicated Multi-Setpoint YA-03] at the same time. Note: If you use this function and one of $H1-xx = 3E$ or $3F$ [PID Setpoint Selection 1 or 2] at the same time, the drive will detect an $oPE03$ [Multi-Function Input Setting Err]. ON : $YA-04$ is PID setpoint. OFF : $YA-01$ [Setpoint 1], $YA-02$ [Setpoint 2], or $YA-03$ [Setpoint 3] is PID setpoint. |
| 88 | Thermostat Fault | Sets the drive to show the $VLTS$ [Thermostat Fault] when the input terminal is ON. Note: This function is active when the drive is running. |
| A8 | PI2 Control Disable | Sets the command to disable the PI2 Control function. Parameter $S3-12$ [PI2 Control Disable Mode Sel] sets the output performance. ON : Enabled OFF : Disabled |
| AA | PI2 Control Inverse Operation | Sets the command to change the sign of the PI2 Control input. |
| AB | PI2 Control Integral Reset | Sets the command to reset the PI2 Control integral value. Note: This input has priority over $H1-xx = AC$ [MFDI Function Selection = PI2 Control Integral Hold]. |
| AC | PI2 Control Integral Hold | Sets the command to lock the PI2 Control integral value. |
| AD | Select PI2 Control PI Parameters | Sets the command to use the $S3-06$ [PI2 Control Proportional Gain] and $S3-07$ [PI2 Control Integral Time] values instead of the $b5-02$ [Proportional Gain (P)] and $b5-03$ [Integral Time (I)] values. Set $S3-01 = 0$ [PI2 Control Enable Selection = Disabled] to enable this function. Note: This multi-function input does not have an effect on PI2 Control. Use this input for the primary PI controller ($b5-xx$). |
| B9 | Disable Pre-charge | Sets the command to disable the Pre-charge function. ON : Pre-charge function is disabled |

| Setting Value | Function | Description |
|---------------|----------------------|--|
| 188 | !Thermostat Fault | Sets the drive to show the <i>VLTS [Thermostat Fault]</i> when the input terminal is OFF. Note: This function is active when the drive is running. |
| 1A8 | !PI2 Control Disable | Sets the command to disable the PI2 Control function. Parameter <i>S3-12 [PI2 Control Disable Mode Sel]</i> sets the output performance. ON : Disabled OFF : Enabled |

◆ H2: Digital Outputs

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------|----------------------------------|---|-------------------------|
| H2-01 (040B) | Term M1-M2 Function Selection | Sets the function for MFDO terminal M1-M2. Note: Set this parameter to <i>F</i> when the terminal is not being used or to use the terminal in through mode. | 0 (0 - 1FF) |
| H2-02 (040C) | Term M3-M4 Function Selection | Sets the function for MFDO terminal M3-M4. Note: Set this parameter to <i>F</i> when the terminal is not being used or to use the terminal in through mode. | 1 (0 - 1FF) |
| H2-03 (040D) | Term M5-M6 Function Selection | Sets the function for MFDO terminal M5-M6. Note: When you do not use this terminal, or when you will use the terminal in through mode, set this parameter to <i>F</i> . | 2 (0 - 1FF) |
| H2-06 (0437) | Watt Hour Output Unit Selection | Sets the unit for the output signal when <i>H2-01 to H2-03 = 39 [MFDO Function Selection = Watt Hour Pulse Output]</i> . 0 : 0.1 kWh units 1 : 1 kWh units 2 : 10 kWh units 3 : 100 kWh units 4 : 1000 kWh units | 0 (0 - 4) |
| H2-07 (0B3A) | Modbus Register 1 Address Select | Sets the address of the MEMOBUS/Modbus register output to the MFDO terminal. | 0001 (0001 - 1FFF) |
| H2-08 (0B3B) | Modbus Register 1 Bit Select | Sets the bit of the MEMOBUS/Modbus register output to the MFDO terminal. | 0000 (0000 - FFFF) |
| H2-09 (0B3C) | Modbus Register 2 Address Select | Sets the address of the MEMOBUS/Modbus register output to the MFDO terminal. | 0001 (0001 - 1FFF) |
| H2-10 (0B3D) | Modbus Register 2 Bit Select | Sets the bit of the MEMOBUS/Modbus register output to the MFDO terminal. | 0000 (0000 - FFFF) |
| H2-40 (0B58) | Mbus Reg 15E0h bit0 Output Func | Sets the MFDO for bit 0 of MEMOBUS register 15E0 (Hex.). | F (0 - 1FF) |
| H2-41 (0B59) | Mbus Reg 15E0h bit1 Output Func | Sets the MFDO for bit 1 of MEMOBUS register 15E0 (Hex.). | F (0 - 1FF) |
| H2-42 (0B5A) | Mbus Reg 15E0h bit2 Output Func | Sets the MFDO for bit 2 of MEMOBUS register 15E0 (Hex.). | F (0 - 1FF) |
| H2-60 (1B46) Expert | Term M1-M2 Secondary Function | Sets the second function for terminal M1-M2. Outputs the logical calculation results of the terminals assigned to functions by <i>H2-01 [Term M1-M2 Function Selection]</i> . | F (0 - FF) |
| H2-61 (1B47) Expert | Terminal M1-M2 Logical Operation | Sets the logical operation for the functions set in <i>H2-01 [Term M1-M2 Function Selection]</i> and <i>H2-60 [Term M1-M2 Secondary Function]</i> . | 0 (0 - 8) |
| H2-62 (1B48) Expert | Terminal M1-M2 Delay Time | Sets the minimum on time used to output the logical calculation results from terminal M1-M2. | 0.1 s (0.0 - 25.0 s) |
| H2-63 (1B49) Expert | Term M3-M4 Secondary Function | Sets the second function for terminal M3-M4. Outputs the logical calculation results of the terminals assigned to functions by <i>H2-02 [Term M3-M4 Function Selection]</i> . | F (0 - FF) |

7.8 H: Terminal Functions

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------|----------------------------------|--|----------------------|
| H2-64 (1B4A) Expert | Terminal M3-M4 Logical Operation | Sets the logical operation for the functions set in H2-02 [Term M3-M4 Function Selection] and H2-63 [Term M3-M4 Secondary Function]. | 0 (0 - 8) |
| H2-65 (1B4B) Expert | Terminal M3-M4 Delay Time | Sets the minimum on time used to output the logical calculation results from terminal M3-M4. | 0.1 s (0.0 - 25.0 s) |
| H2-66 (1B4C) Expert | Term M5-M6 Secondary Function | Sets the second function for terminal M5-M6. Outputs the logical calculation results of the terminals assigned to functions by H2-03 [Terminal M5-M6 Function Select]. | F (0 - FF) |
| H2-67 (1B4D) Expert | Terminal M5-M6 Logical Operation | Sets the logical operation for the functions set in H2-03 [Term M5-M6 Function Selection] and H2-66 [Term M5-M6 Secondary Function]. | 0 (0 - 8) |
| H2-68 (1B4E) Expert | Terminal M5-M6 Delay Time | Sets the minimum on time used to output the logical calculation results from terminal M5-M6. | 0.1 s (0.0 - 25.0 s) |

◆ H2-xx: MFDO Setting Values

| Setting Value | Function | Description |
|---------------|---------------------------------|--|
| 0 | During Run | The terminal activates when you input a Run command and when the drive is outputting voltage. ON : Drive is running OFF : Drive is stopped |
| 1 | Zero Speed | The terminal activates when the output frequency < E1-09 [Minimum Output Frequency]. ON : Output frequency < E1-09. OFF : Output frequency ≥ E1-09. |
| 2 | Speed Agree 1 | The terminal activates when the output frequency is in the range of the frequency reference ± L4-02 [Speed Agree Detection Width]. Note: The detection function operates in the two motor rotation directions. ON : The output frequency is in the range of "frequency reference ± L4-02". OFF : The output frequency does not align with the frequency reference although the drive is running. |
| 3 | User-Set Speed Agree 1 | The terminal activates when the output frequency is in the range of L4-01 [Speed Agree Detection Level] ± L4-02 [Speed Agree Detection Width] and in the range of the frequency reference ± L4-02. Note: The detection function operates in the two motor rotation directions. The drive uses the L4-01 value as the forward/reverse detection level. ON : The output frequency is in the range of "L4-01 ± L4-02" and the range of frequency reference ± L4-02. OFF : The output frequency is not in the range of "L4-01 ± L4-02" or the range of frequency reference ± L4-02. |
| 4 | Frequency Detection 1 | The terminal deactivates when the output frequency > "L4-01 [Speed Agree Detection Level] + L4-02 [Speed Agree Detection Width]". After the terminal deactivates, the terminal stays deactivated until the output frequency is at the value of L4-01. Note: The detection function operates in the two motor rotation directions. The drive uses the L4-01 value as the forward/reverse detection level. ON : The output frequency < L4-01, or the output frequency ≤ "L4-01 + L4-02" OFF : The output frequency > "L4-01 + L4-02" |
| 5 | Frequency Detection 2 | The terminal activates when the output frequency > L4-01 [Speed Agree Detection Level]. After the terminal activates, the terminal stays activated until the output frequency is at the value of "L4-01 - L4-02 [Speed Agree Detection Width]". Note: The detection function operates in the two motor rotation directions. The drive uses the L4-01 value as the forward/reverse detection level. ON : The output frequency > L4-01 OFF : The output frequency < "L4-01 - L4-02", or the output frequency ≤ L4-01 |
| 6 | Drive Ready | The terminal activates when the drive is ready and running. |
| 7 | DC Bus Undervoltage | The terminal activates when the DC bus voltage or control circuit power supply is at the voltage set in L2-05 [Undervoltage Detection Lvl (Uv1)] or less. The terminal also activates when there is a fault with the DC bus voltage. ON : The DC bus voltage ≤ L2-05 OFF : The DC bus voltage > L2-05 |
| 8 | During Baseblock (N.O.) | The terminal activates during baseblock. When the drive is in baseblock, the drive output transistor stops switching and does not make DC bus voltage. ON : During baseblock OFF : The drive is not in baseblock. |
| 9 | Frequency Reference from Keypad | Shows the selected frequency reference source. This terminal has no function when part of a bypass configuration. |

| Setting Value | Function | Description |
|---------------|-------------------------------|---|
| B | Torque Detection 1 (N.O.) | The terminal activates when the drive detects overtorque or undertorque. ON : The output current/torque > L6-02 [Torque Detection Level 1], or the output current/torque < L6-02 for longer than the time set in L6-03 [Torque Detection Time 1]. |
| C | Frequency Reference Loss | The terminal activates when the drive detects a loss of frequency reference. This terminal has no function when part of a bypass configuration. |
| E | Fault | The terminal activates when the drive detects a fault. Note: The terminal will not activate for CPF00 and CPF01 [Control Circuit Error] faults. |
| F | Not Used | Use this setting for unused terminals or to use terminals in through mode. Also use this setting as the PLC contact output via serial communication or the communication option. This signal does not function if signals from the PLC are not configured. |
| 10 | Alarm | The terminal activates when the drive detects a minor fault. The terminal will not activate for bypass-specific alarms. |
| 11 | Fault Reset Command Active | The terminal activates when the drive receives the Reset command from the control circuit terminal, serial communications, or the communication option. |
| 12 | Timer Output | Use this setting when the drive uses the timer function as an output terminal. |
| 13 | Speed Agree 2 | The terminal activates when the output frequency is in the range of the frequency reference $\pm L4-04$ [Speed Agree Detection Width (+/-)]. Note: The detection function operates in the two motor rotation directions. ON : The output frequency is in the range of "frequency reference $\pm L4-04$ ". OFF : The output frequency is not in the range of "frequency reference $\pm L4-04$ ". |
| 14 | User-Set Speed Agree 2 | The terminal activates when the output frequency is in the range of L4-03 [Speed Agree Detection Level (+/-)] $\pm L4-04$ [Speed Agree Detection Width (+/-)] and in the range of the frequency reference $\pm L4-04$. Note: The detection level set in L4-03 is a signed value. The drive will only detect in one direction. ON : The output frequency is in the range of "L4-03 $\pm L4-04$ " and the range of frequency reference $\pm L4-04$. OFF : The output frequency is not in the range of "L4-03 $\pm L4-04$ " or the range of frequency reference $\pm L4-04$. |
| 15 | Frequency Detection 3 | The terminal deactivates when the output frequency > "L4-03 [Speed Agree Detection Level (+/-)] + L4-04 [Speed Agree Detection Width (+/-)]". After the terminal deactivates, the terminal stays deactivated until the output frequency is at the value of L4-03. Note: The detection level set in L4-03 is a signed value. The drive will only detect in one direction. ON : The output frequency < L4-03, or the output frequency $\leq L4-03 + L4-04$. OFF : The output frequency > "L4-03 + L4-04". |
| 16 | Frequency Detection 4 | The terminal activates when the output frequency > L4-03 [Speed Agree Detection Level (+/-)]. After the terminal activates, the terminal stays activated until the output frequency is at the value of "L4-03 - L4-04". Note: The detection level set in L4-03 is a signed value. The drive will only detect in one direction. ON : The output frequency > L4-03. OFF : The output frequency < "L4-03 - L4-04", or the output frequency $\leq L4-03$. |
| 17 | Torque Detection 1 (N.C.) | The terminal deactivates when the drive detects overtorque or undertorque. OFF : The output current/torque > L6-02 [Torque Detection Level 1], or the output current/torque < L6-02 for longer than the time set in L6-03 [Torque Detection Time 1]. |
| 18 | Torque Detection 2 (N.O.) | The terminal activates when the drive detects overtorque or undertorque. ON : The output current/torque > L6-05 [Torque Detection Level 2], or the output current/torque < L6-05 for longer than the time set in L6-06 [Torque Detection Time 2]. |
| 19 | Torque Detection 2 (N.C.) | The terminal deactivates when the drive detects overtorque or undertorque. OFF : The output current/torque > L6-05 [Torque Detection Level 2], or the output current/torque < L6-05 for longer than the time set in L6-06 [Torque Detection Time 2]. |
| 1A | During Reverse | The terminal activates when the motor operates in the reverse direction. ON : The motor is operating in the reverse direction. OFF : The motor is operating in the forward direction or the motor stopped. |
| 1B | During Baseblock (N.C.) | The terminal deactivates during baseblock. When the drive is in baseblock, the drive output transistor stops switching and does not make DC bus voltage. ON : The drive is not in baseblock. OFF : During baseblock |
| 1E | Executing Auto-Restart | The terminal activates when the Auto Restart function is trying to restart after a fault. |
| 1F | Motor Overload Alarm (oL1) | The terminal activates when the electronic thermal protection value of the motor overload protective function is a minimum of 90% of the detection level. |
| 20 | Drive Overheat Pre-Alarm (oH) | The terminal activates when the drive heatsink temperature is at the level set with L8-02 [Overheat Alarm Level]. |
| 21 | Safe Torque OFF | The terminal activates (safety stop state) when the safety circuit and safety diagnosis circuit are operating correctly and when terminals H1-HC and H2-HC are OFF (Open). ON : Safety stop state OFF : Safety circuit fault or RUN/READY |

7.8 H: Terminal Functions

| Setting Value | Function | Description |
|---------------|---------------------------------|--|
| 2F | Maintenance Notification | The terminal activates when drive components are at their estimated maintenance period. Tells the user about the maintenance period for these items: <ul style="list-style-type: none"> • IGBT • Cooling fan • Capacitor • Soft charge bypass relay |
| 37 | During Frequency Output | The terminal activates when the drive outputs frequency. ON : The drive outputs frequency. OFF : The drive does not output frequency. |
| 38 | Drive Enabled | This terminal activates when the <i>H1-xx = 6A [Drive Enable]</i> terminal activates. |
| 39 | Watt Hour Pulse Output | Outputs the pulse that shows the watt hours. |
| 3A | Drive Overheat Alarm | The terminal activates when the drive heatsink temperature is at the <i>L8-02 [Overheat Alarm Level]</i> setting while <i>L8-03 = 4 [Overheat Pre-Alarm Selection = Operate at Reduced Speed (L8-19)]</i> and the drive is running. |
| 3D | During Speed Search | The terminal activates when the drive is doing speed search. |
| 42 | Pressure Reached | The terminal activates when the drive is at the Pressure Setpoint. |
| 4C | During Fast Stop | The terminal activates when the fast stop is in operation. |
| 4D | oH Pre-Alarm Reduction Limit | The terminal activates when <i>L8-03 = 4 [Overheat Pre-Alarm Selection = Operate at Reduced Speed (L8-19)]</i> and <i>oH [Heatsink Overheat]</i> does not clear after the drive decreases the frequency for 10 cycles. |
| 51 | Sequence Timer 1 | The terminal activates when Sequence Timer 1 is active. |
| 52 | Sequence Timer 2 | The terminal activates when Sequence Timer 2 is active. |
| 53 | Sequence Timer 3 | The terminal activates when Sequence Timer 3 is active. |
| 54 | Sequence Timer 4 | The terminal activates when Sequence Timer 4 is active. |
| 58 | UL6 Underload Detected | The terminal activates when the drive detected <i>UL6 [Underload or Belt Break Detected]</i> . |
| 60 | Internal Cooling Fan Failure | The terminal activates when the drive detects a cooling fan failure in the drive. |
| 62 | Modbus Reg 1 Status Satisfied | The terminal activates when the bit specified by <i>H2-08 [Modbus Register 1 Bit Select]</i> for the MEMOBUS register address set with <i>H2-07 [Modbus Register 1 Address Select]</i> activates. |
| 63 | Modbus Reg 2 Status Satisfied | The terminal activates when the bit specified by <i>H2-10 [Modbus Register 2 Bit Select]</i> for the MEMOBUS register address set with <i>H2-09 [Modbus Register 2 Address Select]</i> activates. |
| 69 | External Power 24V Supply | The terminal activates when there is an external 24V power supply between terminals PS-AC. ON : An external 24V power supply supplies power. OFF : An external 24V power supply does not supply power. |
| 6A | Data Logger Error | The terminal activates when the drive detects <i>LoG [Com Error / Abnormal SD card]</i> . |
| 71 | Low PI2 Control Feedback Level | The terminal activates when the PI2 Control Feedback Level is less than <i>S3-13 [PI2 Control Low Feedback Lvl]</i> . |
| 72 | High PI2 Control Feedback Level | The terminal activates when the PI2 Control Feedback Level is more than <i>S3-15 [PI2 Control High Feedback Lvl]</i> . |
| 89 | Output Current Lim | The terminal activates when the output current limit is limiting the drive output speed. |
| 94 | Loss of Prime | The terminal activates when the drive is in an <i>LOP [Loss of Prime]</i> condition. |
| 95 | Thermostat Fault | The terminal activates when the terminal set for <i>H1-xx = 88 [MFDI Function Selection = Thermostat Fault]</i> is active. |
| 96 | High Feedback | The terminal activates when the drive is in a High Feedback Condition as specified by <i>Y1-11 [High Feedback Level]</i> and <i>Y1-12 [High Feedback Lvl Fault Dly Time]</i> and when the drive detects an <i>HFB [High Feedback Sensed]</i> fault or an <i>HIFB [High Feedback Sensed]</i> alarm. |
| 97 | Low Feedback | The terminal activates when the drive is in a Low Feedback Condition as specified by <i>Y1-08 [Low Feedback Level]</i> and <i>Y1-09 [Low Feedback Lvl Fault Dly Time]</i> and when the drive detects an <i>LFB [Low Feedback Sensed]</i> fault or an <i>LOFB [High Feedback Sensed]</i> alarm. |
| 9E | Low PI Auxiliary Control Level | The terminal activates when the PI Aux Feedback Level is less than <i>YF-09 [PI Aux Control Low Level Detect]</i> or if the drive detects an <i>LOAUX [Low PI Aux Feedback Level]</i> fault. |
| 9F | High PI Auxiliary Control Level | The terminal activates when the PI Aux Feedback Level is more than <i>YF-12 [PI Aux Control High Level Detect]</i> or if the drive detects an <i>HIAUX [High PI Aux Feedback Level]</i> fault. |
| A9 | RELAY Operator Control | The terminal changes to OFF or ON when you push the RELAY (F3) button. When the terminal is ON, push F3 to turn it OFF. When the terminal is OFF, push F3 to turn in ON. |
| AB | Thrust Mode | The terminal activates when the output frequency is between 0.0 Hz and the value set in <i>Y4-12 [Thrust Frequency]</i> and the Thrust Bearing function is active. |
| AC | Setpoint Not Maintained | The terminal activates when the drive detects <i>NMS [Setpoint Not Met]</i> condition. |

| Setting Value | Function | Description |
|---------------|--------------------------------|--|
| B2 | BAS Interlock | The terminal activates when the Run command is active or the drive is outputting the voltage. The drive will use this as an actuation signal for an external damper. |
| B8 | Pump Fault | The terminal activates when one of these faults is active: <i>LFB [Low Feedback Sensed]</i> , <i>HFB [High Feedback Sensed]</i> , <i>NMS [Setpoint Not Met]</i> , or <i>EFx [External Fault (Terminal Sx)]</i> . |
| B9 | Transducer Loss | The terminal activates when the current into the analog input associated with PID feedback is more than 21 mA or less than 3 mA, or an <i>FDBKL [WIRE Break] Fault</i> or an <i>FDBKL [Feedback Loss Wire Break] Alarm</i> is active. |
| BA | PI Auxiliary Control Active | The terminal activates when the PI Auxiliary Controller has an effect on the output speed. |
| BB | Differential Feedback Exceeded | The terminal activates when the difference between the PID Feedback and the value from the terminal set for <i>H3-xx = 2D [Differential Feedback]</i> is more than <i>Y4-18 [Differential Level]</i> for the time set in <i>Y4-19 [Differential Lvl Detection Time]</i> . |
| BC | Sleep Active | The terminal activates when the Sleep function is active and the drive is not operating. Note: The terminal will not activate for Sleep Boost function. |
| BD | Start Delay | The terminal activates when the Feedback is more than the start level or the Feedback is less than the Inverse PID and the start timer is timing. Note: You must set <i>Y1-04 [Sleep Wake-up Level] ≠ 0</i> and <i>Y1-05 [Sleep Wake-up Level Delay Time] ≠ 0</i> to use this function. |
| BE | Pre-Charge | The terminal activates when the drive is in Pre-Charge Mode. |
| C0 | HAND Mode | The terminal activates when the drive is in HAND Mode operation. |
| C1 | AUTO Mode | The terminal activates when the drive is in AUTO Mode operation. |
| C2 | OFF Mode | The terminal activates when the drive is in OFF Mode operation. |
| C3 | Main Feedback Lost | The terminal activates when the drive loses the main PID feedback. |
| C4 | Backup Feedback Lost | The terminal activates when the drive loses the backup PID feedback. |
| 100 | !During Run | The terminal deactivates when you input a Run command and when the drive is outputting voltage. ON : Drive is stopping OFF : Drive is running |
| 101 | !Zero Speed | The terminal deactivates when the output frequency < <i>E1-09 [Minimum Output Frequency]</i> . ON : Output frequency ≥ value of <i>E1-09</i> . OFF : Output frequency < value of <i>E1-09</i> . |
| 102 | !Speed Agree 1 | The terminal deactivates when the output frequency is in the range of the frequency reference ± <i>L4-02 [Speed Agree Detection Width]</i> . Note: The detection function operates in the two motor rotation directions. ON : The output frequency does not align with the frequency reference although the drive is running. OFF : The output frequency is in the range of "frequency reference ± <i>L4-02</i> ". |
| 103 | !User-Set Speed Agree 1 | The terminal deactivates when the output frequency is in the range of <i>L4-01 [Speed Agree Detection Level] ± L4-02 [Speed Agree Detection Width]</i> and in the range of the frequency reference ± <i>L4-02</i> . Note: The detection function operates in the two motor rotation directions. The drive uses the <i>L4-01</i> value as the forward/reverse detection level. ON : The output frequency is not in the range of " <i>L4-01 ± L4-02</i> " or the range of frequency reference ± <i>L4-02</i> . OFF : The output frequency is in the range of " <i>L4-01 ± L4-02</i> " and the range of frequency reference ± <i>L4-02</i> . |
| 104 | !Frequency Detection 1 | The terminal activates when the output frequency > " <i>L4-01 [Speed Agree Detection Level] + L4-02 [Speed Agree Detection Width]</i> ". After the terminal activates, the terminal stays activated until the output frequency is at the value of <i>L4-01</i> . Note: The detection function operates in the two motor rotation directions. The drive uses the <i>L4-01</i> value as the forward/reverse detection level. ON : The output frequency > " <i>L4-01 + L4-02</i> ". OFF : The output frequency < <i>L4-01</i> , or the output frequency ≤ " <i>L4-01 + L4-02</i> " |
| 105 | !Frequency Detection 2 | The terminal deactivates when the output frequency > <i>L4-01 [Speed Agree Detection Level]</i> . After the terminal deactivates, the terminal stays deactivated until the output frequency is at the value of " <i>L4-01 - L4-02 [Speed Agree Detection Width]</i> ". Note: The detection function operates in the two motor rotation directions. The drive uses the <i>L4-01</i> value as the forward/reverse detection level. ON : The output frequency < " <i>L4-01 - L4-02</i> ", or the output frequency ≤ <i>L4-01</i> OFF : The output frequency > <i>L4-01</i> |
| 106 | !Drive Ready | The terminal deactivates when the drive is ready and running. |
| 107 | !DC Bus Undervoltage | The terminal deactivates when the DC bus voltage or control circuit power supply is at the voltage set in <i>L2-05 [Undervoltage Detection Lvl (Uv1)]</i> or less. The terminal also deactivates when there is a fault with the DC bus voltage. ON : The DC bus voltage > <i>L2-05</i> OFF : The DC bus voltage ≤ <i>L2-05</i> |

7.8 H: Terminal Functions

| Setting Value | Function | Description |
|---------------|----------------------------------|---|
| 108 | !During Baseblock (N.O.) | The terminal deactivates during baseblock. When the drive is in baseblock, the drive output transistor stops switching and does not make DC bus voltage. ON : The drive is not in baseblock. OFF : During baseblock. |
| 109 | !Frequency Reference from Keypad | Shows the selected frequency reference source. ON : Parameter <i>b1-01</i> [<i>Frequency Reference Selection 1</i>] is the frequency reference source. OFF : The keypad is the frequency reference source. |
| 10B | !Torque Detection 1 (N.O.) | The terminal deactivates when the drive detects overtorque or undertorque. OFF : The output current/torque > <i>L6-02</i> [<i>Torque Detection Level 1</i>], or < <i>L6-02</i> for longer than the time set with <i>L6-03</i> [<i>Torque Detection Time 1</i>]. |
| 10C | !Frequency Reference Loss | The terminal deactivates when the drive detects a loss of frequency reference. |
| 10E | !Fault | The terminal deactivates when the drive detects a fault. Note: The terminal will not deactivate for <i>CPF00</i> and <i>CPF01</i> [<i>Control Circuit Error</i>] faults. |
| 110 | !Alarm | The terminal deactivates when the drive detects a minor fault. |
| 111 | !Fault Reset Command Active | The terminal deactivates when the drive receives the Reset command from the control circuit terminal, serial communications, or the communication option. |
| 112 | !Timer Output | Use this setting when the drive uses the timer function as an output terminal. |
| 113 | !Speed Agree 2 | The terminal deactivates when the output frequency is in the range of the frequency reference \pm <i>L4-04</i> [<i>Speed Agree Detection Width (+/-)</i>]. Note: The detection function operates in the two motor rotation directions. ON : The output frequency is not in the range of "frequency reference \pm <i>L4-04</i> ". OFF : The output frequency is in the range of "frequency reference \pm <i>L4-04</i> ". |
| 114 | !User-Set Speed Agree 2 | The terminal deactivates when the output frequency is in the range of <i>L4-03</i> [<i>Speed Agree Detection Level (+/-)</i>] \pm <i>L4-04</i> [<i>Speed Agree Detection Width (+/-)</i>] and in the range of the frequency reference \pm <i>L4-04</i> . Note: The detection level set in <i>L4-03</i> is a signed value. The drive will only detect in one direction. ON : The output frequency is not in the range of " <i>L4-03</i> \pm <i>L4-04</i> " or the range of frequency reference \pm <i>L4-04</i> . OFF : The output frequency is in the range of " <i>L4-03</i> \pm <i>L4-04</i> " and the range of frequency reference \pm <i>L4-04</i> . |
| 115 | !Frequency Detection 3 | The terminal activates when the output frequency > " <i>L4-03</i> [<i>Speed Agree Detection Level (+/-)</i>] + <i>L4-04</i> [<i>Speed Agree Detection Width (+/-)</i>]" . After the terminal activates, the terminal stays activated until the output frequency is at the value of <i>L4-03</i> . Note: The detection level set in <i>L4-03</i> is a signed value. The drive will only detect in one direction. ON : The output frequency > " <i>L4-03</i> + <i>L4-04</i> " OFF : The output frequency < <i>L4-03</i> , or the output frequency \leq " <i>L4-03</i> + <i>L4-04</i> " |
| 116 | !Frequency Detection 4 | The terminal deactivates when the output frequency > <i>L4-03</i> [<i>Speed Agree Detection Level (+/-)</i>]. After the terminal deactivates, the terminal stays deactivated until the output frequency is at the value of " <i>L4-03</i> - <i>L4-04</i> ". Note: The detection level set in <i>L4-03</i> is a signed value. The drive will only detect in one direction. ON : The output frequency < " <i>L4-03</i> - <i>L4-04</i> ", or the output frequency \leq <i>L4-03</i> OFF : The output frequency > <i>L4-03</i> |
| 117 | !Torque Detection 1 (N.C.) | The terminal activates when the drive detects overtorque or undertorque. ON : The output current/torque > <i>L6-02</i> [<i>Torque Detection Level 1</i>], or the output current/torque < <i>L6-02</i> for longer than the time set in <i>L6-03</i> [<i>Torque Detection Time 1</i>]. |
| 118 | !Torque Detection 2 (N.O.) | The terminal deactivates when the drive detects overtorque or undertorque. OFF : The output current/torque > <i>L6-05</i> [<i>Torque Detection Level 2</i>], or the output current/torque < <i>L6-05</i> for longer than the time set in <i>L6-06</i> [<i>Torque Detection Time 2</i>]. |
| 119 | !Torque Detection 2 (N.C.) | The terminal activates when the drive detects overtorque or undertorque. ON : The output current/torque > <i>L6-05</i> [<i>Torque Detection Level 2</i>], or the output current/torque < <i>L6-05</i> for longer than the time set in <i>L6-06</i> [<i>Torque Detection Time 2</i>]. |
| 11A | !During Reverse | The terminal deactivates when the motor operates in the reverse direction. ON : The motor is operating in the forward direction or the motor stopped. OFF : The motor is operating in the reverse direction. |
| 11B | !During Baseblock (N.C.) | The terminal activates during baseblock. When the drive is in baseblock, the drive output transistor stops switching and does not make DC bus voltage. ON : During baseblock. OFF : The drive is not in baseblock. |
| 11E | !Executing Auto-Restart | The terminal deactivates when the Auto Restart function is trying to restart after a fault. |
| 11F | !Motor Overload Alarm (oL1) | The terminal deactivates when the electronic thermal protection value of the motor overload protective function is a minimum of 90% of the detection level. |
| 120 | !Drive Overheat Pre-Alarm (oH) | The terminal deactivates when the drive heatsink temperature is at the level set with <i>L8-02</i> [<i>Overheat Alarm Level</i>]. |

| Setting Value | Function | Description |
|---------------|----------------------------------|--|
| 121 | !Safe Torque OFF | The terminal deactivates (safety stop state) when the safety circuit and safety diagnosis circuit are operating correctly and when terminals H1-HC and H2-HC are OFF (Open). ON : Safety circuit fault or RUN/READY OFF : Safety stop state |
| 12F | !Maintenance Notification | The terminal deactivates when drive components are at their estimated maintenance period. Tells the user about the maintenance period for these items: <ul style="list-style-type: none"> • IGBT • Cooling fan • Capacitor • Soft charge bypass relay |
| 137 | !During Frequency Output | The terminal deactivates when the drive outputs frequency. ON : The drive does not output frequency. OFF : The drive outputs frequency. |
| 138 | !Drive Enabled | This terminal deactivates when the H1-xx = 6A [Drive Enable] terminal deactivates. |
| 139 | !Watt Hour Pulse Output | Outputs the pulse that shows the watt hours. |
| 13A | !Drive Overheat Alarm | The terminal deactivates when the drive heatsink temperature is at the L8-02 [Overheat Alarm Level] setting while L8-03 = 4 [Overheat Pre-Alarm Selection = Operate at Reduced Speed (L8-19)] and the drive is running. |
| 13D | !During Speed Search | The terminal deactivates when the drive is doing speed search. |
| 142 | !Pressure Reached | The terminal deactivates when the drive is at the Pressure Setpoint. |
| 14C | !During Fast Stop | The terminal deactivates when the fast stop is in operation. |
| 14D | !oH Pre-Alarm Reduction Limit | The terminal deactivates when L8-03 = 4 [Overheat Pre-Alarm Selection = Operate at Reduced Speed (L8-19)] and oH [Heatsink Overheat] does not clear after the drive decreases the frequency for 10 cycles. |
| 151 | !Sequence Timer 1 | The terminal deactivates when Sequence Timer 1 is active. |
| 152 | !Sequence Timer 2 | The terminal deactivates when Sequence Timer 2 is active. |
| 153 | !Sequence Timer 3 | The terminal deactivates when Sequence Timer 3 is active. |
| 154 | !Sequence Timer 4 | The terminal deactivates when Sequence Timer 4 is active. |
| 158 | !UL6 Underload Detected | The terminal deactivates when the drive detected UL6 [Underload or Belt Break Detected]. |
| 160 | !Internal Cooling Fan Failure | The terminal deactivates when the drive detects a cooling fan failure in the drive. |
| 162 | !Modbus Reg 1 Status Satisfied | The terminal deactivates when the bit specified by H2-08 [Modbus Register 1 Bit Select] for the MEMOBUS register address set with H2-07 [Modbus Register 1 Address Select] activates. |
| 163 | !Modbus Reg 2 Status Satisfied | The terminal deactivates when the bit specified by H2-10 [Modbus Register 2 Bit Select] for the MEMOBUS register address set with H2-09 [Modbus Register 2 Address Select] activates. |
| 169 | !External Power 24V Supply | The terminal deactivates when there is an external 24V power supply between terminals PS-AC. ON : An external 24V power supply does not supply power. OFF : An external 24V power supply supplies power. |
| 16A | !Data Logger Error | The terminal deactivates when the drive detects LoG [Com Error / Abnormal SD card]. |
| 171 | !Low PI2 Control Feedback Level | The terminal deactivates when the PI2 Control Feedback Level is less than S3-13 [PI2 Control Low Feedback Lvl]. |
| 172 | !High PI2 Control Feedback Level | The terminal deactivates when the PI2 Control Feedback Level is more than S3-15 [PI2 Control High Feedback Lvl]. |
| 189 | !Output Current Lim | The terminal deactivates when the output current limit is limiting the drive output speed. |
| 194 | !Loss of Prime | The terminal deactivates when the drive is in an LOP [Loss of Prime] condition. |
| 195 | !Thermostat Fault | The terminal deactivates when the terminal set for H1-xx = 88 [MFDI Function Selection = Thermostat Fault] is active. |
| 196 | !High Feedback | The terminal deactivates when the drive is in a High Feedback Condition as specified by Y1-11 [High Feedback Level] and Y1-12 [High Feedback Lvl Fault Dly Time] and when the drive detects an HFB [High Feedback Sensed] fault or an HIFB [High Feedback Sensed] alarm. |
| 197 | !Low Feedback | The terminal deactivates when the drive is in a Low Feedback Condition as specified by Y1-08 [Low Feedback Level] and Y1-09 [Low Feedback Lvl Fault Dly Time] and when the drive detects an LFB [Low Feedback Sensed] fault or an LOFB [High Feedback Sensed] alarm. |
| 19E | !Low PI Auxiliary Control Level | The terminal deactivates when the PI Aux Feedback Level is less than YF-09 [PI Aux Control Low Level Detect] or if the drive detects an LOAUX [Low PI Aux Feedback Level] fault. |
| 19F | !High PI Auxiliary Control Level | The terminal deactivates when the PI Aux Feedback Level is more than YF-12 [PI Aux Control High Level Detect] or if the drive detects an HIAUX [High PI Aux Feedback Level] fault. |
| 1A9 | !RELAY Operator Control | The terminal changes to OFF or ON when you push the RELAY (F3) button. When the terminal is ON, push F3 to turn it OFF. When the terminal is OFF, push F3 to turn in ON. |

7.8 H: Terminal Functions

| Setting Value | Function | Description |
|---------------|---------------------------------|--|
| 1AB | !Thrust Mode | The terminal deactivates when the output frequency is between 0.0 Hz and the value set in Y4-12 [Thrust Frequency] and the Thrust Bearing function is active. |
| 1AC | !Setpoint Not Maintained | The terminal deactivates when the drive detects NMS [Setpoint Not Met] condition. |
| 1B2 | !BAS Interlock | The terminal deactivates when the Run command is active or the drive is outputting the voltage. The drive will use this as an actuation signal for an external damper. |
| 1B8 | !Pump Fault | The terminal deactivates when one of these faults is active: LFB [Low Feedback Sensed], HFB [High Feedback Sensed], NMS [Setpoint Not Met], or EFx [External Fault (Terminal Sx)]. |
| 1B9 | !Transducer Loss | The terminal deactivates when the current into the analog input associated with PID feedback is more than 21 mA or less than 3 mA, or an FDBKL [WIRE Break] Fault or an FDBKL [Feedback Loss Wire Break] Alarm is active. |
| 1BA | !PI Auxiliary Control Active | The terminal deactivates when the PI Auxiliary Controller has an effect on the output speed. |
| 1BB | !Differential Feedback Exceeded | The terminal deactivates when the difference between the PID Feedback and the value from the terminal set for H3-xx = 2D [Differential Feedback] is more than Y4-18 [Differential Level] for the time set in Y4-19 [Differential Lvl Detection Time]. |
| 1BC | !Sleep Active | The terminal deactivates when the Sleep function is active and the drive is not operating. Note: The terminal will not deactivate for Sleep Boost function. |
| 1BD | !Start Delay | The terminal deactivates when the Feedback is more than the start level or the Feedback is less than the Inverse PID and the start timer is timing. Note: You must set Y1-04 [Sleep Wake-up Level] ≠ 0 and Y1-05 [Sleep Wake-up Level Delay Time] ≠ 0 to use this function. |
| 1BE | !Pre-Charge | The terminal deactivates when the drive is in Pre-Charge Mode. |
| 1C0 | !HAND Mode | The terminal deactivates when the drive is in HAND Mode operation. |
| 1C1 | !AUTO Mode | The terminal deactivates when the drive is in AUTO Mode operation. |
| 1C2 | !OFF Mode | The terminal deactivates when the drive is in OFF Mode operation. |
| 1C3 | !Main Feedback Lost | The terminal deactivates when the drive loses the main PID feedback. |
| 1C4 | !Backup Feedback Lost | The terminal deactivates when the drive loses the backup PID feedback. |

◆ H3: Analog Inputs

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------|---------------------------------|--|---------------------------------|
| H3-01 (0410) | Terminal A1 Signal Level Select | Sets the input signal level for MFAI terminal A1. 0 : 0 to 10V (Lower Limit at 0) 2 : 4 to 20 mA 3 : 0 to 20 mA | 0 (0 - 3) |
| H3-02 (0434) | Terminal A1 Function Selection | Sets the function for MFAI terminal A1. | 0 (0 - 31) |
| H3-03 (0411) RUN | Terminal A1 Gain Setting | Sets the gain of the analog signal input to MFAI terminal A1. | 100.0% (-999.9 - +999.9%) |
| H3-04 (0412) RUN | Terminal A1 Bias Setting | Sets the bias of the analog signal input to MFAI terminal A1. | 0.0% (-999.9 - +999.9%) |
| H3-09 (0417) | Terminal A2 Signal Level Select | Sets the input signal level for MFAI terminal A2. 0 : 0-10V (LowLim=0) 2 : 4 to 20 mA 3 : 0 to 20 mA | 2 (0 - 3) |
| H3-10 (0418) | Terminal A2 Function Selection | Sets the function for MFAI terminal A2. Note: The default setting for H3-10 changes when b5-01 [PID Mode Setting] changes: • b5-01 = 0 [Disabled]: 0 • b5-01 ≠ 0: B | Determined by b5-01 (0 - 31) |
| H3-11 (0419) RUN | Terminal A2 Gain Setting | Sets the gain of the analog signal input to MFAI terminal A2. | 100.0% (-999.9 - +999.9%) |
| H3-12 (041A) RUN | Terminal A2 Bias Setting | Sets the bias of the analog signal input to MFAI terminal A2. | 0.0% (-999.9 - +999.9%) |

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|---|---------------------------|
| H3-13 (041B) | Analog Input FilterTime Constant | Sets the time constant for primary delay filters on MFAI terminals. | 0.03 s (0.00 - 2.00 s) |
| H3-14 (041C) | Analog Input Terminal Enable Sel | Sets which terminal or terminals to enable when $H1-xx = C$ [MFDI Function Selection = Analog Terminal Enable Selection] is activated. 1 : Terminal A1 only 2 : Terminal A2 only 3 : Terminals A1 and A2 | 2 (1 - 3) |
| H3-16 (02F0) | Terminal A1 Offset | Sets the offset level for analog signals input to terminal A1. Usually it is not necessary to change this setting. | 0 (-500 - +500) |
| H3-17 (02F1) | Terminal A2 Offset | Sets the offset level for analog signals input to terminal A2. Usually it is not necessary to change this setting. | 0 (-500 - +500) |
| H3-40 (0B5C) | Mbus Reg 15C1h Input Function | Sets the MEMOBUS AI1 function. | F (4 - 2E) |
| H3-41 (0B5F) | Mbus Reg 15C2h Input Function | Sets the MEMOBUS AI2 function. | F (4 - 2E) |
| H3-42 (0B62) | Mbus Reg 15C3h Input Function | Sets the MEMOBUS AI3 function. | F (4 - 2E) |
| H3-43 (117F) | Mbus Reg Inputs FilterTime Const | Sets the time constant to apply a primary delay filter to the MEMOBUS analog input register values. | 0.00 s (0.00 - 2.00 s) |

◆ H3-xx: MFAI Setting Values

| Setting Value | Function | Description |
|---------------|---------------------------------|---|
| 0 | Frequency Reference | This selection has no effect. Use bypass analog input (TB4-2) as the frequency reference. Refer to the Bypass Controller section on page 48 for more information. |
| 1 | Frequency Gain | The drive multiplies the analog frequency reference with the input value from the MFAI set with this function. |
| 2 | Auxiliary Frequency Reference 1 | Sets Reference 2 through multi-step speed reference to enable the command reference (Auxiliary Frequency Reference 1) from the analog input terminal set here. This value is a percentage where the Maximum Output Frequency setting is a setting value of 100%. |
| 3 | Auxiliary Frequency Reference 2 | Sets Reference 3 through multi-step speed reference to enable the command reference (Auxiliary Frequency Reference 2) from the analog input terminal set here. This value is a percentage where the Maximum Output Frequency setting is a setting value of 100%. |
| 4 | Output Voltage Bias | Set this parameter to input a bias signal and amplify the output voltage. |
| 5 | Accel/Decel Time Gain | Enters a signal to adjust the gain used for $C1-01$ to $C1-04$ [Acceleration/Deceleration Times 1 and 2] and $C1-09$ [Fast Stop Time] when the full scale analog signal (10 V or 20 mA) is 100%. |
| 6 | DC Injection Braking Current | Enters a signal to adjust the current level used for DC Injection Braking when the drive rated output current is 100%. |
| 7 | Torque Detection Level | Enters a signal to adjust the overtorque/undertorque detection level. Note: Use this function with $L6-01$ [Torque Detection Selection 1]. This parameter functions as an alternative to $L6-02$ [Torque Detection Level 1]. |
| 8 | Stall Prevent Level During Run | Enters a signal to adjust the stall prevention level during run if the drive rated current is 100%. |
| 9 | Output Frequency Lower Limit | Enters a signal to adjust the output frequency lower limit level as a percentage of the maximum output frequency. |
| B | PID Feedback | Enter the PID feedback value as a percentage of the maximum output frequency. |
| C | PID Setpoint | Enters the PID setpoint as a percentage of the maximum output frequency. |
| D | Frequency Bias | Enters the bias value added to the frequency reference as a percentage of the maximum output frequency. |
| E | Motor Temperature (PTC Input) | Uses the motor Positive Temperature Coefficient (PTC) thermistor to prevent heat damage to the motor as a percentage of the current value when the 10 V analog signal is input. |
| F | Not Used | Use this setting for unused terminals or to use terminals in through mode. |
| 16 | Differential PID Feedback | Enters the PID differential feedback value if the full scale analog signal (10 V or 20 mA) is 100%. |
| 1F | Not Used | Use this setting for unused terminals or to use terminals in through mode. |
| 24 | PID Feedback Backup | Enters the PID Feedback Backup signal for the drive to use when it loses the primary PID feedback set for $H3-xx = B$ [PID Feedback]. Note: The full-scale of the analog signal goes from $b5-71$ [Min PID Transducer Scaling] to $b5-38$ [PID User Unit Display Scaling]. |

7.8 H: Terminal Functions

| Setting Value | Function | Description |
|---------------|---------------------------------|---|
| 25 | PI2 Control Setpoint | Enters the PI2 Control setpoint level as a percentage of the S3-02 [PI2 Control Transducer Scale] value. Note: Parameters S3-03 [PI2 Control Decimal Place Pos] and S3-04 [PI2 Control Unit Selection] set the resolution and unit. |
| 26 | PI2 Control Feedback | Enters the PI2 Control feedback level as a percentage of the S3-02 [PI2 Control Transducer Scale] value. Note: Parameters S3-03 [PI2 Control Decimal Place Pos] and S3-04 [PI2 Control Unit Selection] set the resolution and unit. |
| 27 | PI Auxiliary Control Feedback | Enters the PI Auxiliary Control feedback value when YF-01 = 1 [PI Aux Control Selection = Enabled]. Note: • The full-scale of the analog signal goes from 0% to YF-02 [PI Aux Control Transducer Scale]. • Parameter YF-22 [PI Aux Level Decimal Place Pos] sets the resolution. |
| 2B | Emergency Override PID Feedback | This input is the PID Feedback source when Emergency Override is running in PID mode (S6-02 = 2 or 3 [Emergency Override Ref Selection = System PID Mode or Independent PID Mode]). Note: • When S6-02 = 2 [Emergency Override Ref Selection = System PID Mode], the full-scale of the analog signal goes from b5-71 [Min PID Transducer Scaling] to b5-38 [PID User Unit Display Scaling]. • When S6-02 = 3 [Independent PID Mode], the full-scale of the analog signal goes from b5-71 to S6-03 [EMOVR Independent PID Scale]. • When you set MEMOBUS register 3A93h bit 4, register 3A95h becomes the Emergency Override Feedback source. |
| 2C | Emergency Override PID Setpoint | This input is the PID Setpoint source when Emergency Override is running in PID mode (S6-02 = 2 or 3 [Emergency Override Ref Selection = System PID Mode or Independent PID Mode]). Note: • When S6-02 = 2 [Emergency Override Ref Selection = System PID Mode], the full-scale of the analog signal goes from b5-71 [Min PID Transducer Scaling] to b5-38 [PID User Unit Display Scaling]. • When S6-02 = 3 [Independent PID Mode], the full-scale of the analog signal goes from b5-71 to S6-03 [EMOVR Independent PID Scale]. • When you set MEMOBUS register 3A93h bit 5, register 3A96h becomes the Emergency Override Setpoint source. |
| 2D | Differential Level Source | Enters a feedback value to calculate the Differential Level between the Differential Level Source feedback and the primary PID Feedback [H3-xx = B]. Note: The full-scale of the analog signal goes from b5-71 [Min PID Transducer Scaling] to b5-38 [PID User Unit Display Scaling]. |
| 2E | HAND Frequency Ref or Setpoint | Enters the S5-05 [HAND Frequency Reference] value or the S5-06 [HAND Setpoint] value. When S5-01 = 0 [HAND Frequency Reference Source = HAND Analog Input] and S5-03 = 0 [HAND Mode PI Selection = Disabled], the drive enters HAND Frequency Reference. When b5-01 ≠ 0, S5-01 = 0, and S5-03 = 1 [Enabled], the drive enters HAND Setpoint. Note: • When PID is enabled, the full-scale of the analog signal goes from b5-71 [Min PID Transducer Scaling] to b5-38 [PID User Unit Display Scaling]. • When PID is disabled, the drive enters this analog signal as the percentage of the E1-04 [Maximum Output Frequency] value. |

◆ H4: Analog Outputs

| No. (Hex.) | Name | Description | Default (Range) |
|------------------|----------------------------------|---|------------------------------|
| H4-01 (041D) | Terminal FM Analog Output Select | Sets the monitor number to send from MFAO terminal FM. Set the x-xx part of the Ux-xx [Monitor]. For example, set H4-01 = 102 to monitor U1-02 [Output Frequency]. | 102 (000 - 999) |
| H4-02 (041E) RUN | Terminal FM Analog Output Gain | Sets the gain of the monitor signal that is sent from MFAO terminal FM. Sets the analog signal output level from the terminal FM at 10 V or 20 mA as 100% when an output for monitoring items is 100%. | 100.0% (-999.9 - +999.9%) |
| H4-03 (041F) RUN | Terminal FM Analog Output Bias | Sets the bias of the monitor signal that is sent from MFAO terminal FM. Set the level of the analog signal sent from terminal FM at 10 V or 20 mA as 100% when an output for monitoring items is 0%. | 0.0% (-999.9 - +999.9%) |
| H4-04 (0420) | Terminal AM Analog Output Select | Sets the monitoring number to be output from the MFAO terminal AM. Set the x-xx part of the Ux-xx [Monitor]. For example, set H4-04 = 103 to monitor U1-03 [Output Current]. | 103 (000 - 999) |
| H4-05 (0421) RUN | Terminal AM Analog Output Gain | Sets the gain of the monitor signal that is sent from MFAO terminal AM. When an output for monitoring items is 0%, this parameter sets the analog signal output level from the AM terminal at 10 V or 20 mA as 100%. | 50.0% (-999.9 - +999.9%) |
| H4-06 (0422) RUN | Terminal AM Analog Output Bias | Sets the bias of the monitor signal that is sent from MFAO terminal AM. When an output for monitoring items is 0%, this parameter sets the analog signal output level from the AM terminal at 10 V or 20 mA as 0%. | 0.0% (-999.9 - +999.9%) |
| H4-07 (0423) | Terminal FM Signal Level Select | Sets the MFAO terminal FM output signal level. Note: Set jumper S5 on the control circuit terminal block accordingly when you change this parameter. 0 : 0 to 10 Vdc 2 : 4 to 20 mA | 0 (0, 2) |

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|---------------------------------|--|-------------------------------|
| H4-08 (0424) | Terminal AM Signal Level Select | Sets the MFAO terminal AM output signal level. Note: Set jumper S5 on the control circuit terminal block accordingly when you change this parameter. 0 : 0 to 10 Vdc 2 : 4 to 20 mA | 0 (0, 2) |
| H4-20 (0B53) | Analog Power Monitor 100% Level | Sets the level at 10 V when you set <i>U1-08 [Output Power]</i> for analog output. | 0.00 kW (0.00 - 650.00 kW) |

◆ H5: Serial Communication

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|--|---------------------------------|
| H5-01 (0425) | Drive Node Address | Sets the communication slave address for drives. Note: • Restart the drive after you change the parameter setting. • Setting 0 will not let the drive respond to serial communications. | 1FH (Determined by protocol) |
| H5-02 (0426) | Communication Speed Selection | Sets the communications speed for serial communications. Note: Re-energize the drive or set <i>H5-20 = 1 [Communication Parameters Reload = Reload Now]</i> after you change the parameter setting. 0 : 1200 bps 1 : 2400 bps 2 : 4800 bps 3 : 9600 bps 4 : 19.2 kbps 5 : 38.4 kbps 6 : 57.6 kbps 7 : 76.8 kbps 8 : 115.2 kbps | 3 (Determined by protocol) |
| H5-03 (0427) | Communication Parity Selection | Sets the communications parity used for serial communications. Note: Re-energize the drive or set <i>H5-20 = 1 [Communication Parameters Reload = Reload Now]</i> after you change the parameter setting. 0 : No parity 1 : Even parity 2 : Odd parity | 0 (0 - 2) |
| H5-04 (0428) | Communication Error Stop Method | Sets the motor Stopping Method when the drive detects a serial communication Error condition. 0 : Ramp to Stop 1 : Coast to Stop 2 : Fast Stop (Use C1-09) 3 : Alarm Only 4 : Run at H5-34 (CE Go-To-Freq) | 3 (0 - 4) |
| H5-05 (0429) | Comm Fault Detection Selection | Sets the function that detects <i>CE [Serial Communication Error]</i> issues during serial communications. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| H5-06 (042A) | Drive Transmit Wait Time | Sets the time to wait to send a response message after the drive receives a command message from the master. Note: Restart the drive after changing the parameter setting. | 5 ms (0 - 65 ms) |
| H5-08 (062D) | Communication Protocol Selection | Selects the communication protocol. 0 : Modbus/MEMOBUS 1 : Metasys/N2 2 : Apogee/P1 3 : BACnet | 3 (0 - 3) |
| H5-09 (0435) | CE Detection Time | Sets the detection time for <i>CE [Serial Communication Error]</i> issues when communication stops. | 2.0 s (0.0 - 10.0 s) |
| H5-10 (0436) | Modbus Register 0025H Unit Sel | Sets the unit of measure used for the serial communications monitor register 0025H (output voltage reference monitor). 0 : 0.1 V units 1 : 1 V units | 0 (0, 1) |

7.8 H: Terminal Functions

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------|----------------------------------|---|----------------------------------|
| H5-11 (043C) | Comm ENTER Command Mode | Sets the function to make the Enter command necessary to change parameters through serial communications. 0 : ENTER Command Required 1 : ENTER Command Not Required | 0 (0, 1) |
| H5-14 (310D) | BACnet Device Obj ID LOW BITS | Sets the lower bits of the BACnet device object ID as a 4-digit hexadecimal number. | 0001 (0000 - FFFF) |
| H5-15 (310E) | BACnet Device Obj ID HIGH BITS | Sets the upper bits of the BACnet device object ID as a 4-digit hexadecimal number. | 0000 (0000 - 003F) |
| H5-18 (11A2) | Motor Speed Filter over Comms | Sets the filter time constant used when monitoring motor speed during serial communications or with a communication option. | 0 ms (0 - 100 ms) |
| H5-20 (0B57) | Communication Parameters Reload | Sets the function to immediately enable updated serial communications parameters. 0 : Reload at Next Power Cycle 1 : Reload Now | 0 (0, 1) |
| H5-22 (11CF) | Speed Search from MODBUS | Enables the serial communication register Speed Search function (bit 0 of 15DFH). 0 : Disabled 1 : Enabled | 0 (0, 1) |
| H5-23 (158D) | BACnet Max Master | Sets the maximum number of master MAC ID to scan to when the drive polls for the next node (Poll for Master). | 7F (1 - 7F) |
| H5-24 (3DA0) | BACnet Max Info Frames | Sets the maximum number of information frames that the bypass will send per token cycle in BACnet. | 3 (1 - 255) |
| H5-25 (1589) RUN | Function 5A Register 1 Selection | Returns the contents of the specified serial communications register when responding to the master device. | 0044H (U1-05) (0000H - FFFFH) |
| H5-26 (158A) RUN | Function 5A Register 2 Selection | Returns the contents of the specified serial communications register when responding to the master device. | 0045H (U1-06) (0000H - FFFFH) |
| H5-27 (158B) RUN | Function 5A Register 3 Selection | Returns the contents of the specified serial communications register when responding to the master device. | 0042H (U1-03) (0000H - FFFFH) |
| H5-28 (158C) RUN | Function 5A Register 4 Selection | Returns the contents of the specified serial communications register when responding to the master device. | 0049H (U1-10) (0000H - FFFFH) |
| H5-33 (3FB3) | Power-up CALL Alarm | Enables and disables <i>CALL [Serial Comm Transmission Error]</i> alarm detection. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| H5-34 (3FB4) RUN | Comm Error (CE) Go-To-Frequency | Sets the speed at which the drive will run when <i>H5-04 = 4 [Communication Error Stop Method = Run at H5-34]</i> and there is a <i>CE</i> . | 0.0 Hz (0.0 - 400.0 Hz) |
| H5-35 (3FB5) RUN | Comm Error (CE) Go-To-Timeout | When <i>H5-04 = 4 [Communication Error Stop Method = Run at H5-34]</i> and a <i>CE</i> is present, the drive will run at the <i>H5-34 [Comm Error (CE) Go-To-Frequency]</i> speed for this length of time before it triggers a <i>CE</i> fault. Note: Set this parameter to 0 s to disable the time-out. | 0 s (0 - 6000 s) |
| H5-36 (3FB6) | CE Fault Restart Select | Sets the drive to restart (<i>L5-01 [Number of Auto-Restart Attempts]</i>) after a <i>CE</i> fault. 0 : No Retry 1 : Retry | 0 (0, 1) |

◆ H7: Virtual MFIO selection

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------------------|---|-----------------|
| H7-00 (116F) Expert | Virtual MFIO selection | Sets the function to enable and disable the virtual I/O function. Set this parameter to 1 to operate the virtual I/O function. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| H7-01 (1185) Expert | Virtual Multi-Function Input 1 | Sets the function that enters the virtual input set in <i>H7-10 [Virtual Multi-Function Output 1]</i> . | F (3 - 1A8) |

| No. (Hex.) | Name | Description | Default (Range) |
|----------------------------------|----------------------------------|--|-----------------------------|
| H7-02 (1186) Expert | Virtual Multi-Function Input 2 | Sets the function that enters the virtual input set in H7-12 [Virtual Multi-Function Output 2]. | F (3 - 1A8) |
| H7-03 (1187) Expert | Virtual Multi-Function Input 3 | Sets the function that enters the virtual input set in H7-14 [Virtual Multi-Function Output 3]. | F (3 - 1A8) |
| H7-04 (1188) Expert | Virtual Multi-Function Input 4 | Sets the function that enters the virtual input set in H7-16 [Virtual Multi-Function Output 4]. | F (3 - 1A8) |
| H7-10 (11A4) Expert | Virtual Multi-Function Output 1 | Sets the function for virtual digital output 1. | F (0 - 1C4) |
| H7-11 (11A5) Expert | Virtual Output 1 Delay Time | Sets the minimum ON time for virtual digital output 1. | 0.1 s (0.0 - 25.0 s) |
| H7-12 (11A6) Expert | Virtual Multi-Function Output 2 | Sets the function for virtual digital output 2. | F (0 - 1C4) |
| H7-13 (11A7) Expert | Virtual Output 2 Delay Time | Sets the minimum ON time for virtual digital output 2. | 0.1 s (0.0 - 25.0 s) |
| H7-14 (11A8) Expert | Virtual Multi-Function Output 3 | Sets the function for virtual digital output 3. | F (0 - 1C4) |
| H7-15 (11A9) Expert | Virtual Output 3 Delay Time | Sets the minimum ON time for virtual digital output 3. | 0.1 s (0.0 - 25.0 s) |
| H7-16 (11AA) Expert | Virtual Multi-Function Output 4 | Sets the function for virtual digital output 4. | F (0 - 1C4) |
| H7-17 (11AB) Expert | Virtual Output 4 Delay Time | Sets the minimum ON time for virtual digital output 4. | 0.1 s (0.0 - 25.0 s) |
| H7-30 (1177) Expert | Virtual Analog Input Selection | Sets the virtual analog input function. | F (0 - 2E) |
| H7-31 (1178) RUN Expert | Virtual Analog Input Gain | Sets the virtual analog input gain. | 100.0% (-999.9 - 999.9%) |
| H7-32 (1179) RUN Expert | Virtual Analog Input Bias | Sets the virtual analog input bias. | 0.0% (-999.9 - 999.9%) |
| H7-40 (1163) | Virtual Analog Out Signal Select | Sets the signal level of the virtual analog output. 0 : 0 to 100% (Absolute Value) 1 : -100 to 100% 2 : 0 to 100% (Lower Limit at 0) | 0 (0 - 2) |
| H7-41 (1164) | Virtual Analog Output Function | Sets the monitor to be output from the virtual analog output. Set the x-xx part of the Ux-xx [Monitor]. For example, set H7-41 = 102 to monitor U1-02 [Output Frequency]. | 102 (0 - 631) |
| H7-42 (1165) | Virtual Analog Output FilterTime | Sets the time constant for a primary filter of the virtual analog output. | 0.00 s (0.00 - 2.00 s) |

7.9 L: Protection Functions

◆ L1: Motor Protection

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|--|--|
| L1-01 (0480) | Motor Overload (oL1) Protection | Sets the motor overload protection with electronic thermal protectors. 0 : Disabled 1 : Variable Torque Note: When you connect only one motor to a drive, set <i>L1-01 = 1 [Variable Torque]</i> . External thermal relays are not necessary in these conditions. | 1 (0, 1) |
| L1-02 (0481) | Motor Overload Protection Time | Sets the operation time for the electronic thermal protector of the drive to prevent damage to the motor. Usually it is not necessary to change this setting. | 1.0 min (0.1 - 5.0 min) |
| L1-03 (0482) | Motor Thermistor oH Alarm Select | Sets drive operation when the PTC input signal entered into the drive is at the <i>oH3 [Motor Overheat Alarm]</i> detection level. 0 : Ramp to Stop 1 : Coast to Stop 2 : Fast Stop (Use C1-09) 3 : Alarm Only | 3 (0 - 3) |
| L1-04 (0483) | Motor Thermistor oH Fault Select | Sets the drive operation when the PTC input signal to the drive is at the <i>oH4 [Motor Overheat Fault (PTC Input)]</i> detection level. 0 : Ramp to Stop 1 : Coast to Stop 2 : Fast Stop (Use C1-09) | 1 (0 - 2) |
| L1-05 (0484) | Motor Thermistor Filter Time | Sets the primary delay time constant for the PTC input signal entered to the drive. This parameter prevents accidental motor overheat faults. | 0.20 s (0.00 - 10.00 s) |
| L1-08 (1103) | oL1 Current Level | Sets the reference current for the motor 1 thermal overload detection. When the current level > 0.0 A, you cannot set this value < 10% of drive rated current. | 0.0 A (0.0 A or 10% to 150% of the drive rated current) |
| L1-13 (046D) | Motor Overload Memory Selection | Sets the function that keeps the current electronic thermal protector value after power loss. 0 : Disabled 1 : Enabled 2 : Enabled, using RTC | 2 (0 - 2) |

◆ L2: Power Loss Ride Through

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|--|--|
| L2-01 (0485) | Power Loss Ride Through Select | Sets the drive operation after a momentary power loss. 0 : Disabled 1 : Enabled for L2-02 Time 2 : Enabled while CPU Power Active | 2 (0 - 2) |
| L2-02 (0486) | Power Loss Ride Through Time | Sets the maximum time that the drive will wait until it tries to restart after power loss. | Determined by o2-04 (0.0 - 25.5 s) |
| L2-03 (0487) | Minimum Baseblock Time | Sets the minimum time to continue the drive output block (baseblock) after a baseblock. | Determined by o2-04 (0.1 - 5.0 s) |
| L2-04 (0488) | Powerloss V/f Recovery Ramp Time | Sets the time for the drive output voltage to go back to the correct voltage after it completes speed searches. | Determined by o2-04 (0.0 - 5.0 s) |
| L2-05 (0489) | Undervoltage Detection Lvl (Uv1) | Sets the voltage at which the drive triggers a <i>Uv1 [DC Bus Undervoltage]</i> fault. Usually it is not necessary to change this setting. | Determined by o2-04 and E1-01 (208/240 V: 150 - 220 V, 480 V: 300 - 440 V) |

◆ L3: Stall Prevention

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|-----------------------------------|--|--|
| L3-01 (048F) | Stall Prevention during Accel | Sets the method of Stall Prevention During Acceleration. 0 : Disabled 1 : Enabled 2 : Intelligent (Ignore Decel Ramp) | 1 (0 - 2) |
| L3-02 (0490) | Stall Prevent Level during Accel | Sets the output current level to activate the Stall Prevention function during acceleration as a percentage of the drive rated output current. | Determined by L8-38 (0 - 120%) |
| L3-03 (0491) | Stall Prevent Limit during Accel | Sets the lower limit for the stall prevention level used in the constant output range as a percentage of the drive rated output current. | 50% (0 - 100%) |
| L3-04 (0492) | Stall Prevention during Decel | Sets the method that the drive will use to prevent overvoltage faults when decelerating. 0 : Disabled 1 : General Purpose 2 : Intelligent (Ignore Decel Ramp) 4 : Overexcitation/High Flux | 1 (0 - 4) |
| L3-05 (0493) | Stall Prevention during RUN | Sets the function to enable and disable Stall Prevention During Run. Note: An output frequency lower than 6 Hz will disable Stall Prevention during Run. The L3-05 and L3-06 [Stall Prevent Level during Run] settings do not have an effect. 0 : Disabled 1 : Deceleration Time 1 (C1-02) 2 : Deceleration Time 2 (C1-04) | 2 (0 - 2) |
| L3-06 (0494) | Stall Prevent Level during Run | Sets the output current level to enable the Stall Prevention function during operation as a percentage of the drive rated output current. Note: This parameter is applicable when L3-05 = 1, 2 [Stall Prevention during RUN = Deceleration Time 1 (C1-02), Deceleration Time 2 (C1-04)]. | Determined by L8-38 (5 - 120%) |
| L3-11 (04C7) | Overvoltage Suppression Select | Sets the overvoltage suppression function. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| L3-17 (0462) | DC Bus Regulation Level | Sets the target value for the DC bus voltage when the overvoltage suppression function and the Decel Stall Prevention function (Intelligent Stall Prevention) are active. | 208/240 V: 375 V, 480 V: 750 V (208/240 V: 150 - 400 V, 480 V: 300 - 800 V) |
| L3-20 (0465) Expert | DC Bus Voltage Adjustment Gain | Sets the proportional gain used to control the DC bus voltage. | 1.00 (0.00 - 5.00) |
| L3-21 (0466) Expert | OVSsuppression Accel/Decel P Gain | Sets the proportional gain to calculate acceleration and deceleration rates. | 1.00 (0.10 - 10.00) |
| L3-23 (04FD) | Stall P Reduction at Constant HP | Sets the function to automatically decrease the Stall Prevention Level during Run for constant output ranges. 0 : Use L3-06 for Entire Speed Range 1 : Automatic Reduction @ CHP Region | 0 (0, 1) |
| L3-24 (046E) Expert | Motor Accel Time @ Rated Torque | Sets the motor acceleration time to reach the maximum frequency at the motor rated torque for stopped single-drive motors. | Determined by o2-04, E2-11 (0.001 - 10.000 s) |
| L3-25 (046F) Expert | Load Inertia Ratio | Sets the ratio between motor inertia and machine inertia. | 1.0 (0.1 - 1000.0) |
| L3-26 (0455) Expert | Additional DC Bus Capacitors | Sets the capacity for external main circuit capacitors. Usually it is not necessary to change this setting. | 0 μF (0 to 65000 μF) |
| L3-27 (0456) | Stall Prevention Detection Time | Sets a delay time between reaching the Stall Prevention level and starting the Stall Prevention function. | 50 ms (0 - 5000 ms) |
| L3-35 (0747) Expert | Speed Agree Width for Auto Decel | Sets the width for speed agreement when L3-04 = 2 [Decel Stall Prevention Selection = Automatic Decel Reduction]. Usually it is not necessary to change this setting. | 0.00 Hz (0.00 - 1.00 Hz) |

◆ L4: Speed Detection

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|-----------------------------------|---|--------------------------------|
| L4-01 (0499) | Speed Agree Detection Level | Sets the level to detect speed agree or motor speed when H2-01 to H2-03 = 2, 3, 4, 5 [MFDO Function Selection = Speed Agree 1, User-set Speed Agree 1, Frequency Detection 1, Frequency Detection 2]. | 0.0 Hz (0.0 - 400.0 Hz) |
| L4-02 (049A) | Speed Agree Detection Width | Sets the width to detect speed agree or motor speed when H2-01 to H2-03 = 2, 3, 4, 5 [MFDO Function Selection = Speed Agree 1, User-set Speed Agree 1, Frequency Detection 1, Frequency Detection 2]. | 2.0 Hz (0.0 - 20.0 Hz) |
| L4-03 (049B) | Speed Agree Detection Level (+/-) | Sets the speed agree detection level or motor speed detection level when H2-01 to H2-03 = 13, 14, 15, 16 [MFDO Function Selection = Speed Agree 2, User-set Speed Agree 2, Frequency Detection 3, Frequency Detection 4]. | 0.0 Hz (-400.0 - +400.0 Hz) |
| L4-04 (049C) | Speed Agree Detection Width (+/-) | Sets the width to detect speed agree or motor speed when H2-01 to H2-03 = 13, 14, 15, 16 [MFDO Function Selection = Speed Agree 2, User-set Speed Agree 2, Frequency Detection 3, Frequency Detection 4]. | 2.0 Hz (0.0 - 20.0 Hz) |
| L4-05 (049D) | Fref Loss Detection Selection | Sets the operation when the drive detects a loss of frequency reference. 0 : Stop 1 : Run at (L4-06 x Last Reference) | 1 (0, 1) |
| L4-06 (04C2) | Frequency Reference @Loss of Ref | Sets the frequency reference as a percentage to continue drive operation after it detects a frequency reference loss. The value is a percentage of the frequency reference before the drive detected the loss. | 80.0% (0.0 - 100.0%) |
| L4-07 (0470) | Speed Agree Detection Selection | Sets the condition that activates speed detection. 0 : No Detection during Baseblock 1 : Detection Always Enabled | 0 (0, 1) |

◆ L5: Fault Restart

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|---------------------------------|--|----------------------------|
| L5-01 (049E) | Number of Auto-Restart Attempts | Sets the number of times that the drive will try to restart. | 0 (0 - 10 times) |
| L5-02 (049F) | Fault Contact at Restart Select | Sets the function that sends signals to the MFDO terminal set for Fault [H2-xx = E] while the drive is automatically restarting. 0 : Active Only when Not Restarting 1 : Always Active | 0 (0, 1) |
| L5-04 (046C) | Interval Method Restart Time | Sets the time interval between each Auto Restart attempt. | 10.0 s (0.5 - 3600.0 s) |
| L5-07 (0B2A) | Fault Reset Enable Select Grp1 | Use these 4 digits to set the Auto Restart function for oL1 to oL4. From left to right, the digits set oL1, oL2, oL3, and oL4, in order. 0000 : Disabled 0001 : Enabled (—/—/—/—oL4) 0010 : Enabled (—/—/—oL3/—) 0011 : Enabled (—/—/—oL3/oL4) 0100 : Enabled (—/oL2/—/—) 0101 : Enabled (—/oL2/—/oL4) 0110 : Enabled (—/oL2/oL3/—) 0111 : Enabled (—/oL2/oL3/oL4) 1000 : Enabled (oL1/—/—/—) 1001 : Enabled (oL1/—/—/oL4) 1010 : Enabled (oL1/—/—oL3/—) 1011 : Enabled (oL1/—/—oL3/oL4) 1100 : Enabled (oL1/oL2/—/—) 1101 : Enabled (oL1/oL2/—/oL4) 1110 : Enabled (oL1/oL2/oL3/—) 1111 : Enabled (oL1/oL2/oL3/oL4) | 1111 (0000 - 1111) |

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|---|-----------------------|
| L5-08 (0B2B) | Fault Reset Enable Select Grp2 | Use these 4 digits to set the Auto Restart function for <i>Uv1</i> , <i>ov</i> , <i>oH1</i> , and <i>GF</i> . From left to right, the digits set <i>Uv1</i> , <i>ov</i> , <i>oH1</i> , and <i>GF</i> , in order. 0000 : Disabled 0001 : Enabled (—/—/—/GF) 0010 : Enabled (—/—/oH1/—) 0011 : Enabled (—/—/oH1/GF) 0100 : Enabled (—/ov/—/—) 0101 : Enabled (—/ov/—/GF) 0110 : Enabled (—/ov/oH1/—) 0111 : Enabled (—/ov/oH1/GF) 1000 : Enabled (Uv1/—/—/—) 1001 : Enabled (Uv1/—/—/GF) 1010 : Enabled (Uv1/—/oH1/—) 1011 : Enabled (Uv1/—/oH1/GF) 1100 : Enabled (Uv1/ov/—/—) 1101 : Enabled (Uv1/ov/—/GF) 1110 : Enabled (Uv1/ov/oH1/—) 1111 : Enabled (Uv1/ov/oH1/GF) | 1111 (0000 - 1111) |
| L5-40 (3670) | Low Feedback Flt Retry Selection | Sets the drive to do an Auto Restart when the drive detects an <i>LFB [Low Feedback Sensed]</i> fault. 0 : No Retry 1 : Retry | 0 (0, 1) |
| L5-41 (3671) | Hi Feedback Flt Retry Selection | Sets the drive to do an Auto Restart when the drive detects an <i>HFB [High Feedback Sensed]</i> fault. 0 : No Retry 1 : Retry | 0 (0, 1) |
| L5-42 (3672) | Feedback Loss Fault Retry Select | Sets the drive to try an Auto Restart when it drive detects an <i>FDBKL [WIRE Break]</i> fault. 0 : No Retry 1 : Retry | 0 (0, 1) |
| L5-49 (3679) | Fault Retry Speed Search Select | Sets the drive to do a speed search at the start of a Fault Retry. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| L5-50 (367A) | Setpoint Not Met Fault Retry Sel | Sets the drive to try an Auto Restart when it detects an <i>NMS [SetPoint Not Met]</i> fault. 0 : No Retry 1 : Retry | 0 (0, 1) |
| L5-51 (367B) | Loss of Prime Fault Retry Select | Sets the drive to try an Auto Restart if it detects an <i>LOP [Loss Of Prime]</i> fault. 0 : No Retry 1 : Retry | 0 (0, 1) |
| L5-53 (3251) | Thermostat Fault Retry Selection | Sets the drive to try an Auto Restart if it detects a <i>VLTS [Thermostat Fault]</i> fault. Note: • To use this function, set <i>S5-01</i> ≠ 0 [<i>HAND Frequency Reference Source</i> ≠ <i>HAND Analog Input</i>] • The drive will only restart after the Thermostat digital input de-activates and the <i>L5-04 [Interval Method Restart Time]</i> timer is expired. 0 : No Retry 1 : Retry | 1 (0, 1) |

◆ L6: Torque Detection

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|---|--------------------------|
| L6-01 (04A1) | Torque Detection Selection 1 | Sets the speed range that detects overtorque and undertorque and the operation of drives (operation status) after detection. 0 : Disabled 1 : oL @ Speed Agree - Alarm only 2 : oL @ RUN - Alarm only 3 : oL @ Speed Agree - Fault 4 : oL @ RUN - Fault 5 : UL @ Speed Agree - Alarm only 6 : UL @ RUN - Alarm only 7 : UL @ Speed Agree - Fault 8 : UL @ RUN - Fault 9 : UL6 @ Speed Agree - Alarm only 10 : UL6 @ RUN - Alarm only 11 : UL6 @ Speed Agree - Fault 12 : UL6 @ RUN - Fault | 0 (0 - 12) |
| L6-02 (04A2) | Torque Detection Level 1 | Sets the detection level for Overtorque/Undertorque Detection 1. In V/f control, drive rated output current = 100% value. | 15% (0 - 300%) |
| L6-03 (04A3) | Torque Detection Time 1 | Sets the detection time for Overtorque/Undertorque Detection 1. | 10.0 s (0.0 - 10.0 s) |
| L6-04 (04A4) | Torque Detection Selection 2 | Sets the speed range that detects overtorque and undertorque and the operation of drives (operation status) after detection. 0 : Disabled 1 : oL @ Speed Agree - Alarm only 2 : oL @ RUN - Alarm only 3 : oL @ Speed Agree - Fault 4 : oL @ RUN - Fault 5 : UL @ Speed Agree - Alarm only 6 : UL @ RUN - Alarm only 7 : UL @ Speed Agree - Fault 8 : UL @ RUN - Fault | 0 (0 - 8) |
| L6-05 (04A5) | Torque Detection Level 2 | Sets the detection level for Overtorque/Undertorque Detection 2. In V/f control, drive rated output current = 100% value. | 150% (0 - 300%) |
| L6-06 (04A6) | Torque Detection Time 2 | Sets the detection time for Overtorque/Undertorque Detection 2. | 0.1 s (0.0 - 10.0 s) |
| L6-13 (062E) | Motor Underload Curve Select | Sets the motor underload protection (<i>UL6 [Undertorque Detection 6]</i>) based on motor load and sets the level of <i>L6-02 [Torque Detection Level 1]</i> to refer to Fbase or Fmax. 0 : Base Frequency Enable 1 : Max Frequency Enable | 0 (0, 1) |
| L6-14 (062F) | Motor Underload Level @ Min Freq | Sets the <i>UL6 [Undertorque Detection 6]</i> detection level at minimum frequency by percentage of drive rated current. | 15% (0 - 300%) |

◆ L8: Drive Protection

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|---------------------------------|---|--------------------------------------|
| L8-02 (04AE) | Overheat Alarm Level | Sets the <i>oH</i> detection level temperature. | Determined by o2-04 (50 - 150 °C) |
| L8-03 (04AF) | Overheat Pre-Alarm Selection | Sets drive operation if it detects an <i>oH</i> alarm. 0 : Ramp to Stop 1 : Coast to Stop 2 : Fast Stop (Use C1-09) 3 : Alarm Only 4 : Operate at Reduced Speed (L8-19) | 4 (0 - 4) |
| L8-05 (04B1) | Input Phase Loss Protection Sel | Sets the function to enable and disable input phase loss detection. 0 : Disable 1 : Enabled Note: This parameter only affects operation in Drive Mode. Use <i>Z1-50 and Z1-52 [Bypass Input Phase Loss Level and Bypass Input Phase Loss Delay]</i> for Bypass Mode operation. | 1 (0, 1) |

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------------|---|--------------------------------|
| L8-07 (04B3) | Output Phase Loss Protection Sel | Sets the function to enable and disable output phase loss detection. The drive starts output phase loss detection when the output current decreases to less than 5% of the drive rated current. Note: • The drive can incorrectly start output phase loss detection when the motor rated current is very small compared to the drive rating. • This parameter only affects operation in Drive Mode. 0 : Disabled 1 : Fault when one phase is lost 2 : Fault when two phases are lost | 1 |
| L8-09 (04B5) | Output Ground Fault Detection | Sets the function to enable and disable ground fault protection. 0 : Disabled 1 : Enabled Note: This parameter only affects operation in Drive Mode. | Determined by o2-04 (0, 1) |
| L8-10 (04B6) | Heatsink Fan Operation Selection | Sets operation of the heatsink cooling fan. 0 : During Run, w/ L8-11 Off-Delay 1 : Always On 2 : On when Drive Temp Reaches L8-64 | 0 (0 - 2) |
| L8-11 (04B7) | Heatsink Fan Off-Delay Time | Sets the length of time that the drive will wait before it stops the cooling fan after it cancels the Run command when <i>L8-10 = 0</i> [<i>Heatsink Fan Operation Selection = During Run, w/ L8-11 Off-Delay</i>]. | 300 s (0 - 300 s) |
| L8-12 (04B8) | Ambient Temperature Setting | Sets the ambient temperature of the drive installation area. Note: The setting range changes when the <i>L8-35</i> [<i>Installation Method Selection</i>] setting changes. • When <i>L8-35 = 0 or 2</i> [<i>IP20/UL Open Type or IP20/UL Type 1</i>]: -10 °C ~ +60 °C • When <i>L8-35 = 1 or 3</i> [<i>Side-by-Side Mounting or IP55/UL Type 12</i>]: -10 °C ~ +50 °C | 40 °C (Determined by L8-35) |
| L8-15 (04BB) | Drive oL2 @ Low Speed Protection | Sets the function to decrease drive overload at low speeds to prevent damage to the main circuit transistor during low speed operation (at 6 Hz or slower) to prevent oL2 [<i>Drive Overloaded</i>]. Note: Contact Yaskawa or your nearest sales representative before disabling this function at low speeds. If you frequently operate drives with high output current in low speed ranges, it can cause heat stress and decrease the life span of drive IGBTs. 0 : Disabled (No Additional Derate) 1 : Enabled (Reduced oL2 Level) | 1 (0, 1) |
| L8-18 (04BE) | Software Current Limit Selection | Set the software current limit selection function to prevent damage to the main circuit transistor caused by too much current. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| L8-19 (04BF) | Freq Reduction @ oH Pre-Alarm | Sets the ratio at which the drive derates the frequency reference during an oH alarm. | 20.0% (10.0 - 100.0%) |
| L8-35 (04EC) | Installation Method Selection | Sets the type of drive installation. 0 : IP20/UL Open Type 1 : Side-by-Side Mounting 2 : IP20/UL Type 1 3 : IP55/UL Type 12 | 2 (0 - 3) |
| L8-38 (04EF) | Carrier Frequency Reduction | Sets the carrier frequency reduction function. The drive decreases the carrier frequency when the output current is more than a specified level. 1 : Enabled below 6 Hz 2 : Enabled for All Speeds 3 : Enable at Overload | Determined by o2-04 (1 - 3) |
| L8-41 (04F2) | High Current Alarm Selection | Sets the function to cause an HCA [<i>High Current Alarm</i>] when the output current is more than 150% of the drive rated current. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| L8-97 (3104) | Carrier Freq Reduce during OH | Sets the function to decrease carrier frequency during oH pre-alarm. 0 : Disabled 1 : Enabled | 0 (0, 1) |

◆ L9: Drive Protection 2

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|------------------|---|-------------------------|
| L9-16 (11DC) Expert | FAn1 Detect Time | Sets the detection time for <i>FAn1 [Drive Cooling Fan Fault]</i> . Yaskawa recommends that you do not change this parameter value. | 4.0 s (0.0 - 30.0 s) |

7.10 n: Special Adjustment

◆ n1: Hunting Prevention

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|----------------------------------|---|-------------------------------------|
| n1-01 (0580) | Hunting Prevention Selection | Sets the function to prevent hunting. 0 : Disabled 1 : Enabled (Normal) | 1 (0, 1) |
| n1-02 (0581) Expert | Hunting Prevention Gain Setting | Sets the performance of the hunting prevention function. Usually it is not necessary to change this parameter. | 1.00 (0.00 - 2.50) |
| n1-03 (0582) Expert | Hunting Prevention Time Constant | Sets the primary delay time constant of the hunting prevention function. Usually it is not necessary to change this parameter. | Determined by o2-04 (0 - 500 ms) |
| n1-05 (0530) Expert | Hunting Prevent Gain in Reverse | Sets the performance of the hunting prevention function. This parameter adjusts Reverse run. Usually it is not necessary to change this parameter. | 0.00 (0.00 - 2.50) |
| n1-13 (1B59) Expert | DC Bus Stabilization Control | Sets the oscillation suppression function for the DC bus voltage. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| n1-14 (1B5A) Expert | DC Bus Stabilization Time | Adjusts the responsiveness of the oscillation suppression function for the DC bus voltage. Set <i>n1-13 = 1</i> [<i>DC Bus Stabilization Control = Enabled</i>] to enable this parameter. | 100.0 ms (0.0 - 500.0 ms) |

◆ n3: High Slip/Overexcite Braking

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|----------------------------------|---|-----------------------------------|
| n3-01 (0588) Expert | HSB Deceleration Frequency Width | Sets the amount by which the output frequency is to be lowered during high-slip braking, as a percentage of <i>E1-04</i> [<i>Maximum Output Frequency</i>], which represents the 100% value. | 5% (1 - 20%) |
| n3-02 (0589) Expert | HSB Current Limit Level | Sets the maximum current output during high-slip braking as a percentage, where <i>E2-01</i> [<i>Motor Rated Current (FLA)</i>] is 100%. Also sets the current suppression to prevent exceeding drive overload tolerance. | Determined by L8-38 (0 - 200%) |
| n3-03 (058A) Expert | HSB Dwell Time at Stop | Sets the dwell time, a length of time when high-slip braking is ending and during which the motor speed decreases and runs at a stable speed. For a set length of time, the drive will hold the actual output frequency at the minimum output frequency set in <i>E1-09</i> . | 1.0 s (0.0 - 10.0 s) |
| n3-04 (058B) Expert | HSB Overload Time | Sets the time used to detect <i>oL7</i> [<i>High Slip Braking Overload</i>], which occurs when the output frequency does not change during high-slip braking. Usually it is not necessary to change this parameter. | 40 s (30 - 1200 s) |
| n3-13 (0531) | OverexcitationBraking (OEB) Gain | Sets the gain value that the drive multiplies by the <i>V/f</i> pattern output value during overexcitation deceleration to calculate the overexcitation level. | 1.10 (1.00 - 1.40) |
| n3-21 (0579) | HSB Current Suppression Level | Sets the upper limit of the current that is suppressed at the time of overexcitation deceleration as a percentage of the drive rated current. | 100% (0 - 150%) |
| n3-23 (057B) | Overexcitation Braking Operation | Sets the direction of motor rotation where the drive will enable overexcitation. 0 : Disabled 1 : Enabled Only when Rotating FWD 2 : Enabled Only when Rotating REV | 0 (0 - 2) |

7.11 o: Keypad-Related Settings

◆ o1: Keypad Display



| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------------|---|------------------------------------|
| o1-03 (0502) | Frequency Display Unit Selection | Sets the display units for the frequency reference and output frequency. 0 : 0.01Hz units 1 : 0.01% units 2 : min ⁻¹ (r/min) unit 3 : User Units (o1-09 -o1-11) | 0 (0 - 3) |
| o1-05 (0504) RUN | LCD Contrast Adjustment | Sets the contrast of the LCD display on the keypad. | 5 (0 - 10) |
| o1-09 (051C) | Freq. Reference Display Units | Sets the unit of display for the frequency reference parameters and frequency-related monitors when o1-03 = 3 [Frequency Display Unit Selection = User Units (o1-09 ~ o1-11)]. 0 : "WC: inches of water column 1 : PSI: pounds per square inch 2 : GPM: gallons/min 3 : °F: Fahrenheit 4 : ft ³ /min: cubic feet/min 5 : m ³ /h: cubic meters/hour 6 : L/h: liters/hour 7 : L/s: liters/sec 8 : bar: bar 9 : Pa: Pascal 10 : °C: Celsius 11 : m: meters 12 : ft: feet 13 : L/min: liters/min 14 : m ³ /min: cubic meters/min 15 : "Hg: Inch Mercury 16 : kPa: kilopascal 48 : %: Percent 49 : Custom(o1-13~15) 50 : None | 50 (0 - 50) |
| o1-10 (0520) | User Units Maximum Value | Sets the value that the drive shows as the maximum output frequency. | Determined by o1-03 (1 - 60000) |
| o1-11 (0521) | User Units Decimal Position | Sets the number of decimal places for frequency reference and monitor values. 0 : No Decimal Places (XXXXX) 1 : One Decimal Places (XXXX.X) 2 : Two Decimal Places (XXX.XX) 3 : Three Decimal Places (XX.XXX) | Determined by o1-03 (0 - 3) |
| o1-13 (3105) | Freq. Reference Custom Unit 1 | Sets the first character of the custom unit display when o1-03 = 3 [Frequency Display Unit Selection = User Units] and o1-09 = 49 [Freq. Reference Display Units = Custom (o1-13~15)]. | 41 (20 - 7A) |
| o1-14 (3106) | Freq. Reference Custom Unit 2 | Sets the second character of the custom unit display when o1-03 = 3 [Frequency Display Unit Selection = User Units] and o1-09 = 49 [Freq. Reference Display Units = Custom (o1-13~15)]. | 41 (20 - 7A) |
| o1-15 (3107) | Freq. Reference Custom Unit 3 | Sets the third character of the custom unit display when o1-03 = 3 [Frequency Display Unit Selection = User Units] and o1-09 = 49 [Freq. Reference Display Units = Custom (o1-13~15)]. | 41 (20 - 7A) |
| o1-18 (310A) | User Defined Parameter 1 | Lets you set values to use as reference information. | 0 (0 - 999) |
| o1-19 (310B) | User Defined Parameter 2 | Lets you set values to use as reference information. | 0 (0 - 999) |
| o1-24 (11AD) RUN | Custom Monitor 1 | Sets Custom Monitor 1. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 101 (0, 31, 101 - 1201) |
| o1-25 (11AE) RUN | Custom Monitor 2 | Sets Custom Monitor 2. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 102 (0, 31, 101 - 1201) |

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------------------|--|--|
| o1-26 (11AF) RUN | Custom Monitor 3 | Sets Custom Monitor 3. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. Note: The default setting changes when <i>b5-01 [PID Mode Setting]</i> changes: • <i>b5-01 = 0 [Disabled]</i> : 103 • <i>b5-01 ≠ 0</i> : 501 | Determined by b5-01 (0, 31, 101 - 1201) |
| o1-27 (11B0) RUN | Custom Monitor 4 | Sets Custom Monitor 4. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-28 (11B1) RUN | Custom Monitor 5 | Sets Custom Monitor 5. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-29 (11B2) RUN | Custom Monitor 6 | Sets Custom Monitor 6. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-30 (11B3) RUN | Custom Monitor 7 | Sets Custom Monitor 7. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-31 (11B4) RUN | Custom Monitor 8 | Sets Custom Monitor 8. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-32 (11B5) RUN | Custom Monitor 9 | Sets Custom Monitor 9. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-33 (11B6) RUN | Custom Monitor 10 | Sets Custom Monitor 10. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-34 (11B7) RUN | Custom Monitor 11 | Sets Custom Monitor 11. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-35 (11B8) RUN | Custom Monitor 12 | Sets Custom Monitor 12. You can set a maximum of 12 monitors as user monitors. This parameter is only available on an HOA keypad. | 0 (0, 101 - 1212) |
| o1-36 (11B9) RUN | LCD Backlight Brightness | Sets the intensity of the HOA keypad backlight. | 5 (1 - 5) |
| o1-37 (11BA) RUN | LCD Backlight ON/OFF Selection | Sets the automatic shut off function for the LCD backlight. 0 : OFF 1 : ON | 1 (0, 1) |
| o1-38 (11BB) RUN | LCD Backlight Off-Delay | Sets the time until the LCD backlight automatically turns off. | 60 s (10 - 300 s) |
| o1-39 (11BC) RUN | Show Initial Setup Screen | Sets the function to show the HOA keypad initial setup screen each time you energize the drive. This parameter is only available on an HOA keypad. 0 : No 1 : Yes | 1 (0, 1) |
| o1-40 (11BD) RUN | Home Screen Display Selection | Sets the monitor display mode for the Home screen. This parameter is only available on an HOA keypad. 0 : Custom Monitor 1 : Bar Graph 2 : Analog Gauge 3 : Trend Plot | 0 (0 - 3) |
| o1-41 (11C1) RUN | 1st Monitor Area Selection | Sets the horizontal range used to display the monitor set in <i>o1-24 [Custom Monitor 1]</i> as a bar graph. This parameter is only available on an HOA keypad. 0 : +/- Area (- o1-42 ~ o1-42) 1 : + Area (0 ~ o1-42) | 0 (0 - 1) |
| o1-42 (11C2) RUN | 1st Monitor Area Setting | Sets the horizontal axis value used to display the monitor set in <i>o1-24 [Custom Monitor 1]</i> as a bar graph. This parameter is only available on an HOA keypad. | 100.0% (0.0 - 100.0%) |

7.11 o: Keypad-Related Settings

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------------|---|-------------------------------|
| o1-43 (11C3) RUN | 2nd Monitor Area Selection | Selects the horizontal range used to display the monitor set in o1-25 [Custom Monitor 2] as a bar graph. This parameter is only available on an HOA keypad. 0 : +/- Area (- o1-44 ~ o1-44) 1 : + Area (0 ~ o1-44) | 0 (0 - 1) |
| o1-44 (11C4) RUN | 2nd Monitor Area Setting | Sets the horizontal axis value used to display the monitor set in o1-25 [Custom Monitor 2] as a bar graph. This parameter is only available on an HOA keypad. | 100.0% (0.0 - 100.0%) |
| o1-45 (11C5) RUN | 3rd Monitor Area Selection | Sets the horizontal range used to display the monitor set in o1-26 [Custom Monitor 3] as a bar graph. This parameter is only available on an HOA keypad. 0 : +/- Area (- o1-46 ~ o1-46) 1 : + Area (0 ~ o1-46) | 0 (0 - 1) |
| o1-46 (11C6) RUN | 3rd Monitor Area Setting | Sets the horizontal axis value used to display the monitor set in o1-26 [Custom Monitor 3] as a bar graph. This parameter is only available on an HOA keypad. | 100.0% (0.0 - 100.0%) |
| o1-47 (11C7) RUN | Trend Plot 1 Scale Minimum Value | Sets the horizontal axis minimum value used to display the monitor set in o1-24 [Custom Monitor 1] as a trend plot. This parameter is only available on an HOA keypad. | -100.0% (-300.0 - +300.0%) |
| o1-48 (11C8) RUN | Trend Plot 1 Scale Maximum Value | Sets the horizontal axis maximum value used to display the monitor set in o1-24 [Custom Monitor 1] as a trend plot. This parameter is only available on an HOA keypad. | 100.0% (-300.0 - +300.0%) |
| o1-49 (11C9) RUN | Trend Plot 2 Scale Minimum Value | Sets the horizontal axis minimum value used to display the monitor set in o1-25 [Custom Monitor 2] as a trend plot. This parameter is only available on an HOA keypad. | -100.0% (-300.0 - +300.0%) |
| o1-50 (11CA) RUN | Trend Plot 2 Scale Maximum Value | Sets the horizontal axis maximum value used to display the monitor set in o1-25 [Custom Monitor 2] as a trend plot. This parameter is only available on an HOA keypad. | 100.0% (-300.0 - +300.0%) |
| o1-51 (11CB) RUN | Trend Plot Time Scale Setting | Sets the time scale (horizontal axis) to display the trend plot. When you change this setting, the drive automatically adjusts the data sampling time. This parameter is only available on an HOA keypad. | 300 s (1 - 3600 s) |
| o1-55 (11EE) RUN | Analog Gauge Area Selection | Sets the range used to display the monitor set in o1-24 [Custom Monitor 1] as an analog gauge. This parameter is only available on an HOA keypad. 0 : +/- Area (- o1-56 ~ o1-56) 1 : + Area (0 ~ o1-56) | 1 (0, 1) |
| o1-56 (11EF) RUN | Analog Gauge Area Setting | Sets the value used to display the monitor set in o1-24 [Custom Monitor 1] as an analog meter. This parameter is only available on an HOA keypad. | 100.0% (0.0 - 100.0%) |
| o1-58 (3125) | Motor Power Unit Selection | Sets the setting unit for parameters that set the motor rated power. 0 : kW 1 : HP | 1 (0, 1) |
| o1-80 (31BA) | Fault Screen Display | Sets a full-screen display message to show on the keypad when a fault or CPF occurs. 0 : OFF 1 : ON | 1 (0, 1) |
| o1-81 (31BB) | Alarm Screen Display | Sets a full-screen display message to show on the keypad when an alarm occurs. 0 : OFF 1 : ON | 0 (0, 1) |
| o1-82 (31BC) | Message Screen Display | Sets a full-screen display message to show on the keypad when a status message is active. 0 : OFF 1 : ON | 0 (0, 1) |

◆ o2: Keypad Operation

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|-------------------------------|---|--------------------------------|
| o2-02 (0506) | OFF Key Function Selection | Sets the function to use  on the keypad to stop the drive when the Run command source for the drive is REMOTE (external) and not assigned to the keypad. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| o2-03 (0507) | User Parameter Default Value | Sets the function to keep the settings of changed parameters as user parameter defaults to use during initialization. 0 : No change 1 : Set defaults 2 : Clear all | 0 (0 - 2) |
| o2-04 (0508) | Drive Model (KVA) Selection | This parameter is automatically read from the connected drive. Do not change this parameter. | Determined by the drive (-) |
| o2-05 (0509) | Home Mode Freq Ref Entry Mode | Sets the function that makes it necessary to push  to use the keypad to change the frequency reference value while in Drive Mode. 0 : ENTER Key Required 1 : Immediate / MOP-style | 0 (0, 1) |
| o2-06 (050A) | Keypad Disconnect Detection | Sets the function that stops the drive if you disconnect the keypad connection cable from the drive or if you damage the cable while the keypad is the Run command source. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| o2-09 (050D) | Region Code | This parameter is read-only | 1 (1) |
| o2-19 (061F) | Parameter Write during Uv | Enables and disables the function to change parameter settings during a <i>Uv [DC Bus Undervoltage]</i> condition. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| o2-24 (11FE) | LED Light Function Selection | Sets the function to show the LED status rings and keypad LED lamps. Note: When you use <i>A1-03 [Initialize Parameters]</i> to initialize the drive, the drive will not reset this parameter. 0 : Enable Status Ring & Keypad LED 1 : LED Status Ring Disable 2 : Keypad LED Light Disable | 0 (0 - 2) |
| o2-27 (1565) | bCE Detection Selection | Sets drive operation if the Bluetooth device is disconnected when you operate the drive in Bluetooth Mode. 0 : Ramp to Stop 1 : Coast to Stop 2 : Fast Stop (Use <i>C1-09</i>) 3 : Alarm Only 4 : No Alarm Display | 3 (0 - 4) |

◆ o3: Copy Keypad Function

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|--------------------------------|--|-----------------|
| o3-01 (0515) | Copy Keypad Function Selection | Sets the function that saves and copies drive parameters to a different drive with the keypad. 0 : Copy Select 1 : Backup (drive → keypad) 2 : Restore (keypad → drive) 3 : Verify (check for mismatch) 4 : Erase (backup data of keypad) | 0 (0 - 4) |
| o3-02 (0516) | Copy Allowed Selection | Sets the copy function when <i>o3-01 = 1 [Copy Keypad Function Selection = Backup (drive → keypad)]</i> . 0 : Disabled 1 : Enabled | 0 (0, 1) |

7.11 o: Keypad-Related Settings

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|---------------------------------|---|-----------------|
| o3-04 (0B3E) | Select Backup/Restore Location | Sets the storage location for drive parameters when you back up and restore parameters. This parameter is only available on an HOA keypad. 0 : Memory Location 1 1 : Memory Location 2 2 : Memory Location 3 3 : Memory Location 4 | 0 (0 - 3) |
| o3-06 (0BDE) | Auto Parameter Backup Selection | Sets the function that automatically backs up parameters. This parameter is only available on an HOA keypad. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| o3-07 (0BDF) | Auto Parameter Backup Interval | Sets the interval at which the automatic parameter backup function saves parameters from the drive to the keypad. Note: This parameter is only available when using an LCD keypad. 0 : Every 10 minutes 1 : Every 30 minutes 2 : Every 60 minutes 3 : Every 12 hours | 1 (0 - 3) |

◆ o4: Maintenance Monitors

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------------|--|---------------------|
| o4-01 (050B) | Elapsed Operating Time Setting | Sets the initial value of the cumulative drive operation time in 10-hour units. | 0 h (0 - 9999 h) |
| o4-02 (050C) | Elapsed Operating Time Selection | Sets the condition that counts the cumulative operation time. 0 : U4-01 Shows Total Power-up Time 1 : U4-01 Shows Total RUN Time | 1 (0, 1) |
| o4-03 (050E) | Fan Operation Time Setting | Sets the value from which to start the cumulative drive cooling fan operation time in 10-hour units. | 0 h (0 - 9999 h) |
| o4-05 (051D) | Capacitor Maintenance Setting | Sets the U4-05 [<i>CapacitorMaintenance</i>] monitor value. | 0% (0 - 150%) |
| o4-07 (0523) | Softcharge Relay Maintenance Set | Sets the U4-06 [<i>PreChargeRelayMainte</i>] monitor value. | 0% (0 - 150%) |
| o4-09 (0525) | IGBT Maintenance Setting | Sets the U4-07 [<i>IGBT Maintenance</i>] monitor value. | 0% (0 - 150%) |
| o4-11 (0510) | Fault Trace/History Init (U2/U3) | Resets the records of Monitors U2-xx [<i>Fault Trace</i>] and U3-xx [<i>Fault History</i>]. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| o4-12 (0512) | kWh Monitor Initialization | Resets the monitor values for U4-10 [<i>kWh, Lower 4 Digits</i>] and U4-11 [<i>kWh, Upper 5 Digits</i>]. 0 : No Reset 1 : Reset | 0 (0, 1) |
| o4-13 (0528) | RUN Command Counter @ Initialize | Resets the monitor values for U4-02 [<i>Num of Run Commands</i>], U4-24 [<i>Number of Runs (Low)</i>], and U4-25 [<i>Number of Runs (High)</i>]. 0 : No Reset 1 : Reset | 0 (0, 1) |
| o4-22 (154F) RUN | Time Format | Sets the time display format. This parameter is only available on an HOA keypad. 0 : 24 Hour Clock 1 : 12 Hour Clock 2 : 12 Hour JP Clock | 1 (0 - 2) |
| o4-23 (1550) RUN | Date Format | Sets the date display format. This parameter is only available on an HOA keypad. 0 : YYYY/MM/DD 1 : DD/MM/YYYY 2 : MM/DD/YYYY | 2 (0 - 2) |
| o4-24 (310F) RUN | bAT Detection Selection | Sets operation when the drive detects bAT [<i>Keypad Battery Low Voltage</i>] and TiM [<i>Keypad Time Not Set</i>]. 0 : Disable 1 : Enable (Alarm Detected) 2 : Enable (Fault Detected) | 0 (0 - 2) |

◆ o5: Log Function

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------------|---|----------------------------|
| o5-01 (1551) RUN | Log Start/Stop Selection | Sets the data log function. This parameter is only available on an HOA keypad. 0 : OFF 1 : ON Note: You must insert a compatible SD card into the keypad before you enable this parameter. | 0 (0 - 1) |
| o5-02 (1552) RUN | Log Sampling Interval | Sets the data log sampling cycle. This parameter is only available on an HOA keypad. | 100 ms (100 - 60000 ms) |
| o5-03 (1553) RUN | Log Monitor Data 1 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 101 (000, 101 - 1212) |
| o5-04 (1554) RUN | Log Monitor Data 2 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 102 (000, 101 - 1212) |
| o5-05 (1555) RUN | Log Monitor Data 3 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 103 (000, 101 - 1212) |
| o5-06 (1556) RUN | Log Monitor Data 4 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 107 (000, 101 - 1212) |
| o5-07 (1557) RUN | Log Monitor Data 5 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 108 (000, 101 - 1212) |
| o5-08 (1558) RUN | Log Monitor Data 6 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 0 (000, 101 - 1212) |
| o5-09 (1559) RUN | Log Monitor Data 7 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 000 (000, 101 - 1212) |
| o5-10 (155A) RUN | Log Monitor Data 8 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 000 (000, 101 - 1212) |
| o5-11 (155B) RUN | Log Monitor Data 9 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 000 (000, 101 - 1212) |
| o5-12 (155C) RUN | Log Monitor Data 10 | Sets the data log monitor. This parameter is only available on an HOA keypad. | 000 (000, 101 - 1212) |

7.12 S: Special Applications

◆ S1: Dynamic Noise Control

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|---------------------------------|--|------------------------------|
| S1-01 (3200) | Dynamic Noise Control | Sets the function that decreases the output voltage in variable torque applications to decrease audible noise. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| S1-02 (3201) | Voltage Reduction Rate | Sets the rate at which the drive will decrease the output voltage as a percentage of the V/f pattern when operating with no load. | 50.0% (50.0 - 100.0%) |
| S1-03 (3202) | Voltage Restoration Level | Sets the level at which the drive will start to restore the voltage as a percentage of the drive rated torque. | 20.0% (0.0 - 90.0%) |
| S1-04 (3203) | Voltage Restoration Off Level | Sets the level at which voltage restoration for the V/f pattern is complete as a percentage of the drive rated torque. If the output is more than S1-04, the drive will control the voltage as specified by the V/f pattern setting. Note: The lower limit of this parameter is the value of S1-03 [Voltage Restoration Level] + 10.0%. | 50.0% (10.0 - 100.0%) |
| S1-05 (3204) | Volt Restore Sensitivity Time K | Sets the level of sensitivity of the output torque and LPF time constant for the voltage reduction rate. You can adjust the level of sensitivity with the load response. | 1.000 s (0.000 - 3.000 s) |
| S1-06 (3205) | Volt Restore Impact Load Time K | Sets the voltage restoration time constant when you add an impact load. | 0.050 s (0.000 - 1.000 s) |
| S1-07 (324C) | Output Phase Loss Level | Decreases the output phase loss level when Dynamic Noise control is active. | 100.0% (10.0 - 100.0%) |

◆ S2: Sequence Run Timers

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------|--|--------------------------------|
| S2-01 (3206) | Timer 1 Start Time | Sets the start time for timer 1. Note: • Default is when o4-22 = 1 [Time Format = 12 Hour Clock]. When o4-22 = 0 [24 Hour Clock], default is 00:00. When o4-22 = 2 [12 Hour JP Clock], default is 00:00 AM. • Range is when o4-22 = 1. When o4-22 = 0, range is 00:00 to 24:00. When o4-22 = 2, range is 00:00 AM to 11:59 PM. | 12:00 (12:00 AM - 11:59 PM) |
| S2-02 (3207) | Timer 1 Stop Time | Sets the stop time for timer 1. Note: • Default is when o4-22 = 1 [Time Format = 12 Hour Clock]. When o4-22 = 0 [24 Hour Clock], default is 00:00. When o4-22 = 2 [12 Hour JP Clock], default is 00:00 AM. • Range is when o4-22 = 1. When o4-22 = 0, range is 00:00 to 24:00. When o4-22 = 2, range is 00:00 AM to 11:59 PM. | 12:00 (12:00 AM - 11:59 PM) |
| S2-03 (3208) | Timer 1 Day Selection | Sets the days for which sequence timer 1 is active. 0 : Timer Disabled 1 : Daily 2 : Mon - Fri 3 : Sat - Sun 4 : Monday 5 : Tuesday 6 : Wednesday 7 : Thursday 8 : Friday 9 : Saturday 10 : Sunday | 0 (0 - 10) |
| S2-04 (3209) | Timer 1 Sequence Selection | Sets the drive response when sequence timer 1 is active. 0 : Digital Out Only 1 : Run 2 : Run - PID Disable | 0 (0 - 2) |

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------|---|--------------------------------|
| S2-05 (320A) | Timer 1 Reference Source | Selects the frequency reference source to run the drive when sequence timer 1 is active (only applicable when $S2-04 > 0$ [Timer 1 Sequence Selection ≠ Digital Out Only]). 0 : Operator (d1-01/YA-01) 1 : Operator (d1-02/YA-02) 2 : Operator (d1-03/YA-03) 3 : Operator (d1-04/YA-04) 4 : Terminals 5 : Serial Com 6 : Option PCB 8 : Set by b1-01 Note: For reference source 0 to 3, the drive will use <i>d1-xx</i> frequency reference when PID mode is disabled and <i>YA-xx</i> setpoint when PID is enabled. | 0 (0 - 8) |
| S2-06 (320B) | Timer 2 Start Time | Sets the start time for timer 2. Note: • Default is when $o4-22 = 1$ [Time Format = 12 Hour Clock]. When $o4-22 = 0$ [24 Hour Clock], default is 00:00. When $o4-22 = 2$ [12 Hour JP Clock], default is 00:00 AM. • Range is when $o4-22 = 1$. When $o4-22 = 0$, range is 00:00 to 24:00. When $o4-22 = 2$, range is 00:00 AM to 11:59 PM. | 12:00 (12:00 AM - 11:59 PM) |
| S2-07 (320C) | Timer 2 Stop Time | Sets the stop time for timer 2. Note: • Default is when $o4-22 = 1$ [Time Format = 12 Hour Clock]. When $o4-22 = 0$ [24 Hour Clock], default is 00:00. When $o4-22 = 2$ [12 Hour JP Clock], default is 00:00 AM. • Range is when $o4-22 = 1$. When $o4-22 = 0$, range is 00:00 to 24:00. When $o4-22 = 2$, range is 00:00 AM to 11:59 PM. | 12:00 (12:00 AM - 11:59 PM) |
| S2-08 (320D) | Timer 2 Day Selection | Sets the days for which sequence timer 2 is active. 0 : Timer disabled 1 : Daily 2 : Mon - Fri 3 : Sat - Sun 4 : Monday 5 : Tuesday 6 : Wednesday 7 : Thursday 8 : Friday 9 : Saturday 10 : Sunday | 0 (0 - 10) |
| S2-09 (320E) | Timer 2 Sequence Selection | Sets the drive response when sequence timer 2 is active. 0 : Digital Out Only 1 : Run 2 : Run - PID Disable | 0 (0 - 2) |
| S2-10 (320F) | Timer 2 Reference Source | Selects the frequency reference source to run the drive when sequence timer 2 is active (only applicable when $S2-09 > 0$ [Timer 2 Sequence Selection ≠ 0]). 0 : Operator (d1-01/YA-01) 1 : Operator (d1-02/YA-02) 2 : Operator (d1-03/YA-03) 3 : Operator (d1-04/YA-04) 4 : Terminals 5 : Serial Com 6 : Option PCB 8 : Set by b1-01 Note: For reference source 0 to 3, the drive will use <i>d1-xx</i> frequency reference when PID mode is disabled and <i>YA-xx</i> setpoint when PID is enabled. | 0 (0 - 8) |
| S2-11 (3210) | Timer 3 Start Time | Sets the start time for timer 3. Note: • Default is when $o4-22 = 1$ [Time Format = 12 Hour Clock]. When $o4-22 = 0$ [24 Hour Clock], default is 00:00. When $o4-22 = 2$ [12 Hour JP Clock], default is 00:00 AM. • Range is when $o4-22 = 1$. When $o4-22 = 0$, range is 00:00 to 24:00. When $o4-22 = 2$, range is 00:00 AM to 11:59 PM. | 12:00 (12:00 AM - 11:59 PM) |
| S2-12 (3211) | Timer 3 Stop Time | Sets the stop time for timer 3. Note: • Default is when $o4-22 = 1$ [Time Format = 12 Hour Clock]. When $o4-22 = 0$ [24 Hour Clock], default is 00:00. When $o4-22 = 2$ [12 Hour JP Clock], default is 00:00 AM. • Range is when $o4-22 = 1$. When $o4-22 = 0$, range is 00:00 to 24:00. When $o4-22 = 2$, range is 00:00 AM to 11:59 PM. | 12:00 (12:00 AM - 11:59 PM) |

7.12 S: Special Applications

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------|--|--------------------------------|
| S2-13 (3212) | Timer 3 Day Selection | Sets the days for which sequence timer 3 is active. 0 : Timer Disabled 1 : Daily 2 : Mon - Fri 3 : Sat - Sun 4 : Monday 5 : Tuesday 6 : Wednesday 7 : Thursday 8 : Friday 9 : Saturday 10 : Sunday | 0 (0 - 10) |
| S2-14 (3213) | Timer 3 Sequence Selection | Sets the drive response when sequence timer 3 is active. 0 : Digital Out Only 1 : Run 2 : Run - PID Disable | 0 (0 - 2) |
| S2-15 (3214) | Timer 3 Reference Source | Selects the frequency reference source to run the drive when sequence timer 3 is active (only applicable when $S2-14 > 0$ [Timer 3 Sequence Selection \neq Digital Out Only]). 0 : Operator (d1-01/YA-01) 1 : Operator (d1-02/YA-02) 2 : Operator (d1-03/YA-03) 3 : Operator (d1-04/YA-04) 4 : Terminals 5 : Serial Com 6 : Option PCB 8 : Set by b1-01 Note: For reference source 0 to 3, the drive will use $d1-xx$ frequency reference when PID mode is disabled and $YA-xx$ setpoint when PID is enabled. | 0 (0 - 8) |
| S2-16 (3215) | Timer 4 Start Time | Sets the start time for timer 4. Note: • Default is when $o4-22 = 1$ [Time Format = 12 Hour Clock]. When $o4-22 = 0$ [24 Hour Clock], default is 00:00. When $o4-22 = 2$ [12 Hour JP Clock], default is 00:00 AM. • Range is when $o4-22 = 1$. When $o4-22 = 0$, range is 00:00 to 24:00. When $o4-22 = 2$, range is 00:00 AM to 11:59 PM. | 12:00 (12:00 AM - 11:59 PM) |
| S2-17 (3216) | Timer 4 Stop Time | Sets the stop time for timer 4. Note: • Default is when $o4-22 = 1$ [Time Format = 12 Hour Clock]. When $o4-22 = 0$ [24 Hour Clock], default is 00:00. When $o4-22 = 2$ [12 Hour JP Clock], default is 00:00 AM. • Range is when $o4-22 = 1$. When $o4-22 = 0$, range is 00:00 to 24:00. When $o4-22 = 2$, range is 00:00 AM to 11:59 PM. | 12:00 (12:00 AM - 11:59 PM) |
| S2-18 (3217) | Timer 4 Day Selection | Sets the days for which sequence timer 4 is active. 0 : Timer disabled 1 : Daily 2 : Mon - Fri 3 : Sat - Sun 4 : Monday 5 : Tuesday 6 : Wednesday 7 : Thursday 8 : Friday 9 : Saturday 10 : Sunday | 0 (0 - 10) |

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------|--|-----------------|
| S2-19 (3218) | Timer 4 Sequence Selection | Sets the drive response when sequence timer 4 is active. 0 : Digital Out Only 1 : Run 2 : Run - PID Disable | 0 (0 - 2) |
| S2-20 (3219) | Timer 4 Reference Source | Selects the frequency reference source to run the drive when sequence timer 4 is active (only applicable when $S2-19 > 0$ [Timer 4 Sequence Selection \neq Digital Out Only]). 0 : Operator (d1-01/YA-01) 1 : Operator (d1-02/YA-02) 2 : Operator (d1-03/YA-03) 3 : Operator (d1-04/YA-04) 4 : Terminals 5 : Serial Com 6 : Option PCB 8 : Set by b1-01 Note: For reference source 0 to 3, the drive will use dI -xx frequency reference when PID mode is disabled and YA -xx setpoint when PID is enabled. | 0 (0 - 8) |

◆ S3: PI2 Control

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|-------------------------------|---|---------------------------|
| S3-01 (321A) | PI2 Control Enable Selection | Sets when the PI2 Control function is enabled: 0 : Disabled 1 : Always 2 : Drive Running 3 : Motor Running | 0 (0 - 3) |
| S3-02 (321B) RUN | PI2 Control Transducer Scale | Sets the full scale (10 V or 20 mA) output of the pressure transducer that is connected to the analog input terminals programmed for PI2 (Setpoint or Feedback). Note: Parameters $S3-04$ [PI2 Control Unit Selection], $S3-03$ [PI2 Control Decimal Place Pos], and $S3-02$ [PI2 Control Transducer Scale] set the unit, resolution, and upper limit. | 100.00 (1.00 - 600.00) |
| S3-03 (321C) RUN | PI2 Control Decimal Place Pos | Sets the decimal place display for secondary PI units. 0 : No Decimal Places (XXXXX) 1 : One Decimal Places (XXXX.X) 2 : Two Decimal Places (XXX.XX) 3 : Three Decimal Places (XX.XXX) | 2 (0 - 3) |
| S3-04 (321D) RUN | PI2 Control Unit Selection | Sets the units displayed for the PI2 Control parameters and monitor. 0 : "WC: inches of water column 1 : PSI: pounds per square inch 2 : GPM: gallons/min 3 : °F: Fahrenheit 4 : ft ³ /min: cubic feet/min 5 : m ³ /h: cubic meters/hour 6 : L/h: liters/hour 7 : L/s: liters/sec 8 : bar: bar 9 : Pa: Pascal 10 : °C: Celsius 11 : m: meters 12 : ft: feet 13 : L/min: liters/min 14 : m ³ /min: cubic meters/min 15 : "Hg: Inch Mercury 16 : kPa: kilopascal 48 : %: Percent 49 : Custom($S3-18-20$) 50 : None | 48 (0 - 50) |
| S3-05 (321E) RUN | PI2 Control Setpoint | Sets the PI2 Control target setpoint. Note: Parameters $S3-04$ [PI2 Control Unit Selection], $S3-03$ [PI2 Control Decimal Place Pos], and $S3-02$ [PI2 Control Transducer Scale] set the unit, resolution, and upper limit. | 0.00 (0.00 - 600.00) |

7.12 S: Special Applications

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------------------|--|----------------------------|
| S3-06 (321F) RUN | PI2 Control Proportional Gain | Sets the proportional gain of the PI2 Control. Set this parameter to 0.00 to disable proportional control. | 1.00 (0.00 - 25.00) |
| S3-07 (3220) RUN | PI2 Control Integral Time | Sets the integral time for the suction pressure control. Set this parameter to 0.00 to disable the integrator. | 1.0 s (0.0 - 360.0 s) |
| S3-08 (3221) RUN | PI2 Control Integral Max Limit | Sets the maximum output possible from the integrator. | 100.0% (0.0 - 100.0%) |
| S3-09 (3222) RUN | PI2 Control Output Upper Limit | Sets the maximum output possible from the PI Auxiliary Control function. | 100.0% (0.0 - 100.0%) |
| S3-10 (3223) RUN | PI2 Control Output Lower Limit | Sets the minimum output possible from the PI Auxiliary Control function. | 0.0% (-100.0 - +100.0%) |
| S3-11 (3224) | PI2 Control Output Level Sel | Sets the PI2 controller output direction. 0 : Direct Acting (Normal Output) 1 : Inverse Acting (Reverse Output) | 0 (0, 1) |
| S3-12 (3225) RUN | PI2 Control Disable Mode Sel | Sets what <i>U5-20 [PI2 Control Output]</i> will output when disabled. 0 : No Output (0%) 1 : Lower Limit (S3-10) 2 : Setpoint | 0 (0 - 2) |
| S3-13 (3226) RUN | PI2 Control Low Feedback Lvl | Sets the secondary PI low feedback detection level. Note: Parameters <i>S3-04 [PI2 Control Unit Selection]</i> , <i>S3-03 [PI2 Control Decimal Place Pos]</i> , and <i>S3-02 [PI2 Control Transducer Scale]</i> set the unit, resolution, and upper limit. | 0.00 (0.00 - 600.00) |
| S3-14 (3227) RUN | PI2 Control Low Feedback Time | Sets the secondary PI low feedback detection delay time in seconds. | 1.0 s (0.0 - 25.5 s) |
| S3-15 (3228) RUN | PI2 Control High Feedback Lvl | Sets the secondary PI high feedback detection level. Note: Parameters <i>S3-04 [PI2 Control Unit Selection]</i> , <i>S3-03 [PI2 Control Decimal Place Pos]</i> , and <i>S3-02 [PI2 Control Transducer Scale]</i> set the unit, resolution, and upper limit. | 100.00 (0.00 - 600.00) |
| S3-16 (3229) RUN | PI2 Control High Feedback Time | Sets the secondary PI high feedback detection delay time in seconds. | 1.0 s (0.0 - 25.5 s) |
| S3-17 (322A) RUN | PI2 Control Feedback Det Sel | Sets when the low and high feedback detection multifunction outputs (71h and 72h) for PI2 Control are active. 0 : While PI2 Control Enabled 1 : Always Note: Feedback level detection compares PI2 Control Feedback from analog input <i>H3-xx = 26 [MFAI Function Selection = PI2 Control Feedback]</i> to these parameters: • <i>S3-13 [PI2 Control Low Feedback Lvl]</i> for low feedback level detection • <i>S3-15 [PI2 Control High Feedback Lvl]</i> for high feedback level detection | 0 (0, 1) |
| S3-18 (322B) RUN | PI2 Control Custom Unit 1 | Sets the first character of the PI2 Control custom unit display when <i>S3-04 = 49 [PI2 Control Unit Selection = Custom(S3-18-20)]</i> . | 41 (20 - 7A) |
| S3-19 (322C) RUN | PI2 Control Custom Unit 2 | Sets the second character of the PI2 Control custom unit display when <i>S3-04 = 49 [PI2 Control Unit Selection = Custom(S3-18-20)]</i> . | 41 (20 - 7A) |
| S3-20 (322D) RUN | PI2 Control Custom Unit 3 | Sets the third character of the PI2 Control custom unit display when <i>S3-04 = 49 [PI2 Control Unit Selection = Custom(S3-18-20)]</i> . | 41 (20 - 7A) |

◆ S5: Hand/Off/Auto Operation

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|---------------------------------|---|-------------------------------|
| S5-01 (322F) | HAND Frequency Reference Source | Sets the frequency reference source when HAND Mode is active. 0 : HAND Analog Input 1 : HAND Ref S5-05 or PID SP S5-06 2 : Set by b1-01 | 1 (0 - 2) |
| S5-02 (3230) | HAND/AUTO Switchover During Run | Sets the function to enable or disable switching between HAND and AUTO Mode during run. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| S5-03 (3231) RUN | HAND Mode PID Selection | Sets the function to enable or disable PI function when HAND mode is active. 0 : Disabled 1 : Enabled Note: If <i>b5-01 = 0</i> [PID Mode Setting = Disabled], the drive disables Hand Mode PID. | 0 (0, 1) |
| S5-05 (3233) RUN | HAND Frequency Reference | Sets the frequency reference when HAND Mode is active, PID is disabled and <i>S5-01 = 1</i> [HAND Frequency Reference Source = HAND Ref S5-05 or PID SP S5-06]. | 0.00 Hz (0.00 - 400.00 Hz) |
| S5-06 (3234) RUN | HAND Setpoint | Sets the System Setpoint when HAND Mode is active, PID is enabled and <i>S5-01 = 1</i> [HAND Frequency Reference Source = HAND Ref S5-05 or PID SP S5-06]. Note: Parameters <i>b5-46</i> [PID Unit Display Selection], <i>b5-38</i> [PID User Unit Display Scaling], and <i>b5-39</i> [PID User Unit Display Digits] set the unit, range, and resolution. | 0.0 (0.0 - 6000.0) |
| S5-07 (3235) | Operation HAND Key | Sets the HAND key on the HOA keypad to let you switch between HAND Mode and AUTO Mode. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| S5-08 (3D31) RUN | HAND Reference Prime Loss Level | Sets the level at which the drive will detect the Loss of Prime in the pump. Note: • If these conditions occur at the same time, the drive will detect LOP [Loss of Prime]: –The monitor set by <i>Y1-18</i> [Prime Loss Detection Method] \leq <i>S5-08</i> for longer than <i>Y1-20</i> [Prime Loss Time] –Output frequency \geq <i>S5-05</i> [HAND Frequency Reference] • The drive response to the Loss of Prime condition changes when the <i>Y1-22</i> [Prime Loss Selection] setting changes. • Parameter <i>Y1-18</i> [Prime Loss Detection Method] sets the units for this parameter. | 0.0 (0.0 - 1000.0) |

◆ S6: Protection

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------------|---|------------------------------|
| S6-01 (3236) | Emergency Override Speed | Sets the speed command for emergency override mode when <i>S6-02 = 0</i> [Emergency Override Ref Selection = Use S6-01 Reference]. Note: Parameter default is lower-limited to <i>E1-09</i> . The default setting will automatically increase when <i>E1-09 > S6-01</i> . | 1.50 Hz (1.50 - 60.00 Hz) |
| S6-02 (3237) | Emergency Override Ref Selection | Sets the Emergency Override Speed Source: 0 : Use S6-01 Reference 1 : Use Frequency Reference 2 : System PID Mode 3 : Independent PID Mode | 0 (0 - 3) |
| S6-03 (323A) | EMOVR Independent PID Scale | Sets the scaling on the Emergency PID Feedback and Setpoint (if programmed) Analog Inputs. Note: • <i>S6-05</i> [EMOVR Independent PID Unit Digit] sets the resolution for this parameter. • <i>S6-04</i> [EMOVR Independent PID Unit] sets the units for this parameter. | 100.00 (0.10 - 600.00) |

7.12 S: Special Applications

| No. (Hex.) | Name | Description | Default (Range) |
|------------------|----------------------------------|---|-------------------------------|
| S6-04 (323B) | EMOVR Independent PID Unit | Sets the units displayed for S6-06 [EMOVR PID Setpoint] when S6-02 = 3 [Emergency Override Ref Selection = Independent PID Mode]. 0 : "WC: inches of water column 1 : PSI: pounds per square inch 2 : GPM: gallons/min 3 : °F: Fahrenheit 4 : ft³/min: cubic feet/min 5 : m³/h: cubic meters/hour 6 : L/h: liters/hour 7 : L/s: liters/sec 8 : bar: bar 9 : Pa: Pascal 10 : °C: Celsius 11 : m: meters 12 : ft: feet 13 : L/min: liters/min 14 : m³/min: cubic meters/min 15 : "Hg: Inch Mercury 16 : kPa: kilopascal 48 : %: Percent 49 : Custom(b5-68~70) 50 : None | 48 (0 - 50) |
| S6-05 (323C) | EMOVR Independent PID Unit Digit | Sets the number of digits for S6-06 [EMOVR PID Setpoint] when S6-02 = 3 [Emergency Override Ref Selection = Independent PID Mode]. 0 : No Decimal Places (XXXXX) 1 : One Decimal Places (XXXX.X) 2 : Two Decimal Places (XXX.XX) 3 : Three Decimal Places (XX.XXX) | 2 (0 - 3) |
| S6-06 (323D) RUN | EMOVR PID Setpoint | Sets the PID Setpoint when S6-02 = 3 [Emergency Override Ref Selection = Independent PID Mode]. Note: When S6-02 = 3: units and resolution are dependent on S6-04 [EMOVR Independent PID Unit] and S6-05 [EMOVR Independent PID Unit Digit]. Value is internally limited to 300% of S6-03 [EMOVR Independent PID Scale]. | 0.00 (0 - 600.00) |
| S6-07 (323E) | EMOVR Fault Suppression Mode | Sets the drive to let Emergency Override disable faults during operation. 0 : Fault Suppression 1 : Test Mode | 0 (0, 1) |
| S6-08 (323F) | EMOVR Drive Enable Input Mode | Sets whether the Drive Enable Input (if programmed) must be inactive (drive is disabled) for Emergency Override to function. 0 : Drive Enable Status Ignored 1 : EMOVR Run Only When Drive Disabled Note: You must program Drive Enable to a Digital Input for this parameter to have an effect. | 0 (0, 1) |
| S6-09 (3240) | Emergency Override Min Speed | When Emergency Override is active, the output frequency is lower-limited to this value. | 0.00 Hz (0.00 - 400.00 Hz) |
| S6-10 (3241) | Emergency Override Max Speed | When Emergency Override is active, the output frequency is upper-limited to this value. Note: Set this parameter to 0.00 Hz to disable the limit. | 0.00 Hz (0.00 - 400.00) |

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|---------------------------------|---|--------------------|
| S6-11 (3242) Expert | EMOVR Drive Protection Fault ON | Sets the bit to enable fault detection during Emergency Override. bit 0 : Uv1 - DC Bus Undervoltage bit 1 : CoF - Current Offset Fault bit 2 : Reserved bit 3 : Err - EEPROM Write Error bit 4 : Reserved bit 5 : Reserved bit 6 : oL2 - Drive Overload bit 7 : oPr - Operator Connection bit 8 : PF - Input Phase Loss bit 9 : Reserved bit 10 : Reserved bit 11 : oH - Heatsink Overheat bit 12 : oH1 - Heatsink Overheat bit 13 : OD - Output Disconnect bit 14 : FAn1 - Cooling Fan Fault bit 15 : ov2 - DC Bus Overvoltage 2 Note: The drive sets the bits in Hex. | 0 (0 - FFFF) |
| S6-12 (3243) Expert | EMOVR Motor Protection Fault ON | Sets the bit to enable fault detection during Emergency Override. bit 0 : LF - Output Phase Loss bit 1 : LF2 - Output Current Imbalance bit 2 : oH3 - Motor Overheat PTC Input bit 3 : oH4 - Motor Overheat PTC Input bit 4 : Reserved bit 5 : oL1 - Motor Overload bit 6 : oL3 - Overtorque Detection 1 bit 7 : oL4 - Overtorque Detection 2 bit 8 : oL7 - High Slip Braking Overload bit 9 : Reserved bit 10 : UL3 - Undertorque Detection 1 bit 11 : UL4 - Undertorque Detection 2 bit 12 : UL6 - Motor Underload bit 13 : Reserved bit 14 : oS - Overspeed bit 15 : dEv: Speed Deviation Note: The drive sets the bits in Hex. | 0 (0 - FFFF) |
| S6-13 (3244) Expert | EMOVR Option Fault ON | Sets the bit to enable fault detection during Emergency Override. bit 0 : bUS - Option Communication bit 1 : CE - Communication Error bit 2 : E5 - SI-T3 Watch Dog Timer bit 3 : EF0 - Option Card External Fault bit 4 : PE1 - PLC Fault 1 bit 5 : PE2 - PLC Fault 2 bit 6 : nSE - Node Setup Error bit 7 to 15 : Reserved Note: The drive sets the bits in Hex. | 0 (0 - FFFF) |
| S6-14 (3245) Expert | EMOVR Application 1 Fault ON | Sets the bit to enable fault detection during Emergency Override. bit 0 : EFx - External Faults bit 1 : Reserved bit 2 : HLCE - High Level Communications Error bit 3 : bAT - HOA Keypad Battery Voltage Low bit 4 : TiM - Keypad Time Not Set bit 5 : bCE - Bluetooth Communication Fault bit 6 : Reserved bit 7 : Reserved bit 8 : Reserved bit 9 : MSL - Net Master Lost bit 10 : VLTS - Thermostat Fault bit 11 to 15 : Reserved Note: The drive sets the bits in Hex. | 0 (0 - FFFF) |

7.12 S: Special Applications

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|----------------------------|---|----------------------------|
| S6-16 (3247) | EMOVR Customer Safety Mode | Sets the status for the customer safety input (when programmed) that must occur for Emergency Override to function. 0 : Customer Safety Ignored 1 : EMOVRRun Only When Safety OK 2 : EMOVRRun Only When Safety NOT OK Note: You must set one of the bypass control digital inputs to a safety [<i>Z2-0x = 22, 38-43</i>] for this parameter to have an effect. | 0 (0 - 2) |
| S6-17 (3248) | EMOVR BAS Interlock Mode | Sets the status for the BAS Interlock input (when programmed) that must occur for Emergency Override to function. 0 : BAS Interlock Ignored 1 : EMOVRRun Only When Interlock OK 2 : EMOVRRun When Interlock NOT OK Note: You must set one of the bypass control digital inputs to Run Interlock (BAS) [<i>Z2-0x = 23</i>] for this parameter to have an effect. | 0 (0 - 2) |
| S6-20 (324B) Expert | EMOVR Bypass Fault ON | Sets the bit to enable fault detection during Emergency Override. bit 0 : FB02 bit 1 : FB03 bit 2 : FB05 bit 3 : FB06 bit 4 : FB07 bit 5 : FB08 bit 6 : FB09 bit 7 : FB10 bit 8 : FB13 bit 9 : FB15 bit 10 : FB16 bit 11 : FB17 bit 12 : FB18 | 0 (0 - FFFF) |
| S6-23 (324E) | OV2 Detect Time | Sets the detection time of <i>ov2</i> [<i>DC Bus Overvoltage 2</i>] in 0.1 s increments. Note: Set this parameter to 0.0 s to disable <i>ov2</i> detection. | 10.0 s (0.0 - 1200.0 s) |

7.13 Y: Application Features

◆ Y1: Application Basics

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------------|---|-------------------------------|
| Y1-04 (3C03) RUN | Sleep Wake-up Level | Sets the level that feedback must be less than for the time set in <i>Y1-05 [Sleep Wake-up Level Delay Time]</i> to start the system. This level also sets the wake up level when the drive is in Sleep Mode. When <i>Y1-04 < 0</i> , the feedback level must decrease this amount to less than the setpoint. Note: <ul style="list-style-type: none">When PID operates in reverse mode, the feedback value must increase to more than the start level for the time set in <i>Y1-05</i> for the system to start.When <i>Y2-01 = 5 [Sleep Level Type = Output Frequency (non-PID)]</i>, the drive will ignore this parameter.Set this parameter to 0.0 to disable the function.Range is 0.00 to 99.99 with sign-bit "-" or "+" indicating Delta to Setpoint.Display unit and scaling change when the system units change. | 0.0 (-999.9 - +999.9) |
| Y1-05 (3C04) RUN | Sleep Wake-up Level Delay Time | Sets the drive to start the System again when the feedback decreases to less than <i>Y1-04 [Sleep Wake-up Level]</i> for the time set in this parameter. | 1 s (0 - 3600 s) |
| Y1-06 (3C05) RUN | Minimum Speed | Sets the minimum frequency at which the drive will run. The drive applies this setting to HAND and AUTO modes. Note: <ul style="list-style-type: none">The unit, decimal place, and setting range change when the <i>Y1-07 [Minimum Speed Units]</i> setting changes:<i>Y1-07 = 0 [Hz]</i>: The setting range is 0.0 Hz to <i>E1-04</i> Hz.<i>Y1-07 = 1 [RPM]</i>: The setting range is 0 RPM to (<i>E1-04</i> × 60) RPM. | 0.0 Hz Determined by Y1-07 |
| Y1-07 (3C06) | Minimum Speed Units | Sets the units and decimal place for <i>Y1-06 [Minimum Speed]</i> . 0 : Hz 1 : RPM Note: Changing <i>Y1-07</i> will set <i>Y1-06 [Minimum Speed]</i> to the default value. | 0 (0, 1) |
| Y1-08 (3C07) RUN | Low Feedback Level | Sets the lower detection level for the PID feedback. Note: <ul style="list-style-type: none">Unit and decimal place change when the system units change.Range is 0.00 to 99.99 with sign-bit "-" indicating Delta to Setpoint. | 0.00% (0.00 - 99.99%) |
| Y1-09 (3C08) RUN | Low Feedback Lvl Fault Dly Time | Sets the delay time for the drive to detect an <i>LFB [Low Feedback Sensed]</i> fault after the feedback level decreases to less than the value set in <i>Y1-08 [Low Feedback Level]</i> . Note: Set <i>Y1-10 = 0 [Low Feedback Selection = Fault (and Digital Output)]</i> to enable this parameter. | 10 s (0 - 3600 s) |
| Y1-10 (3C09) | Low Feedback Selection | Sets the drive response when the feedback decreases to less than <i>Y1-08 [Low Feedback Level]</i> for longer than the time set in <i>Y1-09 [Low Feedback Lvl Fault Dly Time]</i> . 0 : Fault (and Digital Output) 1 : Alarm (and Digital Output) 2 : Digital Output Only | 0 (0 - 2) |
| Y1-11 (3C0A) RUN | High Feedback Level | Sets the upper detection level for the PID feedback. Note: <ul style="list-style-type: none">Unit and decimal place change when the system units change.Range is 0.00 to 99.99 with sign-bit "+" indicating Delta to Setpoint. | 0.00% (0.00 - 99.99%) |
| Y1-12 (3C0B) RUN | High Feedback Lvl Fault Dly Time | Sets the delay time between when the drive detects high feedback until the drive faults on an <i>HFB [High Feedback Sensed]</i> fault. Note: This parameter is effective only when <i>Y1-13 = 0 [High Feedback Selection = Fault (and Digital Output)]</i> . | 5 s (0 - 3600 s) |
| Y1-13 (3C0C) | High Feedback Selection | Sets the drive response when the feedback increased to more than <i>Y1-11 [High Feedback Level]</i> for longer than the time set in <i>Y1-12 [High Feedback Lvl Fault Dly Time]</i> . 0 : Fault (and Digital Output) 1 : Alarm (and Digital Output) 2 : Digital Output Only | 0 (0 - 2) |
| Y1-14 (3C0D) RUN | Feedback Hysteresis Level | Sets the hysteresis level for low and high level feedback detection. Note: Unit and decimal place change when the system units change. | 0.0% (0.0 - 10.00%) |

7.13 Y: Application Features

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|-------------------------------|--|-------------------------------|
| Y1-15 (3C0E) RUN | Maximum Setpoint Difference | Sets a percentage of difference between the setpoint and the feedback. The difference must be more than this value for the time set in Y1-16 [Not Maintaining Setpoint Time] to trigger the drive response set in Y1-17 [Not Maintaining Setpoint Sel]. Note: • Unit and decimal place change when the system units change. • If there is a fault, the drive will coast to a stop. • Set this parameter to 0.0 to disable the function. • This function is only active during run when in Auto Mode. | 0.0% (0.0 - 6000.0%) |
| Y1-16 (3C0F) RUN | Not Maintaining Setpoint Time | Sets the delay time before a Setpoint Not Met condition occurs. The drive must detect the setpoint difference set in Y1-15 [Maximum Setpoint Difference] before the timer will start. Note: Set Y1-15 = 0 [Maximum Setpoint Difference = 0] to disable this function. | 60 s (0 - 3600 s) |
| Y1-17 (3C10) | Not Maintaining Setpoint Sel | Sets the drive response when the feedback increases to more or decreases to less than the setpoint for more than the amount set in Y1-15 [Maximum Setpoint Difference]. 0 : Fault (and Digital Output) 1 : Alarm (and Digital Output) 2 : Digital Output Only | 0 (0 - 2) |
| Y1-18 (3C11) | Prime Loss Detection Method | Sets the units and quantity that the drive will use to determine LOP [Loss of Prime]. 0 : Current (A) 1 : Power (kW) 2 : Torque (%) | 0 (0 - 2) |
| Y1-19 (3C12) RUN | Prime Loss Level | Sets the level to detect the LOP [Loss of Prime] in the pump when in Auto or Sleep Boost Mode. | 0.0 (0.0 - 1000.0) |
| Y1-20 (3C13) RUN | Prime Loss Time | Sets the delay time before the drive detects an LOP [Loss of Prime] condition. The timer starts when the drive detects the conditions in Y1-18 [Prime Loss Detection Method] and Y1-19 [Prime Loss Level]. | 20 s (0 - 600 s) |
| Y1-21 (3C14) | Prime Loss Activation Freq | Sets the frequency level above which the drive enables Loss of Prime detection. | 0.0 Hz (0.0 - 400.0) |
| Y1-22 (3C15) | Prime Loss Selection | Sets the drive response when the drive is in the Loss of Prime condition. 0 : Fault (and Digital Output) 1 : Alarm (and Digital Output) 2 : Digital Output Only | 0 (0 - 2) |
| Y1-23 (3C16) | Prime Loss Max Restart Time | Sets the time in minutes that the drive will wait before it tries a restart after a restart fails or after it does not do a restart because of a fault. | 0.2 min (0.2 - 6000.0 min) |
| Y1-40 (3C27) RUN | Maximum Speed | Sets the maximum speed. Note: This parameter is not effective when Y1-40 = 0.0 Hz or Y1-40 > E1-04 [Maximum Output Frequency] × d2-01 [Frequency Reference Upper Limit]. | 0.0 Hz (0.0 - 416.0) |

◆ Y2: PID Sleep and Protection

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|------------------|---|-----------------------|
| Y2-01 (3C64) | Sleep Level Type | Sets the data source that the drive uses to know when to activate the Sleep Function. 0 : Output Frequency 1 : Output Current 2 : Feedback 3 : Output Speed (RPM) 5 : Output Frequency (non-PID) Note: • Feedback depends on PID direction operation. • When the Sleep Function is active, the keypad will show the "Sleep" Alarm. | 5 (0 - 5) |
| Y2-02 (3C65) RUN | Sleep Level | Sets the level that the level type set in Y2-01 [Sleep Level Type] must be at for the time set in Y2-03 [Sleep Delay Time] for the drive to enter Sleep Mode. Note: • When you set this parameter to 0.0, this function will not be active. • This function is active only when the drive operates in AUTO Mode. • When Y2-01 = 5 [Output Frequency (non-PID)], the drive will disable the Sleep function when you set this parameter to 0.0. • When Y2-01 ≠ 5, the drive will set the sleep level to the largest value from d2-02 [Frequency Reference Lower Limit], Y1-06 [Minimum Speed], and Y4-12 [Thrust Frequency] when you set this parameter to 0.0. | 0.0 (0.0 - 6000.0) |

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|------------------------------|---|----------------------------|
| Y2-03 (3C66) RUN | Sleep Delay Time | Sets the delay time before the drive enters Sleep Mode when the drive is at the sleep level set in Y2-02 [Sleep Level]. | 5 s (0 - 3600 s) |
| Y2-04 (3C67) RUN | Sleep Activation Level | Sets the level above which the output frequency must increase to activate the Sleep Function when Y2-01 = 0, 3, or 5 [Sleep Level Type = Output Frequency, Output Speed (RPM), or Output Frequency (non-PID)]. Note: When you set this parameter to 0.0, this function will not be active, and the Sleep Function will activate above the minimum speed (largest value from d2-02 [Frequency Reference Lower Limit], Y1-06 [Minimum Speed], and Y4-12 [Thrust Frequency]). | 0.0 (0.0 - 6000.0) |
| Y2-05 (3C68) RUN | Sleep Boost Level | Sets the quantity of boost that the drive applies to the setpoint before it goes to sleep. Note: Set this parameter to 0.00 to disable Sleep Boost Function. | 0.00% (0.00 - 600.00%) |
| Y2-06 (3C69) RUN | Sleep Boost Hold Time | Sets the length of time that the drive will keep the boosted pressure before it goes to sleep. | 5.0 s (0.5 - 160.0 s) |
| Y2-07 (3C6A) RUN | Sleep Boost Max Time | Sets the length of time that the system (feedback) has to reach the boosted setpoint. The system must reach the boosted setpoint in the time set in this parameter, or it will go to sleep. | 20.0 s (1.0 - 160.0 s) |
| Y2-08 (3C6B) RUN | Delta Feedback Drop Level | Sets the level of the PID Error (set-point minus feedback) to deactivate the Sleep Mode operation. Note: Set this parameter to 0.00 to disable the function. | 0.00% (0.00 - 600.00%) |
| Y2-09 (3C6C) RUN | Feedback Drop Detection Time | Sets the time during which the software monitors the feedback to detect a flow/no-flow condition. Refer to Y2-08 [Delta Feedback Drop Level] for more information. | 10.0 s (0.0 - 3600.0 s) |
| Y2-23 (3C7A) RUN | Anti-No-Flow Bandwidth | Sets the quantity of PI error bandwidth that the drive uses to detect an Anti- No-Flow condition. A setting of 0.00% disables Anti-No-Flow detection. Note: Do not set this parameter value too high, because operation can become unstable. | 0.00% (0.00 - 2.00%) |
| Y2-24 (3C7B) RUN | Anti-No-Flow Detection Time | Sets the time delay before the drive starts the increased deceleration rate after it detects Anti-No-Flow. | 10.0 s (1.0 - 60.0 s) |
| Y2-25 (3C7C) RUN | Anti-No-Flow Release Level | Sets the amount below the setpoint which the feedback must decrease before the drive will disengage Anti-No-Flow and return to normal PI operation. Note: The display unit and scaling change when the System Units change. | 0.30% (0.00 - 10.00%) |

◆ Y4: Application Advanced

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------------------|---|-------------------------------|
| Y4-01 (3CFA) RUN | Pre-Charge Level | Sets the level at which the drive will activate the pre-charge function when the drive is running at the frequency set in Y4-02 [Pre-Charge Frequency]. Note: The drive will stop when one of these conditions is true: • The feedback level increases to more than Y4-01 • The pre-charge time set in Y4-03 [Pre-Charge Time] expires | 0.00% (0.00 - 600.00%) |
| Y4-02 (3CFB) RUN | Pre-Charge Frequency | Sets the frequency at which the pre-charge function will operate. | 0.0 Hz (0.0 - 400.0 Hz) |
| Y4-03 (3CFC) RUN | Pre-Charge Time | Sets the length of time that the Pre-Charge function will run. Note: Set this parameter to 0.0 to disable the function. | 0.0 min (0.0 - 3600.0 min) |
| Y4-05 (3CFE) RUN | Pre-Charge Loss of Prime Level | Sets the level at which the drive will detect loss of prime in the pump. | 0.0 A (0.0 - 1000.0 A) |
| Y4-11 (3D04) RUN | Thrust Acceleration Time | Sets the time at which the drive output frequency will ramp up to the reference frequency set in Y4-12 [Thrust Frequency]. | 1.0 s (0.0 - 600.0 s) |

7.13 Y: Application Features

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------------|--|-----------------------------|
| Y4-12 (3D05) RUN | Thrust Frequency | Sets the Thrust Frequency that the drive will use to know which acceleration and deceleration time to use. The drive will accelerate to this frequency in the Y4-11 [Thrust Acceleration Time] time and decelerate from this frequency in the Y4-13 [Thrust Deceleration Time] time. | 0.0 Hz (0.0 - 400.0 Hz) |
| Y4-13 (3D06) RUN | Thrust Deceleration Time | Sets the length of time necessary for the drive to go from the Thrust Frequency in Y4-12 [Thrust Frequency] to stop when Thrust Mode is active. | 5.0 s (0.0 - 600.0 s) |
| Y4-18 (3D0B) RUN | Differential Level | Sets the maximum difference that the drive will allow when it subtracts the Differential Feedback from the Primary PID Feedback. Note: • The drive will respond as specified by the setting in Y4-20 [Differential Level Detection Selection] when the difference increases to more than the value set in this parameter for the time set in Y4-19 [Differential Level Detection Time]. • Set this parameter to 0.00 to disable Differential Feedback Detection. | 0.00% (-99.99 - +99.99%) |
| Y4-19 (3D0C) RUN | Differential Lvl Detection Time | Sets the length of time that the difference between PID Feedback and the Differential Feedback must be more than Y4-18 [Differential Level] before the drive will respond as specified by Y4-20 [Differential Level Detection Selection]. | 10 s (0 - 3600 s) |
| Y4-20 (3D0D) RUN | Differential Level Detection Sel | Sets the drive response during a Differential Level Detected condition. 0 : Fault (and Digital Out) 1 : Alarm (and Digital Out) 2 : Digital Out Only | 0 (0 - 2) |
| Y4-22 (3D0F) RUN | Low City On-Delay Time | Sets the length of time that the drive will wait to stop when the drive detects a Low City Pressure condition. | 10 s (1 - 1000 s) |
| Y4-23 (3D10) RUN | Low City Off-Delay Time | Sets the length of time that the drive will wait to start again after you clear a Low City Pressure condition. | 5 s (0 - 1000 s) |
| Y4-24 (3D11) RUN | Low City Alarm Text | Sets the alarm message to show on the keypad when the drive detects a Low City Pressure condition. 0 : Low City Pressure 1 : Low Suction Pressure 2 : Low Water in Tank | 0 (0 - 2) |
| Y4-36 (3D1D) RUN | Pressure Reached Exit Conditions | Sets how the digital output responds to Feedback changes after it activates. 0 : Hysteresis Above & Below 1 : Hysteresis 1-Way | 1 (0, 1) |
| Y4-37 (3D1E) RUN | Pressure Reached Hysteresis Lvl | Sets the hysteresis level that will cause the drive to exit the Pressure Reached condition. | 0.30% (0.1 - 10.00%) |
| Y4-38 (3D1F) RUN | Pressure Reached On Delay Time | Sets the length of time that the drive will wait before it activates the Pressure Reached condition. | 1.0 s (0.1 - 60.0 s) |
| Y4-39 (3D20) RUN | Pressure Reached Off Delay Time | Sets the length of time that the drive will wait before it deactivates the Pressure Reached condition. | 1.0 s (0.1 - 60.0 s) |
| Y4-40 (3D21) RUN | Pressure Reached Detection Sel | Sets the drive status that triggers the Pressure Reached Detection digital output. 0 : Always 1 : Drive Running 2 : Run Command | 0 (0 - 2) |
| Y4-41 (3D22) RUN | Diff Lvl Src Fdbk Backup Select | Sets the function to enable or disable <i>Differential Level Source</i> [H3-xx = 2D] as the backup transducer if there is a failure with the primary PID Feedback transducer [H3-xx = B] and the PID Feedback Backup transducer [H3-xx = 2A] is not available. 0 : Disabled 1 : Enabled | 0 (0, 1) |

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------------|---|------------------|
| Y4-42 (3D23) | Output Disconnect Detection Sel | This parameter applies only when in Drive Mode. It sets the drive response if the connection between the drive and the motor is disconnected. 0 : Disabled 1 : Alarm - Speed Search 2 : Alarm - Start at Zero 3 : Fault Note: 1. Loss Of Load [Z1-31 to Z1-36], Load Verify [Z1-53], and Bypass Energy Savings [Z1-16] can interfere with the correct operation of Output Disconnect Detection. 2. When the Output Disconnect is active, the drive internally disables Output Phase Loss Detection of more than one phase. 3. The Output Current Limit function is not active when operating in Bypass Mode. | 0 (0 - 3) |
| Y4-43 (3D24) | Output Disconnect Inject Current | Sets the level of DC injection current during output disconnect as a percentage of the drive rated current. | 30% (5 - 50%) |

◆ YA: Preset Setpoint

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|------------|--|-------------------------|
| YA-01 (3E58) RUN | Setpoint 1 | Sets the PID Setpoint when $b1-01 = 0$ [Frequency Reference Selection 1 = Keypad or Multi-Speed Selection]. Note: Parameters $b5-46$ [PID Unit Display Selection], $b5-38$ [PID User Unit Display Scaling], and $b5-39$ [PID User Unit Display Digits] set the unit, range, and resolution. | 0.00 (0.00 - 600.00) |
| YA-02 (3E59) RUN | Setpoint 2 | Sets the PID Setpoint as specified by the Multi-Setpoint digital inputs. Note: Parameters $b5-46$ [PID Unit Display Selection], $b5-38$ [PID User Unit Display Scaling], and $b5-39$ [PID User Unit Display Digits] set the unit, range, and resolution. | 0.00 (0.00 - 600.00) |
| YA-03 (3E5A) RUN | Setpoint 3 | Sets the PID Setpoint as specified by the Multi-Setpoint digital inputs. Note: Parameters $b5-46$ [PID Unit Display Selection], $b5-38$ [PID User Unit Display Scaling], and $b5-39$ [PID User Unit Display Digits] set the unit, range, and resolution. | 0.00 (0.00 - 600.00) |
| YA-04 (3E5B) RUN | Setpoint 4 | Sets the PID Setpoint as specified by the Multi-Setpoint digital inputs. Note: Parameters $b5-46$ [PID Unit Display Selection], $b5-38$ [PID User Unit Display Scaling], and $b5-39$ [PID User Unit Display Digits] set the unit, range, and resolution. | 0.00 (0.00 - 600.00) |

◆ YC: Foldback Features

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|-----------------------------|--|---------------------------|
| YC-01 (3EBC) | Output Current Limit Select | Sets the function to enable or disable the output current regulator. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| YC-02 (3EBD) RUN | Current Limit | Sets the current limit. Note: Value is internally limited to 300% of the drive rated current set in $n9-01$ [Inverter Rated Current]. | 0.0 A (0.0 - 1000.0 A) |

◆ YF: PI Auxiliary Control

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|---------------------------------|--|-------------------------|
| YF-01 (3F50) | PI Aux Control Selection | Sets the PI Auxiliary Control function. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| YF-02 (3F51) RUN | PI Aux Control Transducer Scale | Sets the full scale (10 V or 20 mA) output of the pressure transducer connected to the analog input terminal programmed for $H3-xx = 27$ [PI Aux Control Feedback Level]. Note: Parameters $YF-21$ [PI Aux Ctrl Level Unit Selection] and $YF-22$ [PI Aux Level Decimal Place Pos] set the unit and resolution. | 145.0 (1.0 - 6000.0) |

7.13 Y: Application Features

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------------|---|-----------------------------------|
| YF-03 (3F52) RUN | PI Aux Control Setpoint | Sets the level to which the drive will try to regulate. Note: Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | 20.0 PSI (0.0 - 6000.0) |
| YF-04 (3F53) RUN | PI Aux Control Minimum Level | Sets the level below which the drive must be for longer than <i>YF-05 [PI Aux Control Sleep Delay Time]</i> before the drive goes to sleep and turns off all lag pumps. Note: • Set this parameter to 0.0 to disable the function. • Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | 10.0 PSI (0.0 - 6000.0) |
| YF-05 (3F54) RUN | PI Aux Control Sleep Delay Time | Sets the length of time that the drive will delay before it goes to sleep after the level is less than <i>YF-04 [PI Aux Control Minimum Level]</i> (when <i>YF-23 = 1 [PI Aux Ctrl Output Level Select = Inverse Acting]</i>) or more than <i>YF-24 [PI Auxiliary Ctrl Maximum Level]</i> (when <i>YF-23 = 0 [Direct Acting]</i>). | 5 s (0 - 3600 s) |
| YF-06 (3F55) RUN | PI Aux Control Wake-up Level | Sets the level to wake up the drive when the drive after <i>YF-04 [PI Aux Control Minimum Level]</i> or <i>YF-24 [PI Auxiliary Ctrl Maximum Level]</i> put the drive to sleep. Note: • Parameter <i>YF-23 [PI Aux Ctrl Output Level Select]</i> sets the condition to wake up the drive. – <i>YF-23 = 0 [Direct Acting]</i> : The PI Aux Feedback must be less than the level set in this parameter for longer than the time set in <i>YF-07</i> to wake up. – <i>YF-23 = 1 [Inverse Acting]</i> : The PI Aux Feedback must be more than the level set in this parameter for longer than the time set in <i>YF-07 [PI Aux Control Wake-up Time]</i> to wake up. • Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | 30.0 PSI (-999.9 - +999.9 PSI) |
| YF-07 (3F56) | PI Aux Control Wake-up Time | Sets the time to wake up the drive when the drive after <i>YF-04 [PI Aux Control Minimum Level]</i> or <i>YF-24 [PI Auxiliary Ctrl Maximum Level]</i> put the drive to sleep. Note: Parameter <i>YF-23 [PI Aux Ctrl Output Level Select]</i> sets the condition to wake up the drive. • <i>YF-23 = 0 [Direct Acting]</i> : The PI Aux Feedback must be less than the level set in <i>YF-06</i> for longer than the time set in <i>YF-07</i> to wake up. • <i>YF-23 = 1 [Inverse Acting]</i> : The PI Aux Feedback must be more than the level set in <i>YF-06 [PI Aux Control Wake-up Level]</i> for longer than the time set in <i>YF-07</i> to wake up. | 1 s (0 - 3600 s) |
| YF-08 (3F57) RUN | PI Aux Control Minimum Speed | Sets the minimum speed at which the drive can run when the PI Auxiliary Control has an effect on the output speed. Note: The drive will use <i>Y1-06 [Minimum Speed]</i> and <i>Y4-12 [Thrust Frequency]</i> as the minimum speed when PI Aux Control does not have an effect on the output speed or when you set <i>YF-08 < Y1-06 and Y4-12</i> . | 0.00 Hz (0.00 - 400.00 Hz) |
| YF-09 (3F58) RUN | PI Aux Control Low Level Detect | Sets the level below which the drive must be for longer than <i>YF-10 [PI Aux Control Low Lvl Det Time]</i> to respond as specified by <i>YF-11 [PI Aux Control Low Level Det Sel]</i> . Note: • Set this parameter to 0.0 to disable the function. • Parameter <i>YF-10</i> only applies to when <i>YF-11 = 2 and 3 [Fault and Auto-Restart (time set by YF-15)]</i> . • Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | 0.0 PSI (-999.9 - +999.9 PSI) |
| YF-10 (3F59) RUN | PI Aux Low Level Detection Time | Sets the length of time that the PI Aux Feedback must be less than <i>YF-09 [PI Aux Control Low Lvl Detection]</i> to trigger a drive response when <i>YF-11 = 2 and 3 [PI Aux Control Low Level Det Sel = Fault and Auto-Restart (time set by YF-15)]</i> . | 0.1 s (0.0 - 300.0 s) |
| YF-11 (3F5A) | PI Aux Control Low Level Det Sel | Sets drive response when the PI Aux Feedback decreases to less than <i>YF-09 [PI Aux Control Low Lvl Detection]</i> for longer than <i>YF-10 [PI Aux Control Low Lvl Det Time]</i> . 0 : No Display 1 : Alarm Only 2 : Fault 3 : Auto-Restart (time set by YF-15) Note: • Set <i>YF-01 = 1 [PI Aux Control Selection = Enabled]</i> and <i>YF-09 [PI Aux Control Low Level Detect] > 0</i> to enable PI Aux Low Level Detection. • Parameter <i>YF-10</i> only applies when <i>YF-11 = 2 or 3</i> . | 1 (0 - 3) |
| YF-12 (3F5B) RUN | PI Aux Control High Level Detect | Sets the value above which the level must be for longer than <i>YF-13 [PI Aux High Level Detection Time]</i> to respond as specified by <i>YF-14 [PI Aux Hi Level Detection Select]</i> . Note: • Set this parameter to 0.0 to disable the function. • Parameter <i>YF-13</i> only applies to when <i>YF-14 = 2 and 3 [Fault and Auto-Restart (time set by YF-15)]</i> . • Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | 0.0 PSI (-999.9 - +999.9 PSI) |
| YF-13 (3F5C) RUN | PI Aux High Level Detection Time | Sets the length of time that the level must be more than <i>YF-12 [PI Aux Control High Level Detect]</i> before the drive will respond when <i>YF-14 = 2, 3 [PI Aux Hi Level Detection Select]</i> . | 0.1 s (0.0 - 300.0 s) |

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|----------------------------------|--|-------------------------------|
| YF-14 (3F5D) | PI Aux Control Hi Level Det Sel | Sets the drive response when the PI Aux Feedback increases to more than the YF-12 [PI Aux Control High Level Detect] level for longer than the time set in YF-13 [PI Aux High Level Detection Time]. 0 : NoDisplay (Digital Output Only) 1 : Alarm Only 2 : Fault 3 : Auto-Restart (time set by YF-15) Note: • Set YF-01 = 1 [PI Aux Control Selection = Enabled] and YF-12 [PI Aux Control High Level Detect] > 0 to enable PI Aux High Level Detection. • Parameter YF-13 only applies when YF-14 = 2 or 3 | 1 (0 - 3) |
| YF-15 (3F5E) | PI Aux Level Detect Restart Time | Sets the length of time the drive will wait before it tries an Auto-Restart of LOAUX [Low PI Aux Feedback Level] or HIAUX [High PI Aux Feedback Level] fault. | 5.0 min (0.1 - 6000.0 min) |
| YF-16 (3F5F) RUN | PI Auxiliary Control P Gain | Sets the proportional gain for the suction pressure control. | 2.00 (0.00 - 25.00) |
| YF-17 (3F60) RUN | PI Auxiliary Control I Time | Sets the integral time for the suction pressure control. Note: Set this parameter to 0.0 to disable the integrator. | 5.0 s (0.0 - 360.0 s) |
| YF-18 (3F61) | PI Aux Control Detect Time Unit | Sets the time unit for YF-10 [PI Aux Control Low Lvl Det Time] and YF-13 [PI Aux High Level Detection Time]. 0 : Minutes (min) 1 : Seconds (sec) | 1 (0, 1) |
| YF-19 (3F62) | PI Aux Ctrl Feedback WireBreak | Sets how the analog input selected for PI Aux Feedback will respond when it is programmed to receive a 4 mA to 20 mA signal and the signal is lost. 0 : Disabled 1 : Alarm Only 2 : Fault (no retry, coast to stop) | 2 (0 - 2) |
| YF-20 (3F63) | PI Aux Main PI Speed Control | Sets if the PI Auxiliary Controller has an effect on output speed. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| YF-21 (3F64) | PI Aux Ctrl Level Unit Selection | Set the units shown for the PI Aux Level parameters and monitors. 0 : "WC: inches of water column 1 : PSI: pounds per square inch 2 : GPM: gallons/min 3 : °F: Fahrenheit 4 : ft³/min: cubic feet/min 5 : m³/h: cubic meters/hour 6 : L/h: liters/hour 7 : L/s: liters/sec 8 : bar: bar 9 : Pa: Pascal 10 : °C: Celsius 11 : m: meters 12 : ft: feet 13 : L/min: liters/min 14 : m³/min: cubic meters/min 15 : "Hg: Inch Mercury 16 : kPa: kilopascal 48 : %: Percent 49 : Custom (YF-32 ~ 34) 50 : None | 1 (0 - 50) |
| YF-22 (3F65) | PI Aux Level Decimal Place Pos | Sets the number of decimal places for the PI Aux Level parameters and monitors. 0 : No Decimal Places (XXXXX) 1 : One Decimal Places (XXXX.X) 2 : Two Decimal Places (XXX.XX) 3 : Three Decimal Places (XX.XXX) | 1 (0 - 3) |
| YF-23 (3F66) | PI Aux Ctrl Output Level Select | Sets the PI Auxiliary Controller to be Direct-acting or Inverse-acting. 0 : Direct Acting 1 : Inverse Acting | 1 (0, 1) |

7.13 Y: Application Features

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|---------------------------------|--|----------------------------------|
| YF-24 (3F67) RUN | PI Auxiliary Ctrl Maximum Level | Sets the maximum level for PI Auxiliary Control. When the level is more than this setting for longer than <i>YF-05 [PI Aux Control Sleep Delay Time]</i> , the drive will go to sleep and turn off all lag drives. Note: • Set this parameter to 0.0 to disable the function. • Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | 0.0 PSI (0.0 - 6000.0 PSI) |
| YF-25 (3F68) RUN | PI Aux Control Activation Level | Sets the level to activate the PI Auxiliary Control. Note: • The drive response changes when the <i>YF-23 [PI Aux Ctrl Output Level Select]</i> setting changes. – <i>YF-23 = 0 [Direct Acting]</i> : When the PI Aux Feedback level is more than this setting for longer than <i>YF-26 [PI Aux Control Activation Delay]</i> , the drive will activate the PI Auxiliary Control to control the output frequency. – <i>YF-23 = 1 [Inverse Acting]</i> : When the PI Aux Feedback level is less than this setting for longer than <i>YF-26</i> , the drive will activate PI Auxiliary Control to control the output frequency. • When you set this parameter to 0.0 PSI, PI Auxiliary Control is always enabled. • Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | 0.0 PSI (0.0 - 6000.0 PSI) |
| YF-26 (3F69) RUN | PI Aux Control Activation Delay | Sets the delay time to activate the PI Auxiliary Control. Note: • The drive response changes when the <i>YF-23 [PI Aux Ctrl Output Level Select]</i> setting changes. – <i>YF-23 = 0 [Direct Acting]</i> : When the PI Aux Feedback level is more than <i>YF-25 [PI Aux Control Activation Level]</i> for longer than this time, the drive will activate the PI Auxiliary Control to control the output frequency. – <i>YF-23 = 1 [Inverse Acting]</i> : When the PI Aux Feedback level is less than <i>YF-25</i> for longer than this time, the drive will activate PI Auxiliary Control to control the output frequency. • When you set this parameter to 0.0 PSI, PI Auxiliary Control is always enabled. | 2 s (0 - 3600 s) |
| YF-32 (3F6F) | PI Aux Custom Unit Character 1 | Sets the first character of the PI Aux custom unit display when <i>YF-21 = 49 [PI Aux Ctrl Level Unit Selection = Custom (YF-32 ~ 34)]</i> . | 41 (20 - 7A) |
| YF-33 (3F70) | PI Aux Custom Unit Character 2 | Sets the second character of the PI Aux custom unit display when <i>YF-21 = 49 [PI Aux Ctrl Level Unit Selection = Custom (YF-32 ~ 34)]</i> . | 41 (20 - 7A) |
| YF-34 (3F71) | PI Aux Custom Unit Character 3 | Sets the third character of the PI Aux custom unit display when <i>YF-21 = 49 [PI Aux Ctrl Level Unit Selection = Custom (YF-32 ~ 34)]</i> . | 41 (20 - 7A) |
| YF-35 (3F72) | PI Aux Minimum Transducer Scale | Sets the minimum scale output of the pressure transducer that is connected to the terminal set for <i>H3-xx = 27 [MFAI Function Selection = PI Auxiliary Control Feedback]</i> . Note: • To enable this parameter, set it to less than <i>YF-02 [PI Aux Control Transducer Scale]</i> . If you set it to more than <i>YF-02</i> , it will disable the PI Auxiliary Feedback (set to 0). • Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | 0.0 PSI (-999.9 - +999.9 PSI) |

7.14 Z: Bypass Parameters

◆ Z1: Bypass Control System

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|---------------------------------|--|---------------------------------|
| Z1-05 (85CA) | Auto Transfer To Bypass | When the drive is running and there is a drive fault, operation will switch to Bypass Mode. When you remove the fault, the operation will go back to Drive Mode 0 : Disabled 1 : Enabled | 0 (0, 1) |
| Z1-06 (85CB) | Power Up Mode | Sets the mode of bypass control at power-up. 0 : OFF-DRIVE 1 : AUTO-DRIVE 3 : AUTO-BYPASS 5 : Powerup HOA Memory | 1 (0 - 5) |
| Z1-10 (85CF) | Emergency Override Transfer | Enables and disables the function to auto transfer to EMOV bypass if the drive declares a fault when the bypass is running in EMOV drive. 0 : Disabled 1 : Enabled | 1 (0, 1) |
| Z1-11 (85D0) | Motor AND/OR Function | - 0 : Disabled 1 : Always Motor 1 2 : Always Motor 2 3 : Always Motor 1 AND 2 4 : OR in HAND and AUTO 5 : MOTOR 1 in HAND OR in AUTO 6 : MOTOR 2 in HAND OR in AUTO 7 : AND/OR in HAND and AUTO 8 : MOTOR 1 in HAND AND/OR in AUTO 9 : MOTOR 2 in HAND AND/OR in AUTO 10 : MOTOR 1,2 in HAND AND/OR in AUTO | 0 (0 - 10) |
| Z1-12 (85D1) | Run Delay Time | When the Run command is issued, the drive will run at speed set in Z1-14 [Run Delay Frequency Reference]. After the time set in this parameter, the frequency reference will return to its programmed source (b1-01 or HAND frequency reference). | 0.0 s (0.0 to 300.0 s) |
| Z1-13 (85D2) | Pre Interlock Run Select | Determines if the drive will run at a preset speed when the BAS Interlock Digital Input is open and a Run command is present. 0 : Disabled 1 : Enabled (DRIVE Mode) 1 : Enabled (BYPASS Mode) | 0 (0, 1) |
| Z1-14 (85D3) | Run Delay Frequency Reference | Sets the frequency that the bypass uses when it delays the Run command. | 60.00 Hz (0.00 - Max. Freq.) |
| Z1-15 (85D4) | Interlock Wait Time | When you enter a Run command, it asserts the damper actuator output. When you program an input for Interlock and the time set to this parameter expires before the Interlock input activates, it will trigger a fault. Note: Set this parameter to 0.0 s to disable this function. | 0.0 s (0.0 - 300.0 s) |
| Z1-16 (85D5) | Energy Savings Mode | Enables the contactor-based Energy Savings function and determines which conditions must be met before the bypass will enter into Energy Savings Mode. 0 : Disabled 1 : Frequency 2 : Frequency + Current Note: If the motor is running in reverse, Energy Savings will not function. | 0 (0 - 2) |
| Z1-17 (85D6) | Energy Savings Frequency Ref | Both frequency reference and output frequency must be within the window defined by this parameter, Z1-19 [Energy Savings Fref Deadband], and Z1-20 [Energy Savings Out Freq Deadband] for Energy Savings operation. | 60.00 Hz (0.00 - Max. Freq.) |
| Z1-18 (85D7) | Energy Savings Output Cur Level | Drive output current must be in the window defined by this parameter and Z1-21 [Energy Savings Out Cur Deadband] to enter Energy Savings Mode. | 0.0% (0.0 - 100.0%) |
| Z1-19 (85D8) | Energy Savings Fref Deadband | Used with Z1-17 [Energy Savings Frequency Ref] to set when to enter and exit Energy Savings Mode. Note: Units, default, and range are different for different o1-03 [Frequency Display Unit Selection] values. | 0.50 Hz (0.00 - 5.00 Hz) |

7.14 Z: Bypass Parameters

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|--|--------------------------------|
| Z1-20 (85D9) | Energy Savings Out Freq Deadband | Used with Z1-17 [Energy Savings Frequency Ref] to set when to enter Energy Savings Mode. Note: Units, default, and range are different for different o1-03 [Frequency Display Unit Selection] values. | 0.50 Hz (0.00 - 5.00 Hz) |
| Z1-21 (85DA) | Energy Savings Out Cur Deadband | Used with Z1-18 [Energy Savings Output Cur Level] to set when to enter Energy Savings Mode. | 15.0% (0.0 - 30.0%) |
| Z1-22 (85DB) | Energy Savings Mode Time | Sets the length of time that all conditions must be in the set limits before transferring into Energy Savings Mode. | 30 s (10 - 3600 s) |
| Z1-23 (85DC) | Energy Savings Freq Ref Increase | Sets the value to add to the drive Frequency Reference when transferring to Bypass Energy Savings Mode. WARNING! Sudden Movement Hazard. This parameter can cause operation higher than the E1-04 [Maximum Output Frequency] setting of the drive. Note: Units, default, and range are different for different o1-03 [Frequency Display Unit Selection] values. | 6.00 Hz (0.00 - 10.00 Hz) |
| Z1-24 (85DD) | Contactor Open Delay | Sets the time to delay after commanding the drive output contactor K2 or bypass contactor K3 or 2-Motor OR/AND contactors K4 and K5 to open to let the contacts open. | 0.2 s (0.0 - 5.0 s) |
| Z1-25 (85DE) | Contactor Close Delay | Sets the time to delay after commanding the drive output contactor K2 or bypass contactor K3 or 2-Motor OR/AND contactors K4 and K5 to close to let the contacts close. | 0.2 s (0.0 - 5.0 s) |
| Z1-27 (85E0) | Brownout Voltage Level | Sets the voltage level below which is a brownout condition. Note: Voltage level is measured on the output of the built-in 120 VAC control transformer. | 98 V (0 - 150 V) |
| Z1-28 (85E1) | Brownout Detection Time | Sets the length of time that the Bypass voltage must be less than the Brownout Voltage Level before the Bypass will trigger a Brownout fault. | 3.0 s (1.0 - 300.0 s) |
| Z1-29 (85E2) | Blackout Voltage Level | Sets the voltage level to determine a blackout condition. Use Z1-60 [Blackout Operation Select] to set power blackout behavior. Note: Voltage level is measured on the output of the built-in 120 VAC control transformer. | 75 V (0 - 150 V) |
| Z1-31 (85E4) | Loss of Load Detection Select | Sets the function to detect loss of load. 0 : Disabled 1 : Enable and Fault 2 : Enable and Alarm | 0 (0 - 2) |
| Z1-32 (85E5) | Loss of Load Drive Frequency | Sets the value to which the drive output frequency must be equal to or more than for the drive to detect a loss of load. | 60.00 Hz (0.00 - Max Freq.) |
| Z1-33 (85E6) | Loss of Load Drive Out Current | For Drive Mode only, the drive output current must be less than this level to detect a Loss of Load condition. | 0.0 A (0.0 - 999.9 A) |
| Z1-34 (85E7) | Loss of Load Drive Det Time | The loss of load conditions must be met for the length of time in this parameter before the bypass will detect a loss of load in Drive Mode. | 1.0 s (0.0 - 300.0 s) |
| Z1-35 (85E8) | Loss of Load Bypass Current | For Bypass Mode only, the motor current must be less than this level to detect a Loss of Load condition. | 0.0 A (0.0 - 999.9 A) |
| Z1-36 (85E9) | Loss of Load Bypass Det Time | The motor current must be less than the value set in Z1-35 [Loss of Load Bypass Current] for the length of time set in this parameter before the bypass will detect a loss of load in Bypass Mode. | 1.0 s (0.0 - 300.0 s) |
| Z1-39 (85EC) | Drive/Bypass Source Select | Sets the function to select the Drive or the Bypass as the source of Drive/Bypass Mode selection. 0 : Keypad 1 : Digital Input 2 : Serial Communications 3 : Option PCB | 0 (0 - 3) |
| Z1-40 (85ED) | Auto Transfer Delay Time | When you enable Auto Transfer and the bypass detects a drive fault, the bypass controller will wait for the length of time set in this parameter before it switches to bypass. | 0.0 s (0.0 - 300.0 s) |

| No. (Hex.) | Name | Description | Default (Range) |
|------------------------|--------------------------------|--|--------------------------|
| Z1-42 (85EF) | Soft Starter Selection | This parameter is normally set at the factory and does not require adjustment. Set this parameter when you use a soft starter used in bypass operation and when you will use the soft starter for a "soft stop". 0 : Not Installed – Contactor Only 1 : Installed – Coast To Stop 2 : Installed – Ramp To Stop Note: When [Z1-42 = 1 or 2] to enable the soft starter: • The bypass automatically disables welded contactor detection. Parameter Z1-55 [Welded Contactor Detection] does not have an effect. • The bypass automatically sets Z2-08 = 29 [Digital Input 8 Function (TB2-8) = External Overload Motor 1 (NC)] and Z2-16 = 0 [Digital Input 8 Invert Select = Normal (Non-inverted)]. When you change Z1-42 FROM 1 or 2 TO 0, the bypass does not automatically change Z2-08 and Z2-16 back to their default values. These parameters stay at their previous settings. When you use serial communications or an option card to set Z1-42, Z2-08 [Digital Input 8 Function (TB2-8)] and Z2-16 [Digital Input 8 Invert Select] will not change unless H5-11 = 1 [Comm ENTER Command Mode = ENTER Command Not Required]. | 0 (0 - 2) |
| Z1-43 (85F0) | Soft Starter Delay Timer | This parameter is normally set at the factory and does not require adjustment. Sets the delay time between closing contactor K3 and energizing the soft starter. Note: This parameter is enabled when Z1-42 = 1 or 2 [Soft Starter Selection = Installed - Coast To Stop or Installed - Ramp To Stop]. | 2.0 s (0.0 - 60.0 s) |
| Z1-44 (85F1) | Soft Starter Rampdown Timeout | Sets the maximum wait time for the current to be less than 5% of E2-01 after removing the soft starter Run command. | 15.0 s (1.0 - 60.0 s) |
| Z1-50 (85F7) | Bypass Input Phase Loss Level | The bypass measures the current unbalance between phases to detect input phase loss. Usually it is not necessary to change this parameter. Sets the current level between phases in Bypass Mode. | 25.0% (5.0 - 50.0%) |
| Z1-51 (85F8) | Bypass Input Phase Loss Delay | Sets the trip time for an input phase loss condition in Bypass Mode. Note: When you set this parameter to 0.0, it will disable bypass phase loss detection. | 5.0 s (0.0 - 30.0 s) |
| Z1-52 (85F9) | Input Phase Rotation Detection | Sets bypass response when the Bypass Mode phase rotation is incorrect. 0 : Disabled 1 : Alarm 2 : Fault | 0 (0 - 2) |
| Z1-53 (85FA) | Load Verify Detection | Enables and disables verification that the motor is running when commanded to run. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| Z1-55 (85FC) | Welded Contactor Detection | Enables and disables detection of K3 "welded contactor" condition. 0 : Disabled 1 : Enabled Note: When Z1-42 = 1 or 2 [Soft Starter Selection = Installed – Coast To Stop or Installed – Ramp To Stop], the bypass will automatically disable welded contactor detection. | 0 (0, 1) |
| Z1-56 (85FD) RUN | Test Mode | Sets the behavior of the drive input contactor K1 during Bypass Mode. 0 : Drive Power Off during Bypass 1 : Drive Power On during Bypass | 0 (0, 1) |
| Z1-60 (8601) | Blackout Operation Select | Sets bypass behavior when contactor voltage is less than Z1-29 [Blackout Voltage Level]. 0 : Fault 1 : Restart Delay with Speed Search 2 : Restart Delay from Zero Speed 3 : Disabled Note: Restart Delay works best when: • A keypad is connected • There is a good battery in the keypad • The date and time are set correctly in the keypad | 1 (0 - 3) |
| Z1-61 (8602) | Power Loss Restart Delay Time | Sets the time delay for restart. This parameter works together Z1-60 [Blackout Operation Select] | 10 s (1 - 300 s) |
| Z1-70 (860B) | Green Contactor Mode | Green Contactor Mode opens the output and motor contactors when the bypass unit is idle and does not have a Run command. 0 : Disabled 1 : Enabled | 0 (0, 1) |

7.14 Z: Bypass Parameters

| No. (Hex.) | Name | Description | Default (Range) |
|---------------------------|----------------------|---|--|
| Z1-98 (8627) Expert | Minimum Drive SW Ver | Only change this parameter under the guidance of Yaskawa technical support (1-800-YASKAWA). If you change this parameter incorrectly, it can cause incorrect operation of the bypass system. Bypass SW VST800440 : Default: 0 Bypass SW VST800441 : Default: 0 Bypass SW VST800442 : Default: 0 Bypass SW VST800443 : Default: 1013 Bypass SW VST800444 : Default: 1013 Bypass SW VST800445 : Default: 1013 Bypass SW VST800446 : Default: 1013 Bypass SW VST800447 : Default: 1013 Bypass SW VST800448 : Default: 1013 | Depends on software version (00000 - 65535) |
| Z1-99 (8628) Expert | Maximum Drive SW Ver | Only change this parameter under the guidance of Yaskawa technical support (1-800-YASKAWA). If you change this parameter incorrectly, it can cause incorrect operation of the bypass system. Bypass SW VST800440 : Default: 1010 Bypass SW VST800441 : Default: 1011 Bypass SW VST800442 : Default: 1012 Bypass SW VST800443 : Default: 1013 Bypass SW VST800444 : Default: 1014 Bypass SW VST800445 : Default: 1015 Bypass SW VST800446 : Default: 1016 Bypass SW VST800447 : Default: 1017 Bypass SW VST800448 : Default: 1017 | Depends on software version (00000 - 65535) |

◆ Z2: Bypass Control Input/Output

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|----------------------------------|--|-----------------|
| Z2-01 (8563) | Digital Input 1 Function (TB2-1) | Sets the function for bypass digital input 1. | 21 (0 - 47) |
| Z2-02 (8564) | Digital Input 2 Function (TB2-2) | Sets the function for bypass digital input 2. | 22 (0 - 47) |
| Z2-03 (8565) | Digital Input 3 Function (TB2-3) | Sets the function for bypass digital input 3. | 23 (0 - 47) |
| Z2-04 (8566) | Digital Input 4 Function (TB2-4) | Sets the function for bypass digital input 4. | 24 (0 - 47) |
| Z2-05 (8567) | Digital Input 5 Function (TB2-5) | Sets the function for bypass digital input 5. | 25 (0 - 47) |
| Z2-06 (8568) | Digital Input 6 Function (TB2-6) | Sets the function for bypass digital input 6. | 0 (0 - 47) |
| Z2-07 (8569) | Digital Input 7 Function (TB2-7) | Sets the function for bypass digital input 7. | 0 (0 - 47) |
| Z2-08 (856A) | Digital Input 8 Function (TB2-8) | Sets the function for bypass digital input 8. | 0 (0 - 47) |
| Z2-09 (856B) | Digital Input 1 Invert Select | Inverts the output of the function selected in Digital Input 1. 0 : Normal (Non-inverted) 1 : Inverted | 0 (0, 1) |
| Z2-10 (856C) | Digital Input 2 Invert Select | Inverts the output of the function selected in Digital Input 2. 0 : Normal (Non-inverted) 1 : Inverted | 0 (0, 1) |
| Z2-11 (856D) | Digital Input 3 Invert Select | Inverts the output of the function selected in Digital Input 3. 0 : Normal (Non-inverted) 1 : Inverted | 0 (0, 1) |
| Z2-12 (856E) | Digital Input 4 Invert Select | Inverts the output of the function selected in Digital Input 4. 0 : Normal (Non-inverted) 1 : Inverted | 0 (0, 1) |
| Z2-13 (856F) | Digital Input 5 Invert Select | Inverts the output of the function selected in Digital Input 5. 0 : Normal (Non-inverted) 1 : Inverted | 0 (0, 1) |

| No. (Hex.) | Name | Description | Default (Range) |
|--------------|----------------------------------|--|------------------------------|
| Z2-14 (8570) | Digital Input 6 Invert Select | Inverts the output of the function selected in Digital Input 6. 0 : Normal (Non-inverted) 1 : Inverted | 0 (0, 1) |
| Z2-15 (8571) | Digital Input 7 Invert Select | Inverts the output of the function selected in Digital Input 7. 0 : Normal (Non-inverted) 1 : Inverted | 0 (0, 1) |
| Z2-16 (8572) | Digital Input 8 Invert Select | Inverts the output of the function selected in Digital Input 8. 0 : Normal (Non-inverted) 1 : Inverted | 0 (0, 1) |
| Z2-23 (8579) | Digital Output 7 (TB1 1-3) | Sets the function for bypass digital output 7. Normally Open: TB1 - Terminals 2 and 3 Normally Closed: TB1 - Terminals 2 and 1 | 7 (0 - 99) |
| Z2-24 (857A) | Digital Output 8 (TB1 4-6) | Sets the function for bypass digital output 8. Normally Open: TB1 - Terminals 5 and 6 Normally Closed: TB1 - Terminals 5 and 4 | 10 (0 - 99) |
| Z2-25 (857B) | Digital Output 9 (TB1 7-9) | Sets the function for bypass digital output 9. Normally Open: TB1 - Terminals 8 and 9 Normally Closed: TB1 - Terminals 8 and 7 | 12 (0 - 99) |
| Z2-26 (857C) | Digital Output 10 (TB1 10-12) | Sets the function for bypass digital output 10. Normally Open: TB1 - Terminals 11 and 12 Normally Closed: TB1 - Terminals 11 and 10 | 15 (0 - 99) |
| Z2-30 (8580) | Analog Input Signal Level Select | Sets the input signal level for the analog input on the bypass control board A2 Terminal TB4-2. 0 : 0 to 10V (Lower Limit at 0) 2 : 4 to 20 mA 3 : 0 to 20 mA | 0 (0 - 3) |
| Z2-32 (8582) | Analog Input Gain Setting | Sets the gain of the analog signal input to the analog input on the bypass control board A2 Terminal TB4-2.. | 100.0% (-999.9 - +999.9%) |
| Z2-33 (8583) | Analog Input Bias Setting | Sets the bias of the analog signal input to the analog input on the bypass control board A2 Terminal TB4-2. | 0.0% (-999.9 - +999.9%) |

◆ Z2-xx: Digital Input Setting Values

| Setting Value | Function | Description |
|---------------|--------------------------------|---|
| 0 | Not Used | Use this setting for unused terminals or to use terminals in through mode. |
| 1 | Drive S1 Passthrough | Simulates a digital input on drive digital input terminal S1. Use H1-01 [Terminal S1 Function Selection] to program the function. |
| 2 | Drive S2 Passthrough | Simulates a digital input on drive digital input terminal S2. Use H1-02 [Terminal S2 Function Selection] to program the function. |
| 3 | Drive S3 Passthrough | Simulates a digital input on drive digital input terminal S3. Use H1-03 [Terminal S3 Function Selection] to program the function. |
| 4 | Drive S4 Passthrough | Simulates a digital input on drive digital input terminal S4. Use H1-04 [Terminal S4 Function Selection] to program the function. |
| 5 | Drive S5 Passthrough | Simulates a digital input on drive digital input terminal S5. Use H1-05 [Terminal S5 Function Selection] to program the function. |
| 6 | Drive S6 Passthrough | Simulates a digital input on drive digital input terminal S6. Use H1-06 [Terminal S6 Function Selection] to program the function. |
| 7 | Drive S7 Passthrough | Simulates a digital input on drive digital input terminal S7. Use H1-07 [Terminal S7 Function Selection] to program the function. |
| 21 | Run (AUTO) | Starts and stops the bypass. |
| 22 | Run Enable - Safety (NC) | Stops the bypass. Normally closed signal. |
| 23 | Run Interlock (BAS) | Stops the drive and triggers alarm AL02. Normally closed signal. |
| 24 | Remote Transfer to Bypass | Forces the bypass into Bypass Mode. |
| 25 | Emergency Override Bypass | Forces the bypass to operate in Bypass Mode. |
| 26 | Emergency Override Drive (FWD) | Forces the bypass to operate in the forward direction in Drive Mode. |
| 27 | Motor OR Select | Sets the command for the bypass to operate motor 1 or motor 2. |
| 28 | Motor AND Select | Sets the command for the bypass to operate motor 1 and motor 2 at the same time. |
| 29 | External Overload Motor 1 (NC) | Input for an external motor overload relay. Normally closed signal. |

7.14 Z: Bypass Parameters

| Setting Value | Function | Description |
|---------------|--------------------------------|--|
| 30 | External Overload Motor 2 (NC) | Input for an external motor overload relay (Motor 2). Normally closed signal. |
| 31 | HAND Select | Selects HAND Mode from the digital inputs instead of the keypad. |
| 32 | AUTO Select | Selects AUTO Mode from the digital inputs instead of the keypad. |
| 33 | Drive/Bypass Select | Sets the bypass to operate in Bypass Mode or Drive Mode. ON : Bypass Mode is selected OFF : Drive Mode is selected |
| 34 | Fault Reset | Resets any faults that are present. |
| 35 | External Fault (EF0) | Forces the drive into an <i>EF0</i> fault condition. |
| 36 | External Fault (EFB) | Triggers external fault <i>EFB</i> on the bypass. |
| 37 | Run Reverse (AUTO) | Starts and stops the bypass in reverse. |
| 38 | Fire Stat Switch (NC) | Stops the drive from running and shows "Fire Stat" on the keypad. |
| 39 | Freeze Stat Switch (NC) | Stops the drive from running and shows "Freeze Stat" on the keypad. |
| 40 | Smoke Alarm (NC) | Stops the drive from running and shows "Smoke Alarm Active" on the keypad. |
| 41 | OverPressure Switch (NC) | Stops the drive from running and shows "Over Pressure Detected" on the keypad. |
| 42 | Low Suction Switch (NC) | Stops the drive from running and shows "Low Suction Detected" on the keypad. |
| 43 | Vibration Switch (NC) | Stops the drive from running and shows "Vibration Detected" on the keypad. |
| 44 | Emergency Override Drive (REV) | Forces the bypass to operate in Drive Mode in the reverse direction. |
| 45 | Serial Hardware Test (RS-485) | Sets the function for the bypass control to self-test the RS-485 serial communications operation. |
| 46 | Low City Pressure | Indicates that sufficient or insufficient pressure is present on the inlet to the pump. Used mainly for pressure booster situations. |
| 47 | Motor Preheat | Sets the command to apply the motor pre-heat current. Use <i>b2-09 [Pre-heat Current 2]</i> to adjust. |

◆ Z2-xx: Digital Output Setting Values

| Setting Value | Function | Description |
|---------------|------------------------------|--|
| 0 | Serial Communication Control | Activates when <i>b1-01 = 2 [Frequency Reference Selection 1 = Serial Communications]</i> , and/or <i>b1-02 = 2 or 8 [Run Command Selection 1 = Serial Communications or AUTO Command + Serial Run]</i> to set the bypass for control by serial communications. Note: This does not apply when Option PCB-based serial communications control the bypass. |
| 1 | K1 Drive Input Contactor | Active when the K1 (Drive Input Power) contactor is energized. |
| 2 | K2 Drive Output Contactor | Active when the K2 (Drive Output) contactor is energized. |
| 3 | K3 Bypass Contactor | Active when the K3 (Bypass Run) contactor is energized. |
| 4 | K4 Motor 1 Contactor | Active when the K4 (Motor 1) contactor is energized. |
| 5 | K5 Motor 2 Contactor | Active when the K5 (Motor 2) contactor is energized. |
| 6 | READY | Active when the system is ready to operate. ON : System is ready to operate OFF : System is faulted, in Programming Mode, or one of the safety digital inputs is open |
| 7 | RUN Active | Active when the system is running in Drive Mode or Bypass Mode. |
| 8 | Drive RUN active | The digital output activates when the system is in Drive Mode and the HV600 drive is running. ON : Running in Drive Mode OFF : Not running or in Bypass Mode |
| 9 | Bypass RUN active | The digital output activates when the system is in Bypass Mode and is running. Contactor K3 is closed. ON : Running in Bypass Mode OFF : Not running or in Drive Mode |
| 10 | HAND mode Active | The digital output activates when the system is running in HAND Mode during Drive Mode and Bypass Mode. ON : Running in HAND Mode OFF : Not running or in AUTO Mode |

| Setting Value | Function | Description |
|---------------|--------------------------|---|
| 11 | OFF mode Active | The digital output activates when the HAND/OFF/AUTO selection is in OFF Mode or if system is faulted. It is also active when in Emergency Override Mode. ON : System is in OFF Mode or is faulted OFF : HAND Mode, AUTO Mode (even if not running), Emergency Override. |
| 12 | Auto mode Active | The digital output activates when the HAND/OFF/AUTO selection is in AUTO Mode. It will activate when the system is running and when the system is not running and in Drive Mode and Bypass Mode. ON : System is in AUTO Mode OFF : HAND Mode, OFF Mode, Faulted, Emergency Override |
| 13 | Drive Mode Selected | The digital output activates when Drive Mode is selected. It stays active during Remote Transfer to Bypass, Emergency Override Bypass, Energy Savings, Fault condition, and when the system is not running. ON : Drive Mode is selected OFF : Bypass Mode is selected |
| 14 | Bypass Mode Selected | The digital output activates when Bypass Mode is selected. It stays active during Emergency Override Drive, Fault condition, and when the system is not running. ON : Bypass Mode is selected OFF : Drive Mode is selected |
| 15 | Fault Active | Set when there is an active Drive fault or Bypass fault. |
| 16 | Drive Fault Active | There is a fault in the HV600 drive. |
| 17 | Bypass Fault Active | There is a fault in the bypass. |
| 18 | Auto Transfer Active | There is a drive fault that activated Auto Transfer to Bypass. |
| 19 | Serial Run Active | Serial Communications is commanding a RUN. |
| 20 | Damper Actuator Output | System commanded to RUN in Drive Mode or Bypass Mode. |
| 21 | ON Always | This digital output is always active. |
| 22 | Loss of Load Detected | The motor current is less than the set value/values. |
| 23 | Run Verify Active | The digital output closes when the drive or bypass output current is more than 10% of E2-01. The digital output opens when the drive or bypass output current is less than 5% of E2-01. |
| 24 | Soft Starter Run Command | Controls the Run command to the soft starter. Use Z1-42 to Z1-44 [Soft Starter Selection to Soft Starter Rampdown Timeout] to configure the soft starter. Use this setting when a soft-starter is part of the bypass package. |
| 25 | Safeties Closed | All of the programmed safety digital inputs are satisfied. |
| 26 | Mirror HV600 M1-M2 | The digital output activates when the HV600 drive digital output (M1-M2) is closed. ON : Digital Output M1-M2 on HV600 is closed OFF : Digital Output M1-M2 on HV600 is open |
| 27 | Mirror HV600 M3-M4 | The digital output activates when the HV600 drive digital output (M3-M4) is closed. ON : Digital Output M3-M4 on HV600 is closed OFF : Digital Output M3-M4 on HV600 is open |
| 28 | Mirror HV600 M5-M6 | The digital output activates when the HV600 drive digital output (M5-M6) is closed. ON : Digital Output M5-M6 on HV600 is closed OFF : Digital Output M5-M6 on HV600 is open |
| 99 | Not Used | This setting allows serial communications to control the output. |

◆ Z3: Bypass Control Serial Comm

| No. (Hex.) | Name | Description | Default (Range) |
|-----------------|---------------------------|---|--------------------|
| Z3-12 (850B) | Network Digital Inputs | Enables and disables control of the digital inputs over a network. When this is enabled, it is not necessary to wire to the physical digital input. 0 : Disabled 1 : Enabled | 0 (0, 1) |
| Z3-13 (850C) | BACnet Register Retention | Sets what to restore when you lose power then reapply power. WARNING! Sudden Movement Hazard. Clear all personnel from the drive, motor, and machine area before you reapply power. If you set this parameter to 2 or 3, the bypass unit can start before it receives a valid network message. Failure to obey can cause injury to personnel. 0 : Disabled 1 : Restore Frequency Reference Only 2 : Restore Commands Only 3 : Restore Commands and Freq Ref | 0 (0 - 3) |
| Z3-16 (850F) | Apogee Run Enable LDO35 | This parameter is applicable only when $H5-08 = 2$ [Communication Protocol Selection = Apogee/PI]. Sets whether the data in point LDO 35 will have an effect on the ability of the bypass to run. 0 : Disabled 1 : Enabled | 0 (0, 1) |

7.15 U: Monitors

◆ U1: Operation Status Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|--------------------------|---|---|
| U1-01 (0040) | Frequency Reference (AI) | Shows the frequency reference value. Parameter <i>o1-03</i> [Keypad Display Unit Selection] sets the display units. Unit: 0.01 Hz | 10 V = Maximum frequency (0 V to +10 V) |
| U1-02 (0041) | Output Frequency | Shows the output frequency. Parameter <i>o1-03</i> [Keypad Display Unit Selection] sets the display units. Unit: 0.01 Hz | 10 V = Maximum frequency (0 V to +10 V) |
| U1-03 (0042) | Output Current | Shows the drive unit output current. The keypad shows the value of <i>U1-03</i> in amperes (A). When you use serial communications to show the monitor, the current is "8192 = drive rated current (A)". Use the formula: "Numerals being displayed / 8192 × drive rated current (A)" to use the serial communication current value shown in the monitor. Note: Use monitor <i>Ub-01</i> to show output current for both drive and bypass modes. Unit: Determined by the drive model. • 0.01 A: 2011 to 2046, 4005 to 4014 • 0.1 A: 2059 to 2273, 4021 to 4302 | 10 V = Drive rated current |
| U1-04 (0043) | Control Method | Shows the drive control method. 0 : V/f Control | No signal output available |
| U1-06 (0045) | Output Voltage Ref | Shows the output voltage reference. Unit: 0.1 V | 208/240 V: 10 V = 200 Vrms 480 V: 10 V = 400 Vrms |
| U1-07 (0046) | DC Bus Voltage | Shows the DC bus voltage. Unit: 1 V | 208/240 V: 10 V = 400 V 480 V: 10 V = 800 V |
| U1-08 (0047) | Output Power | Shows the internally-calculated output power. Unit: Determined by the drive model. • 0.01 kW: 2011 to 2046, 4005 to 4014 • 0.1 kW: 2059 to 2273, 4021 to 4302 | 10 V: Drive capacity (motor rated power) kW (-10 V to +10 V) |
| U1-10 (0049) | Input Terminal Status | Shows the status of the MFDI terminal where 1 = (ON) and 0 = (OFF). For example, <i>U1-10</i> shows "00000011" when terminals S1 and S2 are ON. bit0 : Terminal S1 (MFDI 1) bit1 : Terminal S2 (MFDI 2) bit2 : Terminal S3 (MFDI 3) bit3 : Terminal S4 (MFDI 4) bit4 : Terminal S5 (MFDI 5) bit5 : Terminal S6 (MFDI 6) bit6 : Terminal S7 (MFDI 7) bit7 : Not used (normal value of 0). | No signal output available |
| U1-11 (004A) | Output Terminal Status | Shows the status of the MFDO terminal where 1 = (ON) and 0 = (OFF). For example, <i>U1-11</i> shows "00000011" when terminals M1 and M3 are ON. Note: When <i>H2-xx = 100 to 1C4</i> [Inverse Output of Function], the monitor will show the value before inversion. bit 0 : Terminals M1-M2 bit 1 : Terminals M3-M4 bit 2 : Terminals M5-M6 bit 3 : Not used (normal value of 0). bit 4 : Not used (normal value of 0). bit 5 : Not used (normal value of 0). bit 6 : Not used (normal value of 0). bit 7 : Fault relay MA/MB-MC | No signal output available |
| U1-12 (004B) | Drive Status | Shows drive status where 1 = ON and 0 = OFF. For example, <i>U1-12</i> shows "00000101" during run with the Reverse Run command. bit0 : During Run bit1 : During zero-speed bit2 : During reverse bit3 : During fault reset signal input bit4 : During speed agreement bit5 : Drive ready bit6 : During minor fault detection bit7 : During fault detection | No signal output available |

7.15 U: Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|----------------------|--|---|
| U1-13 (004E) | Terminal A1 Level | Shows the signal level of terminal A1. Unit: 0.1% | 10 V = 100% (0 V to +10 V) |
| U1-14 (004F) | Terminal A2 Level | Shows the signal level of terminal A2. Unit: 0.1% | 10 V = 100% (0 V to +10 V) |
| U1-16 (0053) | SFS Output Frequency | Shows the output frequency after soft start. Shows the frequency with acceleration and deceleration times and S-curves. Parameter <i>o1-03 [Keypad Display Unit Selection]</i> sets the display units. Unit: 0.01 Hz | 10 V = Maximum frequency (0 V to +10 V) |
| U1-18 (0061) | oPE Fault Parameter | Shows the parameter number that caused the <i>oPE02 [Parameter Range Setting Error]</i> or <i>oPE08 [Parameter Selection Error]</i> . | No signal output available |
| U1-19 (0066) | Serial Error Code | Shows the contents of the serial communication error where 1 = "error" and 0 = "no error". For example, <i>U1-19</i> shows "00000001" when there is a CRC error. bit0 : CRC Error bit1 : Data Length Error bit2 : Not used (normal value of 0). bit3 : Parity Error bit4 : Overrun Error bit5 : Framing Error bit6 : Timed Out bit7 : Not used (normal value of 0). | No signal output available |
| U1-25 (004D) | SoftwareNumber Flash | Shows the FLASH ID. | No signal output available |
| U1-26 (005B) | SoftwareNumber ROM | Shows the ROM ID. | No signal output available |
| U1-60 (1089) | System Setpoint | Shows the PID Setpoint. Unit: 0.01% Note: Parameters <i>b5-46 [PID Unit Display Selection]</i> , <i>b5-38 [PID User Unit Display Scaling]</i> , and <i>b5-39 [PID User Unit Display Digits]</i> set the unit, range, and resolution. | No signal output available |
| U1-61 (108A) | System Feedback | Shows the PID Feedback. Unit: 0.01% Note: Parameters <i>b5-46 [PID Unit Display Selection]</i> , <i>b5-38 [PID User Unit Display Scaling]</i> , and <i>b5-39 [PID User Unit Display Digits]</i> set the unit, range, and resolution. | No signal output available |
| U1-64 (108D) | Motor Speed | Shows the absolute value of the parameter <i>U1-02 [Output Frequency]</i> converted to RPM. Unit: 1 RPM | No signal output available |
| U1-99 (3BAE) | Anti-No-Flow Timer | Shows the value of the anti-no-flow timer. When this value is at the <i>Y2-24 [Anti-No-Flow Detection Time]</i> setting, the anti-no-flow feature starts to decrease the output frequency. Unit: 0.1 s | No signal output available |

◆ U2: Fault Trace

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|----------------------|--|----------------------------|
| U2-01 (0080) | Current Fault | Shows the fault that the drive has when viewing the monitor. | No signal output available |
| U2-02 (0081) | Previous Fault | Shows the fault that occurred most recently. | No signal output available |
| U2-03 (0082) | Freq Reference@Fault | Shows the frequency reference at the fault that occurred most recently. Use <i>U1-01 [Frequency Reference]</i> to monitor the frequency reference value. Unit: 0.01 Hz | No signal output available |
| U2-04 (0083) | Output Freq @ Fault | Shows the output frequency at the fault that occurred most recently. Use <i>U1-02 [Output Frequency]</i> to monitor the actual output frequency. Unit: 0.01 Hz | No signal output available |

| No. (Hex.) | Name | Description | MFAO Signal Level |
|-----------------|---------------------------------|--|----------------------------|
| U2-05 (0084) | Output Current@Fault | Shows the motor current at the fault that occurred most recently. Use <i>Ub-01 [Motor Current]</i> to monitor the output current. The keypad shows the value of <i>Ub-01</i> in amperes (A). When you use serial communications to show the monitor, the current is "8192 = drive rated current (A)". Use the formula: "Numerals being displayed / 8192 × drive rated current (A)" to use the serial communication current value shown in the monitor. Unit: Determined by the drive model. • 0.01 A: 2011 to 2046, 4005 to 4014 • 0.1 A: 2059 to 2273, 4021 to 4302 | No signal output available |
| U2-07 (0086) | Output Voltage@Fault | Shows the output voltage reference at the fault that occurred most recently. Use <i>U1-06 [Output Voltage Ref]</i> to monitor the output voltage reference. Unit: 0.1 V | No signal output available |
| U2-08 (0087) | DC Bus Voltage@Fault | Shows the DC bus voltage at the fault that occurred most recently. Use <i>U1-07 [DC Bus Voltage]</i> to monitor the DC bus voltage. Unit: 1 V | No signal output available |
| U2-09 (0088) | Output Power @ Fault | Shows the output power at the fault that occurred most recently. Use <i>U1-08 [Output Power]</i> to monitor the output power. Unit: 0.1 kW | No signal output available |
| U2-11 (008A) | Byp Inp Terminal Status @ Fault | Shows the status of the bypass digital input terminals at the most recent fault where 1 = (ON) and 0 = (OFF). For example, <i>U2-11</i> shows "00000011" when terminals TB2-1 and TB2-2 are ON. Use <i>Ub-02 [Bypass Digital Input Status]</i> to monitor the terminal status. bit 0 : Digital Input 1 (TB2-1) bit 1 : Digital Input 2 (TB2-2) bit 2 : Digital Input 3 (TB2-3) bit 3 : Digital Input 4 (TB2-4) bit 4 : Digital Input 5 (TB2-5) bit 5 : Digital Input 6 (TB2-6) bit 6 : Digital Input 7 (TB2-7) bit 7 : Digital Input 8 (TB2-8) | No signal output available |
| U2-12 (008B) | Byp Relay Status @ Fault | Shows the status of the bypass digital output terminals at the most recent fault where 1 = (ON) and 0 = (OFF). For example, <i>U2-12</i> shows "00000011" when terminals M1 and M3 are ON. Use <i>Ub-02 [Bypass Digital Output Status]</i> to monitor the terminal status. bit 0 : K1 (Input Contactor) bit 1 : K2 (Output Contactor) bit 2 : K3 (Bypass Contactor) bit 3 : K4 (Motor 1 Output Contactor) bit 4 : K5 (Motor 2 Output Contactor) bit 5 : Fan Output Relay bit 6 : Digital Output 7 (TB1 1~3) (Z2-23) bit 7 : Digital Output 8 (TB1 4~6) (Z2-24) | No signal output available |
| U2-13 (008C) | Bypass Status @ Fault | Shows the status of the bypass at the most recent fault where 1 = (ON) and 0 = (OFF). For example, <i>U2-13</i> shows "00000001" during run. Use <i>Ub-05 [Bypass Status 1]</i> to monitor the bypass. bit 0 : Hand Mode Active bit 1 : Off Mode Active bit 2 : Auto Mode Active bit 3 : Drive Mode bit 4 : Bypass Mode bit 5 : Emergency Override Bypass bit 6 : Emergency Override Drive bit 7 : Safety Open | No signal output available |
| U2-14 (008D) | Elapsed Time @ Fault | Shows the cumulative operation time of the drive at the fault that occurred most recently. Use <i>U4-01 [Cumulative Ope Time]</i> to monitor the cumulative operation time. Unit: 1 h | No signal output available |
| U2-15 (07E0) | SFS Output @ Fault | Shows the output frequency after soft start at the fault that occurred most recently. Use <i>U1-16 [SFS Output Frequency]</i> to monitor the output frequency after soft start. Unit: 0.01 Hz | No signal output available |
| U2-16 (07E1) | q-Axis Current@Fault | Shows the q-Axis current of the motor at the fault that occurred most recently. Use <i>U6-01 [Iq Secondary Current]</i> to monitor the q-Axis current of the motor. Unit: 0.1 % | No signal output available |

7.15 U: Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|----------------------|--|----------------------------|
| U2-20 (008E) | Heatsink Temp @Fault | Shows the heatsink temperature at the fault that occurred most recently. Use U4-08 [Heatsink Temperature] to monitor the temperature of the heatsink. Unit: 1 °C | No signal output available |
| U2-30 (3008) | Fault 1 YYYY | Shows the year when the most recent fault occurred. | No signal output available |
| U2-31 (3009) | Fault 1 MMDD | Shows the month and day when the most recent fault occurred. | No signal output available |
| U2-32 (300A) | Fault 1 HHMM | Shows the time when the most recent fault occurred. | No signal output available |

◆ U3: Fault History

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|----------------------|--|----------------------------|
| U3-01 (0090) | 1st MostRecent Fault | Shows the fault history of the most recent fault. Note: The drive saves this fault history to two types of registers at the same time for serial communications. | No signal output available |
| U3-02 (0091) | 2nd MostRecent Fault | Shows the fault history of the second most recent fault. Note: The drive saves this fault history to two types of registers at the same time for serial communications. | No signal output available |
| U3-03 (0092) | 3rd MostRecent Fault | Shows the fault history of the third most recent fault. Note: The drive saves this fault history to two types of registers at the same time for serial communications. | No signal output available |
| U3-04 (0093) | 4th MostRecent Fault | Shows the fault history of the fourth most recent fault. Note: The drive saves this fault history to two types of registers at the same time for serial communications. | No signal output available |
| U3-05 (0804) | 5th MostRecent Fault | Shows the fault history of the fifth most recent fault. | No signal output available |
| U3-06 (0805) | 6th MostRecent Fault | Shows the fault history of the sixth most recent fault. | No signal output available |
| U3-07 (0806) | 7th MostRecent Fault | Shows the fault history of the seventh most recent fault. | No signal output available |
| U3-08 (0807) | 8th MostRecent Fault | Shows the fault history of the eighth most recent fault. | No signal output available |
| U3-09 (0808) | 9th MostRecent Fault | Shows the fault history of the ninth most recent fault. | No signal output available |
| U3-10 (0809) | 10th MostRecentFault | Shows the fault history of the tenth most recent fault. | No signal output available |
| U3-11 (0094) | ElapsedTime@1stFault | Shows the cumulative operation time when the most recent fault occurred. Note: The drive saves this cumulative operation time to two types of registers at the same time for serial communications. Unit: 1 h | No signal output available |
| U3-12 (0095) | ElapsedTime@2ndFault | Shows the cumulative operation time when the second most recent fault occurred. Note: The drive saves this cumulative operation time to two types of registers at the same time for serial communications. Unit: 1 h | No signal output available |
| U3-13 (0096) | ElapsedTime@3rdFault | Shows the cumulative operation time when the third most recent fault occurred. Note: The drive saves this cumulative operation time to two types of registers at the same time for serial communications. Unit: 1 h | No signal output available |


| No. (Hex.) | Name | Description | MFAO Signal Level |
|-----------------|----------------------|--|----------------------------|
| U3-14 (0097) | ElapsedTime@4thFault | Shows the cumulative operation time when the fourth most recent fault occurred. Note: The drive saves this cumulative operation time to two types of registers at the same time for serial communications. Unit: 1 h | No signal output available |
| U3-15 (080E) | ElapsedTime@5thFault | Shows the cumulative operation time when the fifth most recent fault occurred. Unit: 1 h | No signal output available |
| U3-16 (080F) | ElapsedTime@6thFault | Shows the cumulative operation time when the sixth most recent fault occurred. Unit: 1 h | No signal output available |
| U3-17 (0810) | ElapsedTime@7thFault | Shows the cumulative operation time when the seventh most recent fault occurred. Unit: 1 h | No signal output available |
| U3-18 (0811) | ElapsedTime@8thFault | Shows the cumulative operation time when the eighth most recent fault occurred. Unit: 1 h | No signal output available |
| U3-19 (0812) | ElapsedTime@9thFault | Shows the cumulative operation time when the ninth most recent fault occurred. Unit: 1 h | No signal output available |
| U3-20 (0813) | ElapsedTime@10 Fault | Shows the cumulative operation time when the tenth most recent fault occurred. Unit: 1 h | No signal output available |
| U3-21 (300B) | Fault 1 YYYY | Shows the year when the most recent fault occurred. | No signal output available |
| U3-22 (300C) | Fault 1 MMDD | Shows the month and day when the most recent fault occurred. | No signal output available |
| U3-23 (300D) | Fault 1 HHMM | Shows the time when the most recent fault occurred. | No signal output available |
| U3-24 (300E) | Fault 2 YYYY | Shows the year when the second most recent fault occurred. | No signal output available |
| U3-25 (300F) | Fault 2 MMDD | Shows the month and day when the second most recent fault occurred. | No signal output available |
| U3-26 (3010) | Fault 2 HHMM | Shows the time when the second most recent fault occurred. | No signal output available |
| U3-27 (3011) | Fault 3 YYYY | Shows the year when the third most recent fault occurred. | No signal output available |
| U3-28 (3012) | Fault 3 MMDD | Shows the month and day when the third most recent fault occurred. | No signal output available |
| U3-29 (3013) | Fault 3 HHMM | Shows the time when the third most recent fault occurred. | No signal output available |
| U3-30 (3014) | Fault 4 YYYY | Shows the year when the fourth most recent fault occurred. | No signal output available |
| U3-31 (3015) | Fault 4 MMDD | Shows the month and day when the fourth most recent fault occurred. | No signal output available |
| U3-32 (3016) | Fault 4 HHMM | Shows the time when the fourth most recent fault occurred. | No signal output available |
| U3-33 (3017) | Fault 5 YYYY | Shows the year when the fifth most recent fault occurred. | No signal output available |
| U3-34 (3018) | Fault 5 MMDD | Shows the month and day when the fifth most recent fault occurred. | No signal output available |
| U3-35 (3019) | Fault 5 HHMM | Shows the time when the fifth most recent fault occurred. | No signal output available |
| U3-36 (301A) | Fault 6 YYYY | Shows the year when the sixth most recent fault occurred. | No signal output available |
| U3-37 (301B) | Fault 6 MMDD | Shows the month and day when the sixth most recent fault occurred. | No signal output available |
| U3-38 (301C) | Fault 6 HHMM | Shows the time when the sixth most recent fault occurred. | No signal output available |
| U3-39 (301D) | Fault 7 YYYY | Shows the year when the seventh most recent fault occurred. | No signal output available |

7.15 U: Monitors


| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|---------------|--|----------------------------|
| U3-40 (301E) | Fault 7 MMDD | Shows the month and day when the seventh most recent fault occurred. | No signal output available |
| U3-41 (301F) | Fault 7 HHMM | Shows the time when the seventh most recent fault occurred. | No signal output available |
| U3-42 (3020) | Fault 8 YYYY | Shows the year when the eighth most recent fault occurred. | No signal output available |
| U3-43 (3021) | Fault 8 MMDD | Shows the month and day when the eighth most recent fault occurred. | No signal output available |
| U3-44 (3022) | Fault 8 HHMM | Shows the time when the eighth most recent fault occurred. | No signal output available |
| U3-45 (3023) | Fault 9 YYYY | Shows the year when the ninth most recent fault occurred. | No signal output available |
| U3-46 (3024) | Fault 9 MMDD | Shows the month and day when the ninth most recent fault occurred. | No signal output available |
| U3-47 (3025) | Fault 9 HHMM | Shows the time when the ninth most recent fault occurred. | No signal output available |
| U3-48 (3026) | Fault 10 YYYY | Shows the year when the tenth most recent fault occurred. | No signal output available |
| U3-49 (3027) | Fault 10 MMDD | Shows the month and day when the tenth most recent fault occurred. | No signal output available |
| U3-50 (3028) | Fault 10 HHMM | Shows the time when the tenth most recent fault occurred. | No signal output available |

◆ U4: Maintenance Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|----------------------|--|-------------------|
| U4-01 (004C) | Cumulative Ope Time | Shows the cumulative operation time of the drive. Use parameter <i>o4-01 [Elapsed Operating Time Setting]</i> to reset this monitor. Use parameter <i>o4-02 [Elapsed Operating Time Selection]</i> to select the cumulative operation times from: <ul style="list-style-type: none"> The time from when the drive is energized until it is de-energized. The time at which the Run command is turned ON. The maximum value that the monitor will show is <i>99999</i> . After this value is more than <i>99999</i> , the drive automatically resets it and starts to count from <i>0</i> again. Unit: 1 h Note: The MEMOBUS/Modbus communication data is shown in 10 h units. Use register 0099H for data in 1 h units. | 10 V: 99999 h |
| U4-02 (0075) | Num of Run Commands | Shows how many times that the drive has received a Run command. Use parameter <i>o4-13 [RUN Command Counter @ Initialize]</i> to reset this monitor. The maximum value that the monitor will show is <i>65535</i> . After this value is more than <i>65535</i> , the drive automatically resets it and starts to count from <i>0</i> again. Unit: 1 | 10 V: 65535 times |
| U4-03 (0067) | Cooling Fan Ope Time | Shows the cumulative operation time of the cooling fans. Use parameter <i>o4-03 [Fan Operation Time Setting]</i> to reset this monitor. The maximum value that the monitor will show is <i>99999</i> . After this value is more than <i>99999</i> , the drive automatically resets it and starts to count from <i>0</i> again. Unit: 1 h Note: The MEMOBUS/Modbus communication data is shown in 10 h units. Use register 009BH for data in 1 h units. | 10 V: 99999 h |
| U4-04 (007E) | Cool Fan Maintenance | Shows the cumulative operation time of the cooling fans as a percentage of the replacement life of the cooling fans. Use parameter <i>o4-03 [Fan Operation Time Setting]</i> to reset this monitor. Unit: 1% Note: Replace the cooling fans when this monitor is 90%. | 10 V: 100% |

| No. (Hex.) | Name | Description | MFAO Signal Level |
|-----------------|----------------------|---|----------------------------|
| U4-05 (007C) | CapacitorMaintenance | Shows the operation time of the electrolytic capacitors for the main circuit and control circuit as a percentage of the replacement life of the electrolytic capacitors. Use parameter <i>o4-05 [Capacitor Maintenance Setting]</i> to reset this monitor. Unit: 1% Note: Replace the electrolytic capacitor when this monitor is 90%. | 10 V: 100% |
| U4-06 (07D6) | PreChargeRelayMainte | Shows the operation time of the soft charge bypass relay as a percentage of the replacement life of the soft charge bypass relay. Use parameter <i>o4-07 [Softcharge Relay Maintenance Set]</i> to reset this monitor. Unit: 1% Note: Replace the drive when this monitor is 90%. | 10 V: 100% |
| U4-07 (07D7) | IGBT Maintenance | Shows the operation time of the IGBTs as a percentage of the replacement life of the IGBTs. Set parameter <i>o4-09 [IGBT Maintenance Setting]</i> to reset this monitor. Unit: 1% Note: Replace the drive when this monitor is 90%. | 10 V: 100% |
| U4-08 (0068) | Heatsink Temperature | Shows the heatsink temperature of the drive. Unit: 1 °C | 10 V: 100 °C |
| U4-09 (005E) | LED Check | Turns on the LED Status Ring and all of the keypad LEDs to make sure that the LEDs operate correctly. 1. Set <i>o2-24 = 0 [LED Light Function Selection = Enable Status Ring & Keypad LED]</i> . 2. Push  with <i>U4-09</i> shown on the keypad. All LEDs on the keypad and LED Status Ring will turn on. Note: When Safety input 2 CH is open (STo), READY will flash. | No signal output available |
| U4-10 (005C) | kWh, Lower 4 Digits | Shows the lower 4 digits of the watt hour value for the drive. Unit: 1 kWh Note: The watt hour is displayed in 9 digits. Monitor <i>U4-11 [kWh, Upper 5 Digits]</i> shows the upper 5 digits and <i>U4-10</i> shows the lower 4 digits. Example for 12345678.9 kWh: <i>U4-10: 678.9 kWh</i> <i>U4-11: 12345 MWh</i> | No signal output available |
| U4-11 (005D) | kWh, Upper 5 Digits | Shows the upper 5 digits of the watt hour value for the drive. Unit: 1 MWh Note: Monitor <i>U4-11</i> shows the upper 5 digits and <i>U4-10 [kWh, Lower 4 Digits]</i> shows the lower 4 digits. Example for 12345678.9 kWh: <i>U4-10: 678.9 kWh</i> <i>U4-11: 12345 MWh</i> | No signal output available |
| U4-13 (07CF) | Peak Hold Current | Shows the hold value of the peak value (rms) for the drive output current. Use <i>U4-14 [PeakHold Output Freq]</i> to show the drive output frequency at the time that the drive holds the output current. The drive will hold the peak hold current at the next start up and restart of the power supply. The drive keeps the held value during baseblock (during stop). The keypad shows the value of <i>U4-13</i> in amperes (A). When you use serial communications to show the monitor, the current is "8192 = drive rated current (A)." Use the formula: "Numerals being displayed / 8192 × drive rated current (A)" to use the serial communication current value shown in the monitor. Unit: Determined by the drive model. • 0.01 A: 2011 to 2046, 4005 to 4014 • 0.1 A: 2059 to 2273, 4021 to 4302 | No signal output available |
| U4-14 (07D0) | PeakHold Output Freq | Shows the output frequency at which the peak value (rms) of the drive output current is held. The peak hold current can be monitored by <i>U4-13 [Peak Hold Current]</i> . The peak hold output frequency will be cleared at the next startup and restart of the power supply. The drive keeps the value that was under hold during baseblock (during stop). Unit: 0.01 Hz | No signal output available |
| U4-16 (07D8) | Motor oL1 Level | Shows the integrated value of <i>oL1 [Motor Overload]</i> as a percentage of <i>oL1</i> detection level. Unit: 0.1% | 10 V: 100% |

7.15 U: Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|-----------------|-----------------------|--|--|
| U4-18 (07DA) | Reference Source | Shows the selected frequency reference source. The keypad shows the frequency reference source as "XY-nn" as specified by these rules: X: Frequency reference <ul style="list-style-type: none"> • 1: b1-01 [Frequency Reference Selection 1] Y-nn: Frequency reference source <ul style="list-style-type: none"> • 0-01: Keypad (d1-01 [Reference 1]) • 1-00: Analog input (unassigned) • 1-01: MFAI terminal A1 • 1-02: MFAI terminal A2 • 2-02 to 2-17: Multi-step speed reference (d1-02 to d1-17 [Reference 2 to 8, Jog Reference]) • 3-01: Serial communications • 4-01: Communication option card • 7-01: Reserved • 9-01: Reserved • B-00: Hand Reference 1 (Analog) • B-01: Hand Reference 1 (S5-05 [HAND Frequency Reference]) | No signal output available |
| U4-19 (07DB) | Modbus FreqRef (dec) | Shows the frequency reference sent to the drive from the MEMOBUS/Modbus communications as a decimal. Unit: 0.01% | 10 V: Maximum frequency (0 V to +10 V) |
| U4-20 (07DC) | Option Freq Ref (dec) | Shows the frequency reference sent to the drive from the communication option as a decimal. | 10 V: Maximum frequency (0 V to +10 V) |
| U4-21 (07DD) | Run Command Source | Shows the selected Run command source. The keypad shows the Run command source as "XY-nn" as specified by these rules: X: Run command <ul style="list-style-type: none"> • 0: OFF • 1: AUTO • 2: HAND • 3: JOG, Emergency Override Y: Run command source <ul style="list-style-type: none"> • 0: Keypad • 1: Control circuit terminal • 3: Serial communications • 4: Communication option card • 7: Reserved nn: Run command limit status data <ul style="list-style-type: none"> • 00: No limit status. • 01: The Run command stayed ON when the drive stopped in Programming Mode. • 03: The Run command is in standby after the drive was energized until the soft charge bypass contactor turns ON. Note: The drive will detect $Uv1$ [DC Bus Undervoltage] or Uv [Undervoltage] if the soft charge bypass contactor does not turn ON after 10 s. <ul style="list-style-type: none"> • 04: Will not restart after run stop. • 05: An MFDI terminal caused a Fast stop or you pushed  on the keypad to ramp the motor to stop. • 06: $b1-17 = 0$ [Run Command at Power Up = Disregard Existing RUN Command]. • 07: During baseblock while coast to stop with timer. • 08: Frequency reference is less than $E1-09$ [Minimum Output Frequency] during baseblock. • 09: Waiting for the Enter command from PLC. | No signal output available |

| No. (Hex.) | Name | Description | MFAO Signal Level |
|---------------------------|----------------------|--|----------------------------|
| U4-22 (07DE) | Modbus CmdData (hex) | Shows the operation signal (register 0001H) sent to the drive from MEMOBUS/Modbus communications as a 4-digit hexadecimal number (zero suppress). The keypad shows the operation signal as specified by these rules: bit 0 : Forward run/Stop bit 1 : Reverse run/Stop bit 2 : External fault bit 3 : Fault Reset bit 4 : Multi-function input 1 bit 5 : Multi-function input 2 bit 6 : Multi-function input 3 bit 7 : Multi-function input 4 bit 8 : Multi-function input 5 bit 9 : Multi-function input 6 bit A : Multi-function input 7 bit B : Not used (normal value of 0). bit C : Not used (normal value of 0). bit D : Not used (normal value of 0). bit E : Not used (normal value of 0). bit F : Not used (normal value of 0). | No signal output available |
| U4-23 (07DF) | Option CmdData (hex) | Shows the operation signal (register 0001H) sent to the drive from MEMOBUS/Modbus communications as a 4-digit hexadecimal number. The keypad shows the operation signal as specified by these rules: bit 0 : Forward run/Stop bit 1 : Reverse run/Stop bit 2 : External fault bit 3 : Fault Reset bit 4 : Multi-function input 1 bit 5 : Multi-function input 2 bit 6 : Multi-function input 3 bit 7 : Multi-function input 4 bit 8 : Multi-function input 5 bit 9 : Multi-function input 6 bit A : Multi-function input 7 bit B : Not used (normal value of 0). bit C : Not used (normal value of 0). bit D : Not used (normal value of 0). bit E : Not used (normal value of 0). bit F : Not used (normal value of 0). | No signal output available |
| U4-24 (07E6) | Number of Runs (Low) | Shows the lower 4 digits of the drive run count. Note: The drive run count is an 8-digit number. Monitor <i>U4-25 [Number of Runs(High)]</i> shows the upper 4 digits and <i>U4-24</i> shows the lower 4 digits. | No signal output available |
| U4-25 (07E7) | Number of Runs(High) | Shows the lower 4 digits of the drive run count. Note: The drive run count is an 8-digit number. Monitor <i>U4-25</i> shows the upper 4 digits and <i>U4-24 [Number of Runs (Low)]</i> shows the lower 4 digits. | No signal output available |
| U4-61 (3096) Expert | Total EMOVR Run Time | Shows the length of time that the drive operated in Emergency Override Mode. Unit: 1 min Note: • The maximum value is 60,000 min. • This monitor does not accumulate operation time when <i>S6-07 = 1 [EMOVR Fault Suppression Mode = Test Mode]</i> . | No signal output available |

◆ U5: PID Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|-----------------|--------------|--|--|
| U5-01 (0057) | PID Feedback | Shows the PID control feedback value. Unit: 0.01% Note: Parameters <i>b5-46 [PID Unit Display Selection]</i> , <i>b5-38 [PID User Unit Display Scaling]</i> , and <i>b5-39 [PID User Unit Display Digits]</i> set the unit, range, and resolution. | 10 V = Maximum frequency (-10 V to +10 V) |
| U5-02 (0063) | PID Input | Shows the change between the PID setpoint and PID feedback (the quantity of PID input) as a percentage of the maximum output frequency. Unit: 0.01% | 10 V: Maximum frequency (0 V to +10 V) |

7.15 U: Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|----------------------|--|--|
| U5-03 (0064) | PID Output | Shows the PID control output as a percentage of the maximum output frequency. Unit: 0.01% | 10 V: Maximum frequency (0 V to +10 V) |
| U5-04 (0065) | PID Setpoint | Shows the PID setpoint. Unit: 0.01% Note: Parameters <i>b5-46 [PID Unit Display Selection]</i> , <i>b5-38 [PID User Unit Display Scaling]</i> , and <i>b5-39 [PID User Unit Display Digits]</i> set the unit, range, and resolution. | 10 V = Maximum frequency (-10 V to +10 V) |
| U5-05 (07D2) | PID DifferentialFdbk | Shows the PID differential feedback value as a percentage of the maximum output frequency. This monitor is available after you set <i>H3-02</i> or <i>H3-10 = 16 [Terminal A1/A2 Function Selection = Differential PID Feedback]</i> . Unit: 0.01% | 10 V = Maximum frequency (-10 V to +10 V) |
| U5-06 (07D3) | PID FdbkDif PID Fdbk | Shows the difference from calculating " <i>U5-05 [PID DifferentialFdbk] - U5-01 [PID Feedback]</i> ". Unit: 0.01% Note: <i>U5-01 [PID Feedback] = U5-06</i> when <i>H3-02</i> or <i>H3-10 ≠ 16 [Terminal A1/A2 Function Selection ≠ Differential PID Feedback]</i> . | 10 V = Maximum frequency (-10 V to +10 V) |
| U5-07 (0072) | AUTO Mode Freq Ref | Shows the Frequency reference value at AUTO Mode. Unit: 0.01 Hz Note: Parameter <i>o1-03 [Frequency Display Unit Selection]</i> sets the display unit. | No signal output available |
| U5-08 (0073) | HAND Mode Freq Ref | Shows the Frequency reference value at HAND Mode. Unit: 0.01 Hz Note: Parameter <i>o1-03 [Frequency Display Unit Selection]</i> sets the display unit. | No signal output available |
| U5-14 (086B) | PID Out2 Upr4 Digits | Shows the custom PI output. Monitor <i>U5-14</i> shows the upper four digits and <i>U5-15 [PID Out2 Lwr4 Digits]</i> shows the lower four digits. The drive uses <i>b5-43 [PID Out2 Monitor MAX Upper4 Dig]</i> and <i>b5-44 [PID Out2 Monitor MAX Lower4 Dig]</i> to scale the monitors. Unit: 1 Note: Parameter <i>b5-41 [PID Output 2 Unit]</i> sets the display unit. | 10 V = $b5-43 \times 10000$ |
| U5-15 (086C) | PID Out2 Lwr4 Digits | Shows the custom PI output. Monitor <i>U5-14</i> shows the upper four digits and <i>U5-15 [PID Out2 Lwr4 Digits]</i> shows the lower four digits. The drive uses <i>b5-43 [PID Out2 Monitor MAX Upper4 Dig]</i> and <i>b5-44 [PID Out2 Monitor MAX Lower4 Dig]</i> to scale the monitors. Unit: 0.01 Note: Parameter <i>b5-41 [PID Output 2 Unit]</i> sets the display unit. | $b5-43 > 0$: 10 V = 10000 $b5-43 = 0$: 10 V = $b5-44$ |
| U5-16 (086D) | PI Aux Ctrl Feedback | Shows the PI Auxiliary Control Feedback level from the terminal set for <i>H3-xx = 27 [PI Auxiliary Control Feedback]</i> . Unit: PSI Note: Parameters <i>YF-21 [PI Aux Ctrl Level Unit Selection]</i> and <i>YF-22 [PI Aux Level Decimal Place Pos]</i> set the unit and resolution. | No signal output available |
| U5-17 (086E) | PI2 Control Setpoint | Shows the PI2 Control setpoint. Note: Parameters <i>S3-04 [PI2 Control Unit Selection]</i> and <i>S3-03 [PI2 Control Decimal Place Pos]</i> set the unit and resolution. | 10 V = S3-02 |
| U5-18 (086F) | PI2 Control Feedback | Shows the PI2 Control Feedback Level from the terminal set for <i>H3-xx = 26 [PI2 Control Feedback]</i> . Note: Parameters <i>S3-04 [PI2 Control Unit Selection]</i> and <i>S3-03 [PI2 Control Decimal Place Pos]</i> set the unit and resolution. | 10 V = S3-02 |
| U5-19 (0870) | PI2 Control Input | Shows the PI2 Control input (deviation between PI target and feedback). Note: Parameters <i>S3-04 [PI2 Control Unit Selection]</i> and <i>S3-03 [PI2 Control Decimal Place Pos]</i> set the unit and resolution. | 10 V = S3-02 |
| U5-20 (0871) | PI2 Control Output | Shows the PI2 Control output. Note: • Parameters <i>S3-04 [PI2 Control Unit Selection]</i> and <i>S3-03 [PI2 Control Decimal Place Pos]</i> set the unit and resolution. • The drive operation while <i>H1-xx = A8</i> or <i>1A8 [PI2 Control Disable]</i> changes when the <i>S3-12 [PI2 Control Disable Mode Sel]</i> setting changes. | 10 V = S3-02 |

| No. (Hex.) | Name | Description | MFAO Signal Level |
|-----------------|---------------------|--|---|
| U5-30 (3000) | Time Hr Min HHMM | Shows the current time (Hours and Minutes). | No signal output available |
| U5-31 (3001) | Date Year | Shows the current year. | No signal output available |
| U5-32 (3002) | Date Mo Day MMDD | Shows the current date (Month and Date). | No signal output available |
| U5-33 (3003) | Date Week | Shows the current date of the week. bit 0 : Sunday bit 1 : Monday bit 2 : Tuesday bit 3 : Wednesday bit 4 : Thursday bit 5 : Friday bit 6 : Saturday bit 7 : Not used (normal value of 0). | No signal output available |
| U5-79 (3B9A) | PID Feedback Backup | Shows the <i>PID Feedback Backup</i> [H3-xx = 24] signal that the drive uses when it loses the <i>PID Feedback</i> [H3-xx = B]. Unit: 0.01% Note: Display unit and scaling are dependent on System Units. | No signal output available |
| U5-81 (3B9C) | Diff Level Source | Shows the Differential Feedback signal from the terminal set for H3-xx = 2D [<i>Differential Level Source</i>]. Unit: 0.00% Note: Unit and display scaling are dependent on System Units. | No signal output available |
| U5-99 (1599) | Setpoint | Shows the PID setpoint command. Unit: 0.01% Note: Parameters b5-46 [<i>PID Unit Display Selection</i>], b5-38 [<i>PID User Unit Display Scaling</i>], and b5-39 [<i>PID User Unit Display Digits</i>] set the unit, range, and resolution. | 10 V = Maximum frequency (-10 V to +10 V) |

◆ U6: Operation Status Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|---------------------------|----------------------|--|--|
| U6-01 (0051) | Iq Secondary Current | Shows the value calculated for the motor secondary current (q-Axis) as a percentage of the motor rated secondary current. Unit: 0.1% | 10 V: Motor secondary rated current (0 V to +10 V) |
| U6-17 (07D1) Expert | Energy Save Coeff | Shows the total time of direction of motor rotation detections for Speed Estimation Speed Searches. This value adjusts b3-26 [<i>Direction Determination Level</i>]. Note: Upper limit is +32767 and lower limit is -32767. | No signal output available |
| U6-21 (07D5) | Offset Frequency | Shows the total value of d7-01 to d7-03 [<i>Offset Frequency 1 to 3</i>] selected with <i>Add Offset Frequency 1 to 3</i> [H1-xx = 44 to 46]. Unit: 0.1% | 10 V: Maximum Frequency |
| U6-31 (007B) | TorqueDetect Monitor | Monitors the torque reference or the output current after applying the filter. Unit: 0.1% | 10 V:100% |
| U6-36 (0720) Expert | Comm Errors-Host | Shows the number of inter-CPU communication errors. When you de-energize the drive, this value resets to 0. | No signal output available |
| U6-37 (0721) Expert | Comm Errors-Sensor | Shows the number of inter-CPU communication errors. When you de-energize the drive, this value resets to 0. | No signal output available |
| U6-80 (07B0) | Option IP Address 1 | Shows the currently available local IP Address (1st octet). | No signal output available |
| U6-81 (07B1) | Option IP Address 2 | Shows the currently available local IP Address (2nd octet). | No signal output available |
| U6-82 (07B2) | Option IP Address 3 | Shows the currently available local IP Address (3rd octet). | No signal output available |

7.15 U: Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|---------------------|---|----------------------------|
| U6-83 (07B3) | Option IP Address 4 | Shows the currently available local IP Address (4th octet). | No signal output available |
| U6-84 (07B4) | Online Subnet 1 | Shows the currently available subnet mask (1st octet). | No signal output available |
| U6-85 (07B5) | Online Subnet 2 | Shows the currently available subnet mask (2nd octet). | No signal output available |
| U6-86 (07B6) | Online Subnet 3 | Shows the currently available subnet mask (3rd octet). | No signal output available |
| U6-87 (07B7) | Online Subnet 4 | Shows the currently available subnet mask (4th octet). | No signal output available |
| U6-88 (07B8) | Online Gateway 1 | Shows the currently available Gateway address (1st octet). | No signal output available |
| U6-89 (07B9) | Online Gateway 2 | Shows the currently available Gateway address (2nd octet). | No signal output available |
| U6-90 (07F0) | Online Gateway 3 | Shows the currently available Gateway address (3rd octet). | No signal output available |
| U6-91 (07F1) | Online Gateway 4 | Shows the currently available Gateway address (4th octet). | No signal output available |
| U6-92 (07F2) | Online Speed | Shows the currently available communications speed. 10: 10 Mbps 100: 100 Mbps | No signal output available |
| U6-93 (07F3) | Online Duplex | Shows the currently available Duplex setting. | No signal output available |
| U6-98 (07F8) | First Fault | Shows the contents of the most recent communication options fault (Modbus TCP/IP, EtherNet/IP). | No signal output available |
| U6-99 (07F9) | Current Fault | Shows the contents of current fault from communication options (Modbus TCP/IP, EtherNet/IP). | No signal output available |

◆ Ub: Bypass Control Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|-----------------------------|---|----------------------------|
| Ub-01 (8780) | Motor Current | Format is XXX.X amps. The number of decimal places depends on drive kVA rating. Unit: Amp | No signal output available |
| Ub-02 (8781) | Bypass Digital Input Status | View status of bypass digital inputs XXXXXXXX Where X = 0 (not asserted) or 1 (asserted) The right-most digit is the status of digital input 1. This monitor will show the digital input status and any digital input forced to "ON" over serial communications. Unit: - bit 0 : Digital Input 1 (TB2-1) bit 1 : Digital Input 2 (TB2-2) bit 2 : Digital Input 3 (TB2-3) bit 3 : Digital Input 4 (TB2-4) bit 4 : Digital Input 5 (TB2-5) bit 5 : Digital Input 6 (TB2-6) bit 6 : Digital Input 7 (TB2-7) bit 7 : Digital Input 8 (TB2-8) | No signal output available |

| No. (Hex.) | Name | Description | MFAO Signal Level |
|-----------------|-----------------------------------|--|----------------------------|
| Ub-03 (8782) | Bypass Digital Output Status | View status of bypass digital outputs XXXXXXXX Where X = 0 (not asserted) or 1 (asserted) The right-most digit is the status of K1 (Input Contactor). Unit: - bit 0 : K1 (Input Contactor) bit 1 : K2 (Output Contactor) bit 2 : K3 (Bypass Contactor) bit 3 : K4 (Motor 1 Output Contactor) bit 4 : K5 (Motor 2 Output Contactor) bit 5 : Fan Output Relay bit 6 : Digital Output 7 (TB1 1~3) (Z2-23) bit 7 : Digital Output 8 (TB1 4~6) (Z2-24) bit 8 : Digital Output 9 (TB1 7~9) (Z2-25) bit 9 : Digital Output 10 (TB1 10~12) (Z2-26) bit 10, 11 : Reserved | No signal output available |
| Ub-04 (8783) | Bypass Dig Out Status D09/ D10 | View status of bypass digital outputs XXXXXXXX Where X = 0 (not asserted) or 1 (asserted) The right-most digit is the status of digital output 9. Unit: - bit 0 : Digital Output 9 (TB1 7~9) (Z2-25) bit 1 : Digital Output 10 (TB1 10 ~ 12) (Z2-26) | No signal output available |
| Ub-05 (8784) | Bypass Status 1 | bit 0 : HAND Mode : 0: Not in HAND : 1: In HAND Mode bit 1 : OFF Mode : 0: Not in OFF : 1: In OFF Mode bit 2 : AUTO Mode : 0: Not in AUTO : 1: In AUTO Mode bit 3 : DRIVE mode (cmd) : 0: Drive mode not commanded : 1: Drive mode commanded bit 4 : BYPASS mode (cmd) : 0: Bypass mode not commanded : 1: Bypass mode commanded bit 5 : Emergency override BYP Act : 0: Not active : 1: Emergency override bypass is active bit 6 : Emergency override DRV Act : 0: Not active : 1: EMOV Drive is active (Emergency override drive) bit 7 : Safety Open : 0: All programmed safeties closed : 1: At least one programmed safety open bit 8 : Alarm Active : 0: No Alarm : 1: Alarm bit 9 : Drive Run active : 0: Not running in drive : 1: Running in drive mode bit 10 : Bypass run active : 0: Not running in bypass : 1: Running in bypass mode bit 11 : Emergency override Drive REV : 0: running FWD : 1: running REV bit 12 : Drive comms active : 0: Drive comms Not active : 1: Drive comms active bit 13 : System READY : 0: Not READY : 1: READY Note: Bits 12 and 13 are not shown on the keypad. You can use serial communications to read them. Unit: - | No signal output available |

7.15 U: Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|-----------------|-----------------------|--|----------------------------|
| Ub-06 (8785) | Bypass Status 2 | bit 0 : Interlock Open : 0: Interlock is pen : 1: Interlock is closed bit 1 : RUN active : 0: No RUN active : 1: Bypass or Drive run active bit 2 : Fault active : 0: Fault not active : 1: Fault active bit 3 : Auto Xfer Active : 0: Auto Xfer not Active : 1: Auto Xfer Active bit 4 : Remote Xfer Active : 0: Remote Xfer not Active : 1: Remote Xfer Active bit 5 : Energy Sav Active : 0: Energy Savings not Active : 1: Energy Savings Active bit 6 : Motor 1 Selected : 0: Motor 1 not Selected : 1: Motor 1 Selected bit 7 : Motor 2 Selected : 0: Motor 2 not selected : 1: Motor 2 selected bit 8 : Run verify detected : 0: Run verify not detected : 1: Run verify detected bit 9 : Restart delay active : 0: Restart delay not active : 1: Restart delay active bit 10 to 15 : Reserved Unit: - | No signal output available |
| Ub-07 (8786) | Bypass Fault Status 1 | bit 0 : Drive Fault bit 1 : Safety Open bit 2 : FB02-Wait For Interlock Timeout bit 3 : FB03-External Fault Bypass (EFB) bit 4 : FB13-Loss Of Load bit 5 : FB05-Motor Overload (Internal, Electronic) bit 6 : FB06-External Overload 1 bit 7 : FB07-External Overload 2 bit 8 to 11 : Reserved Unit: - | No signal output available |
| Ub-08 (8787) | Bypass Fault Status 2 | bit 0 : FB08-Brownout Detected bit 1 : FB09-Blackout Detected bit 2 : FB10-Loss of Drive Communications bit 3 : FB15-Input Phase Loss bit 4 : FB26-Option on Drive Detected bit 5 : FB13-Loss of Load bit 6 : CE-Serial Communications Error bit 7 : FB16-Input Phase Rotation bit 8 : FB18-Welded Bypass Contactor Detected bit 9 to 11 : Reserved Unit: - | No signal output available |
| Ub-09 (8788) | Current Fault | Displays the current fault. Unit: - | No signal output available |
| Ub-10 (8789) | Current Fault YYYY | Displays the year of the current fault. Unit: - | No signal output available |
| Ub-11 (878A) | Current Fault MMDD | Displays the month and day of the current fault. Unit: - | No signal output available |
| Ub-12 (878B) | Current Fault HHMM | Displays the hour and minute of the current fault. Unit: - | No signal output available |

| No. (Hex.) | Name | Description | MFAO Signal Level |
|---------------------|--------------------------------|--|----------------------------|
| Ub-13 (878C) | Previous Fault | Displays the previous fault. Unit: - | No signal output available |
| Ub-14 (878D) | Previous Fault YYYY | Displays the year of the previous fault. Unit: - | No signal output available |
| Ub-15 (878E) | Previous Fault MMDD | Displays the month and day of the previous fault. Unit: - | No signal output available |
| Ub-16 (878F) | Previous Fault HHMM | Displays the hour and minute of the previous fault. Unit: - | No signal output available |
| Ub-17 (8790) | Contacting Voltage | Displays the measured voltage for the power going to the contactor coils. Unit: 1 Vac | No signal output available |
| Ub-18 (8791) | Software Version | Displays the software version currently programmed into the bypass. Unit: - | No signal output available |
| Ub-19 (8792) | Date Year YYYY | Displays the current year. Unit: - | No signal output available |
| Ub-20 (8793) | Date Month Day MMDD | Displays the current date (Month and Date). Unit: - | No signal output available |
| Ub-21 (8794) | Time Hour Min HHMM | Displays the current time (Hours and Minutes). Unit: - | No signal output available |
| Ub-22 (8795) | Bypass Analog Input | Bypass MFAI level Unit: 0-100% | No signal output available |
| Ub-23 (8796) | Motor 1 Overload | Motor 1 Overload level Unit: 0-100% | No signal output available |
| Ub-24 (8797) | Motor 2 Overload | Motor 2 Overload level Unit: 0-100% | No signal output available |
| Ub-94 (87DD) | Bypass CPU Usage | Current Bypass CPU Load Unit: 0-100% | No signal output available |
| Ub-95 (87DE) | Line Frequency | Calculated AC line frequency Unit: Hz | No signal output available |
| Ub-96 (87DF) | By Phase Loss Level | Current Phase Loss level Unit: 0-100% | No signal output available |
| Ub-99 (87E2) Expert | Desired HV600 software version | Shows the latest version of HV600 software that this version of HV600 Bypass software supports. Unit: - | No signal output available |

◆ UC: BACnet Diagnostic Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|--------------|---------------------|---|----------------------------|
| UC-01 (3DB0) | BN MSTP Net Health | Shows a number between 0.0% and 100.0% that identifies the health of the MSTP network. This number is dependent on the number of CRC errors, token losses, token retries, and net deadtime perceived. Unit: 0.1% | No signal output available |
| UC-02 (3DB1) | BACnet Tokens Rx | Shows the number of received MSTP Tokens after you energize the drive. Unit: 1 | No signal output available |
| UC-03 (3DB2) | BACnet Tokens Tx | Shows the number of transmitted MSTP Tokens after you energize the drive. Unit: 1 | No signal output available |
| UC-04 (3DB3) | BACnet Messages Rx | Shows the number of messages with data (non-token, non-polling) received by the drive. Unit: 1 | No signal output available |
| UC-05 (3DB4) | BACnet Messages Tx | Shows the number of messages with data (non-token, non-polling) transmitted by the drive. Unit: 1 | No signal output available |
| UC-06 (3DB5) | MSTP Next Node Addr | Shows the next known node in the MSTP loop. This is the node to which the drive will pass the token. Unit: Hex | No signal output available |
| UC-07 (3DB6) | MSTP Prev Node Addr | Shows the previous known node in the MSTP loop. This is the node from which the drive received the token. Unit: Hex | No signal output available |

7.15 U: Monitors

| No. (Hex.) | Name | Description | MFAO Signal Level |
|---------------------------|----------------------|--|----------------------------|
| UC-08 (3DB7) | MSTP H MAC Found | Shows the highest MAC address found on the network. This will report the highest value MAC address to which the token was passed by any node on the MSTP loop. Unit: Hex | No signal output available |
| UC-09 (3DB8) | MSTP L MAC Found | Shows the lowest MAC address found on the network. This will report the lowest value MAC address to which the token was passed by any node on the MSTP loop. Unit: Hex | No signal output available |
| UC-10 (3DB9) | MSTP # Nodes Found | Shows the number of unique nodes that transmitted a token on the local MSTP loop. Unit: 1 | No signal output available |
| UC-11 (3DBA) | # of BN COV Sbscrt | Shows the number of COV subscriptions requested by the nodes on the BACnet network. This is limited to the number of objects that support COV subscriptions. Unit: 1 | No Signal output available |
| UC-12 (3DBB) | MSTP Loop Tlme | Shows the number of milliseconds between drive transmitted token and drive token received, showing how long the MSTP loop took to pass the token to all nodes on the MSTP network. Unit: 1 ms | No signal output available |
| UC-13 (3DBC) Expert | BN MSTP CRC Errors | Shows the number of CRC errors detected after you energize the drive. Unit: 1 | No signal output available |
| UC-14 (3DBD) Expert | BN MSTP Tokens Lost | Shows the number of token losses seen by the unit since power-on. This is sensed by a net deadtime of more than 500 ms. Unit: 1 | No signal output available |
| UC-15 (3DBE) Expert | BN MSTP Tokens Retry | Shows the number of token retries seen by the unit since power-on. This is sensed by two subsequent token frames seen from the same node to the same node with the same CRC. Unit: 1 | No signal output available |
| UC-16 (3DBF) Expert | BN MSTP Silence Avg | Shows the average net deadtime (space between active messages), averaged over a 60 packet period. Unit: 1.0 ms | No signal output available |

Network Communications

| | | |
|------------|---|------------|
| 8.1 | Section Safety | 262 |
| 8.2 | Fieldbus Network Support | 263 |
| 8.3 | BACnet Communications..... | 264 |
| 8.4 | Other Embedded Communication Protocols | 283 |

8.1 Section Safety

 **DANGER**

Do not ignore the safety messages in this manual.

If you ignore the safety messages in this manual, it will cause serious injury or death. The manufacturer is not responsible for injuries or damage to equipment.

8.2 Fieldbus Network Support

You can use a PLC or building automation controller to control and monitor the bypass through the network. The bypass has a standard RS-485 interface (serial communications). Install a separately sold communication option on the bypass to support other network communications.

◆ Available Communication Options

Refer to [Table 8.1](#) for the fieldbus networks that are compatible with the bypass. Contact Yaskawa or your nearest sales representative to order a communication option.

Table 8.1 Available Fieldbus Network

| Type of Communications | Option Models | Type of Communications | Option Models |
|------------------------|---------------|-------------------------|---------------|
| LonWorks | SI-W3 | Dual port Modbus TCP/IP | SI-EM3D |
| Modbus TCP/IP | SI-EM3 | Dual port EtherNet/IP | SI-EN3D |
| PROFINET | SI-EP3 | BACnet/IP | JOHB-SMP3 |
| EtherNet/IP | SI-EN3 | | |

8.3 BACnet Communications

This section gives detailed information about the parameters, error codes, and communication procedures for BACnet communications.

◆ Configure Master/Slave

You can monitor and control the bypasses from a controller on a Building Automation and Control network (BACnet) with RS-485 technology and Master-Slave/Token-Passing (MS-TP) protocol. The drives agree with the device profile of the BACnet Application Specific Controller (B-ASC).

A maximum of 127 bypasses can communicate on a single BACnet MS-TP network depending on network conditions. When more bypasses or BACnet devices are necessary, a BACnet router is necessary to let another MS-TP network be available with a possible maximum of another 127 bypasses.

You can use parameters to set the MSTP MAC address, MSTP baud rate, and Device Object ID. You can also use parameters to set Device object properties Max Masters and Max Info Frames. Set other Device Object properties, for example Device Object Name and Device Object Location, through the BACnet network after you connect the bypass and the bypass is communicating.

When you set the addressing, a controller can start communication to the bypass. The bypass will do the specified function and send a response back to the controller. The bypass will usually respond immediately, but can delay its response until it gets the token for commands that can take longer local processing time.

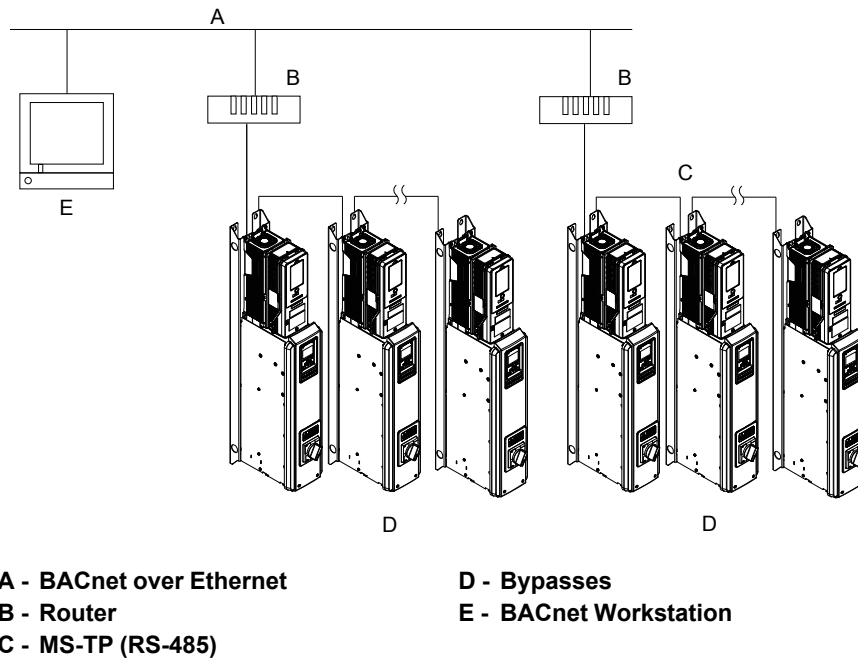


Figure 8.1 Connection Example of Multiple Bypasses to a BACnet Workstation

◆ Communication Specifications

Table 8.2 lists the specifications for the BACnet communications.

Table 8.2 BACnet Specifications

| Item | Specifications |
|-------------------------------------|--|
| Interface | Master-Slave/Token-Passing (MS-TP) |
| | RS-485 |
| Communication parameter | Communications speed: 9.6, 19.2, 38.4, 76.8 kbps |
| | Data length: 8 bit (fixed) |
| | Parity: even, odd, none |
| | Stop Bit: 1 bit (fixed) |
| Communication protocol | BACnet MS-TP |
| Number of possible units to connect | Maximum: 127 units for each MS-TP network segment depending on network conditions. |

◆ Communication with the Controller

This section gives information about the settings for the termination resistor and how to connect to BACnet communications.

■ Connect Communications Cable

Use this procedure to start communication between the controller and bypass.

1. De-energize the bypass then connect the communications cable to the controller and the bypass. The bypass uses terminal TB3 for serial communications.

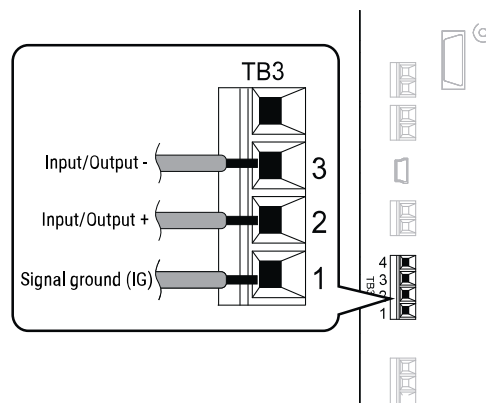


Figure 8.2 Communications Cable Connection Terminal (TB3)

Note:

Isolate the communications wiring from the main circuit wiring and other high-power wiring. Use shielded wires for the communications wiring and connect cable sheaths as shown in "Wiring Diagram for More than One Bypass". Incorrect wiring procedures could cause bypass malfunction because of electrical interference.

2. Enable the termination resistor ONLY when the bypass is at the end of the communications network. Set DIP switch S1 to the "ON" position to enable the termination resistor. Refer to "Set the Termination Resistor" for more information.
3. Energize the bypass.
4. Use the keypad to set the necessary communications parameters *H5-01 to H5-11*.
 - *H5-01 [Drive Node Address]*
 - *H5-02 [Communication Speed Selection]*
 - *H5-04 [Stopping Method after Com Error]*
 - *H5-05 [Comm Fault Detection Select]*
 - *H5-08 [Communication Protocol Selection]*
 - *H5-09 [CE Detection Time]*
5. Because communications parameters do not take effect immediately, either de-energize and re-energize the bypass or set *H5-20 = 1 [Communication Parameters Reload = Reload Now]*.

The bypass is prepared to start communication with the controller.

■ Set the Termination Resistor

You must enable the termination resistor on the serial terminals of the devices on the two physical ends of the network to use serial communications. Use DIP switch S1 on the bypass control PCB to enable and disable the built-in termination resistor. Refer to [Figure 8.3](#) for an example of how to set DIP switch S1. Use the tip of a tweezers or a small flat-blade screwdriver to set the DIP switch. When you install the bypass at the end of the network line, set DIP switch S1 to “ON” to enable the termination resistor. Set DIP switch S1 to “OFF” on all other bypasses.

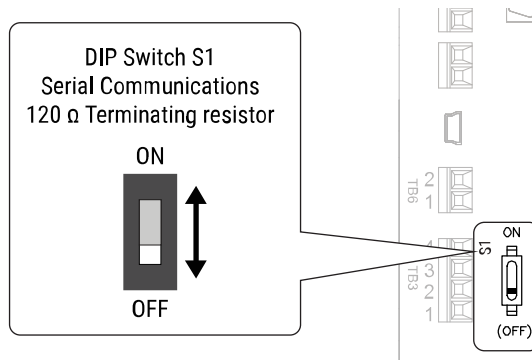


Figure 8.3 Termination Resistor DIP Switch S1

■ Wiring Diagram for More than One Bypass

[Figure 8.4](#) shows how to wire more than one connected bypass using serial communications.

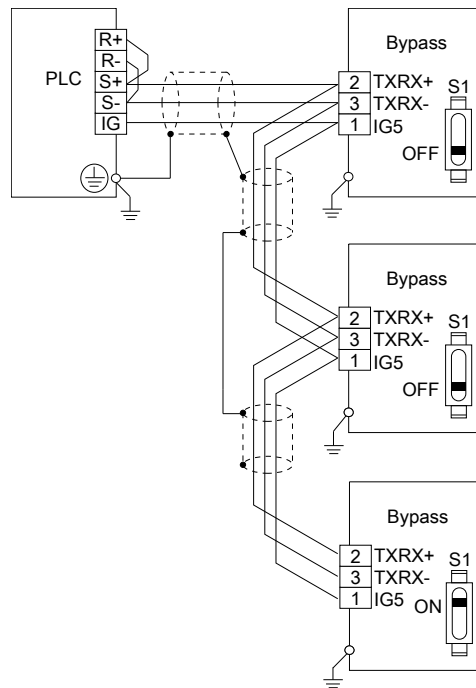


Figure 8.4 Wiring Diagram for More than One Bypass

Note:

When you install the bypass at the end of the network line, set DIP switch S1 to “ON” to enable the termination resistor. Set DIP switch S1 to “OFF” on all other bypasses.

◆ Bypass Operations by Serial Communications

Parameters will apply to the settings when the bypass is running during serial communications. This section gives information about the available functions and their related parameters.

■ Executable Functions

A controller can do these operations with serial communications. Parameter settings (except *H5-xx*) do not have an effect on the availability of these operations.

- Monitor the bypass status and operate the bypass
- Set and view parameters
- Fault Reset Procedure

■ Bypass Control

To use external commands to set the frequency references and motor run/stop with serial communications, set these parameters as specified by the application:

- *b1-01 = 2 [Frequency Reference Selection 1 = Serial Communications]*
- *b1-02 = 2 or 8 [Run Command Selection 1 = Serial Communications or AUTO Command + Serial Run]*

For more information about operation mode selection, refer to *b1-01* and *b1-02*.

◆ BACnet Objects Supported

■ Present Value Access

The Present Value (PV) of BACnet objects can always be read. Some PVs can also be written or commanded. A commandable PV is similar to a writable PV, but the value is actually written into a priority array. The value that then has the highest priority in the array will be used by the drive.

Table 8.3 Present Value Access Types and Descriptions

| PV Access | Name | Description |
|-----------|-------------|--|
| C | Commandable | Value written to a priority array. The highest priority value in the array is then written to the drive. |
| R | Readable | Value is read-only |
| W | Writable | Value written to the drive |

■ Supported Properties of Objects

Table 8.4 Object Properties

| Property | Object Type | | | | | | |
|---------------------------------|-------------|-------------------|--------------------|-------------------|-------------------|--------------------|-------------------|
| | Device | Analog Input (AI) | Analog Output (AO) | Analog Value (AV) | Binary Input (BI) | Binary Output (BO) | Binary Value (BV) |
| Object_Identifier | Yes | Yes | Yes | Yes | Yes | Yes | Yes |
| Object_Name | Yes | Yes | Yes | Yes | Yes | Yes | Yes |
| Location | Yes | - | - | - | - | - | - |
| Object_Type | Yes | Yes | Yes | Yes | Yes | Yes | Yes |
| System_Status | Yes | - | - | - | - | - | - |
| Vendor_Name | Yes | - | - | - | - | - | - |
| Vendor_Identifier | Yes | - | - | - | - | - | - |
| Model_Name | Yes | - | - | - | - | - | - |
| Firmware_Revision | Yes | - | - | - | - | - | - |
| Protocol_Version | Yes | - | - | - | - | - | - |
| Protocol_Revision | Yes | - | - | - | - | - | - |
| Protocol_Services_Supported | Yes | - | - | - | - | - | - |
| Protocol_Object_Types_Supported | Yes | - | - | - | - | - | - |
| Object_List | Yes | - | - | - | - | - | - |
| Max_ADPU_Length_Accepted | Yes | - | - | - | - | - | - |

8.3 BACnet Communications

| Property | Object Type | | | | | | |
|--------------------------|-------------|-------------------|--------------------|-------------------|-------------------|--------------------|-------------------|
| | Device | Analog Input (AI) | Analog Output (AO) | Analog Value (AV) | Binary Input (BI) | Binary Output (BO) | Binary Value (BV) |
| Segmentation_Supported | Yes | - | - | - | - | - | - |
| Local_Time | Yes | - | - | - | - | - | - |
| Local_Date | Yes | - | - | - | - | - | - |
| ADPU_Timeout | Yes | - | - | - | - | - | - |
| Number_Of_ADPU_Retries | Yes | - | - | - | - | - | - |
| Max_Masters | Yes | - | - | - | - | - | - |
| Max_Info_Frames | Yes | - | - | - | - | - | - |
| Device_Address_Binding | Yes | - | - | - | - | - | - |
| Database_Revision | Yes | - | - | - | - | - | - |
| Active_COV_Subscriptions | Yes | - | - | - | - | - | - |
| Present_Value | - | Yes | Yes | Yes | Yes | Yes | Yes |
| Status_Flags | - | Yes | Yes | Yes | Yes | Yes | Yes |
| Event_State | - | - | - | - | - | - | - |
| Reliability | - | Yes | Yes | Yes | Yes | Yes | Yes |
| Out_Of_Service | - | Yes | Yes | Yes | Yes | Yes | Yes |
| Units | - | Yes | Yes | Yes | - | - | - |
| Priority_Array | - | - | Yes */ | Yes */ | - | Yes | Yes |
| Relinquish_Default | - | - | Yes */ | Yes */ | - | Yes | Yes |
| Polarity | - | - | - | - | Yes | Yes | - |
| Inactive_Text | - | - | - | - | Yes | Yes | Yes |
| Active_Text | - | - | - | - | Yes | Yes | Yes |
| COV_Increment *2 | - | Yes | Yes | Yes | - | - | - |
| Property_List | Yes | Yes | Yes | Yes | Yes | Yes | Yes |
| Local Time | Yes | - | - | - | - | - | - |
| Local Date | Yes | - | - | - | - | - | - |

*1 For Commandable Object Instances only.

*2 COV function is only available on objects that are not commandable and not writable.

■ Analog Input Objects

| Object ID | Object Name (Network Display, if Different) | Modbus Reg. | Precision | Range | Units | PV Access |
|-----------|--|-------------|-----------|---------|-------|-----------|
| AI1 | Drive Analog Input 1 Level (Drv Anlg In 1 Level) | 004Eh | XXX.X | 0-100.0 | % | R |
| AI2 | Drive Analog Input 2 Level (Drv Anlg In 2 Level) | 004Fh | XXX.X | 0-100.0 | % | R |
| AI3 | Not Used AI3 | 0050h | XXX.X | 0-100.0 | % | R |
| AI4 | Bypass Analog Input 1 Level (Byp Anlg In 1 Level) | 8795h | XXX.X | 0-100.0 | % | R |
| AI5 | Not Used AI5 | - | - | - | - | R |
| AI6 | Display Format o1-03 | 0502h | XXXXX | 0-65535 | - | R |
| AI7 | Scale Format b5-20 | 01E2h | XXXXX | 0-65535 | - | R |

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Precision | Range | Units | PV Access |
|-----------|---|-------------|---|--|-------|-----------|
| AI8 | Inverter Model o2-04 | 0508h | XXXXXX | 0-65535 | - | R |
| AI9 | Rated Current n9-01 | 05D0h | XXXX.X (for drives rated higher than 11 kVA) XXX.XX (for drives rated 11 kVA or lower) | 0-6553.5 (for drives rated higher than 11 kVA) 0-65535 (for drives rated 11 kVA or lower) | A | R |
| AI10 | Motor Current UB-01 | 8780h | XXXX.X (for drives rated higher than 11 kVA) XXX.XX (for drives rated 11 kVA or lower) | 0-6553.5 (for drives rated higher than 11 kVA) 0-65535 (for drives rated 11 kVA or lower) | A | R |
| AI11 | Contactors Voltage | 8790h | XXXXXX | 0-65535 | V | R |

■ Analog Output Objects

| Object ID | Object Name (<i>Network Display</i>) | Modbus Reg. | Precision | Range | Units | PV Access |
|-----------|---|-------------|-----------|---------|-------|-----------|
| AO1 | Drive Terminal FM Analog Output Level Command (set H4-01 = 0) (<i>Drv Anlg Out1 Level</i>) | 0007h | XXX.X | 0-100.0 | % | C |
| AO2 | Drive Terminal AM Analog Output Level Command (Set H4-04 = 0) (<i>Drv Anlg Out2 Level</i>) | 0008h | XXX.X | 0-100.0 | % | C |

■ Analog Value Objects

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Precision | Range | Units | PV Access |
|-----------|---|-------------|-------------------------------|----------|---------------------|-----------|
| AV1 | Drive Operation Command (<i>Operation Cmd</i>) Note: Do not command bypass using AV1. Use BV58 to BV71 instead. | 0001h | - | 0-65535 | Bitmap | C |
| AV2 | Frequency Cmd | 0002h | XXX.XX Determined by o1-03 | 0-600.00 | Determined by o1-03 | C |
| AV3 | PI Setpoint Cmd | 0006h | XXX.XX | 0-100.00 | % | C |

8.3 BACnet Communications

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Precision | Range | Units | PV Access |
|-----------|--|-------------|-----------|---------|--------|-----------|
| AV4 | Drive Multi-Function Output Command <i>(MF Output Cmd)</i> <ul style="list-style-type: none"> • bit 0: Multi-Function Digital Output 1 (terminal M1-M2) • bit 1: Multi-Function Digital Output 2 (terminal M3-M4) • bit 2: Multi-Function Digital Output 3 (terminal M5-M6) • bit 3: Reserved • bit 4: Reserved • bit 5: Reserved • bit 6: Enables the function in bit 7 • bit 7: Fault Contact Output (terminal MA-MB-MC) • bit 8 to F: Reserved <p>Note: When using AV4, do not use BO1 to BO3 or BV12.</p> | 0009h | - | 0-255 | Bitmap | C |
| AV5 | Drive Reference Select Command <i>(Reference Select Cmd)</i> <ul style="list-style-type: none"> • bit 0: Reserved • bit 1: PID Setpoint Input • bit 2: Reserved • bit 3: Reserved • bit 4: PI2 Target Input • bit 5 to B: Reserved • bit C: Multi-Function Input 5 • bit D: Multi-Function Input 6 • bit E: Multi-Function Input 7 • bit F: Reserved <p>Note: When you use AV5, you must not use AV1, BO4, or BV9 to BV11.</p> | 000Fh | - | 0-32767 | Bitmap | C |
| AV6 | System Status <i>(Drive Status)</i> <ul style="list-style-type: none"> • bit 0: During Run (drive or bypass) • bit 1: During Reverse • bit 2: System ready • bit 3: System faulted • bit 4: Data Setting Error • bit 5: Multi-Function Digital Output 1 (terminal M1-M2) • bit 6: Multi-Function Digital Output 2 (terminal M3-M4) • bit 7: Multi-Function Digital Output 3 (terminal M5-M6) • bit 8 to D: Reserved • bit E: ComRef status • bit F: ComCtrl status | 0020h | - | 0-65535 | Bitmap | R |

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Precision | Range | Units | PV Access |
|-----------|---|-------------|-----------------------------------|---------------------------------------|---------------------|-----------|
| AV7 | Fault Details <ul style="list-style-type: none"> • bit 0: oC [Overcurrent], GF [Ground Fault] • bit 1: ov [Overvoltage] • bit 2: oL2 [Drive Overload] • bit 3: oH1 [Heatsink Overheat], oH2 [External Overheat (H1-XX=B)] • bit 4 to 6: Reserved • bit 7: EF to EF7 [External Fault] • bit 8: CPFxx [Hardware Fault] (includes oFxx) • bit 9: oL1 [Motor Overload], oL3 [Overtorque Detection 1], UL3 [Undertorque Detection 1] • bit A: Reserved • bit B: Uv [DC Bus Undervoltage] • bit C: Uv1 [DC Bus Undervoltage], Uv2 [Control Power Undervoltage], Uv3 [Soft Charge Answerback Fault] • bit D: LF [Output Phase Loss], PF [Input Phase Loss] • bit E: CE [Serial Communication Error], bUS [Option Communication Error] • bit F: oPr [Keypad Connection Fault] | 0021h | - | 0-65535 | Bitmap | R |
| AV8 | Data Link Status <ul style="list-style-type: none"> • bit 0: Writing Data • bit 1: Reserved • bit 2: Reserved • bit 3: Upper or lower limit error • bit 4: Data conformity error • bit 5: Writing to EEPROM • bit 6 to F: Reserved | 0022h | - | 0-63 | Bitmap | R |
| AV9 | Frequency Reference | 0040h | XXX.XX Determined by o1-03 | 0-600.00 | Determined by o1-03 | R |
| AV10 | Output Frequency | 0041h | XXX.XX Determined by o1-03 | 0-600.00 | Determined by o1-03 | R |
| AV11 | Output Voltage | 0045h | XXXX.X | 0-6553.5 | V | R |
| AV12 | Output Current | 0026h | XXXX.X | 0-6553.5 | A | R |
| AV13 | Output Power | 0047h | XXXX.X > 11kVA XXX.XX <= 11kVA | 0-6553.5 > 11kVA 0-655.35 <= 11kVA | KW | R |
| AV14 | Torque Reference | 0048h | XXXX.X | 0-100.0 | % | R |
| AV15 | Drive Multi-Function Input Status (<i>MF Input Status</i>) | 002Bh | XXX | 0-127 | Bitmap | R |
| AV16 | Drive Status 2 | 002Ch | XXXXX | 0-65535 | Bitmap | R |
| AV17 | Drive Multi-Function Output Status (<i>MF Output Status</i>) | 002Dh | XXX | 0-135 | Bitmap | R |

8.3 BACnet Communications

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Precision | Range | Units | PV Access |
|-----------|---|--------------------------------|-------------------------------------|---|------------------------------------|-----------|
| AV18 | DC Bus Voltage | 0031h | XXXX.X | 0-6553.5 | V | R |
| AV19 | PI Feedback Level | 0038h | XXXX.X | 0-100.0 | % | R |
| AV20 | PI Input Level | 0039h | XXXX.X | 0-100.0 | % | R |
| AV21 | PI Output Level | 003Ah | XXXX.X | 0-100.0 | % | R |
| AV22 | Drive SW Num | 004Dh | XXXXXX | 0-65535 | - | R |
| AV23 | Bypass SW Num | 8791h | XXXXXX | 0-65535 | - | R |
| AV24 | Comm Error Detail | 003Dh | XXX | 0-127 | Bitmap | R |
| AV25 | KVA Setting | 0508h | XXXXXX | - | Enumerated Data Vendor Specific | R |
| AV26 | Control Method | 0043h | XXXXXX | - | Enumerated Data Vendor Specific | R |
| AV27 | Accel Time | 0200h | XXXX.X | 0-6000.0 | S | W |
| AV28 | Decel Time | 0201h | XXXX.X | 0-6000.0 | S | W |
| AV29 | Parameter Number | ####h Determined in runtime | XXXXXX | 0-65535 | - | W |
| AV30 | Parameter Data | ####h Determined in runtime | XXXXXX | 0-65535 | - | W |
| AV31 | Motor Current | 8780h | XXXX.X > 11 kVA XXX.XX <= 11 kVA | 0-6553.5 > 11 kVA 0-655.35 <= 11 kVA | A | R |
| AV32 | 120V to Kx Coils | 8790h | XXXXXX | 0-65535 | V | R |
| AV33 | Drive kWh consumed (<i>kWh consumed</i>) | 005Ch -005Dh | XXXXXXXXXX | 0-999999999 | kWh | R |
| AV34 | Not Used AV34 | - | - | - | - | R |
| AV35 | Drive Run Time | 004Ch | XXXXXX | 0-65535 | Hours | R |
| AV36 | Out Freq in % | 003Fh | XXX.XX | 0-100.00 | % | R |
| AV37 | Out Freq in RPM | 003Eh | XXXXXX | 0-65535 | RPM | R |
| AV38 | Torque Iq (U6-01) | 0051h | XXXX.X | 0-6553.5 | % | R |
| AV39 | Drive HOA Status | 004Bh | X | 0-2 | - | R |
| AV40 | Last Drive Fault Refer to page 96 for information on fault decimal values. | 0081h | XXXXXX | 0-65535 | - | R |
| AV41 | Last Bypass Fault Refer to page 96 for information on fault decimal values. | 878Ch | XXXXXX | 0-65535 | - | R |
| AV42 | Current Sys Fault (<i>Current Sys Flt</i>) Refer to 96 for information on fault decimal values. | 0080h | XXXXXX | 0-65535 | - | R |

■ Binary Input Objects

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Active Text | Inactive Text | PV Access |
|-----------|---|-------------|-------------|---------------|-----------|
| BI1 | Drive Input Terminal 1 (<i>Input Terminal 1</i>) | 002Bh:bit 0 | ON | OFF | R |
| BI2 | Drive Input Terminal 2 (<i>Input Terminal 2</i>) | 002Bh:bit 1 | ON | OFF | R |
| BI3 | Drive Input Terminal 3 (<i>Input Terminal 3</i>) | 002Bh:bit 2 | ON | OFF | R |

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Active Text | Inactive Text | PV Access |
|-----------|---|-------------|-------------|---------------|-----------|
| BI4 | Drive Input Terminal 4 (<i>Input Terminal 4</i>) | 002Bh:bit 3 | ON | OFF | R |
| BI5 | Drive Input Terminal 5 (<i>Input Terminal 5</i>) | 002Bh:bit 4 | ON | OFF | R |
| BI6 | Drive Input Terminal 6 (<i>Input Terminal 6</i>) | 002Bh:bit 5 | ON | OFF | R |
| BI7 | Drive Input Terminal 7 (<i>Input Terminal 7</i>) | 002Bh:bit 6 | ON | OFF | R |
| BI8 | Drive MF Output 1 (<i>Multi Function Out 1</i>) | 0020h:bit 5 | ON | OFF | R |
| BI9 | Drive MF Output 2 (<i>Multi Function Out 2</i>) | 0020h:bit 6 | ON | OFF | R |
| BI10 | BYP DI-1 STAT | 8781h:bit 0 | ON | OFF | R |
| BI11 | BYP DI-2 STAT | 8781h:bit 1 | ON | OFF | R |
| BI12 | BYP DI-3 STAT | 8781h:bit 2 | ON | OFF | R |
| BI13 | BYP DI-4 STAT | 8781h:bit 3 | ON | OFF | R |
| BI14 | BYP DI-5 STAT | 8781h:bit 4 | ON | OFF | R |
| BI15 | BYP DI-6 STAT | 8781h:bit 5 | ON | OFF | R |
| BI16 | BYP DI-7 STAT | 8781h:bit 6 | ON | OFF | R |
| BI17 | BYP DI-8 STAT | 8781h:bit 7 | ON | OFF | R |
| BI18 | BYP DO-1 STAT | 8782h:bit 0 | ON | OFF | R |
| BI19 | BYP DO-2 STAT | 8782h:bit 1 | ON | OFF | R |
| BI20 | BYP DO-3 STAT | 8782h:bit 2 | ON | OFF | R |
| BI21 | BYP DO-4 STAT | 8782h:bit 3 | ON | OFF | R |
| BI22 | BYP DO-5 STAT | 8782h:bit 4 | ON | OFF | R |
| BI23 | BYP DO-6 STAT | 8782h:bit 5 | ON | OFF | R |
| BI24 | BYP DO-7 STAT | 8782h:bit 6 | ON | OFF | R |
| BI25 | BYP DO-8 STAT | 8782h:bit 7 | ON | OFF | R |
| BI26 | BYP DO-9 STAT | 8783h:bit 0 | ON | OFF | R |
| BI27 | BYP DO-10 STAT | 8783h:bit 1 | ON | OFF | R |
| BI28 | Drive Fault Status | 004Bh:bit 7 | ON | OFF | R |
| BI29 | Drive Alarm Status | 004Bh:bit 6 | ON | OFF | R |
| BI30 | Sys Alarm Status | 8784h:bit 8 | ON | OFF | R |

■ Binary Output Objects

| Object ID | Object Name | Modbus Reg. | Active Text | Inactive Text | PV Access |
|---------------|---------------------|--------------|-------------|---------------|-----------|
| BO1 | MF Output M1 - M2 | 0009h: Bit 0 | ON | OFF | C |
| BO2 | MF Output M3 - M4 | 0009h: Bit 1 | ON | OFF | C |
| BO3 | MF Output M5 – M6 | 0009h: Bit 2 | ON | OFF | C |
| BO4 | Ref Sel:PI Setpoint | 000Fh: Bit 1 | ON | OFF | C |
| BO5 | Ref Sel:Term S5 IN | 0001h: Bit 8 | ON | OFF | C |
| BO6 | Ref Sel:Term S6 IN | 0001h: Bit 9 | ON | OFF | C |
| BO7 | Ref Sel:Term S7 IN | 0001h: Bit A | ON | OFF | C |
| BO8 <i>*1</i> | BYP DO-07 COMMAND | 8403h: Bit 6 | ON | OFF | C |

8.3 BACnet Communications

| Object ID | Object Name | Modbus Reg. | Active Text | Inactive Text | PV Access |
|-----------|-------------------|--------------|-------------|---------------|-----------|
| BO9 *1 | BYP DO-08 COMMAND | 8403h: Bit 7 | ON | OFF | C |
| BO10 *1 | BYP DO-09 COMMAND | 8403h: Bit 8 | ON | OFF | C |
| BO11 *1 | BYP DO-10 COMMAND | 8403h: Bit 9 | ON | OFF | C |

*1 Set the corresponding Z2-xx parameter = 99 - Not Used.

■ Binary Value Objects

| Object ID | Object Name (Network Display, if Different) | Modbus Reg. | Active Text | Inactive Text | PV Access |
|-----------|--|----------------|-------------|---------------|-----------|
| BV1 | Not Used BV001 | - | - | - | C |
| BV2 | Not Used BV002 | - | - | - | C |
| BV3 | Drive External Fault Command (Ext Fault Cmd) | 0001h: Bit 2 | FAULT | OFF | C |
| BV4 | Drive Fault Reset Command (Fault Reset Cmd) | 0001h: Bit 3 | RESET | OFF | C |
| BV5 | Not Used BV005 | - | - | - | C |
| BV6 | Not Used BV006 | - | - | - | C |
| BV7 | Drive Multi-Function Input 3 Command (MF Input 3 Cmd) | 0001h: Bit 6 | ON | OFF | C |
| BV8 | Drive Multi-Function Input 4 Command (MF Input 4 Cmd) | 0001h: Bit 7 | ON | OFF | C |
| BV9 | Drive Multi-Function Input 5 Command (MF Input 5 Cmd) | 0001h: Bit 8 | ON | OFF | C |
| BV10 | Drive Multi-Function Input 6 Command (MF Input 6 Cmd) | 0001h: Bit 9 | ON | OFF | C |
| BV11 | Drive Multi-Function Input 7 Command (MF Input 7 Cmd) | 0001h: Bit A | ON | OFF | C |
| BV12 | Set Fault Contact Cmd (Set Flt Contact Cmd) | 0009h: Bit 6&7 | ENABLE | OFF | C |
| BV13 | RUN-STOP | 0020h: Bit 0 | RUN | OFF | R |
| BV14 | REV-FWD | 0020h: Bit 1 | REV | FWD | R |
| BV15 | READY | 0020h: Bit 2 | READY | OFF | R |
| BV16 | FAULT | 0020h: Bit 3 | FAULTED | OFF | R |
| BV17 | Data Set Error | 0020h: Bit 4 | ERR | OFF | R |
| BV18 | Overcurrent – Ground Fault (Overcurrent– Gnd Fault) | 0021h: Bit 0 | OC – GF | OFF | R |
| BV19 | Main Circuit Overvoltage (Main Ckt Overvoltage) | 0021h: Bit 1 | OV | OFF | R |
| BV20 | Drive Overload | 0021h: Bit 2 | OL2 | OFF | R |
| BV21 | Drive Overheat | 0021h: Bit 3 | OH1-OH2 | OFF | R |
| BV22 | Fuse Blown | 0021h: Bit 5 | PUF | OFF | R |
| BV23 | PI Feedback Loss | 0021h: Bit 6 | FBL | OFF | R |
| BV24 | External Fault | 0021h: Bit 7 | EF0 – EF | OFF | R |
| BV25 | Hardware Error | 0021h: Bit 8 | CPF | OFF | R |

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Active Text | Inactive Text | PV Access |
|-----------|--|--|-------------|---------------|-----------|
| BV26 | Motor Overload – Overtorque (<i>Mtr OvrLd – OvrTorque</i>) | 0021h: Bit 9 | OL1 – OL3 | OFF | R |
| BV27 | Overspeed | 0021h: Bit A | OS –DEV | OFF | R |
| BV28 | Main Circuit Undervoltage (<i>Main Ckt Undervoltage</i>) | 0021h: Bit B | UV | OFF | R |
| BV29 | MCU, Control Power Supply Error (<i>MCU Cntrl Pwr Sy Err</i>) | 0021h: Bit C | UV1-2-3 | OFF | R |
| BV30 | Output Phase Loss | 0021h: Bit D | LF | OFF | R |
| BV31 | Communication Error | 0021h: Bit E | CE | OFF | R |
| BV32 | Operator Disconnect | 0021h: Bit F | OPR | OFF | R |
| BV33 | Operating | 002Ch: Bit 0 | OPERATING | OFF | R |
| BV34 | Zero Speed | 002Ch: Bit 1 | ON | OFF | R |
| BV35 | Frequency Agree | 002Ch: Bit2 | ON | OFF | R |
| BV36 | Desired Frequency Agree (<i>Desired Freq Agree</i>) | 002Ch: Bit 3 | ON | OFF | R |
| BV37 | Frequency Detect 1 | 002Ch: Bit 4 | ON | OFF | R |
| BV38 | Frequency Detect 2 | 002Ch: Bit 5 | ON | OFF | R |
| BV39 | Drive Startup Complete (<i>Drv Startup Complete</i>) | 002Ch: Bit 6 | ON | OFF | R |
| BV40 | Low Voltage Detect | 002Ch: Bit 7 | ON | OFF | R |
| BV41 | Base Block | 002Ch: Bit 8 | ON | OFF | R |
| BV42 | Frequency Reference Mode (<i>Frequency Ref Mode</i>) | 002Ch: Bit 9 | COM | LOCAL | R |
| BV43 | Run Command Mode | 002Ch: Bit A | COM | LOCAL | R |
| BV44 | Over Torque Detect | 002Ch: Bit B | ON | OFF | R |
| BV45 | Frequency Reference Lost (<i>Frequency Ref Lost</i>) | 002Ch: Bit C | ON | OFF | R |
| BV46 | Retry Error | 002Ch: Bit D | ON | OFF | R |
| BV47 | Modbus Comms Error | 002Ch: Bit E | ON | OFF | R |
| BV48 | Modbus Timeout Error | 002Ch: Bit F | ON | OFF | R |
| BV49 | CRC Error | 003Dh: Bit 0 | ON | OFF | R |
| BV50 | Invalid Data Length | 003Dh: Bit 1 | ON | OFF | R |
| BV51 | Parity Error | 003Dh: Bit 3 | ON | OFF | R |
| BV52 | Overrun Error | 003Dh: Bit 4 | ON | OFF | R |
| BV53 | Framing Error | 003Dh: Bit 5 | ON | OFF | R |
| BV54 | Timeout Error | 003Dh: Bit 6 | ON | OFF | R |
| BV55 | Parameter Accept | Object activates an internal bit that performs desired object function | ON | OFF | W |
| BV56 | Parameter Enter | Object activates an internal bit that performs desired object function | ON | OFF | W |
| BV57 | Drive Comms Error | 002Ch: Bit F | ON | OFF | R |
| BV58 | Bypass Forward Run Cmd (<i>BYP Run Fwd CMD</i>) | 0001h: Bit 0 | ON | OFF | C |
| BV59 | Bypass Reverse Run Cmd (<i>BYP Run Rev CMD</i>) | 0001h: Bit 1 | ON | OFF | C |

8.3 BACnet Communications

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Active Text | Inactive Text | PV Access |
|-----------|--|--------------|-------------|---------------|-----------|
| BV60 | Emergency Override Drive Reverse (<i>Em Over DRV REV CMD</i>) | 8400h: Bit F | ON | OFF | C |
| BV61 | Bypass Transfer to Bypass Cmd (<i>BYP Xfer to BYP CMD</i>) | 8400h: Bit 3 | ON | OFF | C |
| BV62 | Emergency Override Bypass (<i>Em Over BYPASS CMD</i>) | 8400h: Bit 4 | ON | OFF | C |
| BV63 | Emergency Override Drive Forward (<i>Em Over DRV FWD CMD</i>) | 8400h: Bit 5 | ON | OFF | C |
| BV64 | Bypass Motor OR Select Command (<i>BYP Mtr OR Sel CMD</i>) | 8400h: Bit 6 | ON | OFF | C |
| BV65 | Bypass Motor AND Select Command (<i>BYP Mtr AND Sel CMD</i>) | 8400h: Bit 7 | ON | OFF | C |
| BV66 | Not Used BV066 | - | ON | OFF | R |
| BV67 | Not Used BV067 | - | ON | OFF | R |
| BV68 | Not Used BV068 | - | ON | OFF | R |
| BV69 | Bypass BYPASS Select Command (<i>BYP BYPASS Sel CMD</i>) | 8400h: Bit C | ON | OFF | C |
| BV70 | Bypass Fault Reset Command (<i>BYP Fault Reset CMD</i>) | 8400h: Bit D | ON | OFF | C |
| BV71 | Bypass External Fault Command (<i>BYP Ext Fault CMD</i>) | 8400h: Bit E | ON | OFF | C |
| BV72 | Bypass DI-01 Command (<i>BYP DI-01 Command</i>) | 8402h: Bit 0 | ON | OFF | C |
| BV73 | Bypass DI-02 Command (<i>BYP DI-02 Command</i>) | 8402h: Bit 1 | ON | OFF | C |
| BV74 | Bypass DI-03 Command (<i>BYP DI-03 Command</i>) | 8402h: Bit 2 | ON | OFF | C |
| BV75 | Bypass DI-04 Command (<i>BYP DI-04 Command</i>) | 8402h: Bit 3 | ON | OFF | C |
| BV76 | Bypass DI-05 Command (<i>BYP DI-05 Command</i>) | 8402h: Bit 4 | ON | OFF | C |
| BV77 | Bypass DI-06 Command (<i>BYP DI-06 Command</i>) | 8402h: Bit 5 | ON | OFF | C |
| BV78 | Bypass DI-07 Command (<i>BYP DI-07 Command</i>) | 8402h: Bit 6 | ON | OFF | C |
| BV79 | Bypass DI-08 Command (<i>BYP DI-08 Command</i>) | 8402h: Bit 7 | ON | OFF | C |
| BV80 | Bypass HAND Mode Status (<i>BYP HAND Mode Status</i>) | 8784h: Bit 0 | ON | OFF | R |
| BV81 | Bypass OFF Mode Status (<i>BYP OFF Mode Status</i>) | 8784h: Bit 1 | ON | OFF | R |
| BV82 | Bypass AUTO Mode Status (<i>BYP AUTO Mode Status</i>) | 8784h: Bit 2 | ON | OFF | R |
| BV83 | Bypass DRIVE Mode Status (<i>BYP DRV Mode Status</i>) | 8784h: Bit 3 | ON | OFF | R |
| BV84 | Bypass BYPASS Mode Status (<i>BYP BYPASS Mode Stat</i>) | 8784h: Bit 4 | ON | OFF | R |

| Object ID | Object Name (<i>Network Display, if Different</i>) | Modbus Reg. | Active Text | Inactive Text | PV Access |
|-----------|--|--------------|-------------|---------------|-----------|
| BV85 | Bypass Emergency Run Bypass Status (<i>BYP Smk Prg BYP Stat</i>) | 8784h: Bit 5 | ON | OFF | R |
| BV86 | Bypass Emergency Run Drive Fwd Status (<i>BYP Smk Prg DRV Stat</i>) | 8784h: Bit 6 | ON | OFF | R |
| BV87 | Bypass Safety Status (<i>BYP Safety Status</i>) | 8784h: Bit 7 | ON | OFF | R |
| BV88 | Bypass BAS Interlock Status (<i>BYP BAS Interlk Stat</i>) | 8785h: Bit 0 | ON | OFF | R |
| BV89 | Bypass Run Status (<i>BYP RUN Status</i>) | 8785h: Bit 1 | ON | OFF | R |
| BV90 | Bypass Fault Status (<i>BYP Fault Status</i>) | 8785h: Bit 2 | ON | OFF | R |
| BV91 | Bypass Auto Transfer Status (<i>BYP Auto Xfer Status</i>) | 8785h: Bit 3 | ON | OFF | R |
| BV92 | Bypass Remote Transfer Status (<i>BYP Remote Xfer Stat</i>) | 8785h: Bit 4 | ON | OFF | R |
| BV93 | Bypass Energy Savings Status (<i>BYP Energy Save Stat</i>) | 8785h: Bit 5 | ON | OFF | R |
| BV94 | Bypass Motor 1 Select Status (<i>BYP Motor 1 Sel Stat</i>) | 8785h: Bit 6 | ON | OFF | R |
| BV95 | Bypass Motor 2 Select Status (<i>BYP Motor 2 Sel Stat</i>) | 8785h: Bit 7 | ON | OFF | R |
| BV96 | Bypass Drive Fault Status (<i>BYP Drive Flt Status</i>) | 8786h: Bit 0 | ON | OFF | R |
| BV97 | Bypass Safety Fault Status (<i>BYP Safety Flt Stat</i>) | 8786h: Bit 1 | ON | OFF | R |
| BV98 | Bypass BAS Interlock Fault Status (<i>BYP BAS ILock Status</i>) | 8786h: Bit 2 | ON | OFF | R |
| BV99 | Bypass External Fault Status (<i>BYP Ext Fault Stat</i>) | 8786h: Bit 3 | ON | OFF | R |
| BV100 | Not Used BV100 | - | - | - | R |
| BV101 | Bypass Motor OL Status (<i>BYP Motor OL Stat</i>) | 8786h: Bit 5 | ON | OFF | R |
| BV102 | Bypass Motor 1 OL Status (<i>BYP Motor 1 OL Stat</i>) | 8786h: Bit 6 | ON | OFF | R |
| BV103 | Bypass Motor 2 OL Status (<i>BYP Mtr 2 OL Stat</i>) | 8786h: Bit 7 | ON | OFF | R |
| BV104 | Bypass Input Phase Loss Status (<i>BYP Input Phase Loss</i>) | 8787h: Bit 0 | ON | OFF | R |
| BV105 | Bypass Drive Comms Status (<i>BYP Drive Comms</i>) | 8787h: Bit 2 | ON | OFF | R |
| BV106 | Bypass Loss of Load Status (<i>BYP Loss OfLoad</i>) | 8787h: Bit 5 | ON | OFF | R |
| BV107 | Option Board on Drive Status (<i>BYP Option Brd Comms</i>) | 8787h: Bit 4 | ON | OFF | R |

■ Device Object

The Device Object is the BACnet device to the network in this manual. The Device Object Instance ID, the Device Object Name, and the Device Object Location are configurable. Refer to [Table 8.5](#) for more information.

Table 8.5 Device Objects

| Item | Description | Data Type |
|---------------------------|---|--|
| Device Object Instance ID | A unique internetwork-wide numerical value. To set this ID, set <i>H5-14 [BACnet Device Obj ID LOW BITS]</i> and <i>H5-15 [BACnet Device Obj ID HIGH BITS]</i> . | 22-bit value Range: 0 - 4, 194, 302 |
| Device Object Name | A unique internetwork-wide character string that is writable from the BACnet network. | 40-character strings |
| Device Object Location | Character field to describe the location of the device that is writable from the Bacnet network. | 40-character strings |

Note:

Any changes to the parameter settings and any new string written will not take effect until you de-energize the drive.

◆ Accessing Drive Parameters and the Enter Command

■ Read Drive Parameters

To read the drive parameters that are not listed in the analog or digital objects, use AV29 and AV30 as shown in this procedure:

1. Write the desired Modbus register to AV29 in decimal value.
2. Read the decimal value at the given register from AV30.

For example, to read the Frequency Reference Upper Limit, read from parameter *d2-01 [Frequency Reference Upper Limit]*.

Parameter *d2-01* is located at Modbus register 0289H, which is decimal 649.

Set AV29 to "649."

Read AV30 to get the value.

■ Write Drive Parameters

To write the drive parameters that are not listed in the analog or digital objects, use AV29, AV30, and BV55 or BV56 as shown in this procedure:

1. In AV29, write the desired Modbus register number in decimal format.
2. In AV30, write the value that you want to put into the register set in AV29 in decimal format.

At this point the value is written to the drive, but the location is pending.

If necessary, write in more values this way, the drive will accept these settings by one of two methods:

- Set BV55 to "ON" to move data to active memory.
- Set BV56 to "ON" to move data into active memory and save to non-volatile memory.

For example, to reset the KWH Monitor, write a value of "1" to parameter *o4-12 [kWh Monitor Initialization]*.

Parameter *o4-12* is located at Modbus register 0512 (Hex.), which is decimal 1298.

Set AV29 to "1298."

Set AV30 to "1."

Set BV55 to "ON."

■ Enter Command

Enter Commands are only necessary to use AV29 and AV30 to access drive parameters. Enter commands are not necessary to read or write to the other BACnet objects.

This section gives information about the Enter command.

Types of Enter Commands

The drive supports two Enter commands shown in [Table 8.6](#).

Table 8.6 Types of Enter Commands

| BACnet Object | Modbus Address (Hex.) | Description |
|-------------------|-----------------------|---|
| BV55 (Write "ON") | 0910 (Write 0) | This updates the data on the RAM, but does not write data to the EEPROM. This process saves the parameter changes until you de-energize the drive. |
| BV56 (Write "ON") | 0900 (Write 0) | When you write parameter data to the EEPROM, you will enable the data on the RAM at the same time. This process saves the parameter changes until you de-energize the drive. |

Note:

You can write the EEPROM to the drive a maximum of 100,000 times. Do not frequently execute the Enter command (0900 (Hex.)) that is written to EEPROM. The Enter command registers 0900 (Hex.) and 0910 (Hex.) are write-only. If these registers are read, the register address will not be applicable, but BACnet objects BV55 and BV56 can be read without error.

◆ Self-Diagnostics

The bypass can use Self-Diagnostics to verify the hardware transceiver on the control circuit. Self-Diagnostics connects the transmission terminal to the reception terminal on the control circuit and transmits the data to itself to make sure that the bypass can communicate correctly.

Use this procedure to do Self-Diagnostics:

DANGER! Electrical Shock Hazard. Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe. If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

1. Energize the bypass.
2. Set Z2-06 = 45 [Digital Input 6 Function (TB2-6) - Serial Hardware Test (RS-485)].
3. De-energize the bypass.
4. Disconnect the RS-485 terminals (TB3).
5. Connect a jumper between control circuit terminals TB2-6 and TB2-9 or TB2-10.

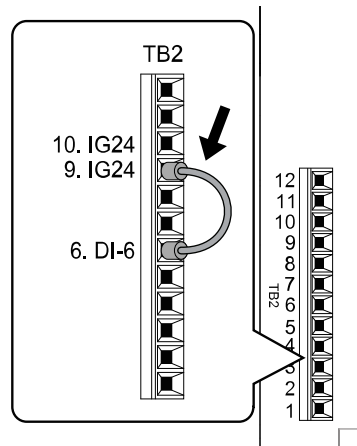


Figure 8.5 Self-Diagnostics Jumper Terminals

6. Energize the bypass.
7. When normal, the keypad will show *PASS* [Serial Communication Test].

Note:

If there is an error, the keypad will show *CE* [Serial Communication Error]. Disconnect the bypass from the network and test the bypass again. If the error stays, there is a possible hardware problem. If there is no error, there is a possible network wiring problem.

8. De-energize the bypass.
9. Disconnect the jumper from Step 4. Set Z2-06 to its initial function.

Self-Diagnostics is complete and the bypass returns to its usual function.

◆ BACnet Protocol Implementation Conformance Statement

- Date: 3/1/2020
- Vendor Name: Yaskawa
- Product Name: VFD Bypass
- Product Model Number: HV600 Bypass
- Application Software Version: VST8004xx
- Firmware Revision: 2.01
- BACnet Protocol Revision: 14
- Product Description:

The Yaskawa VFD Bypass is a high performance product specifically designed for commercial building automation applications. The Yaskawa BACnet feature connects the VFD Bypass to a standard BACnet MS/TP network. These products may be fully controlled and monitored over BACnet. All Bypass and drive parameters are available for reading and writing.
- BACnet Standardized Device Profile (Annex L):
 - BACnet Cross-Domain Advanced Operator Workstation (B-XAWS)
 - BACnet Advanced Operator Workstation (B-AWS)
 - BACnet Operator Workstation (B-OWS)
 - BACnet Operator Display (B-OD)
 - BACnet Advanced Life Safety Workstation (B-ALSWS)
 - BACnet Life Safety Workstation (B-LSWS)
 - BACnet Life Safety Annunciator Panel (B-LSAP)
 - BACnet Advanced Access Control Workstation (B-AACWS)
 - BACnet Access Control Workstation (B-ACWS)
 - BACnet Access Control Security Display (B-ACSD)
 - BACnet Building Controller (B-BC)
 - BACnet Advanced Application Controller (B-AAC)
 - BACnet Application Specific Controller (B-ASC)
 - BACnet Smart Actuator (B-SA)
 - BACnet Smart Sensor (B-SS)
 - BACnet Advanced Life Safety Controller (B-ALSC)
 - BACnet Life Safety Controller (B-LSC)
 - BACnet Advanced Access Control Controller (B-AACC)
 - BACnet Access Control Controller (B-ACC)
 - BACnet Router (B-RTR)
 - BACnet Gateway (B-GW)
 - BACnet Broadcast Management Device (B-BBMD)
 - BACnet Access Control Door Controller (B-ACDC)
 - BACnet Access Control Credential Reader (B-ACCR)
 - BACnet General (B-GENERAL)
- List all BACnet Interoperability Building Blocks Supported (Annex K):
 - Data Sharing-ReadProperty-B (DS-RP-B)
 - Data Sharing-WriteProperty-B (DS-WP-B)
 - Data Sharing-ReadPropertyMultiple-B (DS-RPM-B)
 - Data Sharing-WritePropertyMultiple-B (DS-WPM-B)
 - Data Sharing-Change Of Value-B (DS-COV-B)
 - Data Sharing-Change Of Value Property-B (DS-COVP-B)
 - Device Management-Dynamic Device Binding-B (DM-DDB-B)
 - Device Management-Dynamic Object Binding-B (DM-DOB-B)
 - Device Management-DeviceCommunicationControl-B (DM-DCC-B)
 - Device Management-ReinitializeDevice-B (DM-RD-B)
 - Device Management-TimeSynchronization-B (DM-TS-B)
- Segmentation Capability:

- Able to transmit segmented messages / Window Size:
- Able to receive segmented messages / Window Size:
- Standard Object Types Supported:

| Object Types | Descriptions |
|----------------------|--|
| Device Object | Optional Writeable: – Max_Info_Frames – Max_Master |
| Analog Input Object | Optional properties supported: – COV_Increment Optional Writeable: – COV_Increment - supported on various instances |
| Analog Output Object | - |
| Analog Value Object | Optional properties supported: – COV_Increment Optional Writeable: – COV_Increment - supported on various instances |
| Binary Input Object | - |
| Binary Output Object | - |
| Binary Value Object | - |

- Data Link Layer Options:
 - ARCNET (ATA 878.1), 2.5 Mb. (Clause 8)
 - ARCNET (ATA 878.1), EIA-485 (Clause 8), baud rate(s):
 - BACnet IP, (Annex J)
 - BACnet IP, (Annex J), BACnet Broadcast Management Device (BBMD)
 - BACnet IP, (Annex J), Network Address Translation (NAT Traversal)
 - BACnet IPv6, (Annex U)
 - BACnet IPv6, (Annex U), BACnet Broadcast Management Device (BBMD)
 - BACnet/ZigBee (Annex O)
 - Ethernet, ISO 8802-3 (Clause 7)
 - LonTalk, ISO/IEC 14908.1 (Clause 11), medium:
 - MS/TP master (Clause 9), baud rate(s): 9600, 19200, 38400, 76800
 - MS/TP slave (Clause 9), baud rate(s)
 - Point-To-Point, EIA 232 (Clause 10), baud rate(s):
 - Point-To-Point, modem, (Clause 10), baud rate(s):
 - Other:
- Device Address Binding:

Is static device binding supported? (This is currently necessary for two-way communication with MS/TP slaves and certain other devices.) Yes No
- Networking Options:
 - Router, Clause 6 - List all routing configurations, e.g., ARCNET-Ethernet, Ethernet-MS/TP, etc.
 - Annex H, BACnet Tunneling Router over IP
- Character Sets Supported:

Indicating support for multiple character sets does not imply that they can all be supported simultaneously.

 - ISO 10646 (UTF-8)
 - IBM/Microsoft DBCS
 - ISO 8859-1
 - ISO 10646 (UCS-2)
 - ISO 10646 (UCS-4)
 - JIS X 0208
- Gateway Options:

If this product is a communication gateway, describe the types of non-BACnet equipment/networks(s) that the gateway supports:
Not supported

8.3 BACnet Communications

If this product is a communication gateway which presents a network of virtual BACnet devices, a separate PICS shall be provided that describes the functionality of the virtual BACnet devices. That PICS shall describe a superset of the functionality of all types of virtual BACnet devices that can be presented by the gateway.

- Network Security Options:
 - Non-secure Device - is capable of operating without BACnet Network Security
 - Secure Device - is capable of using BACnet Network Security (NS-SD BIBB)
 - Multiple Application-Specific Keys
 - Supports encryption (NS-ED BIBB)
 - Key Server (NS-KS BIBB)

8.4 Other Embedded Communication Protocols

For detailed information about:

- APOGEE FLN (P1) Communications
- Metasys N2 Communications
- MEMOBUS/Modbus Communications

Refer to the HV600 Bypass Technical Reference (SIEPYAIHB601).

Standards Compliance

This chapter gives information about how to make the machines and devices that use this product comply with UL standards, seismic standards, and European standards.

| | | |
|------------|--------------------------------|------------|
| 9.1 | Section Safety | 286 |
| 9.2 | UL Standards | 288 |
| 9.3 | Seismic Standards | 289 |
| 9.4 | European Standards..... | 290 |

9.1 Section Safety

DANGER

Electrical Shock Hazard

Do not examine, connect, or disconnect wiring on an energized bypass. Before servicing, disconnect all power to the equipment and wait for the time specified on the warning label at a minimum. The internal capacitor stays charged after the bypass is de-energized. The charge indicator LED extinguishes when the DC bus voltage decreases below 50 Vdc. When all indicators are OFF, remove the covers before measuring for dangerous voltages to make sure that the bypass is safe.

If you do work on the bypass when it is energized, it will cause serious injury or death from electrical shock.

WARNING

Electrical Shock Hazard

Do not operate the bypass when covers are missing. Replace covers and shields before you operate the bypass. Use the bypass only as specified by the instructions.

Some figures in this section include bypasses without covers or safety shields to more clearly show the inside of the bypass. If covers or safety shields are missing from the bypass, it can cause serious injury or death.

Always ground the motor-side grounding terminal.

If you do not ground the equipment correctly, it can cause serious injury or death if you touch the motor case.

Do not remove covers or touch circuit boards while the bypass is energized.

If you touch the internal components of an energized bypass, it can cause serious injury or death.

Only let approved personnel install, wire, maintain, examine, replace parts, and repair the bypass.

If personnel are not approved, it can cause serious injury or death.

Do not wear loose clothing or jewelry when you do work on the bypass. Tighten loose clothing and remove all metal objects, for example watches or rings.

Loose clothing can catch on the bypass and jewelry can conduct electricity and cause serious injury or death.

Do not modify the bypass body, drive body, bypass circuitry, or drive circuitry.

Modifications to bypass and drive body and circuitry can cause serious injury or death, will cause damage to the bypass and drive, and will void the warranty. Yaskawa is not responsible for modifications of the product made by the user.

Fire Hazard

Tighten all terminal screws to the correct tightening torque.

Connections that are too loose or too tight can cause incorrect operation and damage to the bypass. Incorrect connections can also cause death or serious injury from fire.

Tighten screws at an angle in the specified range shown in this manual.

If you tighten the screws at an angle not in the specified range, you can have loose connections that can cause damage to the terminal block or start a fire and cause serious injury or death.

Damage to Equipment

Do not apply incorrect voltage to the main circuit of the bypass. Operate the bypass in the specified range of the input voltage on the nameplate.

Voltages that are higher than the permitted nameplate tolerance can cause damage to the bypass.

Fire Hazard

Do not put flammable or combustible materials on top of the bypass and do not install the bypass near flammable or combustible materials. Attach the bypass to metal or other noncombustible material.

Flammable and combustible materials can start a fire and cause serious injury or death.

⚠ WARNING**Crush Hazard**

Wear eye protection when you do work on the bypass.

If you do not use correct safety equipment, it can cause serious injury or death.

Electrical Shock Hazard

After the bypass blows a fuse or trips a GFCI, do not immediately energize the bypass or operate peripheral devices. Wait for the time specified on the warning label at a minimum and make sure that all indicators are OFF. Then check the wiring and peripheral device ratings to find the cause of the problem. If you do not know the cause of the problem, contact Yaskawa before you energize the bypass or peripheral devices.

If you do not fix the problem before you operate the bypass or peripheral devices, it can cause serious injury or death.

NOTICE**Damage to Equipment**

When you touch the bypass, drive, and circuit boards, make sure that you observe correct electrostatic discharge (ESD) procedures.

If you do not follow procedures, it can cause ESD damage to the drive and bypass circuitry.

Do not break the electrical connection between the bypass and the motor when the bypass is outputting voltage.

Incorrect equipment sequencing can cause damage to the bypass.

Make sure that all connections are correct after you install the bypass and connect peripheral devices.

Incorrect connections can cause damage to the bypass.

Note:

Do not use unshielded cable for control wiring. Use shielded, twisted-pair wires and ground the shield to the ground terminal of the bypass. Unshielded wire can cause electrical interference and unsatisfactory system performance.

9.2 UL Standards



Figure 9.1 UL/cUL Mark

The UL/cUL Mark identifies that this product conforms to rigid safety standards. This mark appears on products in the United States and Canada. It shows UL approval, which identifies that the product complies with safety standards after careful inspection and assessment. You must use UL Listed or UL Recognized parts for all primary components that are built into electrical equipment that has UL approval.

This product has been tested in accordance with UL standard UL508A, and has been verified to be in compliance with UL standards.

Machines and devices integrated with this product must satisfy the following conditions for compliance with UL standards.

◆ Area of Use

Install this product in a location with Overvoltage Category III and pollution degree 2 or less.

■ Ambient Temperature Setting

Maintain the ambient temperature within the following ranges according to the enclosure type.

- IP20/UL Type 1: -10 °C to +40 °C (14 °F to 104 °F)
- IP55/UL Type 12: -10 °C to +40 °C (14 °F to 104 °F)

9.3 Seismic Standards

Yaskawa bypasses that have the certification label in [Figure 9.2](#) are capable of structurally and operationally withstanding the seismic response criteria as defined in the International Building Code (IBC), ASCE7, and California Department of Health Care Access and Information (HCAI).

The models in this section were tested in compliance with AC-156 to meet the IBC seismic certification as shown on the certification labels.

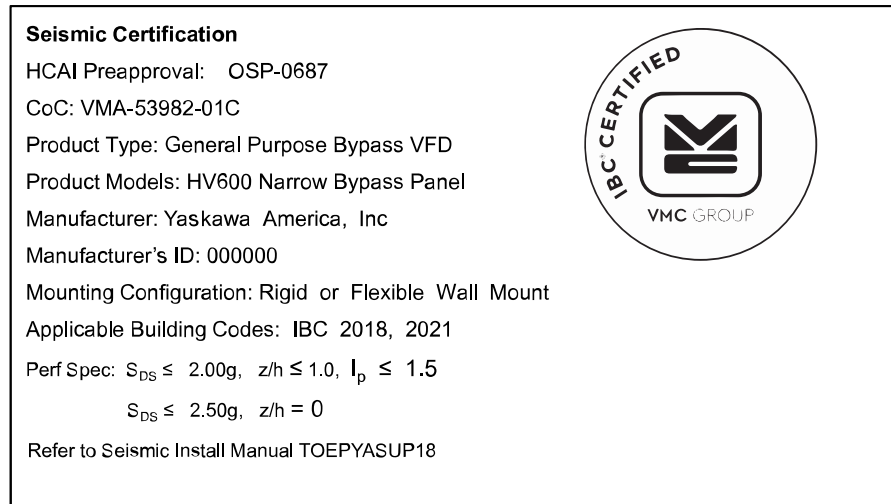


Figure 9.2 Seismic Certification Label Example for Bypasses

9.4 European Standards



Figure 9.3 CE Mark

The CE Mark identifies that the product meets environmental and safety standards in the European Union. Products manufactured, sold, or imported in the European Union must display the CE Mark.

European Union standards include standards for electrical appliances (Low Voltage Directive), standards for electrical noise (EMC Directive), and standards for machinery (Machinery Directive).

This product displays the CE Mark in accordance with the Low Voltage Directive, the EMC Directive, and the Machinery Directive.

Table 9.1 Harmonized Standard

| European Directive | Harmonized Standard |
|-------------------------------------|---|
| Low Voltage Directive 2014/35/EU | EN 61800-5-1:2007 |
| EMC Directive 2014/30/EU | EN 61800-3:2004/A1:2012 First environment restricted distribution |
| Machinery Directive 2006/42/EC | <ul style="list-style-type: none"> • EN 61800-5-2:2007 (SIL3) • EN 62061:2005/A2:2015 (SIL CL3) • EN ISO 13849-1:2015 (PL e (Cat.III)) |

The customer must display the CE Mark on the final device containing this product. Customers must verify that the final device complies with EU standards.

◆ EU Declaration of Conformity

Go to www.yaskawa.com and search for "EU Declaration of Conformity" to get an original copy of the EU Declaration of Conformity.

Yaskawa declares that this product complies with the following directives and standards at our sole responsibility.

◆ CE Low Voltage Directive Compliance

It has been confirmed that this product complies with the CE Low Voltage Directive by conducting a test according to IEC/EN 61800-5-1:2007.

The following conditions must be satisfied for machines and devices incorporating this product to comply with the CE Low Voltage Directive.

■ Area of Use

Install this product in a location with Overvoltage Category III and pollution degree 2 or less.

■ Guarding Against Debris

When you install IP20/UL Open Type drives (model: 2xxxxB, 4xxxxB), use an enclosure that does not let unwanted material enter the drive from above or below.

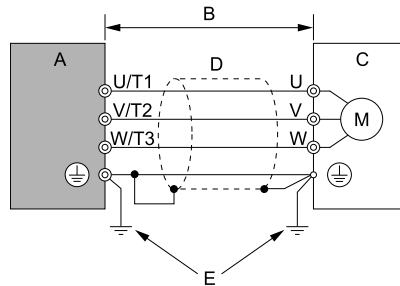
◆ EMC Directive

Drives with built-in EMC filters were tested in accordance with European standard IEC/EN 61800-3:2004/A1:2012, and comply with the EMC Directive.

■ Install a Drive to Conform to the EMC Directive

Use this procedure to install drives that comply with the EMC Directive when the drive is a single unit or installed in a larger device.

1. Install the drive on a grounded metal plate.
2. Wire the drive and motor.
3. Ground the wire shielding on the drive side and motor side.



- | | |
|-----------------------------------|---------------------------|
| A - Drive | D - Metal conduit |
| B - 100 m (328 ft) maximum | E - Grounding wire |
| C - Motor | |

Figure 9.4 Wiring the Drive and Motor

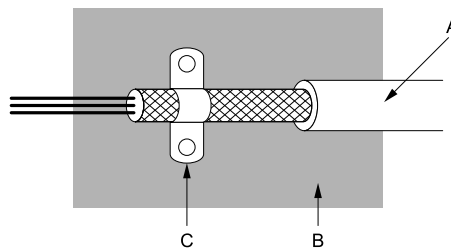
Note:

- Use a braided shield cable for the drive and motor wiring or put the wires through a metal conduit.
- The maximum wiring length between the drive and motor is 100 m (328 ft). Keep the wire as short as possible.
- Keep the grounding wire as short as possible.

4. Use a cable clamp to ground the motor cable to the metal plate.

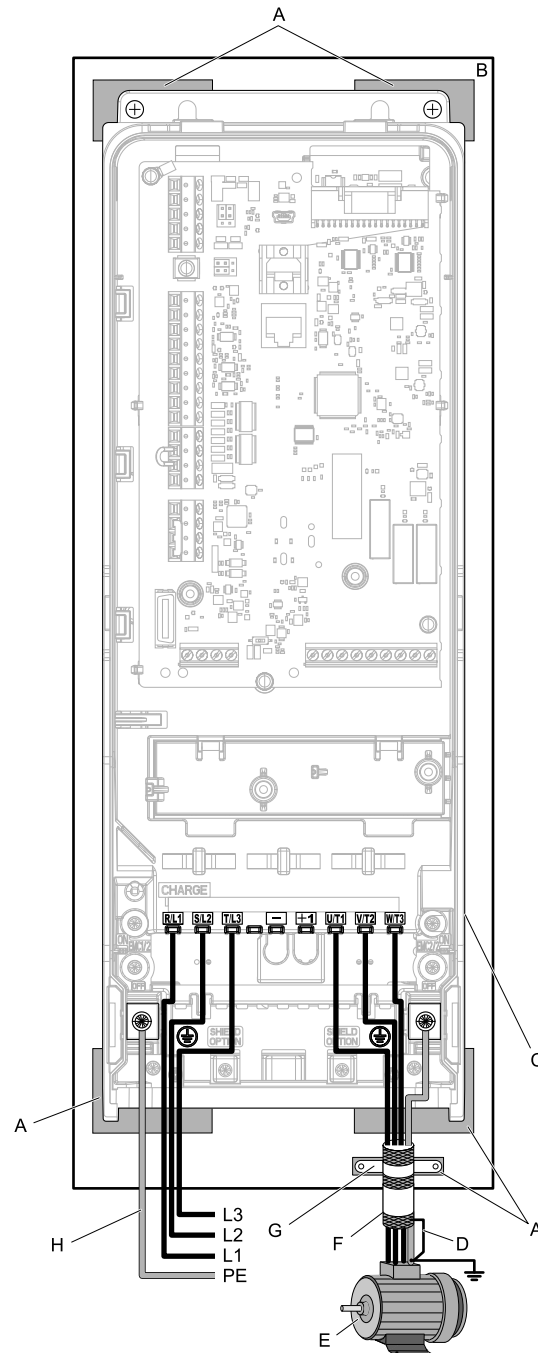
Note:

Make sure that the protective ground wire complies with technical specifications and local safety standards.



- | | |
|---------------------------------|-------------------------------------|
| A - Braided shield cable | C - Cable clamp (conductive) |
| B - Metal plate | |

Figure 9.5 Ground the shield



- | | |
|---|---------------------------|
| A - Grounding surface (Remove any paint or sealant.) | E - Motor |
| B - Metal plate | F - Motor cable |
| C - Drive | G - Cable clamp |
| D - Shielded wire | H - Grounding wire |

Figure 9.6 Install a Drive with a Built-in EMC Filter

Ground Wiring

WARNING! Electrical Shock Hazard. Do not remove covers or touch circuit boards while the bypass is energized. If you touch the internal components of an energized bypass, it can cause serious injury or death.

WARNING! Electrical Shock Hazard. Ground the neutral point on the power supply of the bypass to comply with the EMC Directive before you turn on the EMC filter. If you turn ON the EMC filter, but you do not ground the neutral point, it can cause serious injury or death.

Enable the Internal EMC Filter

Move the screws to turn ON and OFF (enable and disable) the EMC filter.

Make sure that the symmetric grounding network is applied, and install the both screws in the ON position to enable the built-in EMC filter in compliance with the EMC Directive. The EMC filter switch screws are installed in the OFF position by default.

WARNING! *Electrical Shock Hazard. Disconnect all power to the drive, wait for the time specified on the warning label, and check the drive for dangerous voltages before you remove covers or touch EMC filter screws. If you touch the screws when there are dangerous voltages, it will cause serious injury or death.*

WARNING! *Electrical Shock Hazard. Do not remove covers or touch circuit boards while the bypass is energized. If you touch the internal components of an energized bypass, it can cause serious injury or death.*

WARNING! *Electrical Shock Hazard. Ground the neutral point on the power supply of the bypass to comply with the EMC Directive before you turn on the EMC filter. If you turn ON the EMC filter, but you do not ground the neutral point, it can cause serious injury or death.*

WARNING! *Electrical Shock Hazard. Connect the ground cable correctly. If you touch electrical equipment that is not grounded, it can cause serious injury or death.*

NOTICE: *To disable the internal EMC filter, move the screws from ON to OFF and then tighten to the specified torque. If you fully remove the screws or tighten the screws to an incorrect torque, it can cause drive failure.*

NOTICE: *Move the EMC switch screw or screws to the OFF position for networks that are not symmetrically grounded. If the screws are not in the correct position, it can cause damage to the drive.*

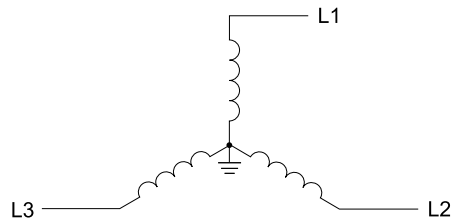


Figure 9.7 Symmetric Grounding

NOTICE: *When you use the drive with a non-grounding, high-resistance grounding, or asymmetric-grounding network, put the EMC Filter screw or screws in the OFF position to disable the built-in EMC filter. Failure to obey the instructions can damage the drive.*

Table 9.2 shows asymmetric grounding networks.

Table 9.2 Asymmetric Grounding

| Type of Grounding | Diagram |
|--|--|
| Grounded at the corner of the delta connection | <p>The diagram shows a delta (Δ) connection of three inductors. The top inductor is L1, the bottom-left is L3, and the bottom-right is L2. The bottom-right corner, where inductors L1 and L2 meet, is connected to a ground symbol.</p> |
| Grounded at the middle of the side | <p>The diagram shows a delta (Δ) connection of three inductors. The top inductor is L1, the bottom-left is L3, and the bottom-right is L2. The bottom side, between inductors L3 and L2, is connected to a ground symbol.</p> |

9.4 European Standards

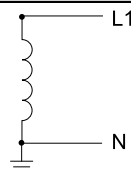
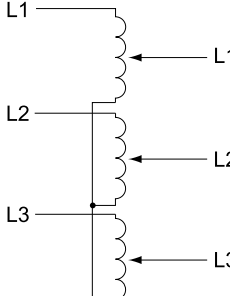
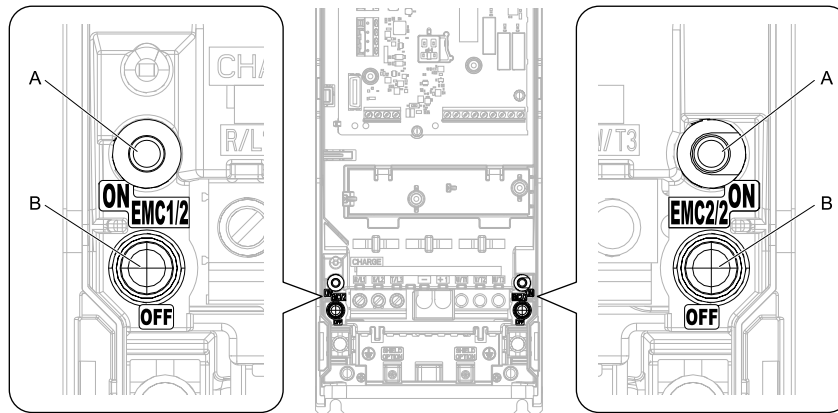
| Type of Grounding | Diagram |
|---|---|
| Single-phase, grounded at the end point |  |
| Three-phase variable transformer without solidly grounded neutral |  |

Table 9.3 EMC Filter Switch Location

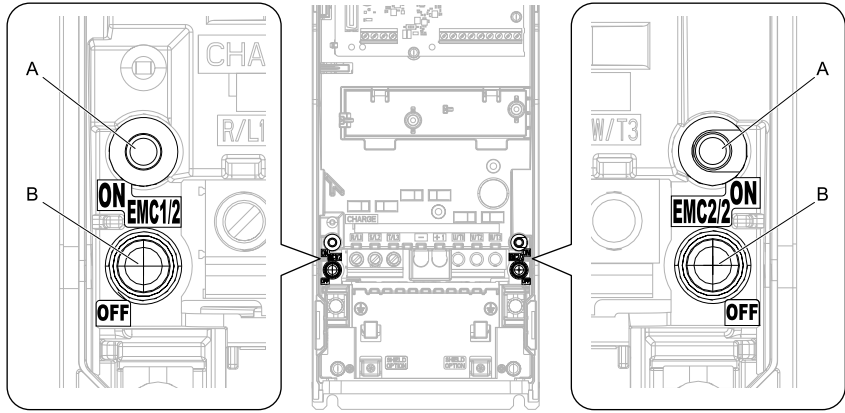
| Bypass Model | Drive Model | Switch Location Diagram |
|----------------------------|-------------------------|-----------------------------|
| D002 - D016 B001 - B014 | 2011, 2017, 4005 - 4014 | Figure 9.8 |
| D024, D030 B021 - B034 | 2024, 2031, 4021 - 4034 | Figure 9.9 |
| D046, D059 B040 - B065 | 2046, 2059, 4040 - 4065 | Figure 9.10 |
| D074 B077 | 2075, 4077 | Figure 9.11 |



A - SW (ON)

B - Screw (OFF)

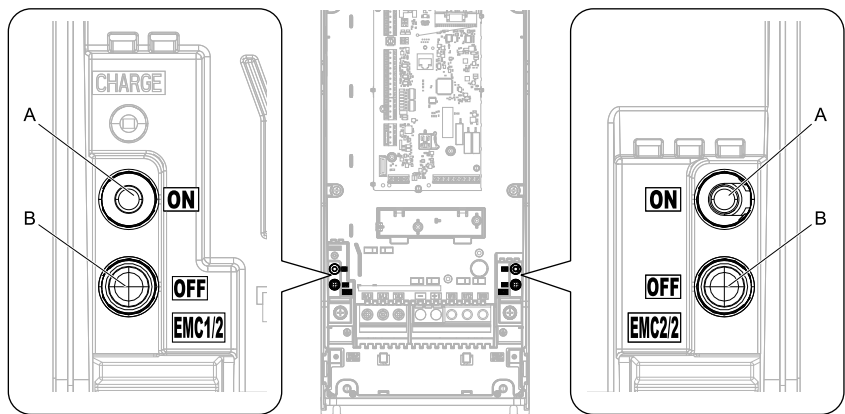
Figure 9.8 EMC Filter Switch Location 1



A - SW (ON)

B - Screw (OFF)

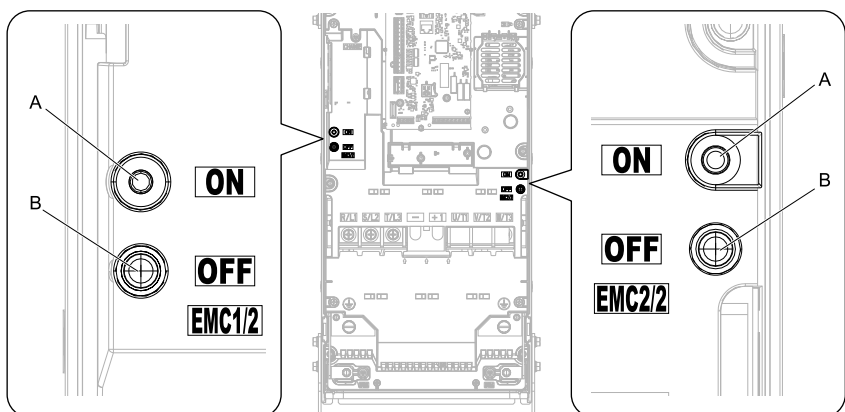
Figure 9.9 EMC Filter Switch Location 2



A - SW (ON)

B - Screw (OFF)

Figure 9.10 EMC Filter Switch Location 3



A - SW (ON)

B - Screw (OFF)

Figure 9.11 EMC Filter Switch Location 4

If you lose an EMC filter switch screw, use [Table 9.4](#) to find the correct replacement screw and install the new screws with the correct tightening torque.

NOTICE: Only use the screws specified in this manual. If you use screws that are not approved, it can cause damage to the drive.

Table 9.4 Screw Sizes and Tightening Torques

| Model | Screw Size | Tightening Torque N·m |
|--------------------------|-------------------|----------------------------------|
| 2011 - 2059, 4005 - 4065 | M4 × 20 | 1.0 - 1.3 |
| 2075 , 4077 | M4 × 30 | 1.0 - 1.3 |

Disposal

| | | |
|-------------|------------------------------------|------------|
| 10.1 | Section Safety | 298 |
| 10.2 | Disposal Instructions | 299 |
| 10.3 | WEEE Directive | 300 |

10.1 Section Safety

WARNING

Electrical Shock Hazard

De-energize the bypass and wait 5 minutes minimum until the Charge LED turns off. Remove the front cover and terminal cover to do work on wiring, circuit boards, and other parts. Use terminals for their correct function only.

Incorrect wiring, incorrect ground connections, and incorrect repair of protective covers can cause death or serious injury.

Only let approved personnel install, wire, maintain, examine, replace parts, and repair the bypass.

If personnel are not approved, it can cause serious injury or death.

Do not wear loose clothing or jewelry when you do work on the bypass. Tighten loose clothing and remove all metal objects, for example watches or rings.

Loose clothing can catch on the bypass and jewelry can conduct electricity and cause serious injury or death.

Fire Hazard

Handle keypad batteries properly. Do not charge the battery or disassemble the keypad.

If the battery explodes, it can cause a fire.

Do not disassemble batteries. Do not expose batteries to heat or fire.

If the battery explodes, it can cause a fire.

Crush Hazard

Wear eye protection when you do work on the bypass.

If you do not use correct safety equipment, it can cause serious injury or death.

Only approved personnel can operate a crane or hoist to move the bypass.

If unapproved personnel operate a crane or hoist, it can cause serious injury or death from falling equipment.

Use a crane or hoist to move large bypasses when necessary.

If you try to move a large bypass without a crane or hoist, it can cause serious injury or death.

CAUTION

Crush Hazard

Tighten terminal cover screws and hold the case safely when you move the bypass.

If the bypass or covers fall, it can cause moderate injury.

NOTICE

Damage to Equipment

The keypad battery stays in use after you de-energize the bypass. When you will keep the bypass de-energized for long periods of time, remove the battery from the keypad. When the expected life of the battery is complete, replace the battery immediately.

A dead battery in the keypad can leak and cause damage to the keypad and bypass.

10.2 Disposal Instructions

Correctly discard the drive, packing material, battery, and microSD card as specified by regional, local, and municipal laws and regulations for this product. (Example: European Waste 16 02 14)

Note:

- Remove the battery and microSD card from the keypad before you discard the drive.
- You cannot recycle the battery. Discard used batteries as specified by the battery manufacturer.
- Customers are responsible for microSD card data protection. PC functions that format and delete the data may not be sufficient to fully erase the microSD card data.
Yaskawa recommends that customers physically destroy the microSD card in a shredder or use data wipe software to fully erase the card.

10.3 WEEE Directive



The wheeled bin symbol on this product, its manual, or its packaging identifies that you must recycle it at the end of its product life.

You must discard the product at an applicable collection point for electrical and electronic equipment (EEE). Do not discard the product with usual waste.

Index

A

| | |
|---|---------|
| Adjustment of control functionality | 83 |
| AFBL | 126 |
| AL02 | 126 |
| AL03 | 126 |
| AL09 | 126 |
| AL13 | 126 |
| AL16 | 126 |
| AL17 | 126 |
| AL18 | 126 |
| Alarm | 88, 126 |
| ALM indicator | 69 |
| Altitude | |
| Environment | 24 |
| Ambient humidity | 24 |
| Ambient Temperature Setting | 24 |
| APOGEE FLN (P1) | 283 |
| AuDis | 126 |
| AuFbl | 126 |
| AUTO indicator | 69, 71 |
| AUTO key | 69 |
| AUTO LED | 71 |
| Auto-Tuning | 81 |
| Induction Motor | 81 |
| Precautions | 81 |
| Rotational Auto-Tuning Precautions | 82 |
| Stationary Auto-Tuning for Line-to-Line Resistance precautions | 82 |
| Stationary Auto-Tuning Precautions | 82 |
| Stator resistance Auto-Tuning precautions | 82 |
| Auto-Tuning Error | 88, 142 |
| AUXFB | |
| Fault | 102 |
| Minor Fault | 126 |

B

| | |
|------------------------------------|-----|
| BACnet | |
| Communication specifications | 264 |
| Enter command | 278 |
| Self-diagnosis | 279 |
| bAT | |
| Fault | 102 |
| Minor Fault | 127 |
| Battery | |
| Disposal | 299 |
| bb | 127 |
| bCE | |
| Fault | 102 |
| Minor Fault | 127 |
| Bu-Fb | 127 |
| BuDif | 127 |
| BuFbl | 127 |
| bUS | |
| Fault | 102 |
| Minor Fault | 127 |
| bUSy | 128 |
| Bypass control circuit terminals | |
| Wiring | 48 |

C

| | |
|---|---------|
| CALL | 128 |
| CE | |
| Fault | 102 |
| Minor Fault | 128–129 |
| CoF | 103 |
| Connection diagram | |
| Connection diagram | 38 |
| Control circuit terminals | |
| Wiring procedure for terminal block | 52, 59 |
| Copy Function Error | 88, 145 |
| CPF00 | 103 |
| CPF01 | 103 |
| CPF02 | 103 |
| CPF03 | 103 |
| CPF06 | 104 |
| CPF07 | 104 |
| CPF08 | 104 |
| CPF11 | 104 |
| CPF12 | 104 |
| CPF13 | 104 |
| CPF14 | 104 |
| CPF16 | 105 |
| CPF17 | 105 |
| CPF18 | 105 |
| CPF19 | 105 |
| CPF20 | 105 |
| CPF21 | 105 |
| CPF22 | 105 |
| CPF23 | 105 |
| CPF24 | 106 |
| CPF26 | 106 |
| CPF27 | 106 |
| CPF28 | 106 |
| CPF29 | 106 |
| CPF30 | 106 |
| CPF31 | 106 |
| CPF32 | 106 |
| CPF33 | 107 |
| CPF34 | 107 |
| CPF35 | 107 |
| CPF36 | 107 |
| CPF37 | 107 |
| CPF38 | 107 |
| CPF39 | 107 |
| CPyE | 145 |
| CrST | 129 |
| CSEr | 145 |
| CyPo | 129 |

D

| | |
|---------------------------------------|---------|
| dEv | |
| Fault | 107 |
| dFPS | 145 |
| Diagnosing and Resetting Faults | 147 |
| DIFF | |
| Fault | 108 |
| Minor Fault | 129 |
| Disposal | |
| Battery | 299 |
| Drive | 299–300 |
| microSD card | 299 |
| Packing material | 299–300 |

| | | | |
|---------------------------------|---------|---------------------------------|---------|
| dnE | 129 | Fault | 88, 102 |
| Drive | | Fault Code List | 89, 96 |
| Disposal | 299–300 | Fault Reset | 147 |
| Rating (208 V) | 151 | FB02 | 110 |
| Rating (480 V) | 153 | FB03 | 110 |
| Drive control circuit terminals | | FB05 | 110 |
| Wiring | 54 | FB06 | 111 |
| Drive cooling fans | 163 | FB07 | 111 |
| Drive watt loss | 157 | FB08 | 111 |
| dv7 | 108 | FB09 | 111 |
| E | | FB10 | 111 |
| EF | 129 | FB13 | 111 |
| EF0 | | FB15 | 112 |
| Fault | 108 | FB16 | 112 |
| Minor Fault | 130 | FB17 | 112 |
| EF1 | | FB18 | 112 |
| Fault | 108 | FB26 | 112 |
| Minor Fault | 130 | FB27 | 112 |
| EF2 | | FB28 | 112 |
| Fault | 108 | FB30 | 113 |
| Minor Fault | 130 | FDBKL | |
| EF3 | | Fault | 113 |
| Fault | 108 | Minor Fault | 131 |
| Minor Fault | 130 | Fine tuning | 83 |
| EF4 | | FIRE_ST | 131 |
| Fault | 109 | FLGT | 131 |
| Minor Fault | 130 | FR<MS | 132 |
| EF5 | | FR<TH | 132 |
| Fault | 109 | FREEZ_ST | 132 |
| Minor Fault | 130 | G | |
| EF6 | | GF | 113 |
| Fault | 109 | Ground | |
| Minor Fault | 130 | Drive | 44 |
| EF7 | | H | |
| Fault | 109 | HAND indicator | 69, 71 |
| Minor Fault | 131 | HAND LED | 71 |
| End1 | 142 | HCA | 132 |
| End2 | 142 | HFB | 114 |
| End3 | 142 | HIAUX | |
| End4 | 142 | Fault | 114 |
| End5 | 142 | Minor Fault | 132 |
| End6 | 142 | HIFB | 132 |
| End7 | 142 | How to read catalog codes | 18 |
| Enter command | 278 | Humidity | |
| EOF | 131 | Environment | 24 |
| EOR | 131 | I | |
| EP24v | 131 | iFEr | 145 |
| Er-01 | 142 | Induction Motor | |
| Er-02 | 143 | Auto-Tuning | 81 |
| Er-03 | 143 | Inspection | 163 |
| Er-04 | 143 | Installation | |
| Er-05 | 143 | Front cover | 31 |
| Er-08 | 143 | Terminal cover | 31 |
| Er-09 | 144 | Installation environment | 24 |
| Er-12 | 144 | INTLK | 133 |
| Er-13 | 144 | K | |
| Er-18 | 144 | Keypad | |
| Er-25 | 144 | Meaning of indicators | 69 |
| Err | 109 | Method of operation | 69 |
| Error Code List | 89, 96 | L | |
| F | | L24v | 133 |
| FAn1 | 109 | | |

| | | | |
|---|---------|--------------------------------|---------|
| LCP | 133 | oFA15 | 117 |
| LF | 114 | oFA16 | 117 |
| LF2 | 114 | oFA17 | 117 |
| LFB | 114 | oFA30 | 117 |
| LOAUX | | oFA31 | 117 |
| Fault | 114 | oFA32 | 118 |
| Minor Fault | 133 | oFA33 | 118 |
| LOFB | 133 | oFA34 | 118 |
| LoG | 133 | oFA35 | 118 |
| LOP | | oFA36 | 118 |
| Fault | 115 | oFA37 | 118 |
| Minor Fault | 133 | oFA38 | 118 |
| LOW_SUCT | 134 | oFA39 | 118 |
| LSP | 134 | oFA40 | 119 |
| LT-1 | 134 | oFA41 | 119 |
| LT-2 | 134 | oFA42 | 119 |
| LT-3 | 134 | oFA43 | 119 |
| LT-4 | 134 | OFF key | 69 |
| LWT | 134 | oH | |
| M | | Fault | 119 |
| Main circuit terminals | | Minor Fault | 135 |
| Line voltage drop | 43 | oH1 | 119 |
| Wire gauge | 43 | oH2 | 135 |
| Wiring | 42 | oH3 | |
| Wiring procedure for terminal block | 46 | Fault | 119 |
| MEMOBUS | | Minor Fault | 135 |
| Self-diagnosis | 279 | oH4 | 120 |
| MEMOBUS/Modbus Communications | 283 | oL1 | 120 |
| Metasys | | oL2 | 121 |
| Self-diagnosis | 279 | oL3 | |
| Metasys N2 Communications | 283 | Fault | 122 |
| microSD card | | Minor Fault | 136 |
| Disposal | 299 | oL4 | |
| Insertion slot | 69 | Fault | 122 |
| Minor Fault | 88, 126 | Minor Fault | 136 |
| Minor Fault Code List | 89, 96 | oL7 | 122 |
| Modbus | | oPE01 | 139 |
| Self-diagnosis | 279 | oPE02 | 139 |
| Motor | | oPE03 | 139 |
| Wiring | 42 | oPE05 | 140 |
| Wiring distance | 44 | oPE07 | 140 |
| N | | oPE08 | 140 |
| Nameplate | 17–18 | oPE09 | 140 |
| ndAT | 145 | oPE10 | 140 |
| NMS | | oPE11 | 141 |
| Fault | 115 | oPE16 | 141 |
| Minor Fault | 134 | oPE20 | 141 |
| O | | oPE29 | 141 |
| oC | 115 | oPE34 | 141 |
| OD | | oPE36 | 141 |
| Fault | 116 | oPr | 122 |
| Minor Fault | 135 | Options | 158–159 |
| oFA00 | 116 | ov | |
| oFA01 | 116 | Fault | 122 |
| oFA05 | 116 | Minor Fault | 136 |
| oFA06 | 116 | OV_PRESS | 136 |
| oFA10 | 116 | ov2 | 123 |
| oFA11 | 116 | ovEr | 136 |
| oFA12 | 117 | P | |
| oFA13 | 117 | PA1 | 136 |
| oFA14 | 117 | Parameter Setting Errors | 88, 139 |
| | | PASS | 136 |

| | | | |
|---|----------|-------------------------------------|--------|
| PC | | Minor Fault..... | 138 |
| Connection procedure..... | 64 | UL4 | |
| PE1..... | 123 | Fault..... | 124 |
| PE2..... | 123 | Minor Fault..... | 138 |
| Peripheral Devices..... | 158–159 | UL6 | |
| PF..... | 123, 136 | Fault..... | 124 |
| Power loss..... | 157 | Minor Fault..... | 138 |
| PSE | | USB port..... | 69 |
| Fault..... | 123 | Connecting a PC..... | 64 |
| R | | Uv..... | 138 |
| Rating (208 V) | | Uv1..... | 125 |
| Drive..... | 151 | Uv2..... | 125 |
| Rating (480 V) | | Uv3..... | 125 |
| Drive..... | 153 | V | |
| rdEr..... | 145 | vAEr..... | 145 |
| Remove | | VBRATION..... | 138 |
| Front cover..... | 31 | vFyE..... | 145 |
| Terminal cover..... | 31 | Vibration-resistant..... | 24 |
| RESET key..... | 69 | VLTS..... | 125 |
| RJ-45 connector..... | 69 | W | |
| Rotational Auto-Tuning | | WEEE..... | 300 |
| Induction Motor..... | 81 | Wire gauge | |
| Precautions..... | 82 | Main circuit terminals..... | 43 |
| S | | Voltage drop..... | 43 |
| SAFE..... | 137 | Wiring | |
| SC..... | 124 | Control circuit terminal block..... | 52, 59 |
| SCF..... | 124 | Control circuit terminals..... | 48, 54 |
| Schematic..... | 38 | Main circuit terminal block..... | 46 |
| SE..... | 137 | Main circuit terminals..... | 42 |
| SEr..... | 124 | Motor..... | 42 |
| SMK_ALARM..... | 137 | Wiring diagram | |
| Stationary Auto-Tuning | | Wiring diagram..... | 38 |
| Induction Motor..... | 81 | Wiring distance | |
| Precautions..... | 82 | Drive and motor..... | 44 |
| Stationary Auto-Tuning for Line-to-Line Resistance..... | 81 | | |
| Precautions..... | 82 | | |
| Stator resistance Auto-Tuning | | | |
| Precautions..... | 82 | | |
| STo..... | 137 | | |
| SToF..... | 137 | | |
| T | | | |
| Temperature | | | |
| Environment..... | 24 | | |
| Terminal function selection | | | |
| Terminal A1..... | 62 | | |
| Terminal A2..... | 62 | | |
| Terminal AM..... | 62 | | |
| Terminal FM..... | 62 | | |
| Test run | | | |
| Fine tuning..... | 83 | | |
| Tightening torque | | | |
| Main circuit terminals..... | 43 | | |
| TiM | | | |
| Fault..... | 124 | | |
| Minor Fault..... | 137 | | |
| Troubleshooting | | | |
| Code Displayed..... | 89, 96 | | |
| TrPC..... | 137 | | |
| U | | | |
| UL3 | | | |
| Fault..... | 124 | | |

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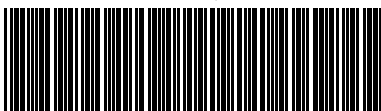
In the event that the end user of this product is to be the military and said product is to be employed in any weapons systems or the manufacture thereof, the export will fall under the relevant regulations as stipulated in the Foreign Exchange and Foreign Trade Regulations. Therefore, be sure to follow all procedures and submit all relevant documentation according to any and all rules, regulations and laws that may apply.

Specifications are subject to change without notice for ongoing product modifications and improvements.

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