ADJUSTABLE FREQUENCY DRIVE
460V 0 5 TO 25HP
REFERENCE MANUAL

LANCER GPD 502

MagneTek Drives & Systems

Eff:5/1/89

MagneTek Louis Allis Drives & Systems

For Lancer GPD 502
Adjustable Frequency Drive

INSTALLATION/START-UP INSTRUCTIONS

INTRODUCTION

Use these procedures, along with the wiring diagram identified on the unit nameplate to install, wire and initially start up the BASIC Louis Allis Drive.

SPECIFICATIONS

Refer to unit nameplate.

INSTALLATION SITE REQUIREMENTS

Ambient Temperature	-10 to 40°C
Relative Humidity	Less than 90%, Noncondensing
Vibration	Less than 0.2G

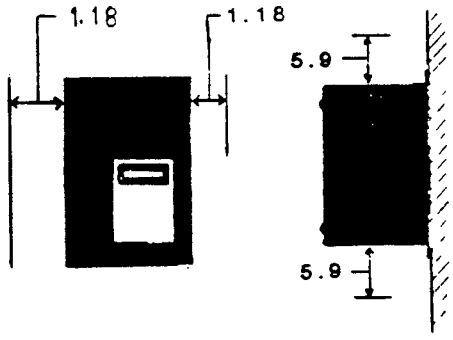
The Drive must be installed indoors in an upright level position protected from corrosive gases and dust. See Figure 1 for minimum free air space requirements.

INITIAL INSPECTION

Upon receipt of your Lancer GPD 502, a careful inspection for shipping damage should be made. After uncrating, check:

1. Whether any parts are loose, broken or separated.

2. Whether the rated capacity shown on the nameplate is the same as specified on your order.



ALL DIMENSIONS IN INCHES

FRONT VIEW SIDE VIEW

Figure 1.

CHANGE RECORD					DWG. NO. 02Y00025-0265
1 STD 30627 5/16/88					SHEET 1 OF 7
					EFF. 3/4/88 (H)

Any damages or shortages evident when the equipment is received must be reported immediately to the commercial carrier who transported the equipment. Assistance, if required, is available from the nearest Louis Allis District Office. Always refer to the Louis Allis order number, equipment description, and number stamped on the unit nameplate when contacting Louis Allis Drives & Systems.

PRECAUTIONS

A. Exercise caution when attempting to wire, adjust, test, service, or repair the Lancer GPD 502 Drive. When the "CHARGE" LED is lit, hazardous DC bus cap potential still exists.

B. Removal of covers exposes voltages which are hazardous to life. Covers may be left off ONLY IF the unit is mounted in a NEMA enclosure.

C. NEVER connect power factor correction capacitors across the Drive output and the motor. This will result in high currents and equipment damage.

D. NEVER connect power factor correction capacitors across input power source without first consulting Louis Allis. Improper use will result in equipment damage.

E. NEVER adjust SPEED pot fully clockwise before first checking the mechanical limitations of your equipment.

F. NEVER move, lift, or handle a wall-mount unit by its front cover.

INSTALLATION - MECHANICAL (Converters rated 25HP and below, 230V, 25HP and below, 460V)

Remove the front cover from the unit and install to wall or panel, using the mounting holes at the rear of the unit.

INSTALLATION - ELECTRICAL (Refer to the wiring diagram identified on the unit nameplate)

IMPORTANT

For equipment stored six months or more, special care must be taken during start-up to minimize the chance of failure of the electrolytic filter capacitor.

NOTE

When installing the Drive in a control panel with other magnetic contactors or relays, connect a noise suppressor across the coil of each component.

IMPORTANT

Do not make connections to motor until specified in START-UP procedure.

A. Installation and interconnection wiring must be done in conformance with the National Electrical Code, regulations of the Occupational Safety and Health Administration, and/or other national, regional, or industry codes and standards.

B. In long cable runs, size wire to avoid excessive voltage drop.

C. The leads used for speed reference, feedback, and other low level signals must be shielded cable and placed in conduit which is separate from conduit used for the motor and AC power leads.

D. Connect the shields of shielded cable at the DRIVE END ONLY. The far end of the shield is to be dressed neatly and left unconnected.

E. Connect terminal GND (E) to an appropriate earth ground.

F. A fused disconnect or a 3-phase circuit breaker (1CB) connected to the incoming AC line and located near the Drive is recommended to serve as a

suitable means of removing and applying input voltage to the Drive. If an input isolation transformer is used, locate the fused disconnect or circuit breaker between the transformer secondary and the Drive.

G. Installation of a motor overload relay (1OL) between the Drive output and the motor is recommended to provide overload protection to the motor. Motor thermal switches (thermoguards) are a suitable substitute for overload relay if available.

OPERATOR CONTROLS

The basic Lancer GPD 502 Drive is equipped with a digital operator. The user has the option of ordering either a Louis Allis remote Operator Control Station or a digital monitor after setting up the unit with a digital operator. The user can also interface their system logic with the Drive.

If operator control is a remote OCS or Customer System Logic, see Drive wiring diagram for appropriate installation/ wiring requirements.

IMPORTANT

The customer system relay logic will determine how the Drive will respond following a power outage or fault shutdown.

STATUS DISPLAY

A. The digital operator displays operating or fault status for the Drive whenever power is applied. Refer to unit's Instruction Manual for explanation of fault codes.

B. RESET - When the Drive has been shut down by a fault condition, while power is still applied, the fault is annunciated on the digital operator and the fault relay is energized. While energized it will prevent restart of the Drive. The relay can be reset by pressing the RESET push button, or by the RESET function on any optional Operator which is present.

If input power was removed for trouble-shooting and repair, the relay is automatically reset when power is reapplied.

PREPOWER CHECKS

Before applying input power, verify:

1. Wires are properly connected and no erroneous grounds exist.

2. Source voltage matches unit nameplate rating, ±10%.

3. All debris inside enclosure is removed.

4. All mechanical connections inside unit are tight.

START-UP

1. Initial conditions (no power applied):

a. SPEED pot set to minimum (fully CCW).

b. RUN-STOP switch/push button in STOP.

c. Drive disconnected from motor.

NOTE

If Drive shutdown occurs during operation, refer to TROUBLESHOOTING procedures in Instruction Manual.

NOTE

All following steps assume that external control signal input is used (remote OCS or customer system logic). If commands are entered through the digital operator, refer to Section 5.2 in Instruction Manual, Simple Operation Using Digital Operator.

2. Apply input power. The "CHARGE" lamp should glow, and "REMOTE" LED should be lit. Place the RUN-STOP switch/push button to RUN. The "RUN" LED should light. Turn SPEED pot slightly CW. The Drive should begin to operate, as indicated by motor speed meter.

3. Slowly increase SPEED pot to maximum (fully CW). Leave setting at full speed and place RUN-STOP switch/push button to STOP. Drive should decelerate smoothly, at a rate determined by the setting of internal DECEL constant. Place RUN-STOP switch/push button back to RUN. Drive should accelerate smoothly to full speed at a rate determined by the setting of internal ACCEL constant.

4. Turn SPEED pot to minimum (fully CCW). After Drive stops, place RUN-STOP switch/push button to STOP.

5. Turn off input power.

6. With motor disconnected from load, make wiring connections to motor.

7. Apply power. Place RUN-STOP switch/push button to RUN position and turn SPEED pot slightly CW; the motor should start turning. If motor runs backward, stop the Drive, turn off power, and reverse any two connections at Drive output terminals (T1, T2 and T3).

8. Connect motor to load.

CAUTION

NEVER ROTATE SPEED POT FULLY CLOCK-WISE BEFORE FIRST CHECKING THE MECHANICAL LIMITATIONS OF YOUR EQUIPMENT.

9. Slowly increase SPEED pot to maximum (fully CW), while monitoring motor operation. Leave setting at full speed and place RUN-STOP switch/push button to STOP. Motor should decelerate without tripping off. Place RUN-STOP switch/push button back to RUN. Motor should accelerate smoothly to full speed without tripping.

10. Check motor current at several different speed settings. Continuous currents above motor full load rating may damage the motor.

11. Start-up is now complete.

ADJUSTMENT PROCEDURE

The Lancer GPD 502 Drive comes pre-adjusted from the factory. The only adjustments that may need to be changed before drive operation are accel time and decel time.

Refer to Drive wiring diagram and Instruction Manual for factory settings.

IMPORTANT

The Drive is shipped calibrated for 3 to 60HZ operation.

PRECAUTIONS:

A. When power is on, high voltage is applied to the Control PCB. To connect or disconnected test equipment:

1. Disconnect all input power.

2. Wait at least 5 minutes.

3. Check that the "CHARGE" LED is extinguished.

CAUTION

THE "CHARGE" LED BEING ILLUMINATED IMPLIES THAT HAZARDOUS DC BUS CAP POTENTIAL STILL EXISTS. AS AN ADDED SAFETY MEASURE, AFTER THE "CHARGE" LED EXTINGUISHES, VERIFY THAT THERE IS NO LONGER A CHARGE BY MEASURING THE POTENTIAL (ACROSS MAIN CIRCUIT CAPACITOR) WITH A VOLTMETER AT TERMINAL N(-) TO TERMINAL P1(+).

B. Do not ground any test instruments when connecting, and ensure the input impedance of these devices is 1M ohms or greater.

WARNING

ADJUSTING THE DRIVE WITH POWER ON REQUIRES SPECIAL PRECAUTIONS: ALL TEST EQUIPMENT SHOULD BE CONNECTED AND DISCONNECTED WITH POWER OFF. HIGH VOLTAGE EXISTS ON THE REGULATOR BOARD; ALL POTENTIOMETERS SHOULD BE ADJUSTED WITH INSULATED HANDLE SCREWDRIVERS. IMPROPER USE OF GROUNDED TEST EQUIPMENT MAY DAMAGE THE DRIVE ENSURE THAT TEST EQUIPMENT IS CONNECTED PROPERLY TO AVOID GROUNDING THE DRIVE. THE DC BUS REMAINS CHARGED FOR SEVERAL MINUTES AFTER POWER IS REMOVED.

CONTROL CONSTANTS

CONTROL CONSTANT NO.	NAME	UNIT	SETTING RANGE	SETTING VALUE PRIOR TO FACTORY SHIPMENT
01	Max Frequency (F max)	0.1HZ	50.0-396.0HZ	60HZ
02	Max Voltage (V max)	0.1V	0.0-230.0V	200V
03	Max Voltage Freq. (F A)	0.1HZ	0.0-396.0HZ	60HZ
04	V/f Constant (F B)	0.1HZ	0.0-396.0HZ	3HZ
05	V/f Constant (V C)	0.1V	0.0-230.0V	13V
06	Min Output Freq. (F min)	0.1HZ	0.0-396.0HZ	1.5HZ
07	Min Output Freq. Voltage (V min)	0.1V	0.0-230.0V	7V
08	Accel Time	0.1s	0.1-1800.0s	10.0s
09	Decel Time	0.1s	0.1-1800.0s	10.0s
10	DC Braking Voltage	0.1V	0.0-100.0V	20.0V
11	DC Braking Time at stop	0.1s	0.0-100.0s	0.5s
12	DC Braking Time at start	0.1s	0.0-25.0s	0.0s
13	Freq. Command Gain	0.01	0.01-2.00	1.00
14	Freq. Command Bias	0.1%	0.0-25.5%	0.0
15	Freq. Command Upper Limit	1%	0-110%	100%
16	Freq. Command Lower Limit	1%	0-110%	0%
17	Setting Prohibited Freq. 1	0.1HZ	0.0-396.0HZ	0.0HZ
18	Setting Prohibited Freq. 2	0.1HZ	0.0-396.0HZ	0.0HZ
19	Setting Prohibited Freq. 3	0.1HZ	0.0-396.0HZ	0.0HZ
20	Motor Rated Current	0.1A	0.1-120.0A	See Table 11 in Instruction Manual

CONTROL CONSTANTS (Continued)

CONTROL CONSTANT NO.	NAME	UNIT	SETTING RANGE	SETTING VALUE PRIOR TO FACTORY SHIPMENT
21	Carrier Freq. Lower	1HZ	380-2500HZ	380HZ
22	Torque Compensation Gain	0.1	0.0-9.9	1.0
23	Over Torque Detecting Level	1%	30-200%	160%
24	Freq. Monitor Gain	0101	0.01-2.00	1.00
25	Current Monitor Gain	0.01	0.01-2.00	1.00
26	Inching Freq.	0.1HZ	0.0-396.0HZ	6.0HZ
27	Freq. Command 1 for Multi-step Run	0.1HZ	0.0-396.0HZ	0.0HZ
28	Freq. Command 2 for Multi-step Run	011HZ	0.0-396.0HZ	0.0HZ
29	Accel/Decel Time	0.1s	0.1-1800.0s	10.0s
30	Save Energy Gain	1%	0-120%	80%

When properly installed, operated and maintained, this equipment will provide a lifetime of service. It is mandatory that the person who operates, inspects, or maintains this equipment thoroughly read and understand this manual, before proceeding.

The Drive is an AC variable speed drive system for high-precision variable speed applications. It basically consists of a three-phase squirrel cage induction motor, a controller, an operator control station, and optional control units. This manual primarily describes the controller, but contains basic information for operator control station as well. For details of the operation of individual units, refer to their respective manuals.

DANGER

Do not touch circuit components until "CHARGE" lamp is extinguished after turning off the AC main circuit power supply. The capacitors are still charged and can be quite dangerous.

Do not connect or disconnect wires and connectors while power is applied to the circuit.

Do not check signals during operation

CAUTION

SET DRIVE CONSTANT SN-Ø3 TO ØØØØ OR Ø1Ø1. RESETTING SN-Ø3 TO 111Ø MAY CAUSE MOTOR TO RUN IN REVERSE DIRECTION W/O RUN COMMAND. POSSIBLE EQUIPMENT DAMAGE OR PERSONNEL INJURY MAY RESULT.

Important

Be sure to ground unit using the ground terminal E . See paragraph 4.4.3 on page 1Ø.

Never connect main circuit output terminals U (T1), V (T2), W (T3) to AC main circuit power supply.

All the potentiometers of the unit have been adjusted at the factory. Do not change their settings unnecessarily

Do not make withstand voltage test on any part of the unit, because it is electronic equipment using semi-conductors and vulnerable to high voltage.

Control PC board employs C MOS 1C which is easily damaged by static electricity. Take care not to touch the CMOS elements inadvertently.

CONTENTS

1. RECEIVING

This unit has been put through demanding tests at the factory before being shipped After unpacking, check for the following.

Verify the part numbers with the purchase order sheet (invoice).

No damage while in transit.

If any part of the unit is damaged or lost, immediately notify us giving full details and nameplate date.

2. MAJOR CONTROL COMPONENT LAYOUT

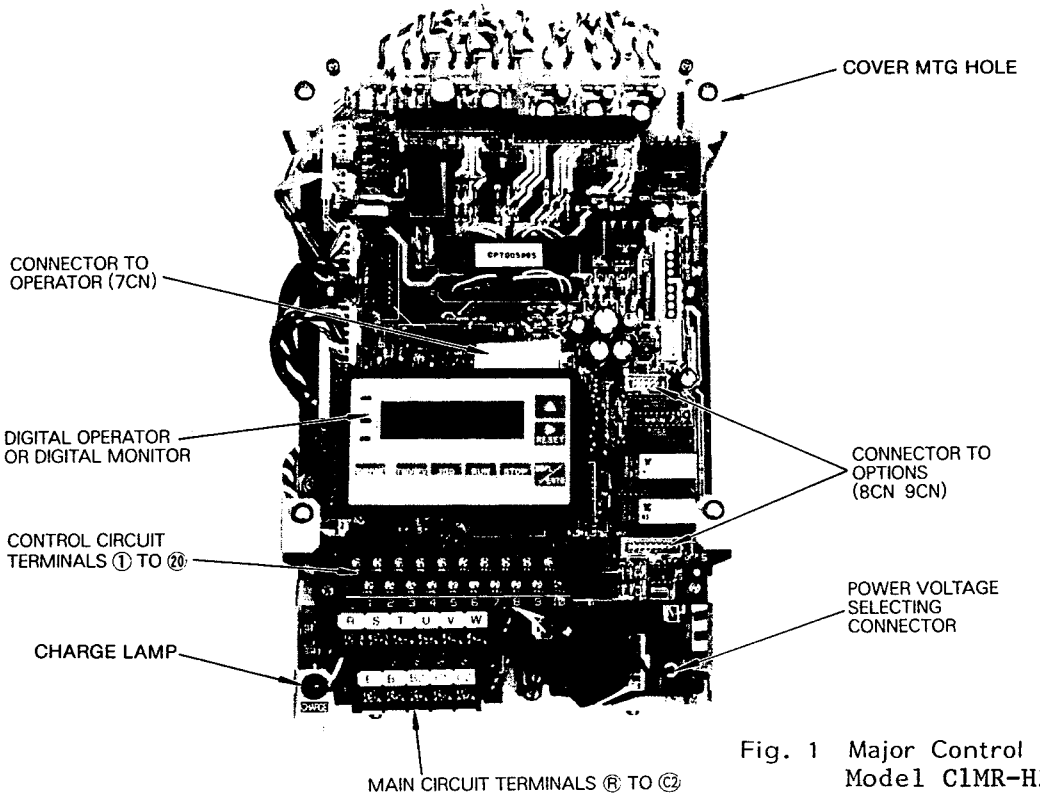


Fig. 1 Major Control Component Layout
Model C1MR-H3.7G2

TERMINAL ARRANGEMENT

⑪	⑫	⑬	⑭	⑮	⑯	⑰	⑱	⑲	⑳
①	②	③	④	⑤	⑥	⑦	⑧	⑨	⑩

Ⓡ	Ⓢ	Ⓣ	Ⓤ	Ⓥ	Ⓦ

Ⓔ	Ⓑ1	Ⓑ2	Ⓒ1	Ⓒ2

3. INSTALLATION

3.1 LOCATION

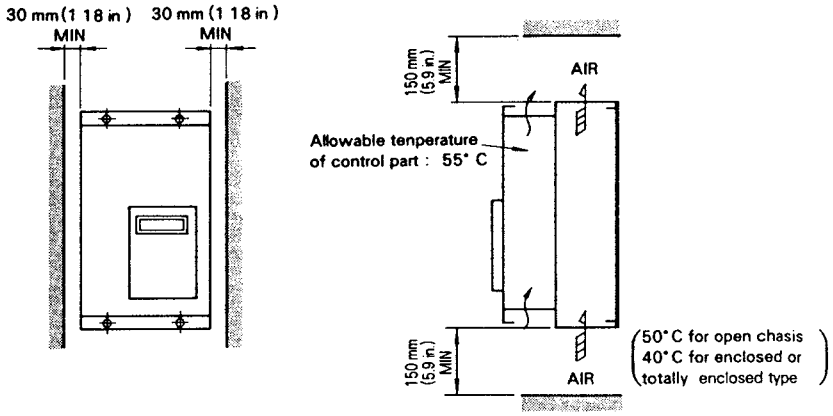
Location of the equipment is important to achieve proper performance and normal operating life. The units should be installed in areas where the following conditions exist.

- Ambient temperature: -10 to +40° C (For enclosed or totally enclosed type),
  -10 to +50° C (For open chasis type)
- Protected from rain or moisture.
- Protected from direct sunlight.
- Protected from corrosive gases or liquids.
- Free from airborne dust or metallic particles.
- Free from vibration.

3. 2 POSITIONING

For cooling and maintenance purposes, make sure that there is sufficient clearance around the equipment, as shown in Fig. 2.

To keep effective cooling conditions, it must be installed vertically to the ground using the four mounting screws.



(a) Front View (b) Side View

Fig. 2 Clearance Requirements for Proper Cooling and Maintenance

3. 3 MOUNTING DIMENSIONS

The mounting dimensions for the unit are given in Fig. 3. and Table 1.

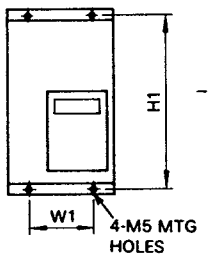


Fig. 3 Cabinet Mounting Holes

Table 1 Cabinet Mounting Dimensions

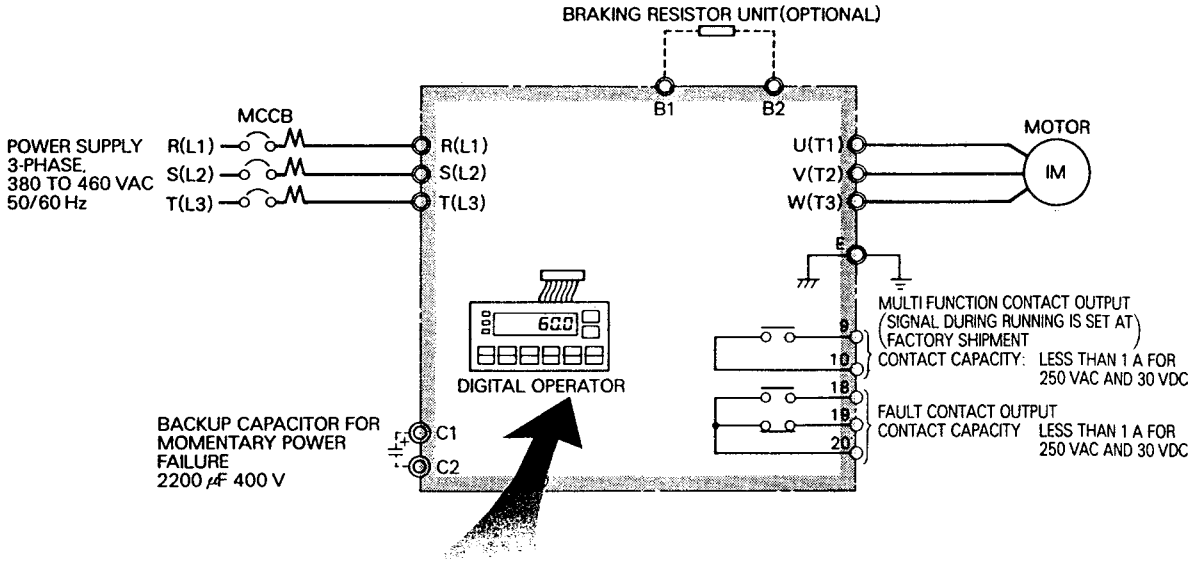
Dimensions in mm (inch)

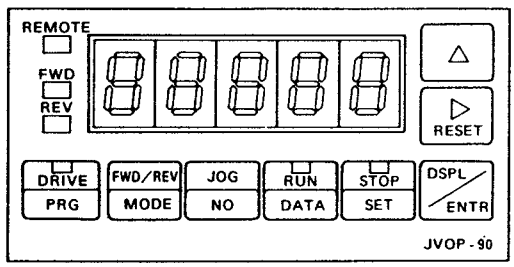
Dimensions	Model	380 TO 460 V							
		CIMR-H0.4G2	CIMR-H0.75G2	CIMR-H2 2G2	CIMR-H3 7G2	CIMR-H5 5G2	CIMR-H7 5G2	CIMR-H11G2	CIMR-H15G2
W1	Open Chasis Type	175 (6 89)				175 (6 89)		200 (7 87)	
	Enclosed Type (NEMA 1)	230 (9 06)				255 (10 04)		280 (11 02)	
H1	Open Chasis Type	340 (13 39)				390 (15 35)		485 (19 09)	
	Enclosed Type (NEMA 1)	300 (11 81)				400 (15 75)		500 (19 69)	

4. WIRING

4.1 INTERCONNECTIONS

Fig. 4 shows the connection diagram for combination of the unit with only digital operator. Remove the front cover before wiring. Connections should be made correctly, referring to Fig. 4.





(DIGITAL OPERATOR)

Note: Terminal symbol: ◎ shows main circuit; and ○ shows control circuit.

Fig.4 Example of Interconnections for Operation with Digital Operator

Fig. 5 shows the connection diagram of unit for operation by external signals.

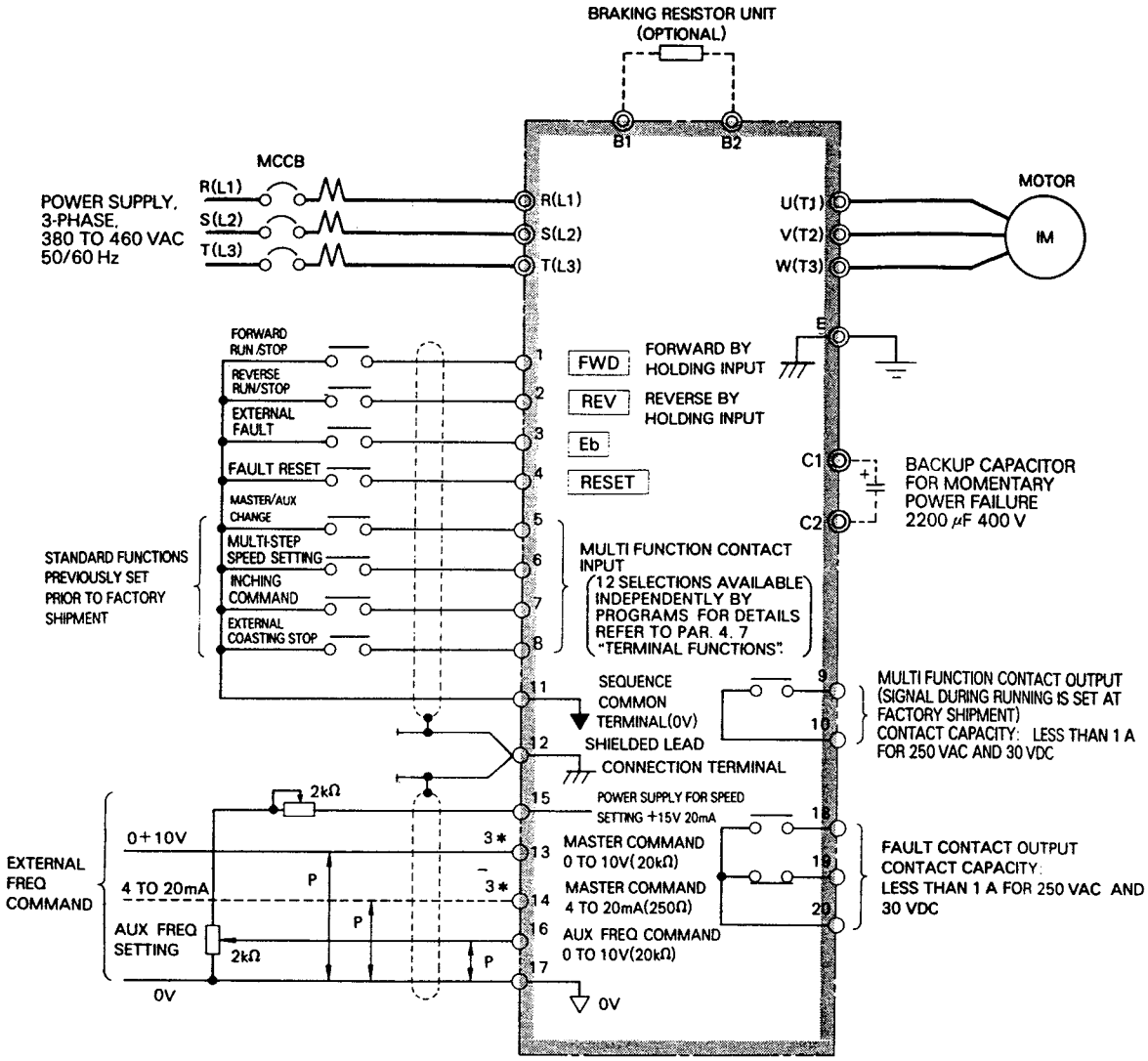


Fig. 5 Example of Interconections for Operation by External Signals

Notes:

1. indicates shielded leads and twisted-pair shielded lends.
2. External terminal ⑮ of +15V has maximum output current capacity of 20mA.
3. Either external teminal ⑬ or ⑭ can be used.
4. Terminal symbols: ◎ shows main circuit; ○ shows control circuit.
5. Use high reliable control relay for switching input command. Contact voltage and current; 24V. 18mA (typical values)

4. 2 MOLDED-CASE CIRCUIT BREAKER (MCCB) AND POWER SUPPLY MAGNETIC CONTACTOR (MC)

Be sure to connect MCCBs between power supply and unit input terminals Ⓡ (Ⓛ1), Ⓢ (Ⓛ2), Ⓣ (Ⓛ3). Recommended MCCBs are listed in Table 2.

When a ground fault interrupter is used to prevent malfunction, setting current should be 200mA or over and operating time, 0.1 sec or over.

Table 2 Molded-Case Circuit Breakers and Magnetic Contactors

	Model CIMR-	H0 4G2	H0 75G2	H2 2G2	H3 7G2	H5 5G2	H7 5G2	H11G2	H15G2
	Capacity kVA	1 4	2 1	4 1	6 9	10 3	13 7	20 6	27 4
	Rated Output Current A	1 8	2 7	5 4	9	13 5	18	27	36
Molded-Case Circuit Breaker	Model and Rated Current*	NF30 5A	NF30 5A	NF30 10A	NF30 20A	NF30 20A	NF30 30A	NF50 50A	NF100 60A
Magnetic Contactors Model		HI-7E	HI-7E	HI-10-2E	HI-20E	HI-20E	HI-20E	HI-30E	HI-50E

*Comply with NEMA AB1.

4. 3 SURGE ABSORBER

For the surge absorbers to be connected to the coils of relays, magnetic contactors, magnetic valves, or magnetic relays, select types from the ones listed in Table 3.

Table 3 Surge Absorbers

Coils of Magnetic Contactor and Control Relay	Surge Absorber*		
	Model	Specifications	Code No
Large-size Magnetic Contactors	DCR2-50A22E	250 VAC 0 5 μF + 200 Ω	C002417
Control Relay LY-2, -3 (OMRON) HH-22, -23 (Fuji) MM-2, -4 (OMRON)	DCR2-10A25C	250 VAC 0 1 μF + 100 Ω	C002482

*Made by MARCON Electronics.

IMPORTANT

Lead size should be determined considering voltage drop of leads. Refer to Par. 9 "wire size".

4.4 WIRING INSTRUCTIONS

4 4 1 Control Circuit

The external interconnection wiring must be performed with following procedures.

After completing unit interconnections, be sure to check that connections are correct. Never use control circuit buzzer check.

(1) Separation of control circuit leads and main circuit leads

Signal leads ① through ⑳ must be separated from main circuit leads Ⓡ (L1), Ⓢ(L2), Ⓣ(L3), B1, B2, Ⓤ(T1), Ⓥ(T2), Ⓦ(T3), and another power cables to prevent erroneous operation caused by noise interference.

(2) Control circuit leads ⑨ ⑩ ⑱ ⑲ ⑳ (contact output) must be separated from leads ① to ⑧ and ⑪ to ⑰.

Use the twisted shielded or twisted-pair shielded lead for the control circuit line and connect the shield sheath to the inverter terminal ⑫. See Fig. 6.

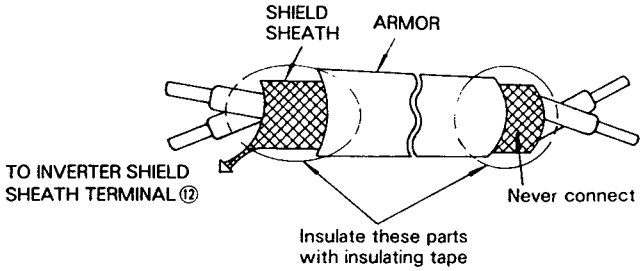


Fig. 6 Shielded Lead Termination

(3) Wiring distance

It is recommended that the wiring distance of the signal leads (① - ⑳) be 50 meters (164 feet) or below.

4.4 2 Main Circuit Input/Output

(1) Direction of phase rotation of power

- Phase rotation of power is available to each direction, clockwise and counterclockwise.
- When inverter output terminals Ⓤ(T1), Ⓥ(T2), and Ⓦ(T3) are connected to motor terminals Ⓤ(T1), Ⓥ(T2), and Ⓦ(T3), respectively, motor rotates counterclockwise, viewed from opposite drive end, upon forward operation command. To reverse the rotation interchange any two of motor leads.

(2) Never connect AC main circuit power supply to output terminals Ⓤ(T1), Ⓥ(T2), and Ⓦ(T3).

(3) Care should be taken to prevent contact of wiring leads with cabinet, for short-circuit may result.

(4) Never connect power factor correction capacitor, noise filter to unit output.

4.4.3 Grounding

Make a positive grounding using ground terminal Ⓔ on the casing of the unit.

(1) Ground resistance should be 100Ω or less.

(2) Never ground unit in common with welding machines, motors, and other large-current electrical equipment, or ground pole. Run the ground lead in a separate conduit from leads for large-current electrical equipment.

(3) Use ground lead listed in Table 17 and make the length as short as possible.

(4) Where several units are used side by side, all the units should preferably be grounded directly to the ground poles. However, connect all the ground terminals in parallel, and ground only one unit to the ground pole is also permissible (Fig. 7). However, do not form a loop with the ground leads.

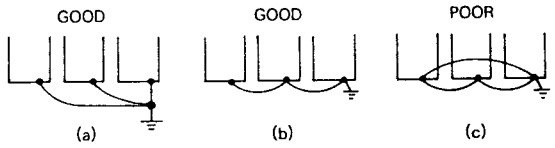


Fig. 7 Grounding of Three Units

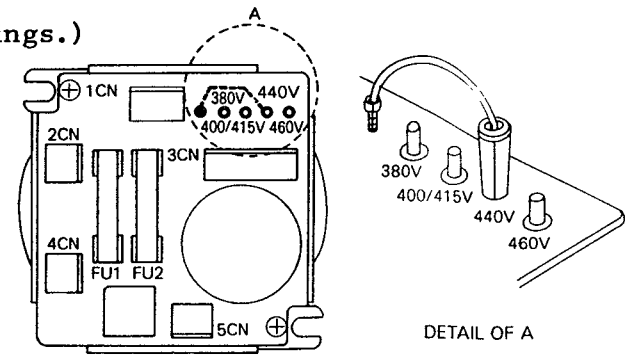
5. TEST RUN

5. 1 CHECKS BEFORE TEST RUN

After completing mounting and connection of units, check for:

- Correct connections
- No short-circuit conditions
- No loose screw terminals
  (Check especially for loose wire clippings.)
- Proper load condition
- Proper power voltage selection

Select the proper position by AC main circuit power voltage value as shown in right figure, and set the connector to it. The voltage is preset to the position of 440V prior to factory shipment.



POWER VOLTAGE SELECTION

5. 2 SIMPLE OPERATION USING DIGITAL OPERATOR

The operation is described for standard motor running at 60Hz.

Wire according to Fig. 4 "Sample of Mutual Wiring" (operation using the digital operator).

Data set with the digital operator is stored after the power is turned off.

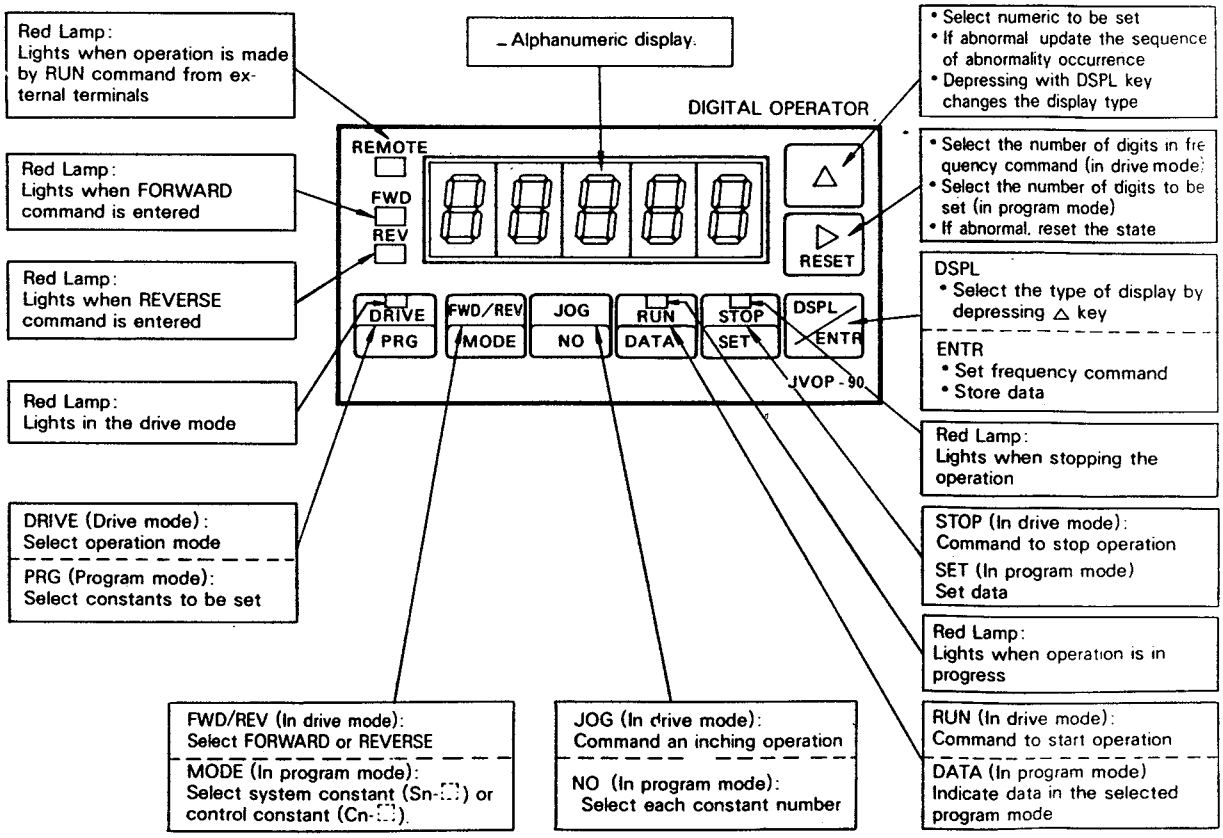


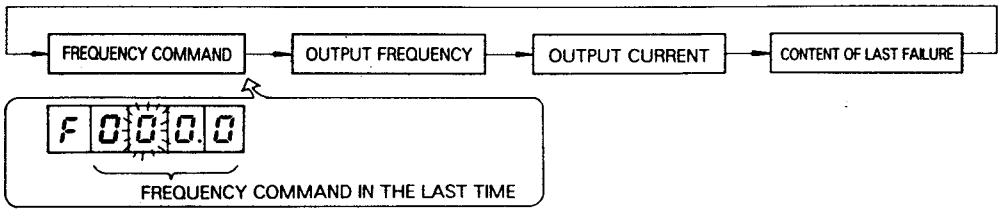
Fig. 8 Functions of digital operator keys

5.2.1 Set and Operate Frequency Command

Set frequency command in drive mode (DRIVE / PRG).

Setting:

(1) Depress △ while depressing DSPL/ENTR ; then the frequency command appears. When this is repeated, the display changes as follows. See (3) for details.



(2) Using ▷ RESET flash can be moved to the digit to be set, and the numeric set with △ key.

(3) Depress DSPL/ENTR to store the frequency command value.
(The data is stored if the power is turned off.)

(4) Depress △ while depressing DSPL/ENTR to select the output frequency to be indicated.

Operation

(5) Depress FWD/REV / MODE to select the motor rotating direction.

(6) Depress RUN / DATA to give run command. The motor accelerates acoording to the specified acceleration time (10 s) and keeps the speed at the specified frequency.

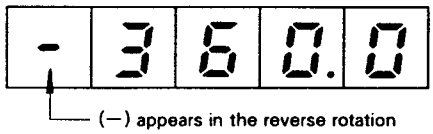
Stop operation

(7) Depress STOP / SET to stop the motor. The motor decelerates according to the specified deceleration time (10 s).

5 2.2 Monitor Function of Digital Operator

(a) Output freuency display

The output frequency appears in units of 0.1 Hz.

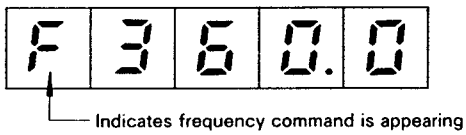


(b) Frequency command display

The following display appears in units of 0.1Hz, depending on the operation performed with the frequency command either from the external terminal or digital operator.

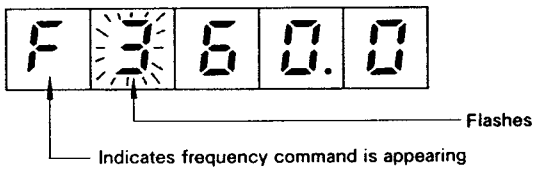
(1) Operation by frequency command from the external terminal

The frequency command specified from the external terminal appears.



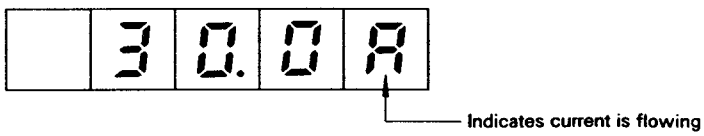
(2) Operation by frequency command from the digital operator.

The frequency command specified from the digital operator appears. The digit at which the numeric is to be set flashes as shown below.
A frequency command can also be set.



(c) Output current display

The inverter output current appears in units of 0.1 A.

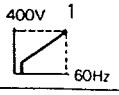


5.3 ADJUSTMENT AND SETTING

The unit has the following two constants to select the function and change the characteristics. Before starting operation, set these constants to meet the operation condition.

- System constants (Sn-01 to Sn-12): Mainly used to select V/f and the function of external terminals (Table 4).
- Control constants (Cn-01 to Cn-30): Mainly used to change characteristics (Table 5).

Table 4 System Constants (Sn-□)

System Constant No	Name	Function			Setting Value at Factory Shipment
Sn-01	kVA selection	Sets printed circuit board constants commonly used for multiple inverters			Already set (Spare part needs new setting.)
02	V/f pattern selection	16 V/f patterns are available for use so that the operation suited to the motor type load characteristics and operation condition can be performed 15 types: V/f pattern cannot be changed 1 type : V/f pattern can be changed.			400V 1  60Hz
03	–	–			0000
04	Operation signal selection	Data / Digit	0	1	0011 (4th digit, 3rd digit, 2nd digit, 1st digit) (Run by digital operator)
		1st	Run by Frequency command from the external terminal.	Run by Frequency command from the digital operator.	
		2nd	Run by Run command from the external terminal.	Run by Run command from the digital operator.	
		3rd	Main speed frequency command 0-10V/0-100%, 4-20mA/0-100%	Main speed frequency command 0-10V/100-0%, 4-20mA/100-0%	
		4th	Reverse allowed	No reverse allowed	
05	Protection characteristics selection	1st	Operation stops at a momentary power failure.	Operation continues at a momentary power failure.	0000
		2nd	Operation stalls during deceleration.	Operation does not stall during deceleration.	
		3rd	The electronic thermal motor protected.	The electronic thermal motor not protected.	
		4th	The electronic thermal protector (reduced torque)	The electronic thermal protector (constant torque).	
06	Overtorque detection	1st	Overtorque not detected	Overtorque detected	0000
		2nd	Overtorque detected during speed synchronization.	Overtorque always detected	
		3rd	Operation continues	Coasting stop.	
		4th			
07	Optional function selection	1st	Used when the optional pulse monitor is installed		0000
		2nd			
		3rd			
		4th			
08	External terminal ⑤	Select terminal 5 function in accordance with table 14.			0
09	External terminal ⑥	Select terminal 6 function n accordance with table 14.			3
10	External terminal ⑦	Select terminal 7 function in accordance with table 14			5
11	External terminal ⑧	Select terminal 8 function in accordance with table 14			6
12	Contact output ⑨,⑩	Select contact output function in accordance with table 16			0

CAUTION

SET DRIVE CONSTANT SN-Ø3 TO ØØØØ OR Ø1Ø1. RESETTING SN-Ø3 TO 111Ø MAY CAUSE MOTOR TO RUN IN REVERSE DIRECTION W/O RUN COMMAND. POSSIBLE EQUIPMENT DAMAGE OR PERSONNEL INJURY MAY RESULT.

Table 5 Control Constants (Cn-□)

Control Constant No	Name	Unit	Setting Range	Setting Value Prior to Factory Shipment
Cn-01	Max Frequency (F MAX)	0 1 Hz	50 0 – 396 0 Hz	60 Hz
02	Max Voltage (V MAX)	0 1 V	0 0 – 460 0 V	400 V
03	Max Voltage Freq (F A)	0 1 Hz	0 0 – 396 0 Hz	60 Hz
04	V/f Constant (F B)	0 1 Hz	0 0 – 396 0 Hz	3 Hz
05	V/f Constant (V C)	0 1 V	0 0 – 460 0 V	26 V
06	Min Output Freq (F MIN)	0 1 Hz	0 0 – 396 0 Hz	1 5 Hz
07	Min Output Freq. Voltage (V MIN)	0 1 V	0 0 – 460 0 V	14 V
08	Accel Time	0 1 s	0 1 – 1800 0 s	10 0 s
09	Decel Time	0 1 s	0 1 – 1800 0 s	10 0 s
10	DC Braking Voltage	0 1 V	0 0 – 200 0 V	40 0 V
11	DC Braking Time at stop	0 1 s	0 0 – 100 0 s	0 5 s
12	DC Braking Time at start	0 1 s	0 0 – 25 0 s	0 0 s
13	Freq Command Gain	0 01	0 01 – 2 00	1 00
14	Freq Command Bias	0 1 %	0 0 – 25 5 %	0 0
15	Freq Command Upper Limit	1 %	0 – 110 %	100 %
16	Freq Command Lower Limit	1 %	0 – 110 %	0 %
17	Setting Prohibited Freq 1	0 1 Hz	0 0 – 396 0 Hz	0 0 Hz
18	Setting Prohibited Freq 2	0 1 Hz	0 0 – 396 0 Hz	0 0 Hz
19	Setting Prohibited Freq 3	0 1 Hz	0 0 – 396 0 Hz	0 0 Hz
20	Motor Rated Current	0 1 A	0 1 – 120 0 A	See Table 11
21	Carrier Freq Lower	1 Hz	380 – 2500 Hz	380 Hz
22	Torque Compensation Gain	0 1	0 0 – 9 9	1 0
23	Over Torque Detecting Level	1 %	30 – 200 %	160 %
24	Freq Monitor Gain	0 01	0 01 – 2 00	1 00
25	Current Monitor Gain	0 01	0 01 – 2 00	1 00
26	Inching Freq	0 1 Hz	0 0 – 396 0 Hz	6 0 Hz
27	Freq Command 1 for Multi-step Run	0 1 Hz	0 0 – 396 0 Hz	0 0 Hz
28	Freq Command 2 for Multi-step Run	0 1 Hz	0 0 – 396 0 Hz	0 0 Hz
29	Accel/Decel Time	0 1 s	0 1 – 1800 0 H s	10 0 s
30	Save Energy Gain	1 %	0 – 120 %	80 %

5. 3 ADJUSTMENT AND SETTING (Cont'd)

[Example: Adjusting acceleration and deceleration time]

An example to set the acceleration/deceleration time using control constants 8 and 9 (Cn-08 and Cn-09) is described below. This must be carried out while the inverter is not running.

Setting acceleration time:

(1) Depress [DRIVE / PRG] to select the program mode. ([DRIVE / PRG] Goes off)

(2) Depress [FWD/REV / MODE] to select control constnt [Cn- 1] .

(3) Using [▷ / RESET] , move the flashing digit, select the numeric with [△] and indicate [Cn-08] (control constant 8).

(4) Depress [RUN / DATE] to indicate the internal data of control constant 8.

(5) Set the required acceleration time by operating [▷ / RESET] and [△]. The time can be set to 1800 seconds at 0.1 second intervals.

(When 12.5 seconds is set, it sppears [0012.5].)

(6) Depress [STOP / SET] to temporarily store data.

Setting deceleration time:

(7) Depress [JOG / NO] to indicate [Cn-08] again.

(8) Depress [△] to indicate [Cn-09] (control constant 9).

(9) Operate the same as setting of acceleration time, and depress [DSPL / ENTR] to store data.

After setting, depress [[DRIVE / PRG]] to resume the drive mode. ([DRIVE / PRG] goes on.)

6. OPERATION AT LOAD

After the no-load operation, turn off the AC main circuit power, and connect the driven machine to the motor. Make sure that the driven machine is in running condition, and there is no danger around the system. Run the motor under load in exactly the same way as for test run.

For preset starting (one-touch operation after setting the frequency) Perform the following beforehand:

(1) Set the frequency and depress RUN/DATA to accelerate the motor in the time determined, as described earlier, and to maintain the rpm at the preset frequency. The acceleration time is set short relative to the load if the rpm of the accelerating motor are not smooth (anti-stalling function during acceleration is functioning); or if trouble is displayed on the digital operator, set the acceleration time longer.

(2) To decelerate the motor in the preset time and to stop it, depress STOP/SET while the motor is rotating. The deceleration time is set short relative to the load if the rpm of the decelerating motor are not smooth (anti-stalling function during deceleration is functioning); or if trouble is displayed on the digital operator, Set the deceleration time longer.

PRECAUTION

(1) Start the motor after making sure that the motor is stopped. If the operation is started during motor coasting, use the control constant (Cn-12) DC Braking Time at start in table 5.

(2) When a standard motor is driven with the inverter, there is a little increase in motor temperature, noise, and vibration as compared to the operation from the commercial power supply.

(3) The motor cooling effect lowers during low-speed running. The torque needs to be reduced in accordance with the frequency. (For the reduction ratio, refer to the catalog or technical sheet.)

(4) Even with small load, never use a motor whose current exceeds the inverter rating.

(5) When two or more motors are operated, check to be sure that the total motor current is not larger than inverter rating.

(6) When starting and stopping the motor, be sure to use the operation signals (FWD/REV), not the magnetic contactor on the power supply side.

7. FAILURE INDICATION AND DETAILS

As table 6 shows, the failure that the unit detects is classified into trouble and alarm. When trouble occurs, the failure contact is output and the operation stops after coasting. When an alarm is issued, the digital operator indicates the alarm for warning. (An alarm is not stored in the inverter.)

Table 6 Failure Indication and Details

Indication	Failure Indication Item	Description	Failure Classification
UU Blink	A low voltage being detected	Two seconds are being counted after the detection of low voltage	Alarm
OU Blink	OV during stop	The DC voltage is higher than the specified value	Alarm
OH2 Blink	Inverter overheat is predicted	An overheat signal is entered from the external terminal	Alarm
OL3 Blink	Overtorque being detected	Operation continues despite over-torque	Alarm
Eb Blink	Both forward run and reverse run commands are closed	Deceleration stop (Not stored internally)	Alarm
UU	Low voltage	The DC voltage is lower than the specified value	Trouble
FU	Fuse blown	The main circuit fuse is blown	Trouble
OC	Overcurrent	A current surge of about 200% or more occurs	Trouble
OU	Overvoltage	The DC voltage is higher than the specified value	Trouble
OH	The radiation fin overheated	The thermo-switch for the radi-ation fin operates	Trouble
OL 1	Overload	Protect the motor	Trouble
OL 2	Overload	Protect the inverter	Trouble
OL 3	Overtorque being detected	Overtorque causes the operation to stop after coasting	Trouble
Eb	External failure	An external failure signal stops operation	Trouble
CPF	Control function self-diagnosis function is faulty	When DSPL/ENTR key is depressed CPF content appears	Trouble
OPE	Illegal constant is set	Constant logic is not coincident	Trouble
• • • • •	Control function hardware is faulty	Watchdog error	Trouble

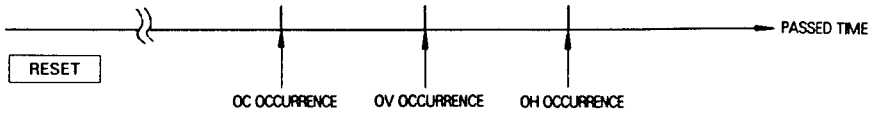
7.1 DISPLAYING THE SEQUENCE OF FAILURE OCCURRENCE

Failure items that currently occur and that occurred before the power was turned off can be sequentially indicated by the following procedure:

(1) To indicate the sequence of failure items that currently occur

When [△] is depressed, the sequence of trouble occurrence appears (up to four faults), except for OPE (illegal constant setting) and control function hardware fault.

[Example of Indication]

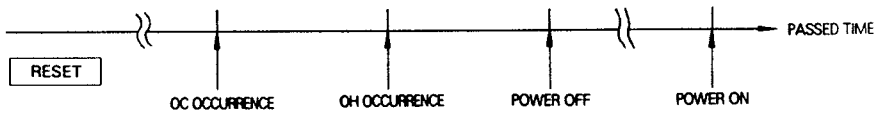


① First indication	OC	④ Depress [△]	3 OH
② Depress [△]	1 OC	⑤ Depress [△]	1 OC
③ Depress [△]	2 OV		Returns to ② state.

(2) To indicate the sequence of failure items that occurred before the power was turned off

The unit uses NV-RAM to store the sequence of failure items that occurred before the power was turned off (when low voltage is detected). Therefore, when the power is turned on again, the sequence of such failure items (up to four) appears on the digital operator display.

[Example of Indication]



After the power is turned on:

1) The first failure item that occurred before the power was turned off appears: U1 OC .... Blinks 5 seconds
2) The first display: [ ] [The type of display selected before turning off the power]
3) Depress [△] + [DSPL/ENTR] to display the sequence of failure occurrence: U1 OC
4) Depress [△] : U2 OH
5) Depress [△] : U1 OC Returns to 2)
6) Return to the display type selected before depressing [△] + [DSPL/ENTR] to display the sequence of failure occurrence: [ ]

Note: If no failure item occurred before the power was turned off, U1-- appears in step 3).

7. 2 STORAGE FUNCTION AT POWER FAILURE

The unit uses the internal NV-RAM to store the following items after the power has been turned off. Therefore, when the power is turned on again, the operation can begin with the same state as when the power was turned off.

- Display items in drive mode
- Frequency command from the digital operator
- The sequence of failure items that occurred before the power was turned off (including the content of CPF failure).

8. TROUBLESHOOTING

If the unit malfunctions, locate the cause and take corrective action by following the flowcharts given in this section.

A. TROUBLESHOOTING MOTOR SYMPTOMS

B. TROUBLESHOOTING FOR FAULT CONDITIONS

WARNING

OSCILLOSCOPE CHASSIS MAY BE AT VOLTAGES POTENTIALLY HAZARDOUS TO LIFE IF NOT PROPERLY GROUNDED. IF OSCILLOSCOPE IS USED TO MEASURE HIGH VOLTAGE WAVEFORMS, USE ONLY A DUAL CHANNEL OSCILLOSCOPE IN THE DIFFERENTIAL MODE WITH X1ØØ PROBES. ALWAYS CONNECT OSCILLOSCOPE CHASSIS TO EARTH GROUND.

WARNING

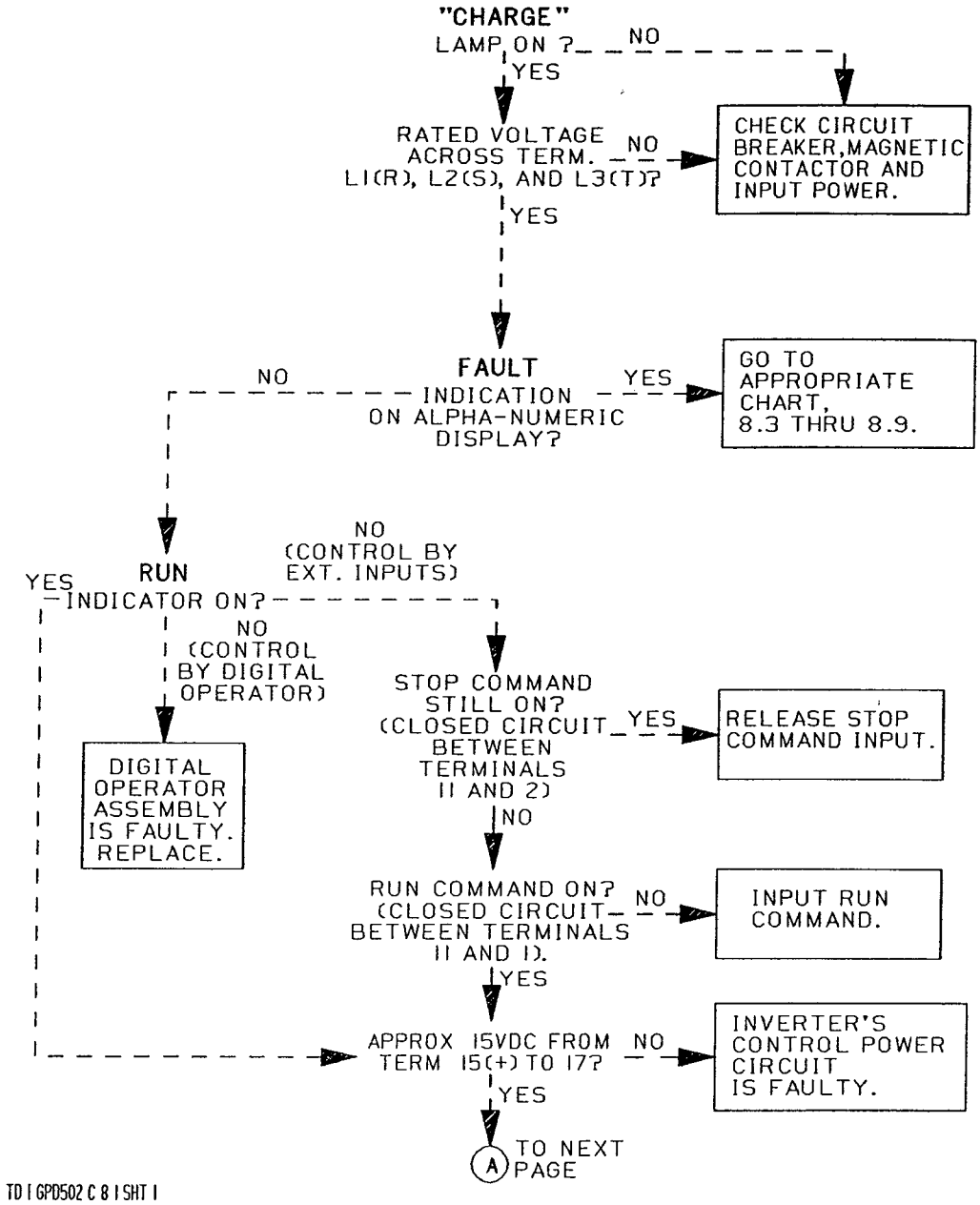
VOLTAGES DANGEROUS TO LIFE EXIST WHEN EQUIPMENT IS OPEN AND ENERGIZED. DO NOT WORK ALONE.

CAUTION

TO PREVENT EQUIPMENT DAMAGE ALWAYS REMOVE INCOMING THREE-PHASE POWER BEFORE TEST EQUIPMENT IS CONNECTED OR REMOVED.

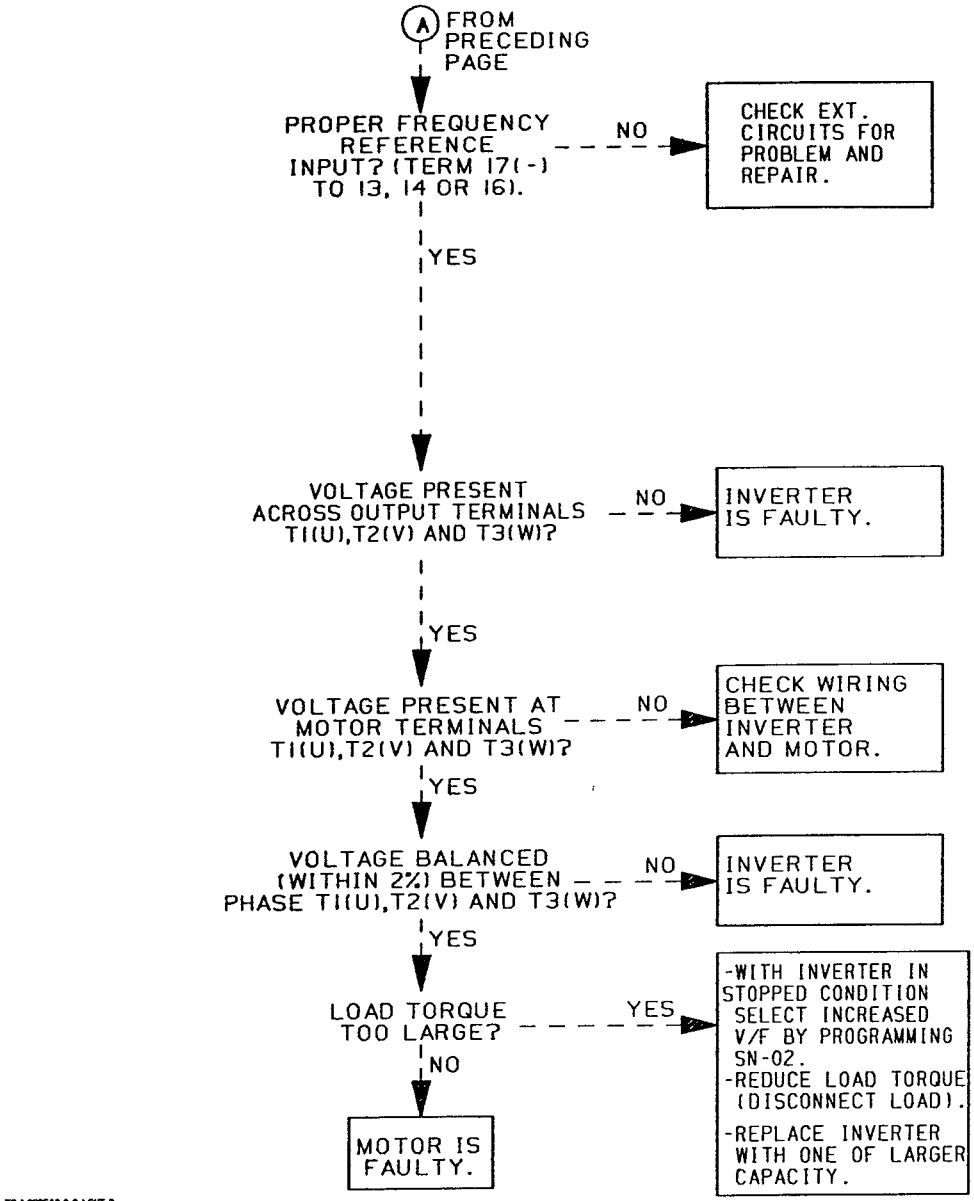
TROUBLESHOOTING CHART 8.1

MOTOR WILL NOT RUN



TD1GP0502C81SHT1

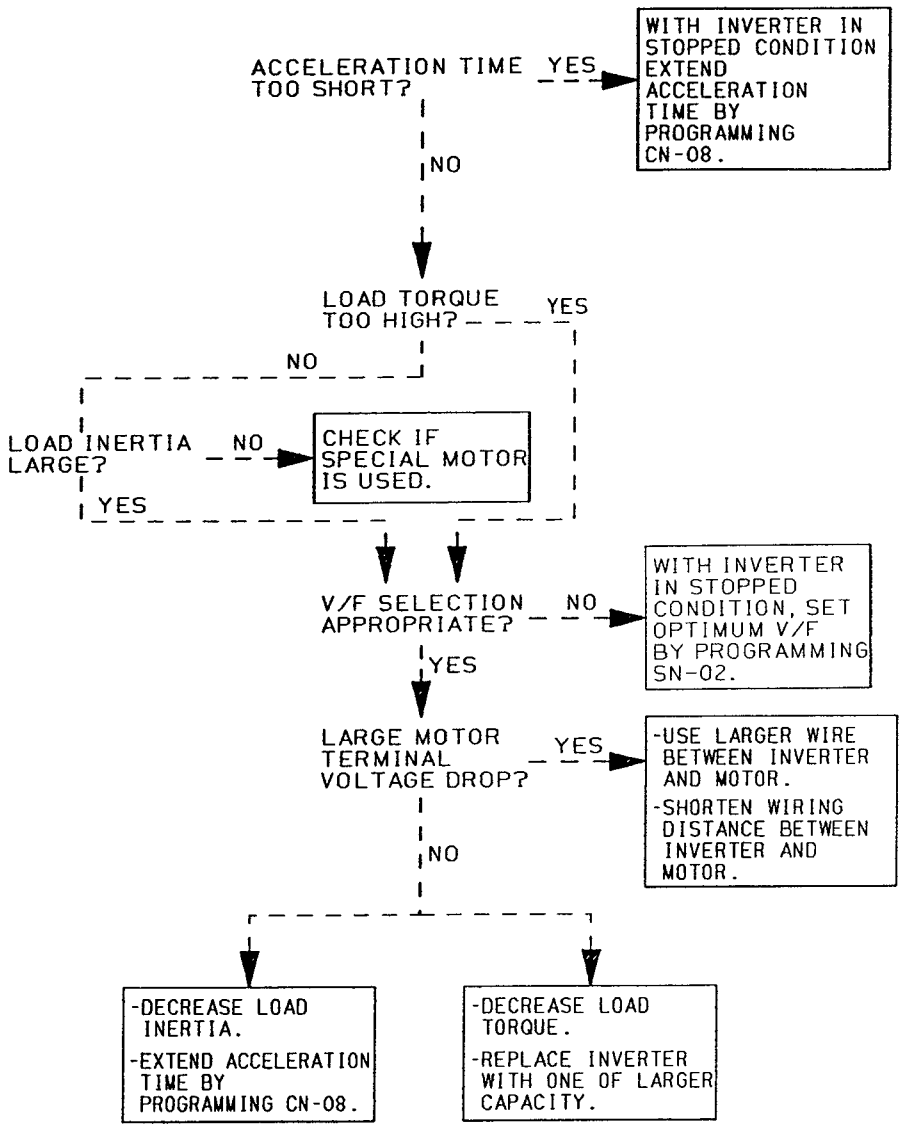
TROUBLESHOOTING CHART 8.1 (Continued)



TB1.GPT502.C 8.1.SHT 2

TROUBLESHOOTING CHART 8.2

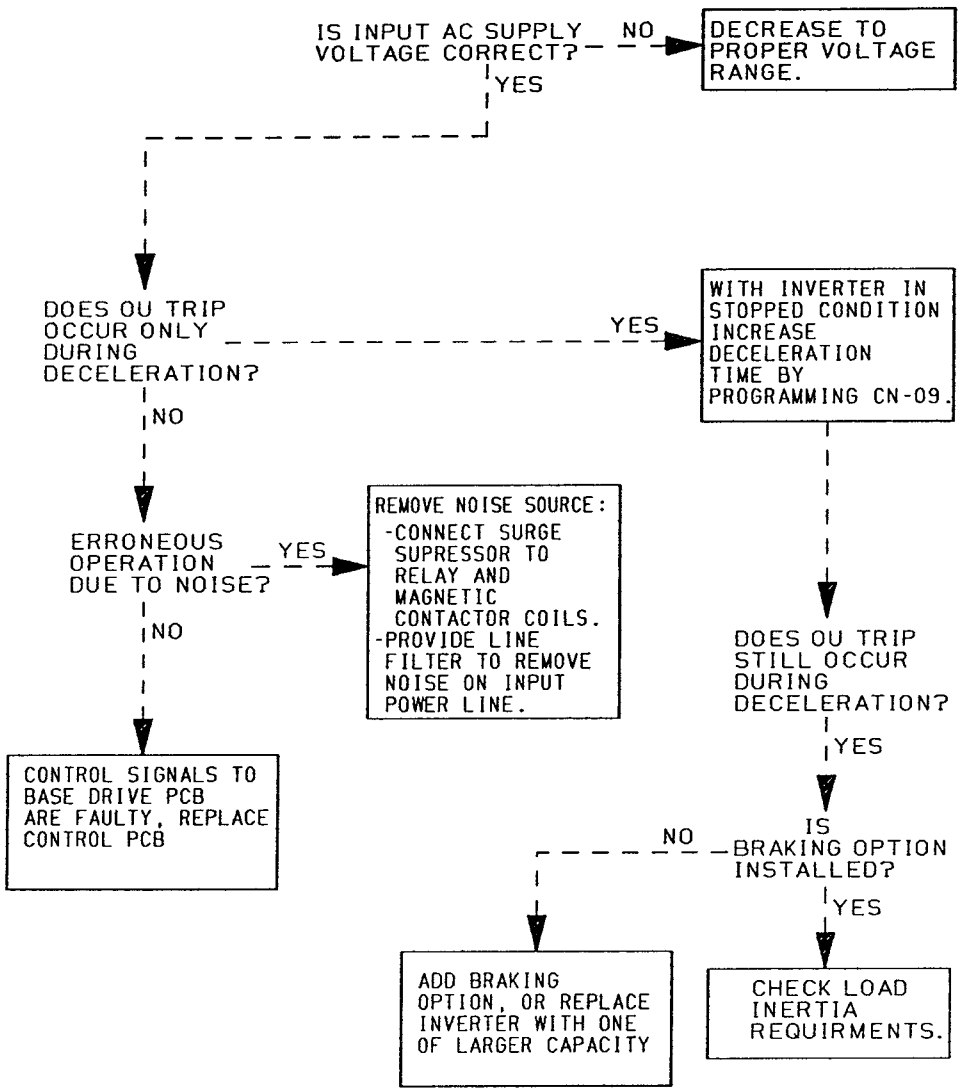
MOTOR STALLS DURING ACCELERATION



TDJ.GPD502.C8.2

TROUBLESHOOTING CHART 8.3

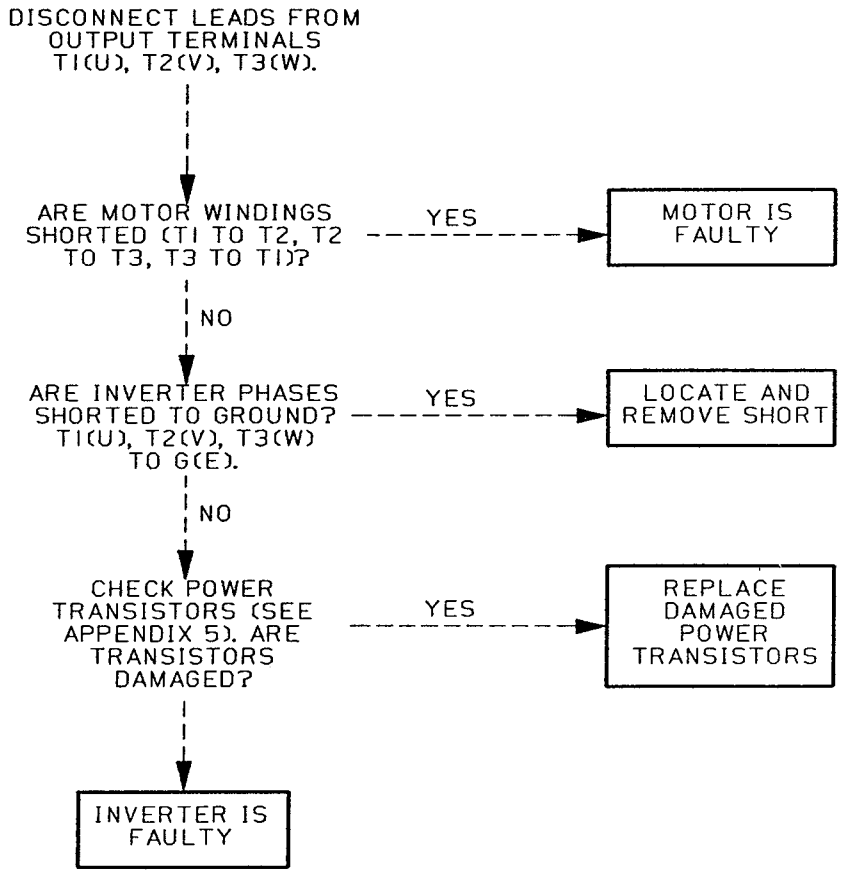
OVERVOLTAGE (OU) FAULT INDICATION



TDIGP0502 C8.3

TROUBLESHOOTING CHART 8.3.1

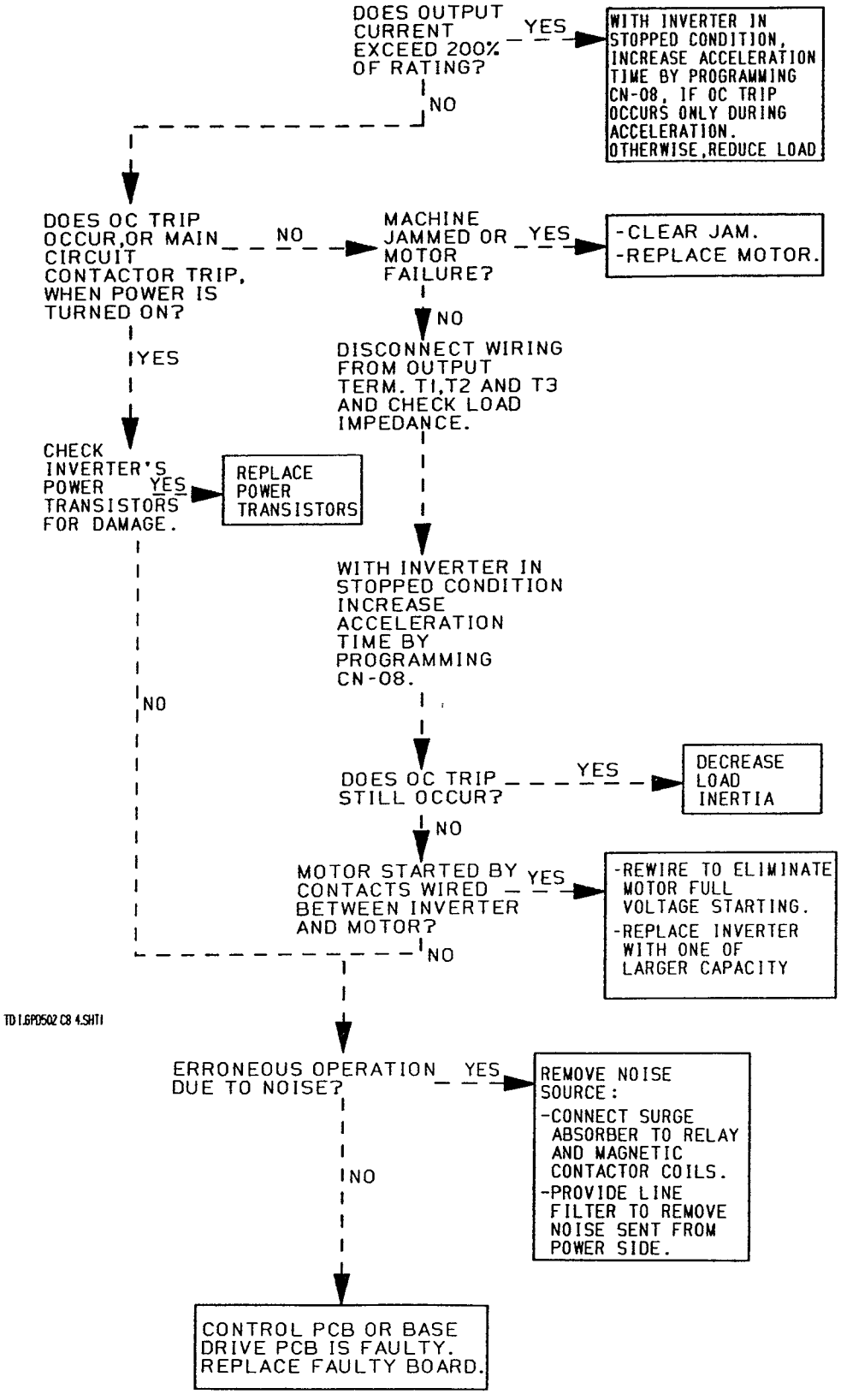
BLOWN FUSE (FU) FAULT INDICATION



TD.I.GPD502.C8.3.1

TROUBLESHOOTING CHART 8.4

OVERCURRENT (OC) FAULT INDICATION

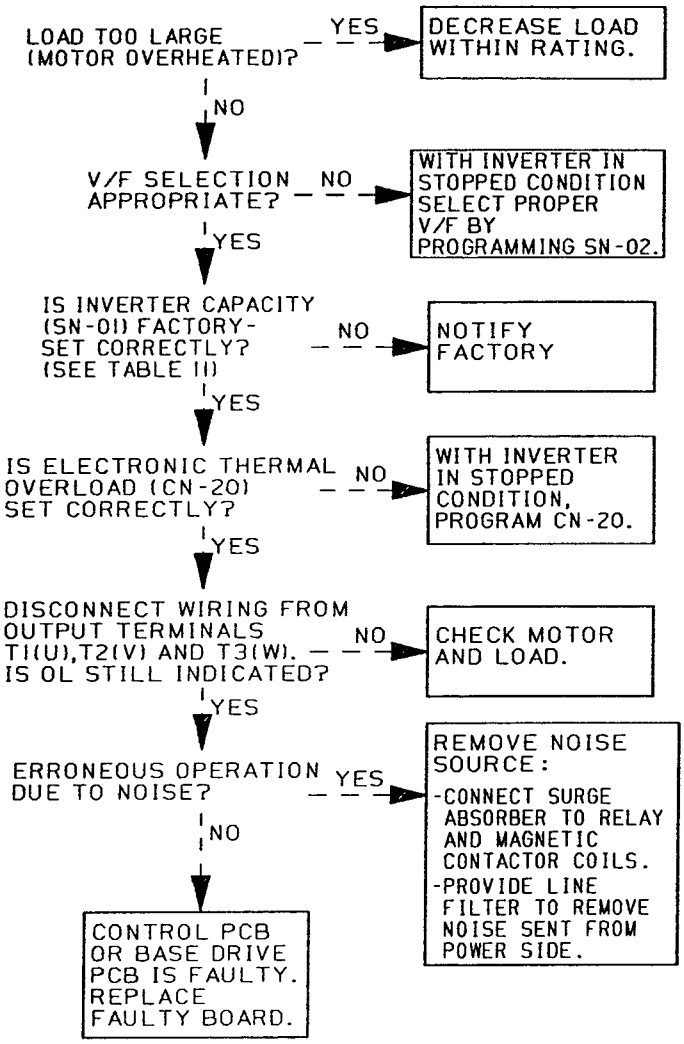


TD1.GP0502 C8 4.SHT1

TD1.GP0502 C8 4.SHT2

TROUBLESHOOTING CHART 8.5

OVERLOAD (OL) FAULT INDICATION



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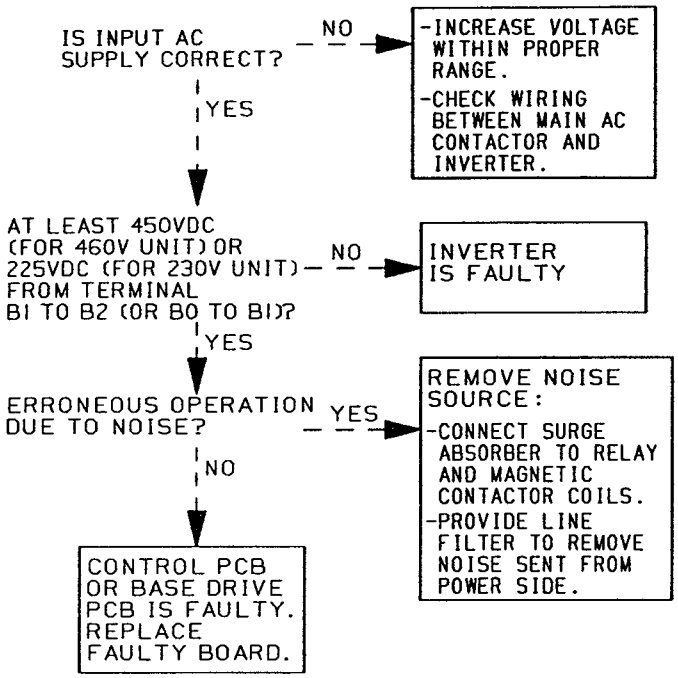
TROUBLESHOOTING CHART 8.6

UNDERVOLTAGE (UU) FAULT INDICATION



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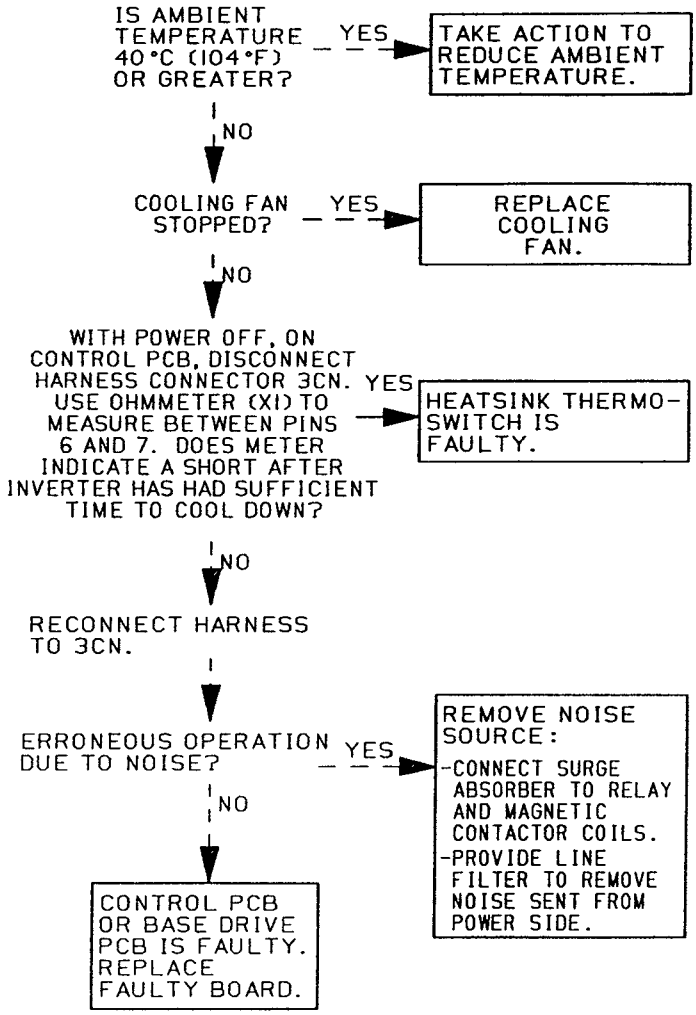
TROUBLESHOOTING CHART 8.7

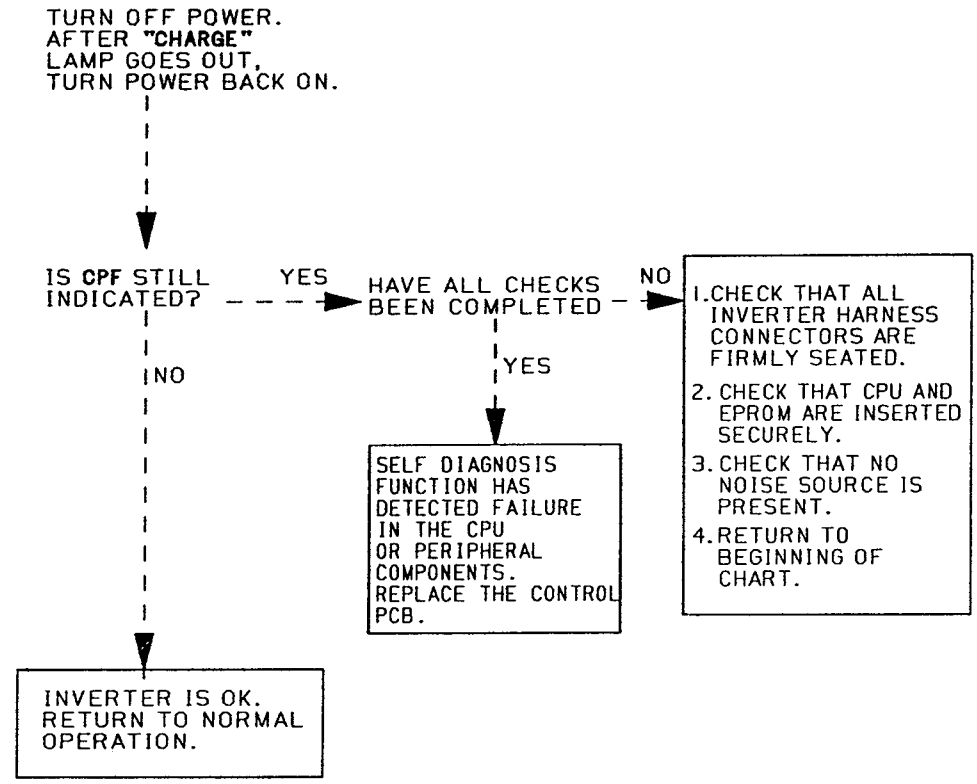
INVERTER OVERHEATED (OH) FAULT INDICATION



TRI.6P8502.08.7

TROUBLESHOOTING CHART 8.8

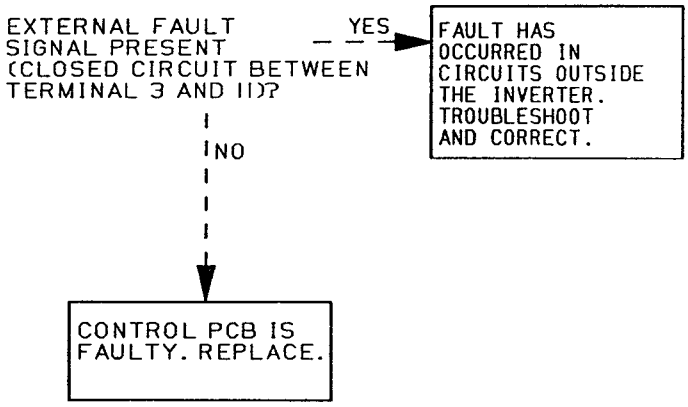
CONTROL FUNCTION ERROR (CPF) FAULT INDICATION



TD1.GP0502 C8.8

TROUBLESHOOTING CHART 8.9

EXTERNAL FAULT (Eb) INDICATION



TD1.GP0502 C8.9

APPENDIX 1 STANDARD SPECIFICATIONS

Table 7 Standard Specifications

Inverter Model CIMR-□			380 to 460 V							
			H0 4G2	H0 75G2	H2 2G2	H3 7G2	H5 5G2	H7 5G2	H11G2	H15G2
Output Characteristics	Inverter Capacity KVA		1 4	2 1	4 1	6 9	10 3	13 7	20 6	27 4
	Rated Output Current A		1 8	2 7	5 4	9	13 5	18	27	36
	Over Load Current for one minute A		2 3	3 4	6 8	11 3	16 9	22 5	33 8	45
	Max Applicable Motor Output kW (HP)*	Overload Capacity 125% for one minute	0 75 (1)	0 75 (1)	2 2 (3)	3 7 (5)	7 5 (10)	11 (15)	15 (20)	18 5 (25)
		Overload Capacity 150% for one minute	0 4 (0 5)	0 75 (1)	2 2 (3)	3 7 (5)	5 5 (7 5)	7 5 (10)	11 (15)	15 (20)
	Max Output Voltage		3-Phase, 380/400/415/440/460 V (Proportional to input voltage)							
	Rated Output Frequency		50, 60, 72 90 120, 180 Hz (up to 396 Hz available)							
Power Supply	Rated Input Voltage and Frequency		3-Phase 380/400/415/440/460 V 50/60 Hz							
	Allowable Voltage Fluctuation		±10 %							
	Allowable Frequency Fluctuation		±5 %							
Control Characteristics	Control Method		Sine wave PWM							
	Frequency Control Range		1 40							
	Frequency Accuracy		Digital command 0 01 % (−10 to 40°C / +14 to 104°F) Analog command 0 2 % (25 ±10°C / 77 ±18°F)							
	Frequency Resolution		Digital operator reference 0 1 Hz Analog refence 0 06 Hz/60 Hz							
	Output Frequency Resolution		0 01 Hz							
	Overload Capacity		125% for one minute or 150% for one minute (Load rate for max applicable motor)							
	Frequency Setting Signal		0 to 10 VDC (20 KΩ) 4-20 mA (250 Ω)							
	Accel/Decel Time		0 1 to 1800 sec (Accel/Decel time setting independently)							
	Braking Torque		Approx 20 %							
	No of V/f Patterns (Total of 15)		4 For general purpose 4 For high starting torque 4 For fans and pumps 3 For machine tools							
Protective Functions	Motor Overload Protection		Electric thermal overload relay							
	Instantaneous Overcurrent		Motor coasts to a stop at approx 200 % rated current							
	Fuse Blown Protection		Motor coasts to a stop by blown-fuse							
	Overload		Motor coasts to a stop at 125 % load for 1 minute							
	Overvoltage		Motor coasts to a stop if converter output voltage exceeds 790 V							
	Undervoltage		Motor coasts to a stop if converter output voltage drops to 420 V or below							
	Momentary Power Failure		Immediately stop by 15 ms and above momentary power failure (Continuous system operation during power failure less than 2 sec) †							
	Fin Overheat		Thermostat							
	Stall Prevention		Stall prevention at acceleration /deceleration and constant speed operation							
	Ground Fault		Provided by electronic circuit							
	Power Charge Indication		Charge lamp keeps ON until bus voltage drops below 50 V							
Environmental Conditions	Location		Indoor (protected from corrosive gases and dust)							
	Ambient Temperature		−10 to 40°C (not frozen)							
	Storage Temperature †		−20 to 60°C							
	Humidity		90 % RH (no condensation)							
	Vibration		1 G less than 20 Hz up to 0 2 G at 20 to 50 Hz							

* Our standard 4-pole motor is used for Max Applicable Motor Output

† For 380 to 460 V ride-through function up to 2 sec momentary power failure available by connecting backup capacitor 2200 μF 400 V between external terminals (C1) and (C2)

† Temperature during shipping Storing in this temperature for a long-period may deteriorate main circuit capacitor

APPENDIX 2 TERMINAL FUNCTIONS

A2-1 Terminals of Main Circuit

Table 8 Terminal Functions and Voltages of Main Circuit

Terminals	Functions	Voltages 380 to 460 V Model CIMR-H0 4G2 to -H15G2
R (L1) S (L2) T (L3)	Main circuit input power supply	Three-phase 380/400/415/440/460 V at 50/60 Hz
U (T1) V (T2) W (T3)	output	Three-phase 380/400/415/440/460 V (proportional to input voltage)
B1 B2	Braking resistor unit	Approx 600 VDC
C1 C2	Backup capacitor for momentary power failure	Approx 300 VDC (capacitor 2200 μF 400 VDC)
E	Ground terminal	—

A2-2 Terminals of Control Circuit

Table 9 Terminal Functions and Signals of Control Circuit

Terminals	Functions		Levels
1	Forward operation-stop signal		Run at closed, stop at open
2	Reverse operation-stop signal		Run at closed stop at open
3	External fault input		Fault at closed
4	Fault reset input (external)		Fault reset at closed
5 6 7 8	Following sequence control commands available to select 5-step speed setting Master/Aux selector Master/Aux selector at forward run, Mastet/Aux selector at reverse run, Energy saving operation, Override External coasting stop command, Forward inching operation Reverse inching operation, Coasting stop command, Speed search from top speed, Speed search from setting value Accel/decel time selection		
9 10	One of the following signals available to select During running Zero speed, Synchronized speed Over-torque Under voltage (NO)		Contact capacity 250 VAC at 1 A or below 30 VDC at 1 A or below
11	Sequence control input common terminal		Sequence control input 0 V
12	Connection to shield sheath of signal lead		—
13	Master speed frequency reference input		0 to +10 V (20 kΩ)
14			4–20 mA (250 Ω)
15	Aux frequency reference input		+15V(Control power supply for frequency setting max 20 mA)
16			0 to +10 V/100 % (20 kΩ)
17			0 V
18	Fault contact output (NONC)	Closed at fault	Contact capacity 250 VAC at 1 A or below 30 VDC at 1 A or below
19		Open at fault	
20		Common	

(1) Tarminals ①, ② (Forward run command, reverse run command)

These status signals differ, as shown in Table 10.

Table 10 Forward/Reverse run command

Forward run command	Reverse run command	Description
Open	Open	Deceleration and stop (Stop indication is delayed 100 ms)
Closed	Open	Forward run*
Open	Closed	Reverse run*
Closed	Closed	The digital operator flashes Eb and when both are closed for 500 ms or more, it decelerates and stops the motor (not stored internally)

Note: Time chart at forward run is shown in Fig. 9.

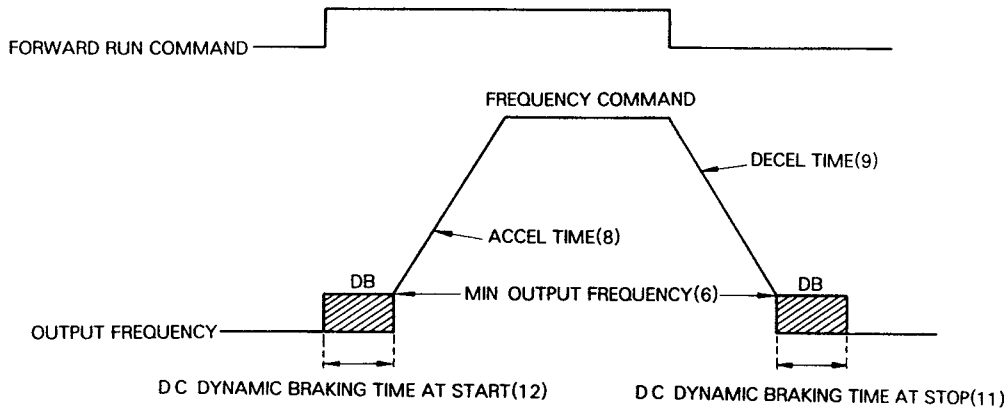


Fig. 9 Time chart at forward run

Note: Parenthesized values indicate the number of control constant.

(2) Terminal ③ (external fault input)

When an external fault is input, the inverter coasts to a stops and the digital operator indicates Eb. Data is stored in the inverter until a fault reset is input.

(3) Terminal ④ (reset fault)

Used to reset fault. This is effective when both forward and reverse comand are open.

(4) Terminals ⑤, ⑥, ⑦, and ⑧ (sequence functional terminals)

The function of terminal ⑤ is selected by the value set to system constant 8 . Similarly, the function of terminal ⑥ is selected by the value set to system constant 9; the function of terminal ⑦ by the value set to system constant 10; the function of terminal ⑧ by the value set to sytem constant 11. (See Par, 4.7 Terminal Function).

A2-2 Terminals of Control Circuit (Cont'd)

(5) Terminals ⑨ - ⑩ (multifunctional contact output)

The output items from terminals ⑨ - ⑩ are selected by constant 12. (See Par 4.8 Contact Output Selection Function)

Contact capacity: 250 VAC, 1 A or less
30 VDC, 1 A or less

(6) Terminals ⑬ and ⑭ (main speed frequency command)

Used to connect the master speed frequency command. When the master speed frequency command is set with a voltage, connect terminal ⑬ ; when set with a current, connect terminal ⑭ .

(7) Terminal ⑯ (auxiliary frequency command)

Used to connect auxiliary frequency command. The function may differ depending on the values set to system constants 8 and 9.

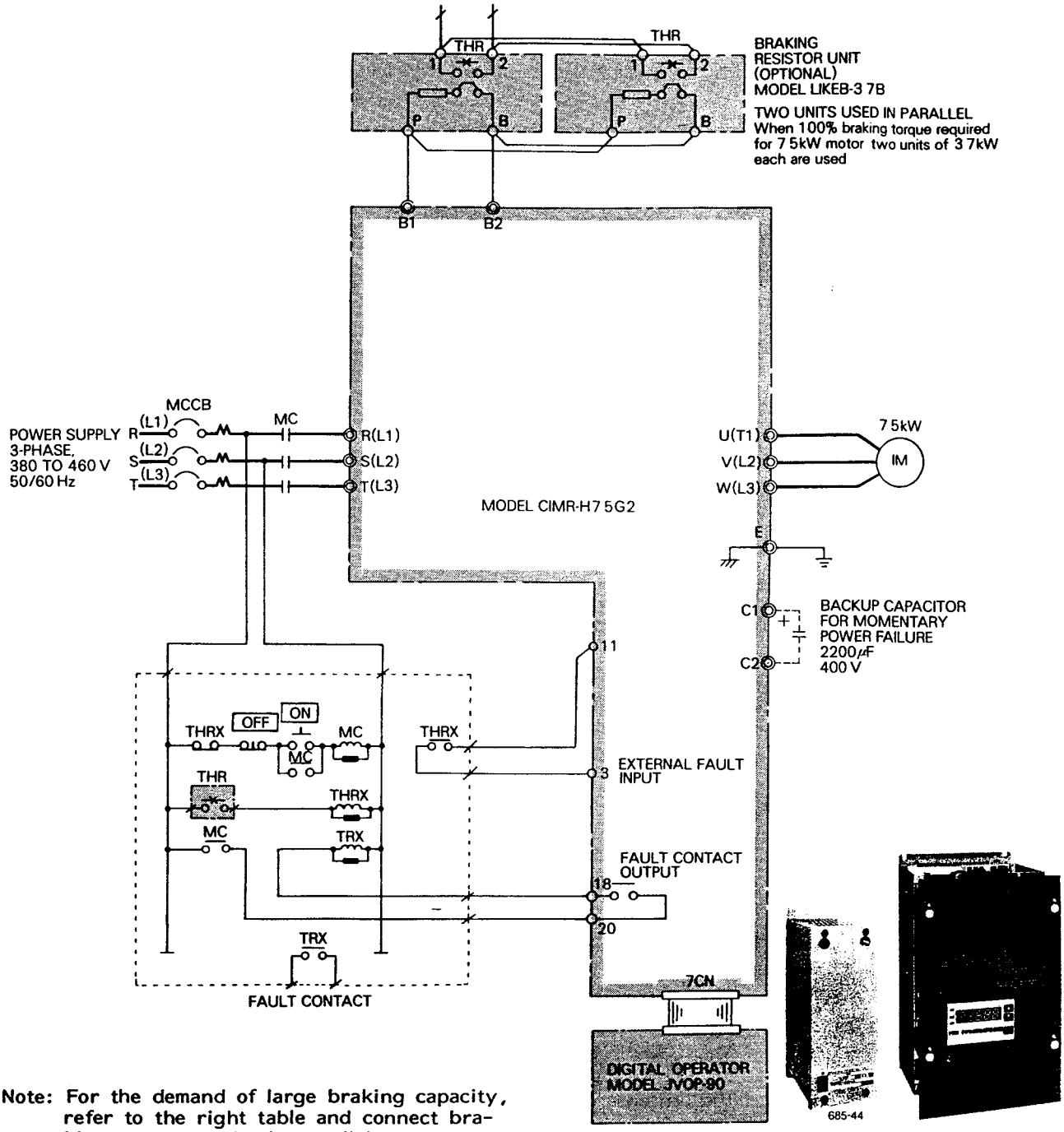
(8) Terminals ⑱ - ⑲ - ⑳ (fault contact output)

When a fault occurs, terminals ⑱ - ⑳ close and terminals ⑲ - ⑳ open.

Contact capacity: 250 VAC, 1 A or less
30 VDC, 1 A or less

APPENDIX 3 INTERNAL CIRCUIT AND INTERCONNECTION DIAGRAMS

A3-1 With Braking Resistor Unit



Note: For the demand of large braking capacity, refer to the right table and connect braking resistor units in parallel.

Model	Braking Resistor Unit Model	Max No of Units to be Connected
CIMR-H0.4G2	LKEB-H0.75B	4
CIMR-H0.75G2	LKEB-H0.75B	4
CIMR-H2.2G2	LKEB-H3 7B	2
CIMR-H3.7G2	LKEB-H3 7B	2
CIMR-H5.5G2	LKEB-H3 7B	3
CIMR-H7.5G2	LKEB-H3 7B	3
CIMR-H11G2	LKEB-H15B	3
CIMR-H15G2	LKEB-H15B	3

APPENDIX 4 SYSTEM CONSTANTS

A4-1 Inverter Capacity Selection (Sn-10)

As Table 11 shows, the inverter capacity has been set already. To use a spare printed circuit board, set the desired capacity.

Table 11 Inverter Capacity Selection

Sn-01 Data	Model (CIMR-□□□)	Max Applicable Motor Output kW (HP)	Inverter Rated Current A	Motor Rated Current A (Factory setting)	Reference Current for Constant Setting* A
10	H0 4G2	0 4 (0 5)	1 8	1 1	1 5
11	H0 75G2	0 75 (1)	2 7	1 7	2 3
12	H2 2G2	2 2 (3)	5 4	4 3	4 5
13	H3 7G2	3 7 (5)	9	6 9	8
14	H5 5G2	5 5 (7 5)	13 5	10 3	12
15	H7 5G2	7 5 (10)	18	13 4	15
16	H11G2	11 (15)	27	20 2	23
17	H15G2	15 (20)	36	26 7	30

* The reference current for setting the overtorque detection level (Cn-23) and during-operation-stall level (On-18).

Table 11 A Model and Code No of Control PC Board

Inverter Voltage	Inverter Model (CIMR-□□)	Control PC Board	
		Model	Code No
380 to 460 V	H0 4G2	JPAC-C360 □□*	ETC00876X-S□□XX+
	H0 75G2		
	H2 2G2	JPAC-C360 □□	ETC00876X-S□□XX
	H3 7G2		
	H5 5G2	JPAC-C361 □□	ETC00877X-S□□XX
	H7.5G2		
	H11G2	JPAC-C362 □□	ETC00878X-S□□XX
	H15G2		

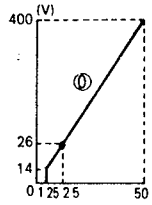
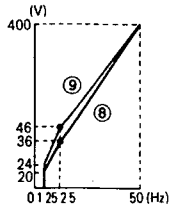
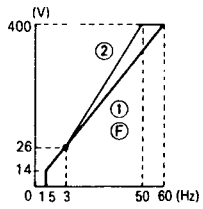
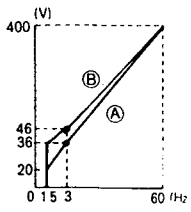
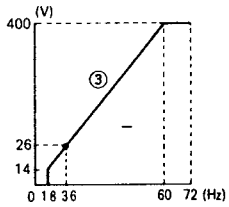
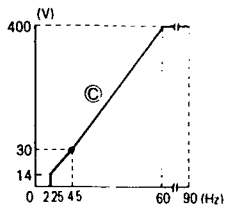
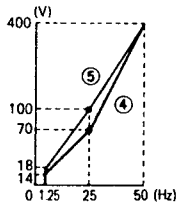
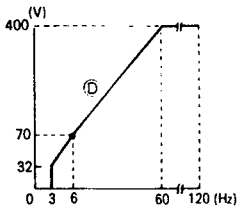
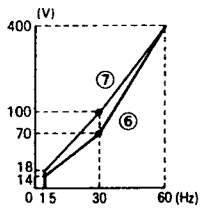
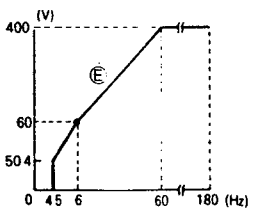
* □□ indicates the contents of function. Use the PC board with same model or code No. as spare parts.

+ xx indicates the number of design change. Use the PC board with same number or more as spare parts.

A4-2 Setting of V/f Pattern Selector Switch (Sn-02)

The V/f pattern selector switch (Sn-02) has been factory-set at the notch ① for most applications. For specific applications such as fans and pumps, high-starting torques, or machine tools, select the optimum V/f pattern for motor running, according to the load characteristics. (See Table 12.)
IF Sn-02 is set to Ⓕ , arbitrary V/f pattern can be selected with control constants 1 to 7.

Table 12 V/f Pattern Selection (15 Patterns)

Application	Specification		1S Notch	V/f Pattern	Application	Specification		1S Notch	V/f Pattern
General Purpose	50Hz		⓪		High Starting Torque	50Hz	Starting Torque Low	⑧	
							Starting Torque High	⑨	
	60Hz	60Hz Saturation	① Ⓕ			50Hz	Starting Torque Low	Ⓐ	
		50Hz Saturation	②				Starting Torque High	Ⓑ	
	72Hz		③		Constant Output Operation (Machine Tools)	90Hz		Ⓒ	
Variable Output Operation (Fans and Pumps)	50Hz	Variable Torque 1	④			120Hz		Ⓓ	
		Variable Torque 2	⑤						
	60Hz	Variable Torque 2	⑥			180Hz		Ⓔ	
		Variable Torque 1	⑦						

Note: 1. Take account of the following conditions and others when selecting V/f pattern:
- Pattern matching the voltage-frequency characteristic of the motor
- According to the maximum motor speed

2 V/f pattern for high starting torque should be selected for:
- Long wiring distance
- Large voltage drop at start
- AC reactor connected to input or output of the inverter
- Use of motor of the rating below the max

A4-3 Run Signal Selection (Sn-04)

The run command and frequency command that are validated by a combination of the 1st and 2nd digits differ (See Table 13).

(1) 1st digit (frequency command selection)

0: Runs by the frequency command from the external terminal.

1: Runs by the frequency command from the digital operator.

(2) 2nd digit (run command selection)

0: Runs by the run command from the external terminal.

1: Runs by the run command from the digital operator.

Table 13 Combination of Frequency and Run Commands

(○ effective × not effective)

Command	System Constant 4	Setting Value (1st and 2nd digits)			
		00	01	10	11
External Terminal	Forward run command	○	○	×	×
	Reverse run command	○	○	×	×
	External fault	○	○	○	○
	Fault reset	Note 2	Note 2	○	○
	Command of terminal ⑤	○	Note 1	×	×
	Command of terminal ⑥	○	Note 1	×	×
	Command of terminal ⑦	○	Note 1	×	×
	Command of terminal ⑧	○	Note 1	×	×
	Master freq command	○	×	○	×
	Aux input	○	×	×	×
	Fault contact output	○	○	○	○
	Contact of terminals ⑨–⑩	○	○	○	○
Operator	Freq command	×	○	×	○
	Run key	×	×	○	○
	Jog key	×	×	○	○
	Stop key	Note 3	Note 3	○	○
	FWD/REV key	×	×	○	○
	△/RESET key	Note 2	Note 2	○	○
	DRIVE/PRG key	Effective duinrg stop	Effective during stop	Effective during stop	Effective during stop
	REMOTE LED	ON	ON	OFF	OFF
	MONITOR indication	○	○	○	○

Note 1: Multi-step speed run, master speed/auxiliary switching, forward master speed/auxiliary switching, reverse master speed/auxiliary switching, override, and inching run commands are invalid.

2. Valid when the forward run command, reverse run command, and DB command are open.

3. When key and STOP/SET key are depressed at the same time, the motor decelerates and stops while STOP LED flashes. This stop command is stored in the inverter. Therefore, to resume operation, open both the forward run command and reverse run command of the external terminal.

(3) 3rd digit (master-speed frequency command)

Depending on the 3rd-digit value, the input method of the master-speed frequency command differs as shown in Fig. 10.

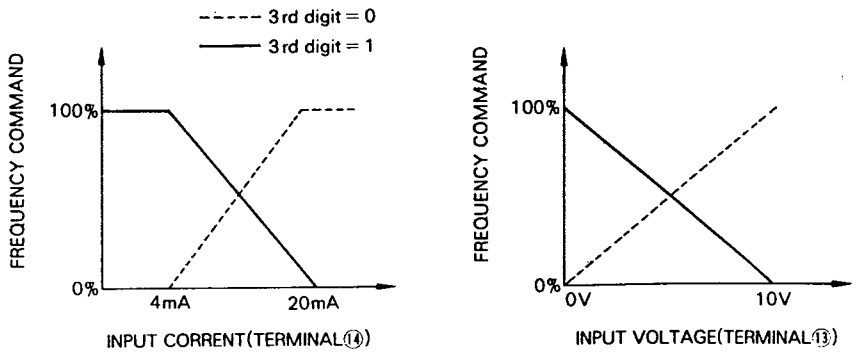


Fig. 10 Input method of Master Frequency Command

(4) 4th digit (reverse prohibit)

4th digit = 1: Disregards the reverse run command from the external terminal or digital operator.

A4-4 Protective Characteristics Selection (Sn-05)

(1) 1st digit (operation continues at momentary power failure)

1st digit = 0: A momentary power failure, when detected, is regarded as a fault in power supply and the operation stops after coasting.

1st digit = 1: When a momentary power failure is within 2 seconds, the operation continues; if longer than 2 seconds, the operation stops after coasting.

(2) 2nd digit (stall or no stall during deceleration)

2nd digit = 0: Stall during deceleration.

2nd digit = 1: No stall during deceleration.

(3) 3rd digit (motor protection)

3rd digit = 0: The electronic thermal protector protects the inverter and motor from overheat.

3rd digit = 1: The electronic thernal protector protects only the inverter from overload.

(4) 4th digit (motor selection)

4th digit = 0: Protection is made with the overload characteristics of the reduced-torque characteristic motor.

4th digit = 1: Protection is made with the overload characteristics of the constant-torque characteristic motor.

A4-5 Overtorque Detection (Sn-06)

(1) 1st digit

1st digit = 0: No overtorque is detected.

1st digit = 1: Overtorque is detected (different function from the stall during operation).

The overtorque detection function detects the following condition:

Inverter output current ≧ overtorque detection level (control constant 23, set to 160% prior to shipment from the factory).

(2) 2nd digit

2nd digit = 0: Overtorque is detected during speed synchronization.

2nd digit = 1: Overtorque is always detected (except during stopping and DB).

(3) 3rd digit

3rd digit = 0: When overtorque is detected, the digital operator flashes OL3 and continues the operation.

3rd digit = 1: When overtorque is detected, the digital operator flashes OL3 and the operation stops after coasting (regarded as trouble and fault contact is output).

A4-6 Optional Function Selection (Sn-07)

(1) 1st and 2nd digits

Sets multiples of the output frequency that is output in the pulse monitor (JOGB-C01 type).

00: Outputs 6.F (F: output frequency)

01: Outputs 10.F (F: output frequency)

10: Outputs 12.F (F: output frequency)

11: Outputs 36.F (F: output frequency)

A4-7 Terminal Function (Sn-08 to Sn-11)

The function of terminal ⑤ is selected by the value set to system constant 8. Similarly, the function of terminal ⑥ is selected by the value set to system constant ⑨ the function of terminal ⑦ by the value set to system constant 10; the function of terminal ⑧ by the value set to system constant 11. Note each of these is independently selected.

When set values 0 to 3 are not set to system constants 8 to 11, the master-speed frequency command is applied for operation.

Table 14 Terminal Functions

Setting Value	Function	Description (0 state signal / 1 pulse signal)
0	Master/Aux selector	Open 0 Master freq command Closed 0 Aux freq command
1	Master/Aux selector for forward run	When forward run command on, Open 0 Master freq command Closed 0 Aux freq command
2	Master/Aux selector for reverse run	When reverse run command on Open 0 Master freq command Closed 0 Aux freq command
3	Multi-step speed setting	–
4	Override	Closed 0 Override
5	Inching operation	Closed 0 Inching freq selection
6	External coasting stop command	Closed 0 Coasting stop
7	Speed search	Closed 1 Speed search from top freq *
8	Speed search	Clpsed 1 Speed search from setting value *
9	Energy saving operation	Closed 0 Energy saving operation
A	Accel/Decel time selector	Open 0 Accel/decel is executed by control constants 8 and 9 Closed 0 Accel/decel is executed by control constant 29
B	Inverter overheat prediction	OH2 blinks on digital operator
C	DC dymamic brake command	Closed 0 Dynamic brake activates if DC dynamic brake command is closed under the conditions of min output freq and below at decelleration stop
D	Not used	
E		
F		

*The search function of setting values 7 and 8 works even by pulse input signal of 20 ms and above.

Precautions for Combination of System Constants 8 to 11

When the following combination is set to system constants 8 to 11, this is regarded as a constant set value error (OPE), OPE is checked when power is supplied and when ENTRY is keyed in.

(1) The set values are not placed in order from small to large. (Except for F, two or more values cannot be set.)

(2) Both search commands of set values 7 and 8 are set.

(3) The forward master speed/auxiliary switching and the reverse master speed/auxiliary switching are not set in pairs.
(Set the forward master speed/auxiliary switching to constant 8 and the reverse master speed/auxiliary switching to constant 9.)

(4) Multispeed setup is set and master speed/auxiliary switching is not set.
(Set the master speed/auxiliary switching to constant 8 and the multispeed setup to constant 9.)

A4-7-1 Description of Functions

(1) Master speed/auxiliary switching function

In both forward and reverse operations, this contact-input signal enables switching the master speed and auxiliary.

Open: The master speed frequency command is made the frequency command.

Close: The auxiliary frequency command is made the frequency command.

(2) The forward master speed/auxiliary switching and the reverse master speed/auxiliary switching functions

The main speed and auxiliary can be switched separately in forward and reverse operations. The forward master speed/auxiliary switching function and the reverse master speed/auxiliary switching function must be used in pairs.

Open: The master speed frequency command is made the frequency command

Close: The auxiliary frequency command is made the frequency command.

(3) Multispeed setup function.

The multispeed setup function must be used in a pair with the master speed/auxiliary switching function. A combination of these terminals makes the frequency command as shown in Table 15.

Table 15 4-step Speed Setting Method

Master/Aux Selector Command	Multi-step Speed Setting	Frequency Command
Open	Open	Master freq command
Closed	Open	Aux freq command
Open	Closed	Freq command 1* for multi-step speed setting
Closed	Closed	Freq command 2* for multi-step speed setting

*Valves set by control constants 27 and 28

(4) Override function

Open: The operation is made by the master speed frequency command (override cut).

Close: Override is carried out as shown in Fig. 11. The overrride gain is given by an auxiliary frequency command (0 to +10 V/0 to 200%).

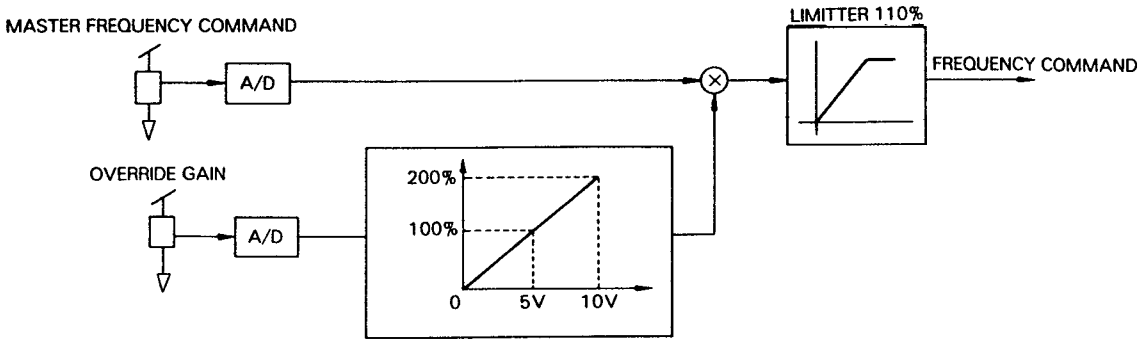


Fig. 11 Block Diagram of Override

(5) Inching function

Close: Only during close, the inching operation with control constant 26 (Setting to 6 Hz prior to shipment from the factory) as the frequency command is carried out. The rotating direction is given by the forward run command or reverse run command. The timing chart in forward and reverse operations are shown in Fig. 12.

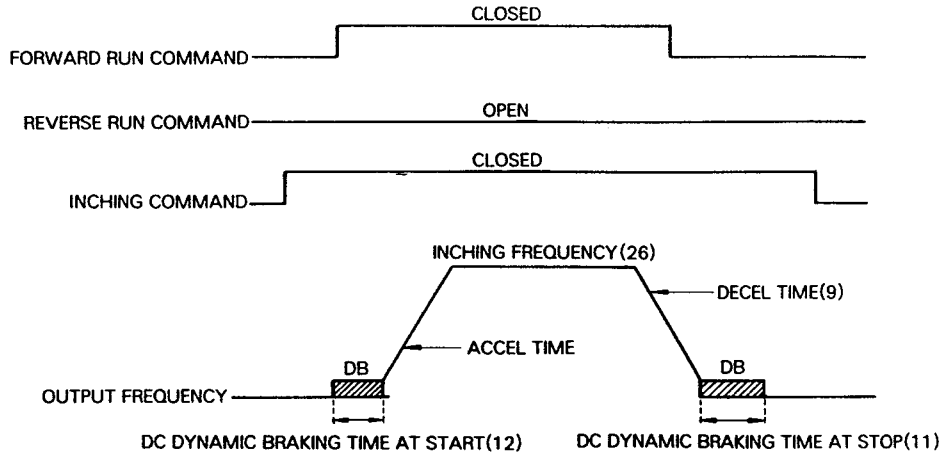


Fig. 12 Time chart at Forward and Inching Operations

Note: Parenthesized vlues indicate the number of control constant.

(6) External coasting stop command function

When the external coasting stop command is closed, the operation depends on the input state of the forward run command and reverse run command.

- When either the forward run command or reverse run command is closed, and the external coasting stop command is also closed, only coasting stop is accomplished and the frequency is maintained.
- When both the forward run command and reverse run commands are open, and the external coasting stop command is closed, coasting stop is accomplished and the frequency is changed to 0 Hz.

(7) Search function (rise detection)

When the search command is made to close, the base is blocked for 0.5 second, then the speed search is made. The operation depends on the selected function either 7 or 8. Note: functions 7 and 8 cannot be simultaneously selected.

- When 7 is set, the speed search begins with the highest set frequency.
- When 8 is set, the speed search begins with the frequency command that has been set after the scarch command was input.

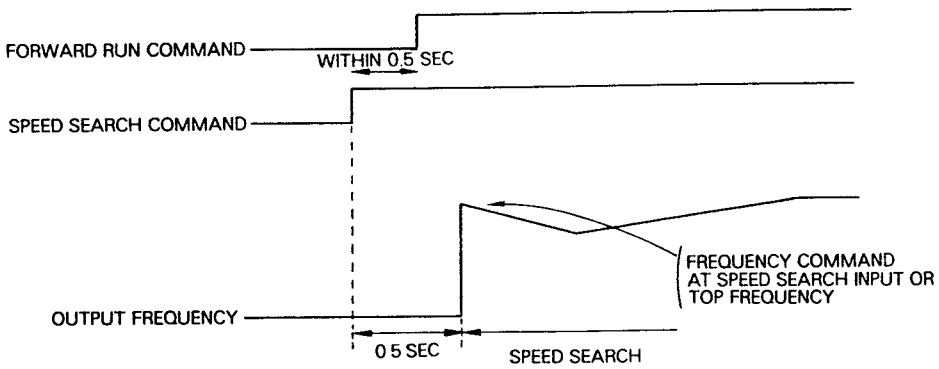


Fig. 13 Time chart at Speed search command Input

Note: When using this function by continuous operation mode at momentary stop, hold speed search command externally.

(8) Energy-saving operation function

When the energy-saving operation command is made to close during speed synchronization, energy-saving operation shown in Fig. 14 is carried out. In the energy-saving operation, the output voltage is the value of the energy- saving gain (control constant 30, set to 80% at shipment from the factory) multiplied by the V/f constant set with control constants 1 to 7.

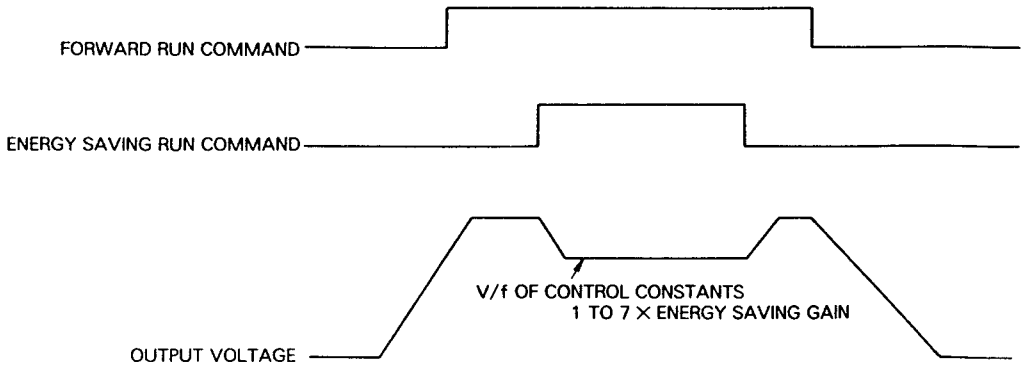


Fig. 14 Time Chart of Energy Saving Run

(9) Acceleration/deceleration time switching function

When the acceleration/deceleration time switching command is input, the acceleration/deceleration time changes. This function is also effective during inching operation.

Open: Operation made with accel/decel time of control constants 8 and 9.

Close: Operation made with acceleration/deceleration time of control constant 29.

(10) Inverter overheat prodiction/display function

When the inverter overheat prediction/display command is input, the inverter flashes only OH2 on the digital operator's display. No other operation is carried out.

A4-7-1 Description of Function (Cont'd)

(11) DC braking (DB) function

When both the forward run commmand and reverse run command are open, and the DC braking command is closed, DC braking operation is carried out.

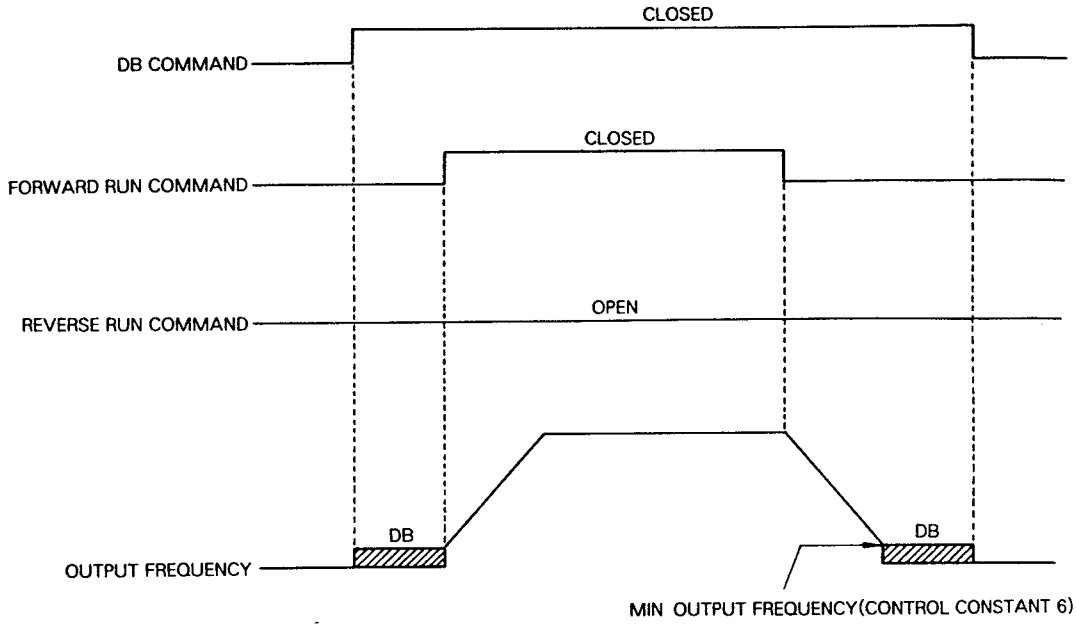


Fig. 15 Time Chart of DC Dynamic Braking

A4-8 Contact Output Selection Function (Sn-12)

The content to be output through external terminals ⑨ - ⑩ is set. Table 12 shows the relationship between the set value of constant 12 and the content to be output.

Table 16 Contact Output Function

Setting Value	Description	
	Name	Signal Level (Closed)
0	Contact during run	Closed During run
1	Contact at zero speed	Closed Zero speed
2	Speed synchronized contact	Closed Speed synchronization
3	Overtorque detected contact	Closed Overtorque detection
4	Contact during UV	Closed During UV

(1) Contact during operation

The contact is closed when either the forward run command or the reverse run command is closed, or when the inverter is outputting a voltage.

(2) Zero-speed contact

The contact is closed when the inverter output frequency is 0Hz.

(3) Speed-synchronization contact

The contact is closed when either the forward run command or the reverse run command is closed, and the speeds are synchronized.

Speed-synchronization set condition:

Software start input - output 0.5%

Speed-synchronization reset condition:

Software start input - output 3%

(4) Overtorque detection contact

The contact is closed when the inverter detects an overtorque.

(5) During low voltage (UV) contact

The contact is closed while the inverter is measuring momentary power failure time when the mode is selected for operation to continue during momentary power failure. The contact is open when the inverter is stopping for a period exceeding the momentary power failure time-compensation period. Use this contact combined with the abnormality contact output.

APPENDIX 5 CONTROL CONSTANTS

(1) V/f constants (Cn-01 to Cn-07)

Sets V/f. Fig. 15 shows the relationship between constants 1 to 7. V_{MAX}, V_C, and V_{MIN} is standardized with the input voltage of 200V in 200-V and the input voltage of 400V in 400-V system. Use the following formula to convert and set V_{MAX}, V_C, and V_{MIN}.

V_{MAX} = Vmax × (200V or 400V)/Vin

V_C = Vc × (200V or 400V)/Vin

V_{MIN} = Vmin × (200V or 400V)/Vin

[Vmax, Vc, and Vmin are the actual output voltages; Vin is input voltage.]

To straighten V/f pattern

When $F_B = F_{MIN}$ is set, V_C setup is invalidated and the output voltages of F_A to F_{MIN} become straight.

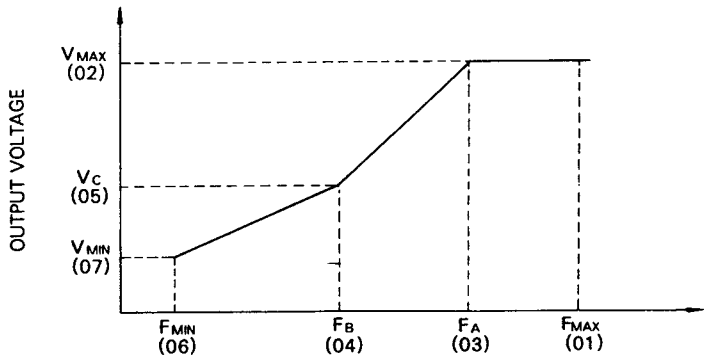


Fig. 16 V/f Characteristics by Control Constants 1 to 7

Notes: 1. Parenthesized values indicate the number of control constant.

2. Control constants 1 to 7 can be set only when system constant 2 is F.

3. When constants not satisfying the condition $F_{MAX} \geq F_A > F_B \geq F_{MIN}$ and $V_{MAX} > V_C \geq V_{MIN}$ are set, an OPE (set value error) ocours. This is checked when power is supplied and when DSPL/ENTR is keyed in.

(2) Acceleration constants (Tace) (Cn-08)

Sets the acceleration time during which the inverter output frequency reaches from 0% to 100%.

(3) Deceleration constants (Tdec) (Cn=09)

Sets the deceleration time during which the inverter output frequency changes from 100% to U%.

(4) DC braking voltage (DBVOL) (Cn-10)

Sets the DC voltage that the inverter outputs at DC braking time in units of 0.1 V.

(5) DC braking time at stopping (DBTIM) (Cn-11)

Sets the braking time in units of 0.1 second during which DC braking is applied at stopping. When the DC braking time is 0, the operation stops after coasting, with the minimum output frequency (constant 6).

(6) DC braking time at starting (DBTWM) (Cn-12)

Sets the braking time in units of 0.1 second during which DC braking is applied at starting (by inputting a forward run command or reverse run command). When the DC braking time is 0, acceleration begins with the minimum output frequency.

(7) Frequency command gain (FGAIN) (cn-13)

Sets the main-speed frequency command gain in units of 0.01. (See Fig. 17).

(8) Frequency command bias (FBIAS) (Cn-14)

Sets the main-speed frequency command bias in units of 0.1%, (See Fig. 17).

(9) Frequency command upper limit (FOUL) (Cn-15)

Sets the upper limit of the frequency command in ratio to the maximum frequency in units of 1%. (See Fig. 17).

(10) Frequency command lower limit (FOLL) (Cn-16)

Sets the lower limit of the frequency command in ratio to the maximum frequency in units of 1%. (See Fig. 17).

(11) Frequencies not allowed to be set 1, 2, and 3 (DEDF1, DEDF2, and DEDF3) (Cn-17 to Cn-19)

Sets the frequencies not allowed to be set in units of 0.1Hz. Frequency command cannot be set in a range within +1Hz of the frequencies not allowed to be set.

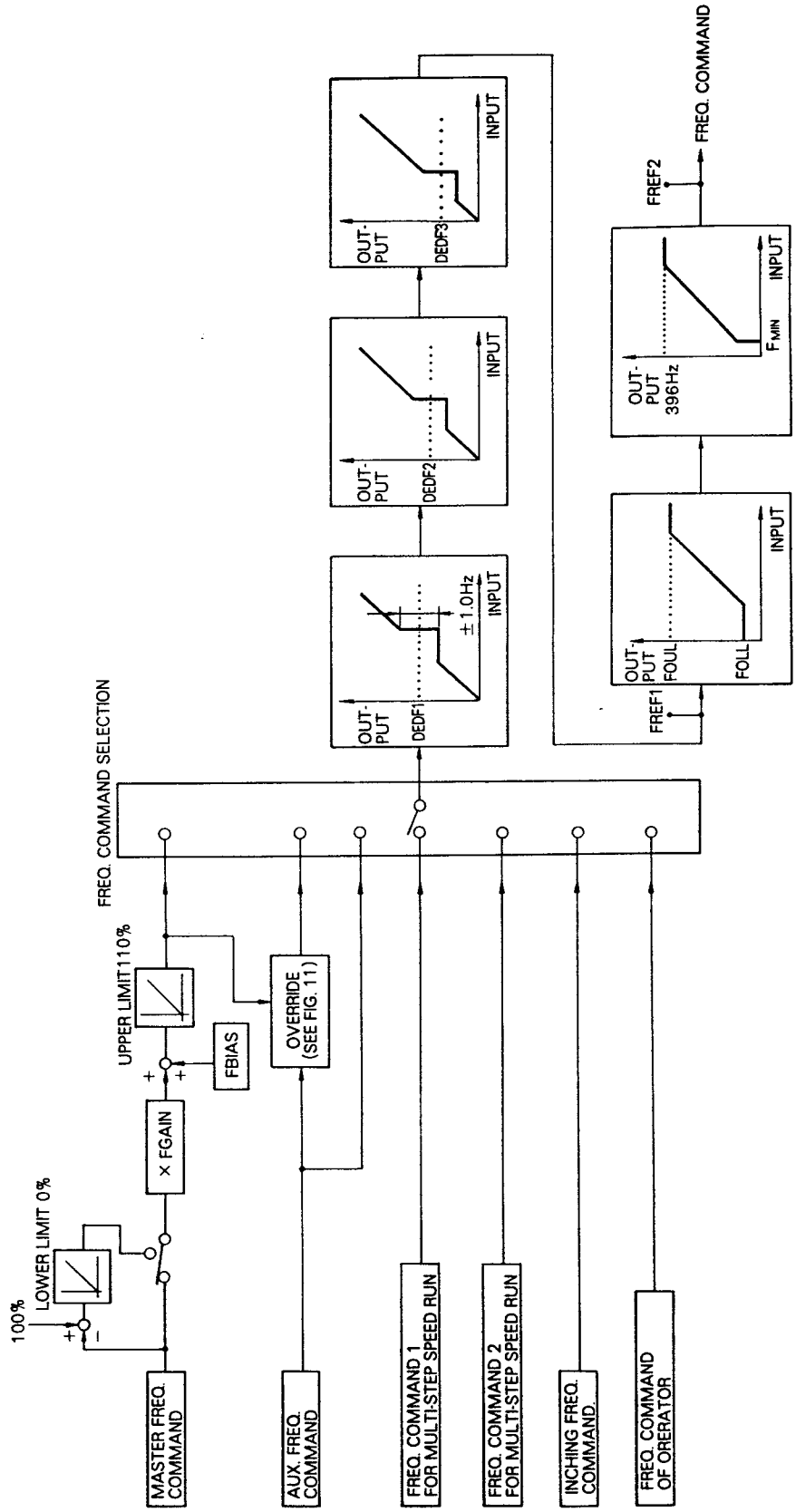


Fig. 17 Block Diagram of Frequency Command

(12) Motor rated current (Iml00) (Cn-20)

Sets the motor rated current in units of 0.1A. (The motor rated current is used in the electronic thermal protector to protect the motor.) (See Table 11).

(13) Carrier frequency lower limit (CARRIER) (Cn-12)

Sets the lower limit of the inverter's carrier frequency in units of 1Hz. Although the carrier frequency depends on the output frequency and load, the minimum carrier frequency is set/here.
Fig. 18 shows the relationship between the carrier frequency and the output frequency.

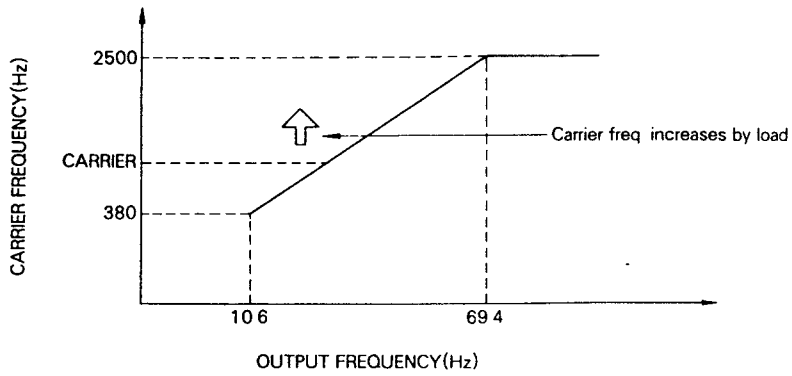


Fig. 18 Carrier Frequency and Output Frequency

(14) Torque compensation gain (K_T) (Cn-22)

Sets the torque compensation gain in units of 0.1.

When the maximum applicable inverter motor has the same capacity as that of the motor actually used, this gain is 1. When a smaller motor is actually used, the gain is set to 1.0 or more.

(15) Overtorque detection level (Cn-23)

Sets the overtorque detection level in ratio to the reference current (See Table 11) for setting constants in units of 1%. Note the overtorque detection function differs from the stall during operation function.

(16) Frequency monitor gain (K_F) (Cn-24)

Sets in units of 0.01 the gain of the frequency-meter output that the F-I monitor (JOGB-C02) outputs. (See Fig. 19).

APPENDIX 5 CONTROL CONSTANTS (Cont'd)

(17) Current monitor gain (K_I) (Cn-25)

Sets in units of 0.01 the gain of the ammeter output that the FOI monitor (JOGB-C02) outputs. (See Fig. 19).

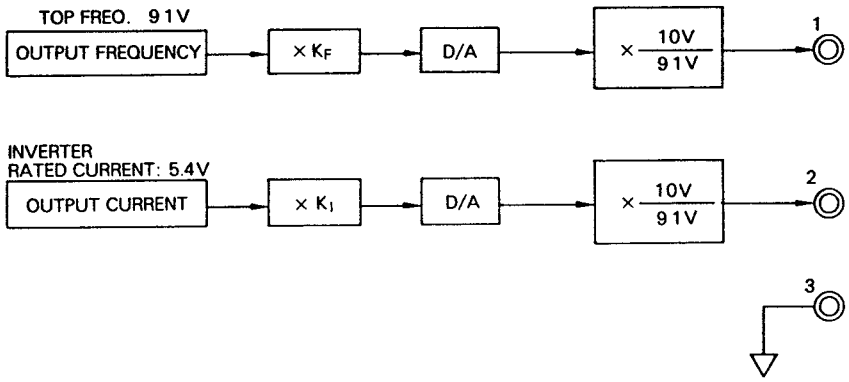


Fig. 19 Block Diagram of F-I Monitor

Calibrate the meter as follows:

In PRB mode, when control constant 24 is selected, the maximum frequency (about 10 V) is available at F-I monitor terminal 1; when control constant 25 is selected, the inverter rated current (about 6V) is available at F-I monitor terminal 2.

Maximum frquency: About 10V ① to ③

Inverter rated current: About 6V ② to ③

(18) Inching frequency (NFJOG) (Cn-26)

Sets inching frequency in units of 0.1 Hz.

(19) Multispeed-run-frequency commands 1 and 2 (FRKF1 and FREF2) (Cn-27 and Cn-28)

Sets multispeed-run-frequency commands in units of 0.1 Hz.

(20) Acceleration/deceleration time (Cn-29)

Sets the acceleration/deceleration time in units of 0.1 second when the acceleration/deceleration time switching command is closed.

(21) Energy-saving gain (KSENG) (Cn-30)

Sets in units of 1% the level to which the output voltage is controlled in the energy-saving operation.

In the energy-saving operation, the output voltage is given by (V/f set by control constants 1 to 7 x energy-saving gain). (See Fig. 20.)

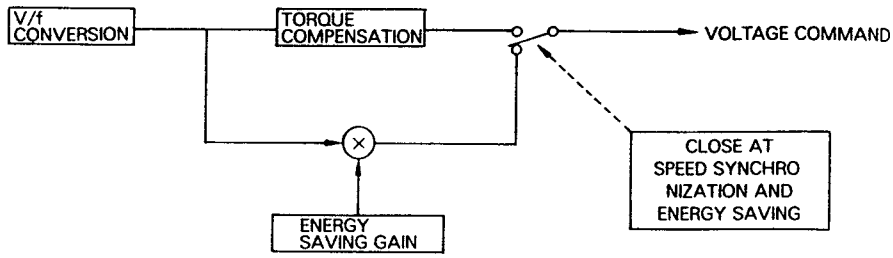


Fig. 20 Output Voltage During Energy-Saving Run

APPENDIX 6 OTHER CONSTANTS (FUNCTIONS)

A6-1 Retry Operation at Fault

When faoult occurs (FU, Eb, and CPF excluded) during operation, a retry operation can be carried out by automatically resetting the fault.

Automatic resetting can be set up to 10 times. Fig. 21 shows the timing chart for retry operation in case of fault.

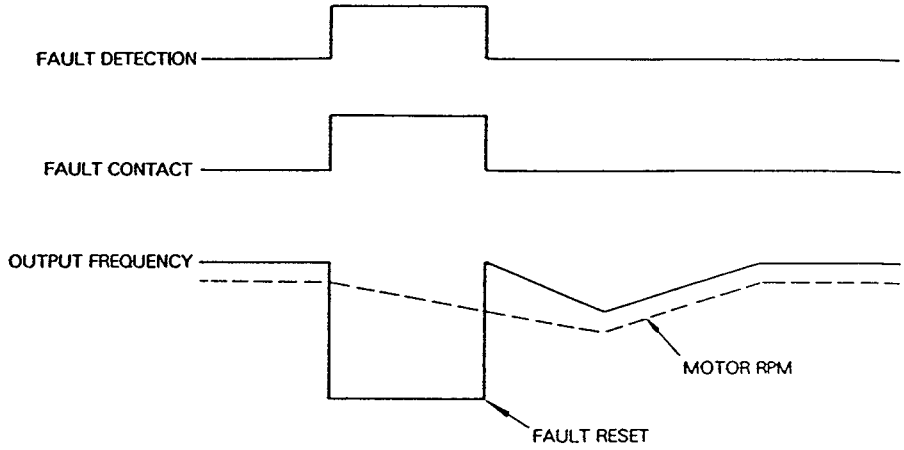


Fig. 21 Time Chart of Retry Operation at fault

The operation procedure for retry operation in case of fault is shown below.

(1) Depress [DRIVE/PRG] to select the program mode. [Goes off [DRIVE/PRG]]

(2) Depress [FWD/REV/MODE] to select system constant [Sn-01].

(3) Select the numeric with [△] and indicate [Sn-03] (system constant 3).

(4) Depress [RUN/DATA] to indicate the internal data of system constant 3.

(5) Set [10 10] by operating [▷/RESET] and [△].

(6) Depress [STOP/SET] to temporarily store data.

(7) Indicate [On-03] by operating [FWD/REV/MODE] and [△].

(8) Depress [RUN/DATA] to indicate the internal data of [On-03]

(9) Set the number of times to reset faults by operating [▷/RESET] and [△].

(When 5 times is set, it appears as [05].)

(10) Depress [STOP/SET] to temporarily store data.

(11) Operate steps (2) to (6) to return the internal data of [Sn-03] to [0000].

(12) Depress [DSPL/ENTR] to store data.

(13) After setting, depress [DRIVE/PRG] to resume the drive mode. [[DRIVE/PRG]]

CAUTION

SET DRIVE CONSTANT SN-Ø3 TO ØØØØ OR Ø1Ø1. RESETTING SN-Ø3 TO 111Ø MAY CAUSE MOTOR TO RUN IN REVERSE DIRECTION W/O RUN COMMAND. POSSIBLE EQUIPMENT DAMAGE OR PERSONNEL INJURY MAY RESULT.

A6-2 Full Range DC Braking Stop (DB)

The use of the full range DC braking stop (DB) function permits a quick stop without using a braking resistor.

When a stop command is input, DC braking stop is carried out. The DB time at stop is set with control constant 11.

The time chart is shown in Fig. 22.

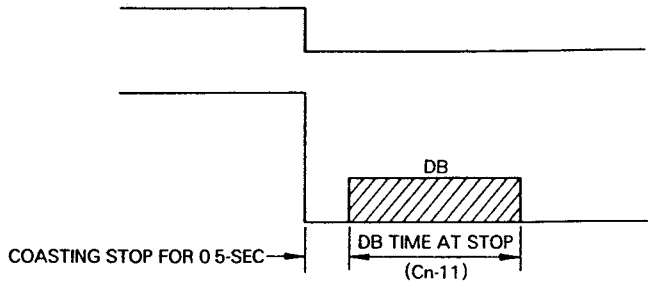


Fig. 22 Time Chart at DB Stop

The operation procedure for full range DC braking stop function is shown below.

(1) Depress [DRIVE / PRG] to select the program mode. [Goes off [DRIVE / PRG]]

(2) Depress [FWD/REV / MODE] to select system constant [Sn-01].

(3) Select the numeric with [△] and indicate [Sn-03] (system constant 3).

(4) Depress [RUN / DATA] to indicate the internal data of system constant 3.

(5) Set [10 10] by operating [▷ / RESET] and [△].

(6) Depress [STOP / SET] to temporarily store data.

(7) Depress [FWD/REV / MODE] to indicate [On-01]

(8) Depress [RUN / DATA] to indicate the internal data of [On-01]

(9) Indicate [10] by operating [▷ / RESET] and [△].

(10) Depress [STOP / SET] to temporarily store data.

(11) Operate steps (2) to (6) to return the internal data of [Sn-03] to [0000].

(12) Depress [DSPL / ENTR] to store data.

(13) After setting, depress [DRIVE / PRG] to resume the drive mode. [[DRIVE / PRG]]

CAUTION

SET DRIVE CONSTANT SN-Ø3 TO ØØØØ OR Ø1Ø1. RESETTING SN-Ø3 TO 111Ø MAY CAUSE MOTOR TO RUN IN REVERSE DIRECTION W/O RUN COMMAND. POSSIBLE EQUIPMENT DAMAGE OR PERSONNEL INJURY MAY RESULT.

A6-3 Range to Prohibit Frequency Setting

Frequency is not permitted to be set in a range usually within ±1 Hz of the frequency set with constants 17 to 19. In this range, frequency command cannot be set (see page 42).

The value of this ±1 Hz range where frequency setting is prohibited can be changed, in a range of 0.0 to 10.0 Hz, in units of 0.1 Hz.

The operation procedure for this purpose is shown below. Operation steps (1) to (6) and (11) to (13) are the same as in A6-1. So, steps (7) to (10) are shown.

(1) Depress DRIVE/PRG to select the program mode. [Goes off DRIVE/PRG]

(2) Depress FWD/REV/MODE to select system constant Sn-01.

(3) Select the numeric with △ and indicate Sn-03 (system constant 3).

(4) Depress RUN/DATA to indicate the internal data of system constant 3.

(5) Set 10 10 by operating ▷/RESET and △.

(6) Depress STOP/SET to temporarily store data.

(7) Indicate On-03 by operating FWD/REV/MODE and △.

(8) Depress RUN/DATA to indicate the internal data of On-02

(9) Set the required range to prohibit frequency setting by operating ▷/RESET and △.

(When 2.0 Hz is set, it appears as 02.0.)

(10) Depress STOP/SET to temporarily store data.

(11) Operate steps (2) to (6) to return the internal data of Sn-03 to 0000.

(12) Depress DSPL/ENTR to store data.

(13) After setting, depress DRIVE/PRG to resume the drive mode. [DRIVE/PRG]

CAUTION

SET DRIVE CONSTANT SN-Ø3 TO ØØØØ OR Ø1Ø1. RESETTING SN-Ø3 TO 111Ø MAY CAUSE MOTOR TO RUN IN REVERSE DIRECTION W/O RUN COMMAND. POSSIBLE EQUIPMENT DAMAGE OR PERSONNEL INJURY MAY RESULT.

A6-4 Stall Prevention During Operation

During operation (while the speed is being synchronized), if the inverter output current exceeds the stall prevention during operation level (setting to 160% at shipment from the factory), the output frequency is dropped at a rate of half the predetermined deceleration time.

When the output current drops below the stall prevention during operation level, the output frequency is accelerated to the set value at the specified acceleration time.

The stall prevention during operation level can be set, in units of 1%, in ratio to the reference current for setting constants. (See Table 11 on page 28).

The operation procedure to set or change the stall prevention during operation level is shown below. Operation steps (1) to (6) and (11) to (13) are the same as in par. A 6.1.

(1) Depress DRIVE/PRG to select the program mode. [Goes off DRIVE/PRG]

(2) Depress FWD/REV/MODE to select system constant Sn-01.

(3) Select the numeric with △ and indicate Sn-03 (system constant 3).

(4) Depress RUN/DATA to indicate the internal data of system constant 3.

(5) Set 10 10 by operating ▷/RESET and △.

(6) Depress STOP/SET to temporarily store data.

(7) Indicate On-18 by operating FWD/REV/MODE, △ and ▷/RESET.

(8) Depress RUN/DATA to indicate the internal data of On-18

(9) Set the stall level during run by operating ▷/RESET and △.

(When 120% is set, it appears as 120.)

(10) Depress STOP/SET to temporarily store data.

(11) Operate steps (2) to (6) to return the internal data of Sn-03 to 0000.

(12) Depress DSPL/ENTR to store data.

(13) After setting, depress DRIVE/PRG to resume the drive mode. [DRIVE/PRG]

To remove the function to prevent stall prevention during operation

To remove the function to prevent stall during operation, set the stall prevention during operation level to 200%.

CAUTION

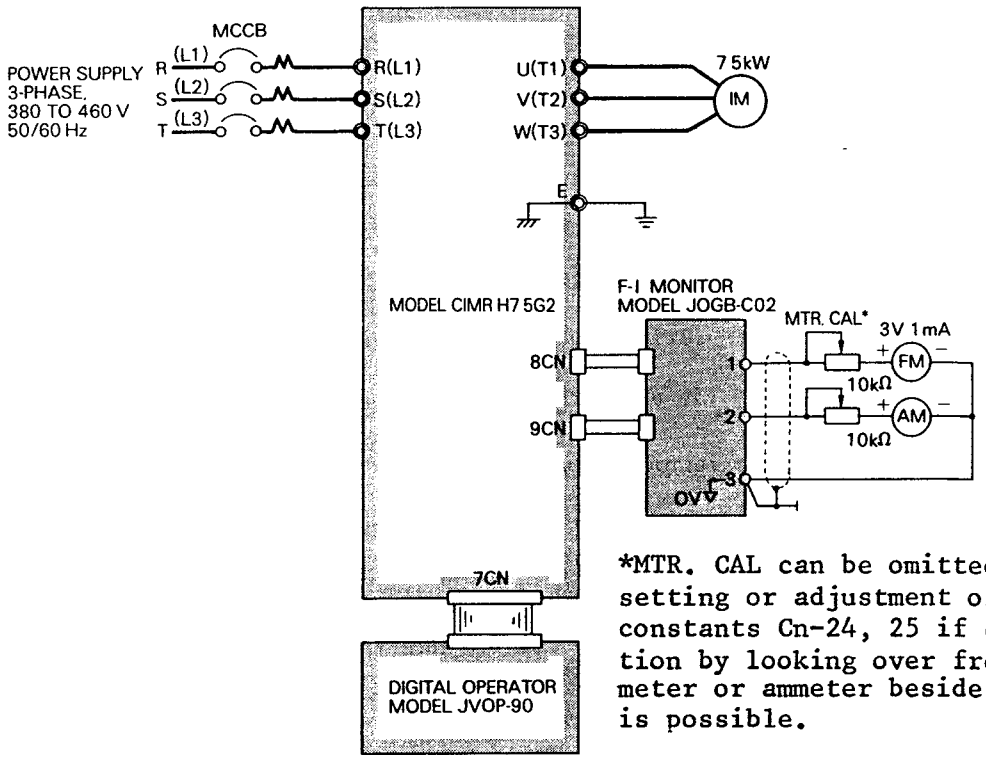
SET DRIVE CONSTANT SN-Ø3 TO ØØØØ OR Ø1Ø1. RESETTING SN-Ø3 TO 111Ø MAY CAUSE MOTOR TO RUN IN REVERSE DIRECTION W/O RUN COMMAND. POSSIBLE EQUIPMENT DAMAGE OR PERSONNEL INJURY MAY RESULT.

APPENDIX 7 OPTION

Name	Model (Code No)	Mounting Place	Specifications			
			Terminal Symbol	Function	Level	Output Accuracy
Pulse Monitor	JOGB-C01 (73616-0051X)	Surface on the controller (Both monitors can not be mounted at a time)	①-② (0V)	Pulse monitor (Inverter output frequency F)	Selection of 6·F, 10·F, 12·F, 36·F possidle (Vo 12V, Iol 20mA Duty 50%) See Sn-07 of Par. A4-6	0 03% (Sampling for 1 sec)
F-I Monitor	JOGB-C02 (73616-0052X)		①-③ (0V)	Frequency monitor (Inverter output frequency	Approx 10V/100% Output Impedance 200Ω	0 5%
			②-③ (0V)	Current monitor (Inverter output current)	Approx 10V/170% Output Impedance . 200Ω	3%

*See Cn-24, 25 of Par.A5 for adjustment of F-I monitor.
Use BVDC, 1mA full scale of frequency meter and ammeter.

INTERCONNECTION DIAGRAM WITH F-I MONITOR



*MTR. CAL can be omitted by setting or adjustment of control constants Cn-24, 25 if calibration by looking over frequency meter or ammeter beside unit is possible.

APPENDIX 8 CHECK FUNCTION

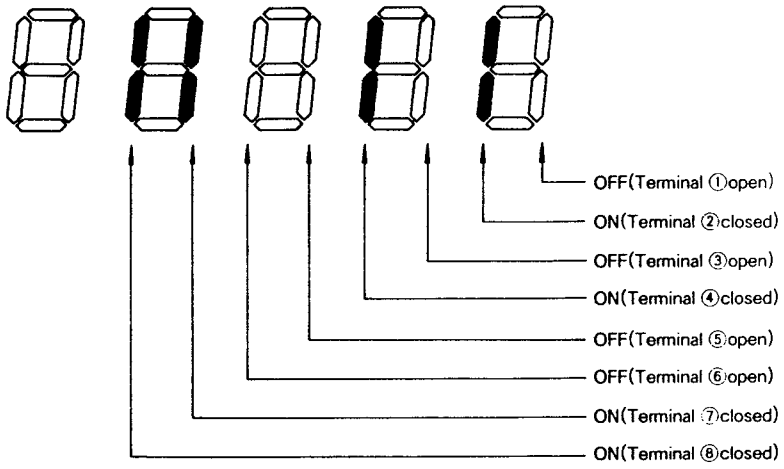
By selecting constants (CH-01 and CH-02) in PRG mode, both the digital operator LED and external terminals ① to ⑧ can be checked.

(1) CH-01 (Checks the digital opertor LED)

Select CH-01 and depress RUN/DATA key. Then, all LEDs light.

(2) CH-02 (Checks external terminals ① to ⑧

Select CH-02 cnd depress RUN/DATA key. Then, the state of external terminals ① to ⑧ appears.
Sample display when external terminals ①, ③, ⑤ and ⑥ are open and ②, ④, ⑦ and ⑧ are closed is shown below.



APPENDIX 9 WIRE SIZE

Table 17 shows the wire sizes used for wiring, Table 18 shows the setup of round pressure terminals.

Circuit	Model	Inverter Capacity kVA	Terminal Symbol	Terminal Screw	Wire Size* mm²	Wire Size* AWG	Lead Type
Main	CIMR-H0 4G2	1 4	ⓇⓁ1, ⓈⓁ2, ⓉⓁ3, ⓊT1, ⓋT2, ⓌT3 ①, ①, Ⓔ	M4	3 5–5 5	14–10	Power cable 600 V vinyl-sheathed lead or equivalent
	CIMR-H0 75G2	2 1					
	CIMR-H2 2G2	4 1	ⓇⓁ1, ⓈⓁ2, ⓉⓁ3, ⓊT1, ⓋT2, ⓌT3, B1, B2	M4	3 5–5 5	12–10	
			Ⓔ		2–5 5	14–10	
	CIMR-H3 7G2	6 9	ⓇⓁ1, ⓈⓁ2, ⓉⓁ3, ⓊT1, ⓋT2, ⓌT3, B1, B2	M4	3 5–5 5	12–10	
			Ⓔ		2–5 5	14–10	
	CIMR-H5 5G2	10 3	ⓇⓁ1, ⓈⓁ2, ⓉⓁ3, ⓊT1, ⓋT2, ⓌT3, B1, B2	M5	5 5–8	10–8	
			Ⓔ		2–5 5	14–10	
	CIMR-H7 5G2	13 7	ⓇⓁ1, ⓈⓁ2, ⓉⓁ3, ⓊT1, ⓋT2, ⓌT3, B1, B2	M5	5 5–8	10–8	
			Ⓔ		2–5 5	14–10	
	CIMR-H11G2	20 6	ⓇⓁ1, ⓈⓁ2, ⓉⓁ3, ⓊT1, ⓋT2, ⓌT3, B0, B1	M6	8–14	8–6	
			Ⓔ		2–5 5	14–10	
	CIMR-H15G2	27 4	ⓇⓁ1, ⓈⓁ2, ⓉⓁ3, ⓊT1, ⓋT2, ⓌT3, B0, B1	M6	8–14	8–6	
			Ⓔ		2–5 5	14–10	
Control	—		①–⑳	M4	0 5–2	20–14	Twisted shieded lead for instrumentation

*Wire size should be determined considering voltage drop of leads.
†Polyethylene-insulated vinyl-sheathed with shielding.

Table 18 Round Pressure Terminals

Wire Size mm²	Wire Size AWG	Terminal Screw	Rouod Pressure Terminal
0 5	20	M4	1 25-4
0 75	18		
1 25	16		
2	14	M4	2-4
		M4	2-5
		M6	2-6
3 5	10	M4	3 5-4
		M5	3 5-5
		M6	3 5-6
5 5	8	M4	55 -4
		M5	5 5-5
		M6	5 5-6
8	8	M5	8-5
		M6	8-6
14	6	M6	14-6