

**ENGINEERING PUBLICATION**  
**MOTION CONTROL DIVISION****TITLE: CORRECTIONS TO JUSP-NS500 USER MANUAL, SIE-C718-8****SUBJECT: JUSP-NS500 USER MANUAL CORRECTIONS****MOST RECENT EDIT - 2/7/05****DISTRIBUTION: ALL**

---

Errors, corrections, and additions in this document are for User Manual # SIE-C718-8 printed in June 2003. See the back cover of the user manual to check the date of printing. Also see [ftp.yaskawa.com](http://ftp.yaskawa.com) for supplemental documentation.

Section 4.3, Page 4-11, Addition, A reference unit is the smallest unit of commanded motion. This manual will also use the word "step" interchangeably with reference unit. A mechanical unit (such as inches) can have any number of reference units as long as the ratio of PN810/Pn811 is within 100 to 0.01. Using 1000 reference units per mechanical unit will simplify the setting of speed parameters, which are set in 1000 reference units per minute. For example if the reference units are set to 0.001 inches, the speed parameters values will be in inches per minute.

Section 4.3.3, Page 4-20, error, PN81A may be set to 0 or 1. The value 2 is not a valid setting.

Chapter 5, omission, Note – The command and response messages contain multi-byte data fields. The most significant byte in the data field occurs in the lowest address. For example the decimal number 5000 is represented as:

Address	Hex	Bit
Byte 4	00	00000000
Byte 5	00	00000000
Byte 6	13	00010011
Byte 7	88	10001000

This format follows most Siemens PLC data formats and is sometimes referred to as big-endian. Many controllers have a byte-swap function that can be used if the controller data format is opposite.

Section 5.3.4 Page 5-21, addition, Command Code 1011 (Set Zero Point). If using an absolute encoder, the current position of the motor is set as the zero point by executing a Set Zero Point command. Execute the Set Zero Point

command by setting 1011 in the command code (byte 1, bits 0-3) and change the C\_STRT bit from 0 to 1. It is not necessary to make any settings in the data area (bytes 2-7 =0). After the Set Zero Point is completed, an offset will be stored in Pn809 (Zero Point Offset). Perform a Module Reset Command to save the value of Pn809 to flash ROM.

Section 5.4.4, Page 5-33, error, Target Speed 1-50 should be set in parameters Pn940-Pn971.

Section 5.4.6, Page 5-38, error, The value in byte 1, bits 0-3 should read 01h (h=hex) in the chart at the top of the page.

Section 5.4.7, Page 5-38, omission, Pn827 sets the feed speed for positioning before the EXTP signal has been reached. Pn827 is also referenced in Chapter 4 parameter settings.

Section 5.4.7, Page 5-38, omission, Pn856 sets the polarity of the EXTP signal. Pn856 is also referenced in Chapter 4 parameter settings.

Section 5.4.7, Page 5-39, error, The value in byte 1, bits 0-3 should read 02h (h=hex) in the chart at the bottom of the page.

Section 5.4.8, Page 5-41, error, The value in byte 1, bits 0-3 should read 03h (h=hex) in the chart in the middle of the page.

Section 5.4.9, Page 5-44, error, The value in byte 1, bits 0-3 should read 04h (h=hex) in the chart at the bottom of the page.

Section 6.3.1, Page 6-10, error in the drawing, The EMSTOP input should be wired to CN4, pin 9. See section 3.4.1, page 3-12.

Section 9.1, Page 9-28, addition, Cause B, Pn505 sets the allowable position error. If Pn505 is too small an A.D0 can result. See the Sigma II user manual for the SGDh amplifier.