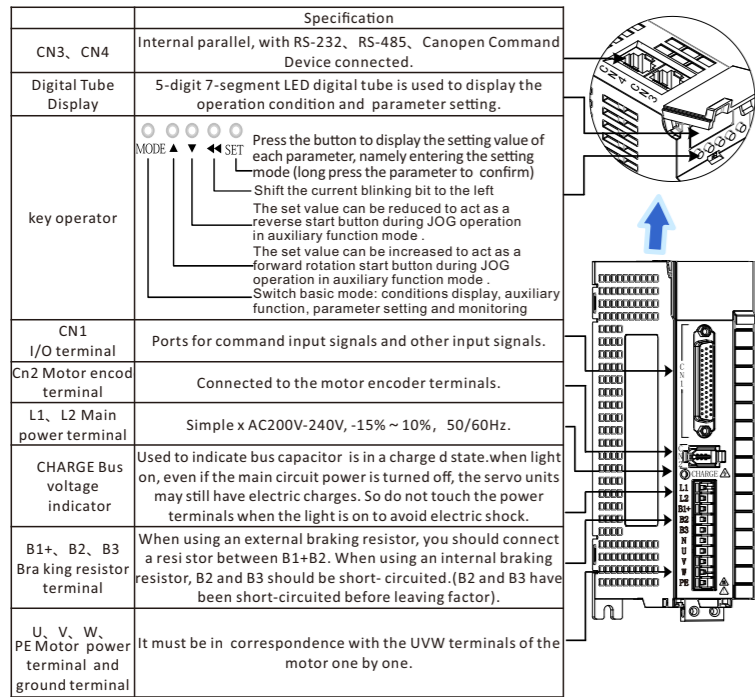


User Manual for E6 Series Servo Driver

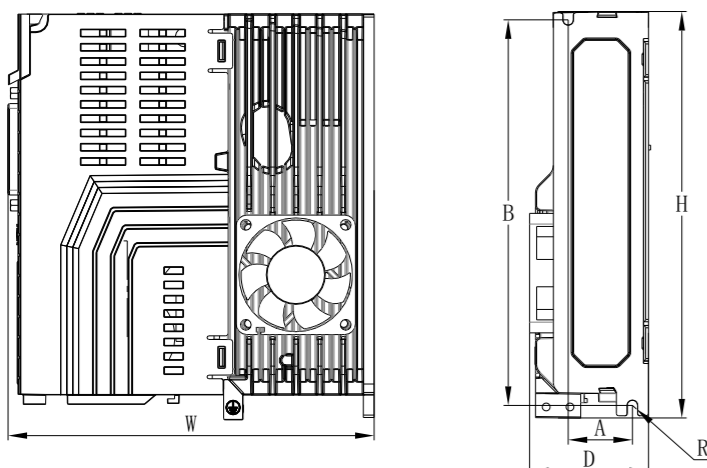
Driver Parts Name



Braking resistor related specifications

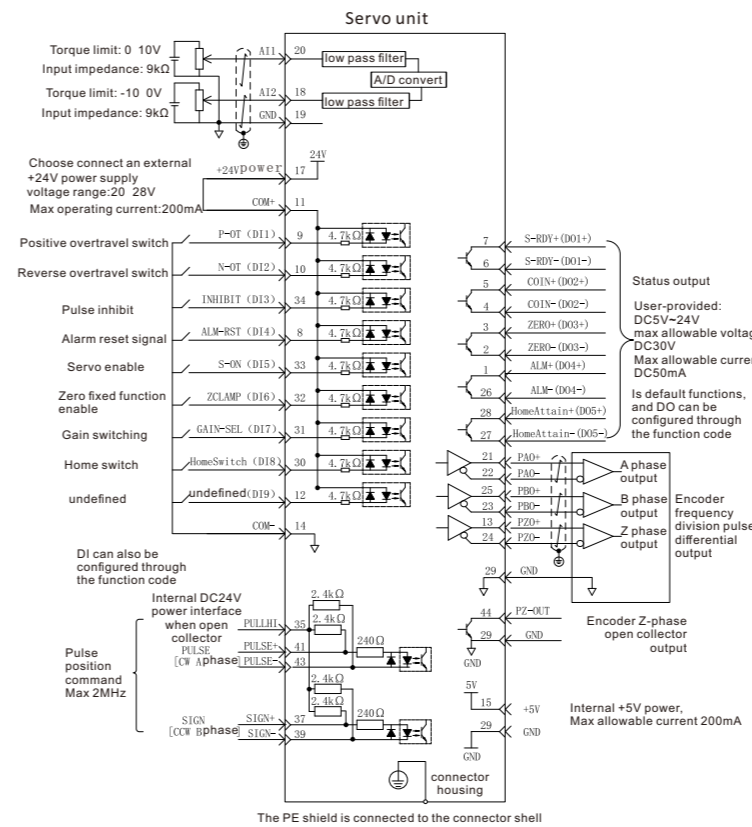
Model Type	Built-in braking resistor specifications		Min. Allowed Resistance (Ω)	Max. Braking Energy Absorbed by Capacitor (J)
	Resistance (Ω)	Power(W)		
Single phase 220V	E6-200RS	-	50	9
	E6-400RS	-	45	18
	E6-750RS	50	50	26
	E6-1000RS	50	50	26

Product Specification

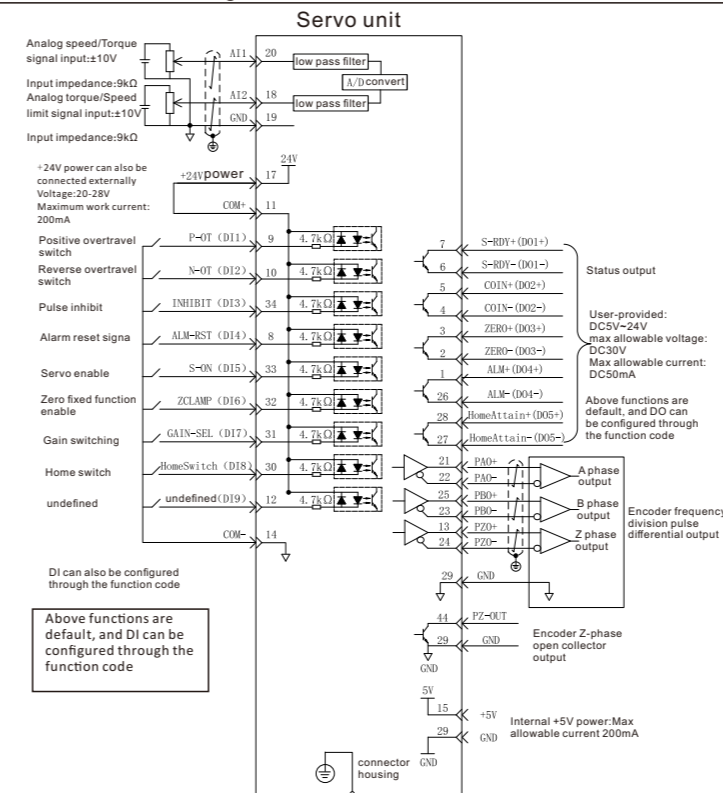


Item	Specification				
	E6 Series	200RS	400RS	750RS	1000RS
Dimension	A(mm)	27			
	B(mm)	162			
	W(mm)	154			
	H(mm)	171			
	D(mm)	51			
	R(mm)	2			
	W(kg)	0.9			
Basic Specifications	Input Power		Single phase AC200V-240V, -15%~10%, 50/60Hz		
	Temperature	Ambient Temperature	0+55°C(from 45°C~to 55°C,keep average load rate within 80%) no freezing		
		Preservation of Ambient Temperature	-20~65°C		
	Humidity	Ambient Humidity	below 20~85%RH (no condensation)		
		Preservation of Ambient Humidity	below 20~85%RH (no condensation)		
	Use and Preservation of Ambient Air		indoor (no direct sunlight), no corrosive gas, flammable gas, oil mist, dust		
	Altitude		below 1000m		
	Vibration		below 5.8m/s ² [0.6G] 10~60Hz(do not use continuously at resonance frequency)		
	Dielectric Withstand Voltage		AC1500V between primary and FG for 1 minute		
	Control Method		three-phase PWM converter sine wave drive		
Encoder Feedback		17bit、23bit (functions as a multi-turn absolute encoder after adding a battery)			
Control Signal	Input	9-way input (DC24V optocoupler isolation) function switching according to the control mode			
	Output	5-way output (DC24V optocoupler isolation, open collector output) switching according to the control mode function			
	Input	2-way input (optocoupler isolation, RS-422 differential, open collector output)			
	Output	4-way output (A/B/Z phase RS-422 differential; Z phase open collector output)			
Communication	RS232	for PC communication (for "Servostudio" connection)			
	RS-485	for host remote control communication (1:n)			
	CAN	CANOPEN bus communication			
Regenerative Functions		Connect regenerative resistor internally or externally pay attention to modifying internal parameters			
Control Modes		6 control modes:speed control,position control,torque control,torque/speed control, speed/position control,torque/position,torque/speed/position mixed control			
Control Input		Alarm reset, proportional action switching, zero fixed function enabling, forward drive prohibited, reverse drive prohibited, external torque limit for forward rotation, external torque limit for reverse rotation, forward jog, reverse jog, forward reset switch, reverse reset switch, origin switch, emergency stop, servo enabling, gain switching			
Control Output		Servo ready, motor rotating, zero speed signal, speed arrival, position arrival, positioning approach signal, torque limit, speed limit, brake output, warning, servo failure, alarm code (3-digit output)			
Position Control	Pulse input	Maximum command pulse frequency	The maximum low speed is 500Kpps, and the pulse width cannot be lower than 1μs; Open collector: maximum 200Kpps, pulse width not less than 2.5μs		
		Input pulse signal form	Differential input; open collector		
	Pulse output	Input pulse signal mode	pulse+direction, right angle phase difference (phase A+phase B), CW+CCW pulse		
		Command filter	Smooth filter, FIR filter		
Speed Control	Pulse output	Output pulse form	Phase A and B: differential output Z-phase: differential output or open collector output		
		Frequency division ratio	Arbitrary frequency division		
	Control Input	Control Input	Servo ON, alarm reset, reverse speed command, zero speed clamping, internal command selection input 1, internal command selection input 2, internal command selection input 3, internal command selection input 4, forward external torque limit input, reverse external torque limit input, emergency stop		
		Control Output	Alarm status, servo ready, brake release, output during torque limit, output during speed limit, speed reached, speed coincidence, motor rotation output, zero speed signal output		
Torque Control	Control Input	Servo ON, alarm reset, torque command reverse, zero speed clamp			
	Control Output	Alarm status, servo preparation, brake release, torque limit, speed limit output, emergency stop			
Similarities	Torque Command Input	(Factory default setting, range can be set by function code)			
	Speed Limit Function	Positive and negative internal speed limit P03.27, P03.28			
	Speed Observer Function	Yes			
	Vibration Control function	Yes			
Adaptive Notch Filter	Yes				
Auto adjustment function	Yes				
Encoder output frequency division and multiplication	Yes				
Internal location planning function	Yes				
Adjustment/Function Setting	Use the upper computer to set the software "Servostudio" to adjust				
Protective function	Over voltage, abnormal power supply, over current, overload, abnormal encoder, overspeed, excessive position deviation, abnormal parameters, etc.				

Location Mode Wiring

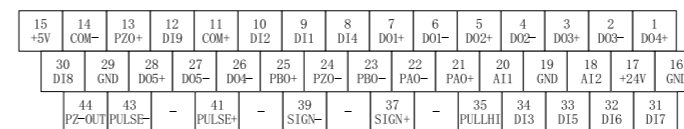


Speed/Torque Control Mode Block Diagram

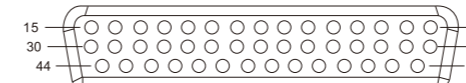


Indicates twisted pair
 Note: ■ Signal cables and power cables must be routed separately, with an interval of at least 30 cm.
 ■ When the signal cable is not long enough to connect the cable, the shielding layer must be connected reliably to ensure reliable shielding and grounding.
 ■ With a reference to GND, when you use +5V, do not exceed the maximum allowable current, otherwise the driver will not work properly.

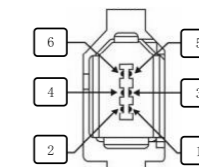
CN1 Terminal arrangement description



Model type show



CN2 Illustration of the terminal arrangement of the absolute encoder

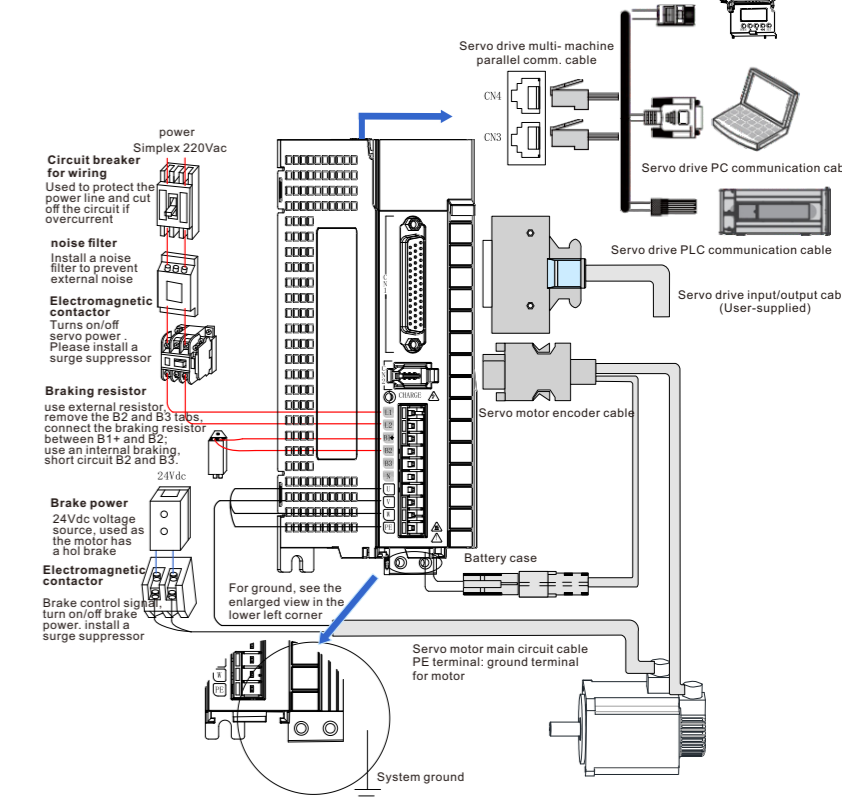


Terminal	Name	Function
1	+5V	PG power+5V
3	-	-
5	PS+	S+ phase
2	OV	Signal
4	-	-
6	PS-	S-phase

CN3, CN4 Illustration of terminal arrangement

Pin	Definition	Description	Terminal Pinout
1	CANH	CAN comm. port	8
2	CANL		
3	CGND	CAN comm. port	7
4	RS485+	RS485 comm. port	6
5	RS485-		
6	RS232-TXD	RS232 Sending end, connected with the receiving end of the host computer	5
7	RS232-RXD	RS232 The receiver is connected to the transmitter of the host computer	4
8	GND	Ground	3
Shell	PE	Ground shield	2

Servo System Wiring



Please pay attention to the power supply capacity when connecting external control power supply or 24Vdc power supply, especially when supplying power to several drives or multiple brakes at the same time, insufficient power supply capacity will lead to insufficient supply current and failure of the drive or the brake. The braking power supply is a 24V DC voltage source. The power should refer to the motor model and meet the braking power requirements.

System wiring precautions:

- When connecting an external braking resistor, please remove the short-circuit wire between terminals B2 and B3 of the servo drive before connecting. Pay attention to modify the internal parameters.
- CN3 and CN4 define exactly the same communication interface for the two pins, which can be used arbitrarily between the two.
- In single-phase 220V wiring, the main circuit terminals are L1 and L2, and the reserved terminals should not be connected.

P02 Group Basic control parameters

Function code	Name	Unit	Factory setting	Effective way	Setting way	Related patterns
P02_00	Control Mode Selection	-	1	Effective immediately	Stop setting	-
P02_01	Absolute value system selection	-	0	Power up again	Stop setting	ALL
P02_02	rotating direction selection	-	0	Power up again	Stop setting	PST
P02_03	Output pulse phase	-	0	Power up again	Stop setting	PST
P02_05	stop model at S-ON off	-	0	Effective immediately	Stop setting	PST
P02_06	Fault No.2 Stop Mode Selection	-	0	Effective immediately	Stop setting	PST
P02_07	Choice of Overhaul Mode	-	1	Effective immediately	Stop setting	PST
P02_08	Fault No.1 Stop Mode Selection	-	0	Effective immediately	Stop setting	PST
P02_09	delay from brake output ON to command received	ms	250	Effective immediately	Run settings	PS
P02_10	delay from brake output OFF to motor de-energized in static state	ms	150	Effective immediately	Run settings	PS
P02_11	motor speed threshold at brake output OFF in rotating state	rpm	30	Effective immediately	Run settings	PS
P02_12	Rotate state, motor does not power to lock output Off delay	ms	500	Effective immediately	Run settings	PS
P02_15	LED Warning Display Select	-	0	Effective immediately	Run settings	PST
P02_18	Servo Enable (S-ON) Filter time constant	ms	0	Effective immediately	Run settings	PST
P02_21	Brake resistance minimum allowed by driver	Ω	-	-	Display	PST
P02_22	Built-in Brake Resistance Power	W	-	-	Display	PST
P02_23	Built-in brake resistance	Ω	-	-	Display	PST

Function code	Name	Unit	Factory setting	Effective way	Setting way	Related patterns
P02_24	Resistance heat dissipation factor	%	30	Effective immediately	Stop setting	PST
P02_25	Brake resistance settings	-	0	Effective immediately	Stop setting	PST
P02_26	External brake resistance power	W	-	Effective immediately	Stop setting	PST
P02_27	External brake resistance resistance	Ω	-	Effective immediately	Stop setting	PST
P02_30	User password	-	0	Power up again	Stop setting	PST
P02_31	System parameter initialization	-	0	Effective immediately	Stop setting	PST
P02_32	Panel Default Display	-	50	Effective immediately	Run settings	-
P02_38	Fault short circuit braking time	ms	5000	Effective immediately	Run settings	PST

P05 Group Position control parameters

Function code	Name	Unit	Factory setting	Effective way	Setting method	Related patterns
P05_00	Location instruction source	-	0	Effective immediately	Stop setting	P
P05_01	Pulse instruction input terminal selection	-	0	Effective immediately	Stop setting	P
P05_02	Number of position instructions per rotation of motor	P/r	0	Power up again	Stop setting	P
P05_04	First-order low-pass filter time constant	ms	5.0	Effective immediately	Stop setting	P
P05_05	Step by step	unit	0.0	Effective immediately	Stop setting	P
P05_06	Average filter time constant	ms	0.0	Effective immediately	Stop setting	P
P05_07	Electronic tooth ratio 1 (Molecules)	-	131072	Effective immediately	Run settings	P
P05_09	Electronic tooth ratio 1 (denominator)	-	10000	Effective immediately	Run settings	P
P05_11	Electronic tooth ratio 2 (Molecules)	-	131072	Effective immediately	Run settings	P
P05_13	Electronic tooth ratio 2 (denominator)	-	10000	Effective immediately	Run settings	P
P05_15	Pulse instruction pattern	-	0	Power up again	Stop setting	P
P05_16	Clear action selection	-	0	Effective immediately	Stop setting	P
P05_17	Number of frequency division pulses	P/r	2500	Power up again	Stop setting	-
P05_19	Speed feedforward control selection	-	1	Effective immediately	Stop setting	P
P05_20	Location Complete Output Condition	-	0	Effective immediately	Run settings	P
P05_21	Location completion threshold	Encoder / Instruction Unit	734	Effective immediately	Run settings	P
P05_22	Positioning proximity threshold	Encoder / Instruction Unit	65535	Effective immediately	Run settings	P
P05_30	Origin Reversion Enable Control	-	0	Effective immediately	Run settings	P
P05_31	Origin Recovery Mode	-	0	Effective immediately	Stop setting	P
P05_32	Speed of high-speed search for origin switch signal	rpm	100	Effective immediately	Run settings	P
P05_33	Speed of low speed search for origin switch signal	rpm	10	Effective immediately	Run settings	P
P05_34	Time of acceleration and deceleration when searching origin	ms	1000	Effective immediately	Stop setting	P
P05_35	Limit the time to find the origin	ms	10000	Effective immediately	Stop setting	P
P05_36	Mechanical origin offset	Instruction unit	0	Effective immediately	Stop setting	P
P05_38	Servo Pulse Output Source Selection	-	0	Power up again	Stop setting	P
P05_39	Electronic gear ratio switching conditions	-	0	Effective immediately	Stop setting	P
P05_40	Mechanical Origin Offset and Limit Treatment	-	0	Effective immediately	Stop setting	P
P05_41	Z Pulse Output Polarity Selection	-	1	Power up again	Stop setting	P
P05_43	Position pulse along selection	1	0	Power up again	Run settings	PST
P05_46	Absolute position linear mode position bias (low 32 bits)	Encoder unit	0	Effective immediately	Stop setting	ALL
P05_48	Absolute position linear mode position bias (high 32 bits)	Encoder unit	0	Effective immediately	Stop setting	ALL
P05_50	Absolute position rotation mode mechanical gear ratio (molecule)	-	65535	Effective immediately	Stop setting	ALL
P05_51	Absolute position rotation mode mechanical gear ratio (denominator)	-	1	Effective immediately	Stop setting	ALL
P05_52	Absolute position rotation mode load rotation cycle number of pulses (low 32 bits)	Encoder unit	0	Effective immediately	Stop setting	ALL
P05_54	Absolute position rotation mode load rotation cycle number of pulses (32 bits high)	Encoder unit	0	Effective immediately	Stop setting	ALL
P05_56	Threshold of zero velocity judgment	rpm	2	Effective immediately	Run settings	P
P05_58	Contact Stop Zero Torque Limit	%	100.0%	Effective immediately	Run settings	P
P05_59	Location Completion Window Time	ms	1	Effective immediately	Run settings	P
P05_60	Positioning completion retention time	ms	0	Effective immediately	Run settings	P
P05_61	Number of divider pulses (32 bits)	P/r	0	Power up again	Stop setting	-
P05_63	Collector Z signal width	μs	0.15	Power up again	Stop setting	P

P06 Group Speed control parameters

Function code	Name	Unit	Factory setting	Effective way	Setting way	Related patterns
P06_00	A Source of Main Speed Instruction	-	0	Effective immediately	Stop setting	S
P06_01	Auxiliary Speed Instruction B Source	-	1	Effective immediately	Stop setting	S
P06_02	Speed Instruction Selection	-	0	Effective immediately	Stop setting	S
P06_03	Speed command keyboard setting	rpm	200	Effective immediately	Run settings	S
P06_04	Set point speed	rpm	100	Effective immediately	Run settings	S
P06_05	Speed command acceleration ramp time constant	ms	0	Effective immediately	Run settings	S
P06_06	Speed command acceleration ramp time constant	ms	0	Effective immediately	Run settings	S
P06_07	Maximum Speed Threshold	rpm	6000	Effective immediately	Run settings	S
P06_08	Forward velocity threshold	rpm	6000	Effective immediately	Run settings	S
P06_09	Reverse velocity threshold	rpm	6000	Effective immediately	Run settings	S
P06_11	Torque Feedforward Control Selection	-	1	Effective immediately	Run settings	S
P06_15	Zero fixed speed threshold	rpm	10	Effective immediately	Run settings	S
P06_16	Motor rotation speed threshold	rpm	20	Effective immediately	Run settings	S
P06_17	Speed consistent signal threshold	rpm	10	Effective immediately	Run settings	S
P06_18	Speed reaches signal threshold	rpm	1000	Effective immediately	Run settings	S
P06_19	Zero speed output signal threshold	rpm	10	Effective immediately	Run settings	S

P07 Group Torque control parameters

Torque instruction 100% corresponding to motor rated torque.

Function code	Name	Unit	Factory setting	Effective way	Setting way	Related patterns
P07_00	A source of master torque instruction	-	0	Effective immediately	Stop setting	T
P07_01	Auxiliary torque instruction B source	-	1	Effective immediately	Stop setting	T
P07_02	Torque Directive Selection	-	0	Effective immediately	Stop setting	T
P07_03	Torque instruction keyboard setting	%	0	Effective immediately	Run settings	T
P07_05	Torque instruction filter time constant	ms	0.79	Effective immediately	Run settings	PST
P07_06	Second torque instruction filtering time constant	ms	0.79	Effective immediately	Run settings	PST
P07_07	Torque limitation sources	-	0	Effective immediately	Stop setting	PST
P07_08	T-LMT selection	-	2	Effective immediately	Stop setting	PST
P07_09	Positive internal torque limit	%	300.0	Effective immediately	Run settings	PST
P07_10	Negative internal torque limit	%	300.0	Effective immediately	Run settings	PST
P07_11	Positive external torque limit	%	300.0	Effective immediately	Run settings	PST
P07_12	Negative External Torque Limit	%	300.0	Effective immediately	Run settings	PST
P07_17	Selection of f speed limit sources	-	0	Effective immediately	Run settings	T
P07_18	V-LMT Selection	-	1	Effective immediately	Run settings	T
P07_19	Torque control forward speed limit value / torque control speed limit value 1	rpm	3000	Effective immediately	Run settings	T
P07_20	Negative Speed Limit for Torque Control / Speed Limit for Torque Control 2	rpm	3000	Effective immediately	Run settings	T
P07_21	Torque reaches reference value	%	0.0	Effective immediately	Run settings	PST
P07_22	Torque reaches effective value	%	20.0	Effective immediately	Run settings	PST
P07_23	Torque arrives invalid	%	10.0	Effective immediately	Run settings	PST
P07_40	Speed restricted window in torque mode	ms	1.0	Effective immediately	Run settings	T

P08 Group Gain class parameters

Function code	Name	Unit	Factory setting	Effective way	Setting method	Related patterns
P08_00	speed gain	Hz	25.0	Effective immediately	Run settings	PS
P08_01	Speed loop integral time constant	ms	31.83	Effective immediately	Run settings	PS
P08_02	Position loop gain	Hz	40.0	Effective immediately	Run settings	P
P08_03	Second speed loop gain	Hz	40.0	Effective immediately	Run settings	PS
P08_04	No.2 Speed loop integral time constant	ms	40.0	Effective immediately	Run settings	PS
P08_05	No.2 Position loop gain	Hz	64.0	Effective immediately	Run settings	P
P08_08	Second Gain Mode Settings	-	1	Effective immediately	Run settings	PST
P08_09	Gain switching condition selection	-	0	Effective immediately	Run settings	PST
P08_10	Gain switching delay time	ms	5.0	Effective immediately	Run settings	PST
P08_11	Gain Switching Level	According to switching conditions	50.0	Effective immediately	Run settings	PST
P08_12	Gain switching delay	According to switching conditions	30.	Effective immediately	Run settings	PST
P08_13	Position gain switching time	ms	3.0.	Effective immediately	Run settings	P
P08_15	Load moment of inertia ratio	times	1.00	Effective immediately	Run settings	PST
P08_18	Speed feed filter time constant	ms	0.50	Effective immediately	Run settings	P
P08_19	Speed feedforward gain	%	0.0	Effective immediately	Run settings	P
P08_20	Torque feed filter time constant	ms	0.50	Effective immediately	Stop setting	PS
P08_21	Torque Feedforward Gain	%	0.0	Effective immediately	Run settings	PS
P08_22	Speed Feedback Filter Option	-	0	Effective immediately	Stop setting	PS
P08_23	Speed feedback low pass filter cutoff frequency	Hz	4000	Effective immediately	Run settings	PS
P08_24	Pseudo-differential feedforward control coefficient	-	100.0	Effective immediately	Run settings	PS
P08_27	Friction gain	%	0.0	Effective immediately	Run settings	P
P08_28	Static friction	%	%	Effective immediately	Run settings	P

P09 Group Self-adjusting parameters

Function code	Name	Unit	Factory setting	Effective way	Setting method	Related patterns
P09_00	Self adjustment mode selection	-	0	Effective immediately	Run settings	PST
P09_01	Rigid grade selection	-	12	Effective immediately	Run settings	PST
P09_02	Adaptive Trap Mode Selection	-	0	Effective immediately	Run settings	PST
P09_03	On-line Inertial Identification Mode	-	0	Effective immediately	Run settings	RST
P09_04	Selection of Low Frequency Resonance Suppression Mode	-	0	Effective immediately	Run settings	P
P09_05	Offline Inertial Identification Mode Selection	-	0	Effective immediately	Stop setting	PST
P09_06	Maximum velocity for inertia identification	rpm	500	Effective immediately	Stop setting	PST
P09_07	Acceleration to maximum velocity time constant for inertia identification	ms	125	Effective immediately	Stop setting	PST
P09_08	Waiting time after completion of single inertia identification	ms	800	Effective immediately	Stop setting	PST
P09_09	Complete single inertia identification number of motor turns	r	-	-	Display	PST
P09_12	Group 1 Trap Frequency	Hz	4000	Effective immediately	Run settings	PS
P09_13	Group 1 Trap width rating	-	2	Effective immediately	Run settings	PS
P09_14	Group 1 Trap depth rating	-	0	Effective immediately	Run settings	PS
P09_15	Group 2 Trap Frequency	Hz	4000	Effective immediately	Run settings	PS
P09_16	Group 2 Trap width rating	-	2	Effective immediately	Run settings	PS
P09_17	Group 2 Trap depth rating	-	0	Effective immediately	Run settings	PS
P09_18	Group 3 Trap Frequency	Hz	4000	Effective immediately	Run settings	PS
P09_19	Group 3 Trap width rating	-	2	Effective immediately	Stop setting	PS
P09_20	Group 3 Trap depth rating	-	0	Effective immediately	Run settings	PS
P09_21	Group 4 Trap Frequency	Hz	4000	Effective immediately	Run settings	PS
P09_22	Group 4 Trap width rating	-	2	Effective immediately	Run settings	PS
P09_23	Group 4 Trap depth rating	-	0	Effective immediately	Run settings	PS
P09_24	Resonance Frequency Identification Results	Hz	0	-	Display	PS
P09_30	Torque disturbance compensation gain	%	0.0	Effective immediately	Run settings	PS
P09_31	Time constant of torque disturbance observer filter	ms	0.50	Effective immediately	Run settings	PS
P09_38	Low frequency resonance frequency	Hz	100.0	Effective immediately	Run settings	P

P0B Group Monitoring parameters

Function code	Name	Unit	Factory setting	Effective way	Setting method	Related patterns
P0B_00	Actual motor speed	rpm	-	-	Display	PST
P0B_01	Speed instruction	rpm	-	-	Display	PS
P0B_02	Internal torque instruction (relative to rated torque)	%	-	-	Display	PST
P0B_03	Input signal (DI signal) monitoring	-	-	-	Display	PST
P0B_05	Output signal (DO signal) monitoring	-	-	-	Display	PST
P0B_07	Absolute position counter (32-bit decimal display)	Instruction Unit	-	-	Display	PST
P0B_09	Mechanical angle (number of pulses starting at origin)	Encoder Unit	-	-	Display	PST
P0B_10	Electrical angle	°	-	-	Display	PST
P0B_11	Input position instruction corresponding speed information	rpm	-	-	Display	P
P0B_12	Average load rate	%	-	-	Display	PST
P0B_13	Input instruction pulse counter (32-bit decimal display)	Instruction Unit	-	-	Display	P
P0B_15	Encoder position deviation counter (32-bit decimal display)	Encoder Unit	-	-	Display	P
P0B_17	Feedback pulse counter (32-bit decimal display)	Encoder Unit	-	-	Display	PST
P0B_19	Total power-up time (32-bit decimal display)	s	-	-	Display	PST
P0B_21	A1 Sampling 21voltage values	V	-	-	Display	PST
P0B_22	A2 Sampling voltage values	V	-	-	Display	PST
P0B_24	Phase current RMS	V	-	-	Display	PST
P0B_26	Bus voltage	V	-	-	Display	PST
P0B_27	Module temperature values	°C	-	-	Display	PST
P0B_33	Failure logging	-	0	Effective	Run	PST
P0B_34	Number of failures selected	-	-	-	Display	PST
P0B_35	Selected fault timestamp	S	-	-	Display	PST
P0B_37	Motor speed at selected faults	rpm	-	-	Display	PST
P0B_38	Electrical U phase current at selected fault	A	-	-	Display	PST
P0B_39	Electrical U phase current at selected fault	A	-	-	Display	PST
P0B_40	Bus voltage at selected fault	V	-	-	Display	PST
P0B_41	Input terminal status at selected fault	-	-	-	Display	PST
P0B_42	Output terminal status at selected fault	-	-	-	Display	PST
P0B_53	Position Deviation Counter	Instruction Unit	-	-	Display	P
P0B_55	Actual motor speed(0.1rpm)	rpm	-	-	Display	PST
P0B_58	Mechanical absolute position (32 bits low)	Encoder Unit	0	-	Display	ALL
P0B_60	Mechanical absolute position (32 bits high)	Encoder Unit	0	-	Display	ALL
P0B_64	Real-time input position instruction counter	Unit of instruction	-	-	Display	PST
P0B_70	Absolute value encoder rotation circle data	r	0	-	Display	ALL
P0B_71	In-circle position of absolute encoder	Encoder Unit	0	-	Display	ALL
P0B_77	Absolute encoder absolute position (low 32 bits)	Encoder Unit	0	-	Display	ALL
P0B_79	Absolute encoder absolute position (high 32 bits)	Encoder Unit	0	-	Display	ALL
P0B_81	Rotating load single loop position (low 32 bits)	Encoder Unit	0	-	Display	ALL
P0B_83	Rotating load single loop position (high 32 bits)	Encoder Unit	0	-	Display	ALL

Troubleshooting

Display	Fault name	Display	Fault name
FU.101	P02 and above group parameters are abnormal	FU.625	Brake closed abnormally
FU.102	Programmable logic configuration failure	FU.626	Brake opened abnormally
FU.104	Programmable logic interrupt fault	FU.630	Motor blocked
FU.105	Internal program exception	FU.650	Radiator overheated
FU.108	Parameter storage failure	FU.730	Encoder battery warning
FU.110	Frequency division pulse output setting failure	FU.731	Encoder battery failure
FU.111	Internal fault	FU.733	Encoder multi-turn counting error
FU.120	Product matching failure	FU.735	Encoder multi-turn counting over flow
FU.121	Servo ON command invalid fault	FU.740	Encoder interference
FU.122	Absolute position mode product matching failure	FU.741	Counting error made by encoder
FU.130	DI function repeated allocation	FU.760	Overheat alarm from encoder
FU.131	DO function allocation exceeds limit	FU.831	Al zero drift is too large
FU.136	Data check error in motor ROM or parameter not saved	FU.834	AD sampling overvoltage
FU.201	Over current 2	FU.835	High-precision AD sampling failure
FU.202	Software over current	FU.900	DI emergency brake
FU.203	Excessive current null point	FU.909	Motor overload warning
FU.207	D/Q axis current overflow fault	FU.920	Braking resistor overload
FU.208	FPGA system sampling operation timeout	FU.922	External braking resistor is too small
FU.210	Output short circuit to ground	FU.939	Motor power line is broken
FU.220	Phase sequence error	FU.941	Change parameters need to be re-powered to take effect
FU.234	Speed car	FU.942	Frequent parameter storage
FU.235	Excessive speed tracking error	FU.950	Forward over travel warning
FU.400	Main circuit over voltage	FU.952	Reverse over travel warning
FU.410	Main circuit under voltage	FU.980	Encoder internal fault
FU.420	Main circuit lack of phase	FU.990	Input phase loss warning
FU.430	Control voltage under voltage	FU.994	CAN address conflict
FU.431	Excessive analog voltage	FU.A33	Encoder data is abnormal
FU.432	Too large null point	FU.A40	Internal fault
FU.500	Over speed	FU.B00	Position deviation is too large
FU.510	Pulse output over speed	FU.B01	Pulse input abnormal
FU.601	Back to origin timeout failure	FU.B02	Full closed loop position deviation is too large
FU.602	Angle recognition failed	FU.B03	Electronic gear ratio setting exceeds limit
FU.610	Drive overload	FU.B04	Full closed loop function parameter setting error
FU.620	Motor over load	FU.D03	CAN communication connection interrupted

MODBUS Communication Protocol

The function codes of servo driver can be divided into 16bits and 32bits in length. Through MODBUS RTU protocol, the data of function code can be read and written. The command code differs owing to different length of data when you write data of function code.

Operation	Command code
Read 16/32 bits function codes	0*03
Write	