



# Operation Manual

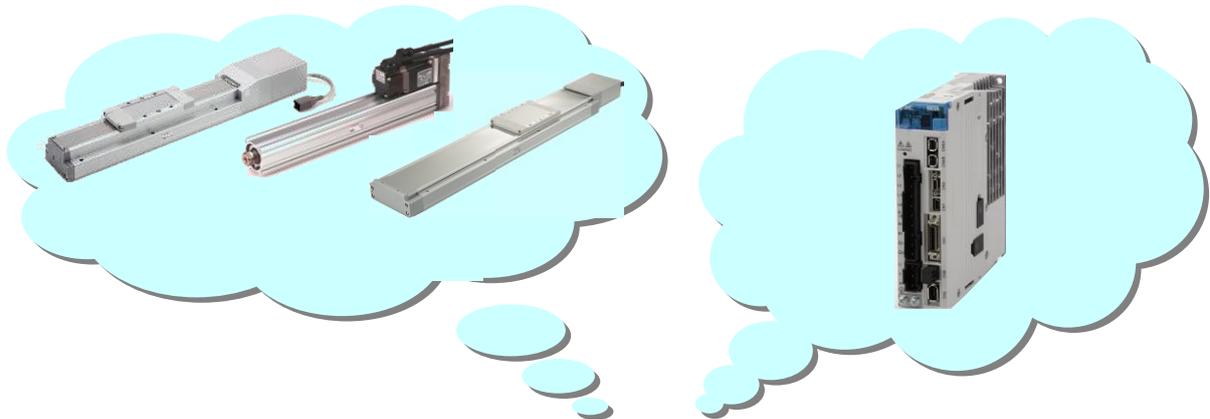
(Simplified edition)

PRODUCT NAME

## *AC Servo Motor Driver* *(MECHATROLINK-III type)*

MODEL / Series / Product Number

### LECYU Series



## SMC Corporation



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# LECYU Series / Driver Safety Instructions

These safety instructions are intended to prevent hazardous situations and/or equipment damage. These instructions indicate the level of potential hazard with the labels of "Caution," "Warning" or "Danger." They are all important notes for safety and must be followed in addition to International Standards (ISO/IEC), and other safety regulations.

- \*1) ISO 4414: Pneumatic fluid power -- General rules relating to systems
- ISO 4413: Hydraulic fluid power -- General rules relating to systems
- IEC 60204-1: Safety of machinery -- Electrical equipment of machines (Part 1: General requirements)
- ISO 10218: Manipulating industrial robots -- Safety
- etc.



## Caution

**Caution** indicates a hazard with a low level of risk which, if not avoided, could result in minor or moderate injury.



## Warning

**Warning** indicates a hazard with a medium level of risk which, if not avoided, could result in death or serious injury.



## Danger

**Danger** indicates a hazard with a high level of risk which, if not avoided, will result in death or serious injury.



## IMPORTANT

Indicates **important** information that should be memorized, as well as precautions, such as alarm displays, that do not involve potential damage to equipment.

## Warning

### **1. The compatibility of the product is the responsibility of the person who designs the equipment or decides its specifications.**

Since the product specified here is used under various operating conditions, its compatibility with specific equipment must be decided by the person who designs the equipment or decides its specifications based on necessary analysis and test results.

The expected performance and safety assurance of the equipment will be the responsibility of the person who has determined its compatibility with the product.

This person should also continuously review all specifications of the product referring to its latest catalog information, with a view to giving due consideration to any possibility of equipment failure when configuring the equipment.

### **2. Only personnel with appropriate training should operate machinery and equipment.**

The product specified here may become unsafe if handled incorrectly.

The assembly, operation and maintenance of machines or equipment including our products must be performed by an operator who is appropriately trained and experienced.

### **3. Do not service or attempt to remove product and machinery/equipment until safety is confirmed.**

The inspection and maintenance of machinery/equipment should only be performed after measures to prevent falling or runaway of the driven objects have been confirmed.

When the product is to be removed, confirm that the safety measures as mentioned above are implemented and the power from any appropriate source is cut, and read and understand the specific product precautions of all relevant products carefully.

Before machinery/equipment is restarted, take measures to prevent unexpected operation and malfunction.

### **4. Contact SMC beforehand and take special consideration of safety measures if the product is to be used in any of the following conditions.**

1) Conditions and environments outside of the given specifications, or use outdoors or in a place exposed to direct sunlight.

2) Installation on equipment in conjunction with atomic energy, railways, air navigation, space, shipping, vehicles, military, medical treatment, combustion and recreation, or equipment in contact with food and beverages, emergency stop circuits, clutch and brake circuits in press applications, safety equipment or other applications unsuitable for the standard specifications described in the product catalog.

3) An application which could have negative effects on people, property, or animals requiring special safety analysis.

4) Use in an interlock circuit, which requires the provision of double interlock for possible failure by using

a mechanical protective function, and periodical checks to confirm proper operation.

Note that the  CAUTION level may lead to a serious consequence according to conditions. Please follow the instructions of both levels because they are important to personnel safety.



# LECYU Series / Driver Safety Instructions

## Caution

**The product is provided for use in manufacturing industries.**

The product herein described is basically provided for peaceful use in manufacturing industries. If considering using the product in other industries, consult SMC beforehand and exchange specifications or a contract if necessary.  
If anything is unclear, contact your nearest sales branch.

## Limited warranty and Disclaimer/Compliance Requirements

The product used is subject to the following “Limited warranty and Disclaimer” and “Compliance Requirements”.

Read and accept them before using the product.

### Limited warranty and Disclaimer

**The warranty period of the product is 1 year in service or 1.5 years after the product is delivered whichever is first. \*3)**

**Also, the product may have specified durability, running distance or replacement parts. Please consult your nearest sales branch.**

**For any failure or damage reported within the warranty period which is clearly our responsibility, a replacement product or necessary parts will be provided.**

**This limited warranty applies only to our product independently, and not to any other damage incurred due to the failure of the product.**

**Prior to using SMC products, please read and understand the warranty terms and disclaimers noted in the specified catalog for the particular products.**

**\*3) Vacuum pads are excluded from this 1 year warranty.**

**A vacuum pad is a consumable part, so it is warranted for a year after it is delivered.**

**Also, even within the warranty period, the wear of a product due to the use of the vacuum pad or failure due to the deterioration of rubber material are not covered by the limited warranty.**

## Compliance Requirements

When the product is exported, strictly follow the laws required by the Ministry of Economy, Trade and Industry (Foreign Exchange and Foreign Trade Control Law).

## Introduction

It is recommended that the operator read the operation manual for LECYU prior to use.

For the handling and details of other equipment, please refer to the operation manual for used equipment.

Select  $\Sigma V$  as an object series when you use SigmaWin+.

Refer to the table for the following type when you select the model (parameter edit at offline etc.).

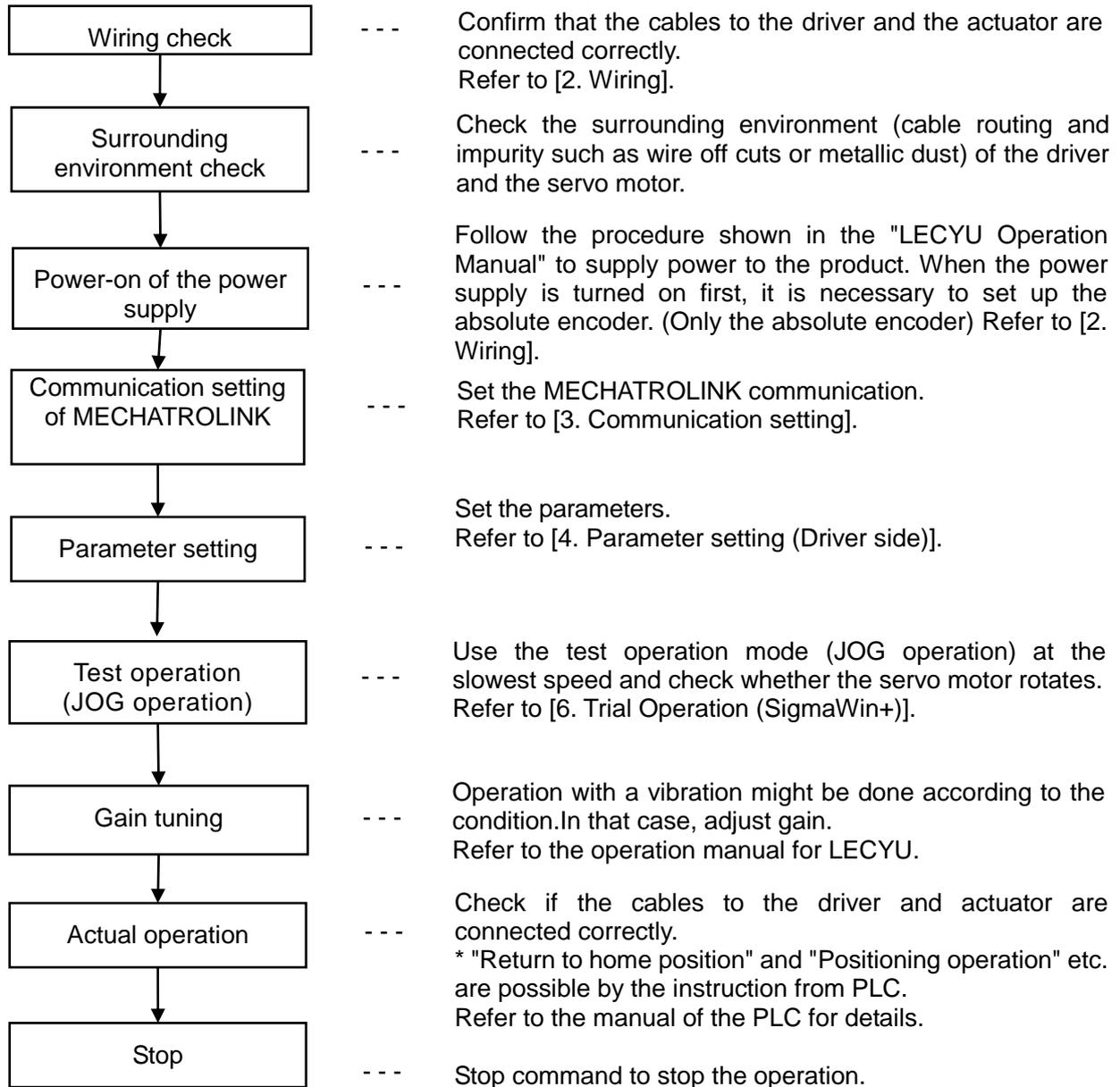
Driver type	Driver select		Motor select	
	SMC	Sigma Win+	SMC	Sigma Win+
MECHATROLINK-III	LECYU2-**	SGDV-****21* Y572AA	V5	SGDV-R90A21B
			V7	SGDV-1R6A21B
			V8	SGDV-2R8A21B
			V9	SGDV-5R5A21A

Please download setup software (SigmaWin+) via our website.

Refer to "LECYU Operation Manual", section 2.2 for method of installing setup software (SigmaWin+).

# 1. Procedure before operation

## 1.1 Flow chart

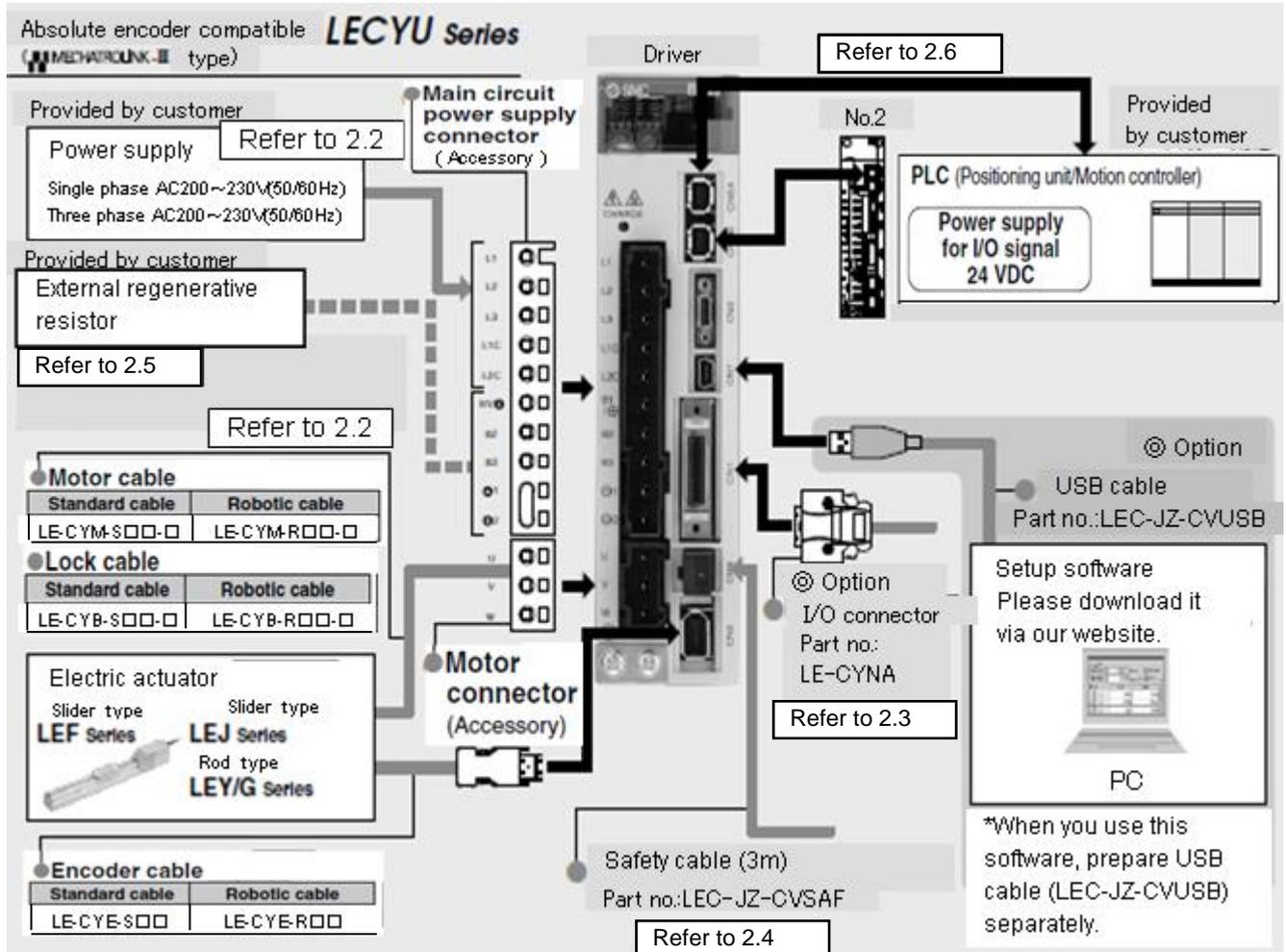


## 2. Wiring

### 2.1 System configuration

The system configuration chart is shown below.

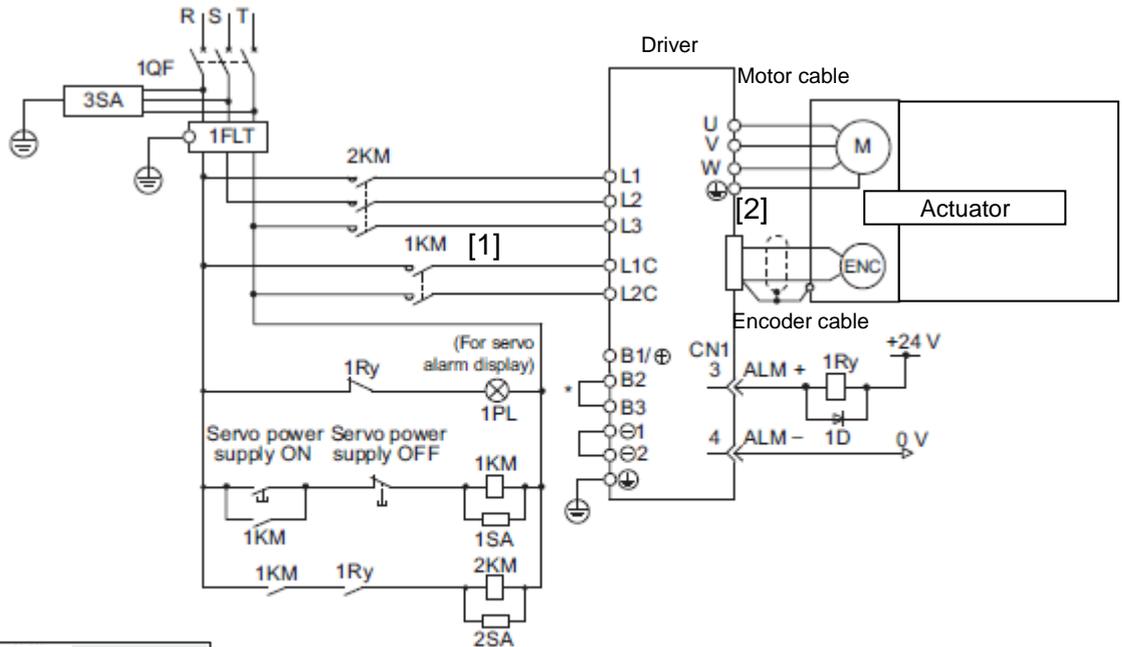
Refer to the next paragraph for details of the wiring for each cable.



## 2.2 Wiring for power supply

Connect the actuator and driver power supply.

(1) Power supply is AC200V three phase



Electric wire specifications

Item	Specifications
Applicable Wire size	L1, L2, L3, L1C, L2C Single line, twisted wire AWG14 (20mm <sup>2</sup> )
Stripped section length	8~9mm

1QF: Molded-case circuit breaker  
 1FLT: Noise filter  
 1KM: Magnetic contactor (for control power supply)  
 2KM: Magnetic contactor (for main circuit power supply)  
 1Ry: Relay

1PL: Indicator lamp  
 1SA: Surge absorber  
 2SA: Surge absorber  
 3SA: Surge absorber  
 1D: Flywheel diode

\* For the LECYU2-V5, V7, V8, terminals B2 and B3 are not short-circuited.  
 Do not short-circuit these terminals.

[1] Main circuit power input terminals, L1, L2, L3 and Control power input terminals, L1, L2: Connect the 200VAC external power supply to the power supply. Refer to the power supply specification for the size of the acceptable electric wire.

[2] Connect the motor cable (U, V, W) to the servomotor connection terminals (U, V, W).  
 Connect the motor ground terminal to the driver ground terminal.  
 Connect the encoder cable to the encoder cable connector.

\*Please connect lock connection terminal (B) with the DC24V power supply for the motor cable with the lock.



**IMPORTANT**

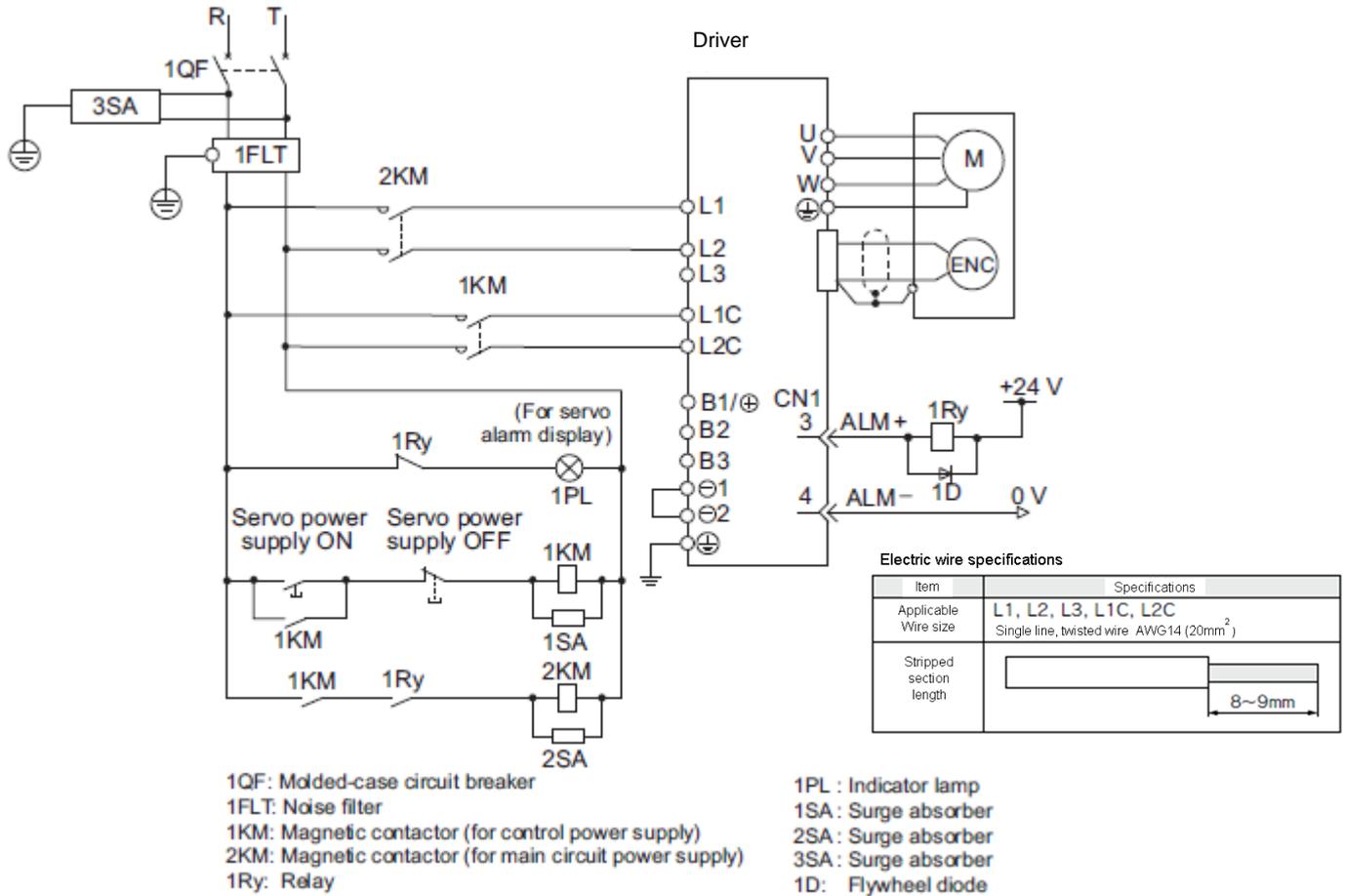
When starting the machine for the first time, setting up and reinitialization of the absolute encoder are necessary. When the absolute encoder is used as the incremental encoder, it is unnecessary.

In the SigmaWin+ main window, click **Setup**, point to **Set Absolute Encoder** and click **Reset Absolute Encoder**.

Please close unnecessary screens such as alarm display screen and parameter screen at this time.

The absolute encoder can only be set up while the servo is off. Turn the power back on after the encoder has been successfully set up.

(2) Power supply is AC200V single phase



\* For the LECYU2-V5, V7, V8, terminals B2 and B3 are not short-circuited.  
Do not short-circuit these terminals.

- [1] Main circuit power input terminals, L1, L2 and Control power input terminals, L1, L2: Connect the 200VAC external power supply to the power supply. Refer to the power supply specification for the size of the acceptable electric wire.
- [2] Connect the motor cable (U, V, W) to the servomotor connection terminals (U, V, W).  
Connect the motor ground terminal to the driver ground terminal.  
Connect the encoder cable to the encoder cable connector.

\*\*Please connect lock connection terminal (B) with the DC24V power supply for the motor cable with the lock.



**IMPORTANT**

When starting the machine for the first time, setting up and reinitialization of the absolute encoder are necessary. When the absolute encoder is used as the incremental encoder, it is unnecessary.

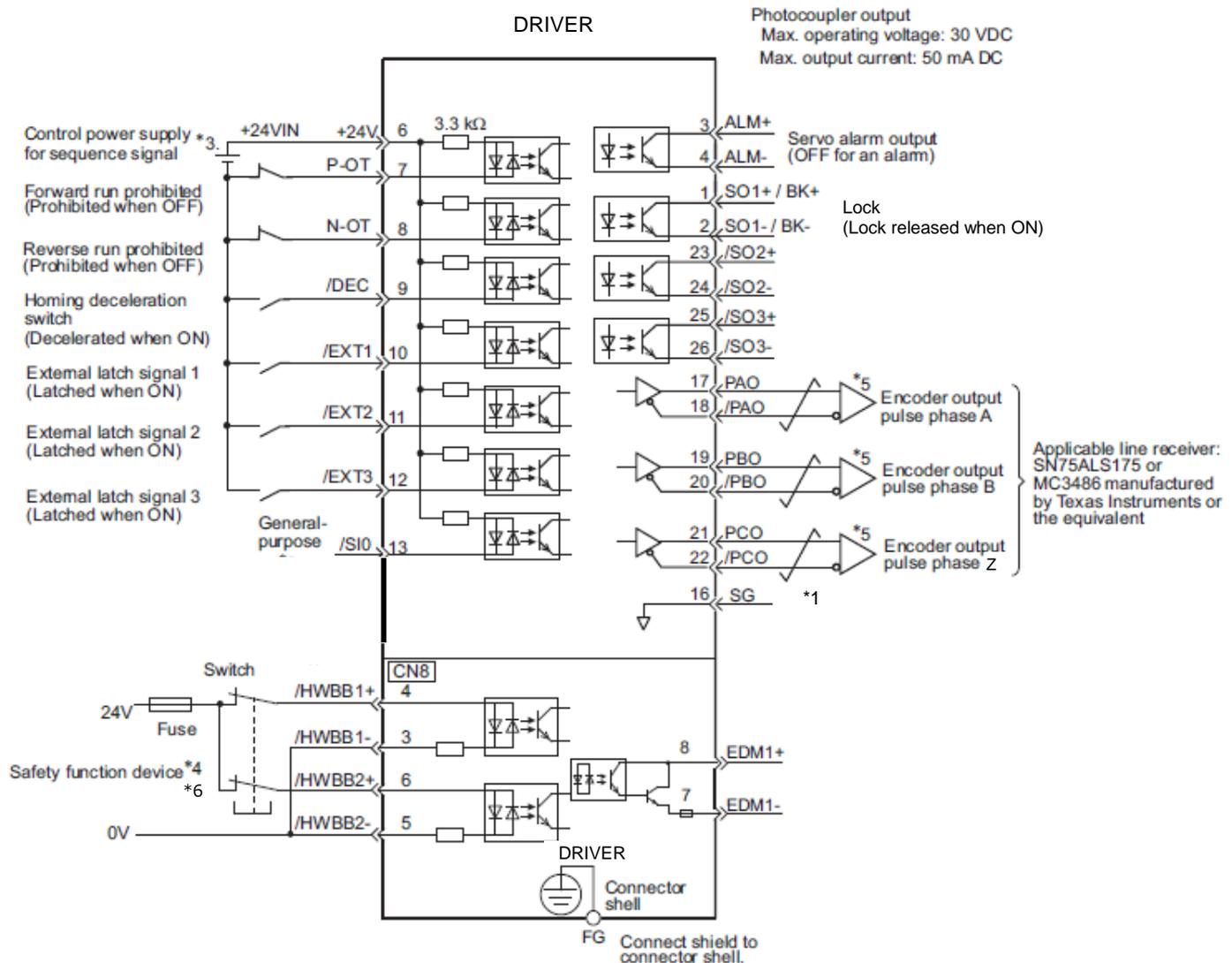
In the SigmaWin+ main window, click **Setup**, point to **Set Absolute Encoder** and click **Reset Absolute Encoder**.

Please close unnecessary screens such as alarm display screen and parameter screen at this time.

The absolute encoder can only be set up while the servo is off. Turn the power back on after the encoder has been successfully set up.

## 2.3 I/O signal connection example (Sink I/O interfaces)

The following diagram shows a typical connection example.



\*1.  represents twisted-pair wires.

\*3. The 24-VDC power supply is not included. Use a 24-VDC power supply with double insulation or reinforced insulation.

\*4. When using the safety function, a safety function device must be connected and the wiring that is necessary to activate the safety function must be done to turn ON the servomotor power. When not using the safety function, use the DRIVER with the Safety Jumper Connector (provided as an accessory) inserted into the CN8.

\*5. Always use line receivers to receive the output signals.

\*6. It is a safety function equivalent to the STO function (IEC 61800-5-2) using the hard wire base block function (HWBB).

Note: Refer to "LECYU Operation Manual", section 3.2.1 and "LECYU Operation Manual (Simplified Edition)", section 2.3.1 for input/output signal details.

Refer to "LECYU Operation Manual", section 3.4 and "LECYU Operation Manual (Simplified Edition)", section 2.3.2 and 2.3.3 for wiring details.

The functions allocated to the input signals /DEC, P-OT, N-OT, /EXT1, /EXT2, and /EXT3 and the output signals /SO1, /SO2, and /SO3 can be changed by using the parameters. Refer to "LECYU Operation Manual", section 3.3.1. and 3.3.2.

### 2.3.1 I/O Signal (CN1) Names and Functions

The following table shows the names and functions of I/O signals (CN1).

#### (1) Input Signals

Signal	Pin No.	Name	Function
P-OT (/SI1) N-OT (/SI2)	7 8	Forward run prohibited, Reverse run prohibited	With overtravel prevention: Stops servomotor when movable part travels beyond the allowable range of motion.
/DEC (/SI3)	9	Homing deceleration switch signal	Connects the deceleration limit switch for homing.
/EXT 1 (/SI4) /EXT 2 (/SI5) /EXT 3 (/SI6)	10 11 12	External latch signal 1 External latch signal 2 External latch signal 3	Connects the external signals that latch the current feedback pulse counter.
/SI0	13	General-purpose input signal	Used for general-purpose input. Monitored in the I/O monitor field of MFCUATP01NK11.
+24VIN	6	Control power supply for sequence signal	Control power supply input for sequence signals. Allowable voltage fluctuation range: 11 to 25 V Note: The 24 VDC power supply is not included.
/P-CL /N-CL	Can be allocated	Forward external torque limit Reverse external torque limit	The allocation of an input signal to a pin can be changed in accordance with the function required.

Note 1. The allocation of the input signals (/SI1 to /SI6) can be changed. For details, refer to "LECYU Operation Manual", section 3.3.1.

2. If the Forward run prohibited/ Reverse run prohibited function is used, the DRIVER is stopped by software controls, not by electrical or mechanical means. If the application does not satisfy the safety requirements, add an external circuit for safety reasons as required.

(2) Output Signals

Signal	Pin No.	Name	Function
ALM+ ALM-	3 4	Servo alarm output signal	Turns OFF when an error is detected.
/BK+ (/SO1+) /BK- (/SO1-	1 2	Lock interlock signal	Controls the lock. The lock is released when the signal turns ON. Allocation can be changed to general-purpose output signals (/SO1+, /SO1-).
/SO2+ /SO2- /SO3+ /SO3-	23 24 25 26	General-purpose output signal	Used for general-purpose output. Note: Set the parameter to allocate a function.
/COIN /V-CMP /TGON /S-RDY /CLT /VLT /WARN /NEAR	Can be allocated	Positioning completion Speed coincidence detection Rotation detection servo ready Torque limit Speed limit detection Warning Near	The allocation of an output signal to a pin can be changed in accordance with the function required.
PAO /PAO	17 18	Phase-A signal	Encoder output pulse signals for two-phase pulse train with 90° phase differential
PBO /PBO	19 20	Phase-B signal	
PCO /PCO	21 22	Phase-Z signal	Origin pulse output signal
SG	16	Signal ground	Connects to the 0 V pin on the control circuit of the PC or PLC...etc.
FG	Shell	Frame ground	Connected to frame ground if the shielded wire of the I/O signal cable is connected to the connector shell.

Note: The allocation of the output signals (/SO1 to /SO3) can be changed.

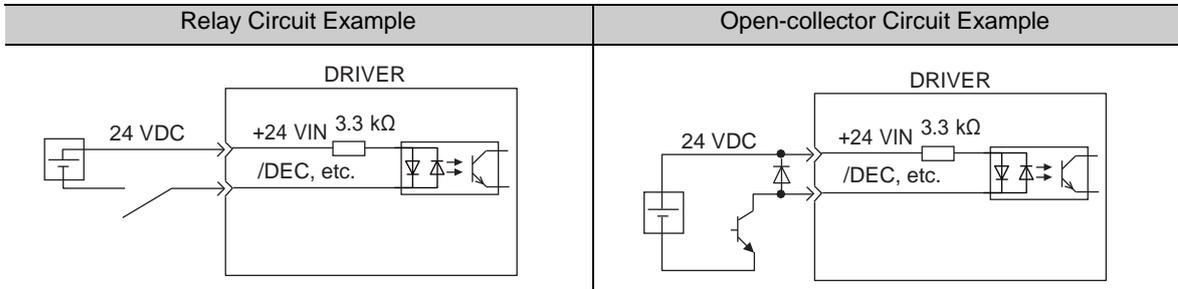
For details, refer to "LECYU Operation Manual", section 3.3.2.

## 2.3.2 Sequence Input Circuit

### (1) Photocoupler Input Circuit

CN1 connector terminals 6 to 13 are explained below.

The sequence input circuit interface is connected through a relay or open-collector transistor circuit. When connecting through a relay, use a low-current relay. If a low-current relay is not used, a faulty contact may result.

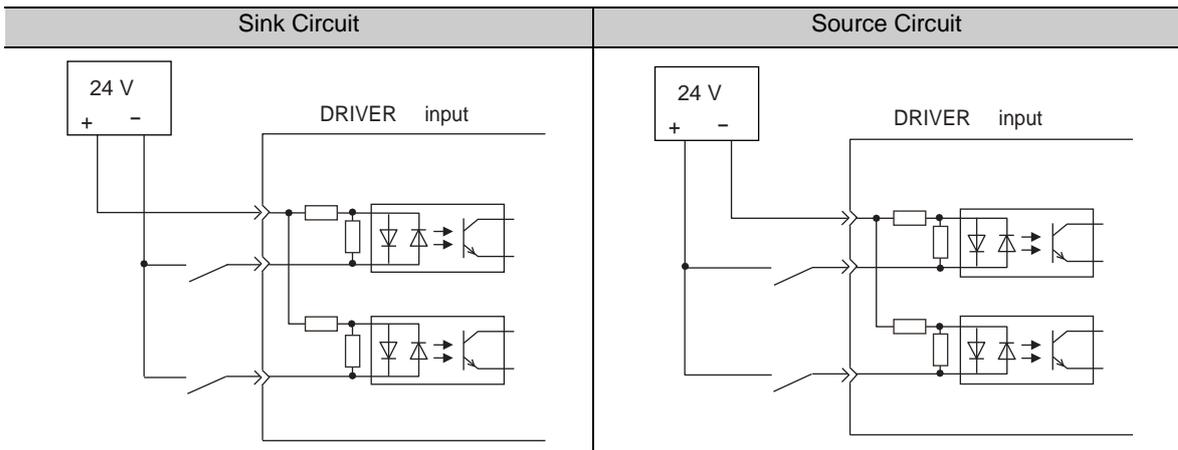


Note: The 24 VDC external power supply capacity must be 50 mA minimum.

The DRIVER's input circuit uses bidirectional photocoupler. Select either the sink circuit or the source circuit according to the specifications required for each machine.

Note: - The connection example in 2.3 shows sink circuits.

- The ON/OFF polarity differs between when a sink circuit is connected and when a source circuit is connected.



Input Signal Polarities				Input Signal Polarities			
Signal	Level	Voltage Level	Contact	Signal	Level	Voltage Level	Contact
ON	Low (L) level	0 V	Close	ON	High (H) level	24 V	Close
OFF	High (H) level	24 V	Open	OFF	Low (L) level	0 V	Open

## 2.3.3 Sequence Input Circuit

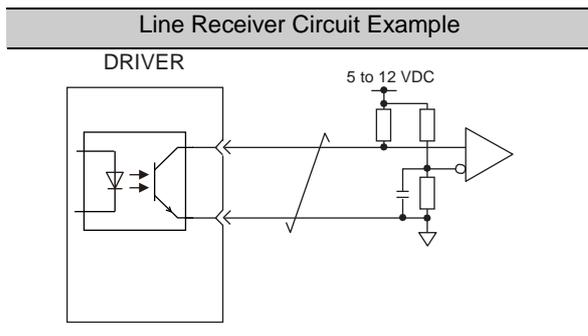
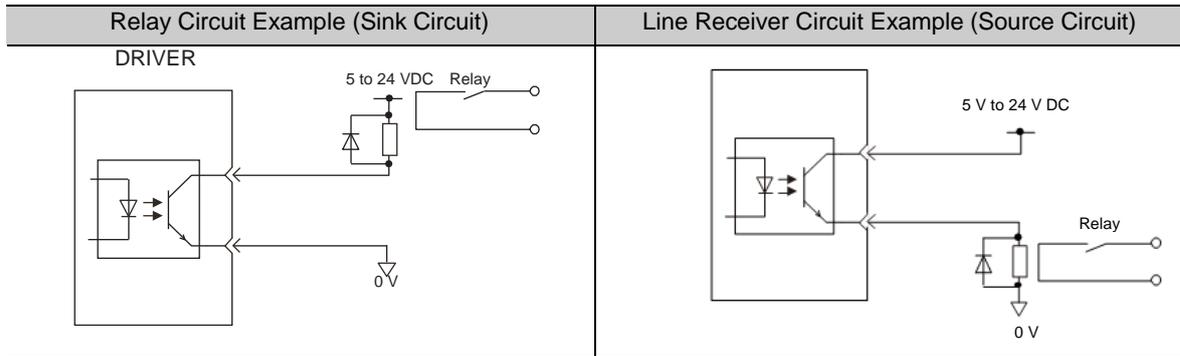


**IMPORTANT**

Incorrect wiring or incorrect voltage application to the output circuit may cause short-circuit. If a short-circuit occurs as a result of any of these causes, the holding lock will not work. This could damage the machine or cause an accident resulting in death or injury.

### (1) Photocoupler Output Circuit

Photocoupler output circuits are used for servo alarm (ALM), servo ready (/S-RDY), and other sequence output signal circuits. Connect a photocoupler output circuit through a relay or line receiver circuit.



Note: The maximum allowable voltage and the allowable range of current capacity for photocoupler output circuits are as follows.

- Voltage: 30 VDC
- Current: 5 to 50 mA DC

Note: The connection example in 2.3 shows sink circuits.

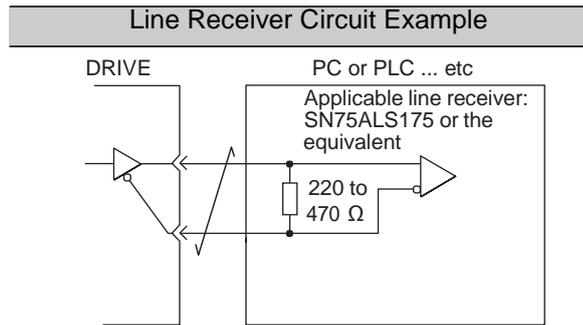
## (2) Line Driver Output Circuit

CN1 connector terminals, 17-18 (phase-A signal), 19-20 (phase-B signal), and 21-22 (phase-Z signal) are explained below.

These terminals output the following signals via the line-driver output circuits.

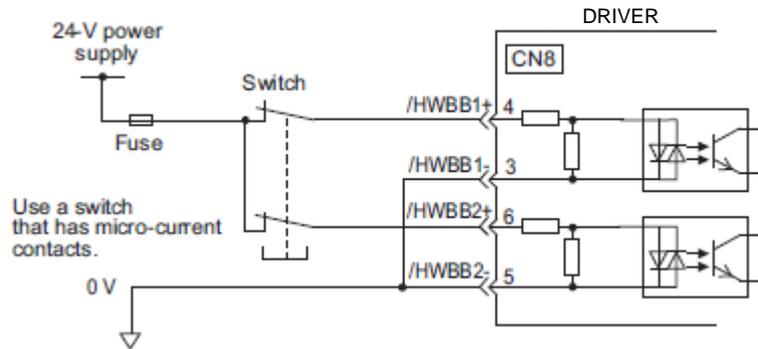
- Output signals for which encoder serial data is converted as two phases pulses (PAO, /PAO, PBO, /PBO)
- Origin pulse signals (PCO, /PCO)

Connect the line-driver output circuit through a line receiver circuit at the PC or PLC ... etc.



## 2.4 Wiring for Safety cable

- (1) Connection Example for input signals  
The input signals must be redundant.



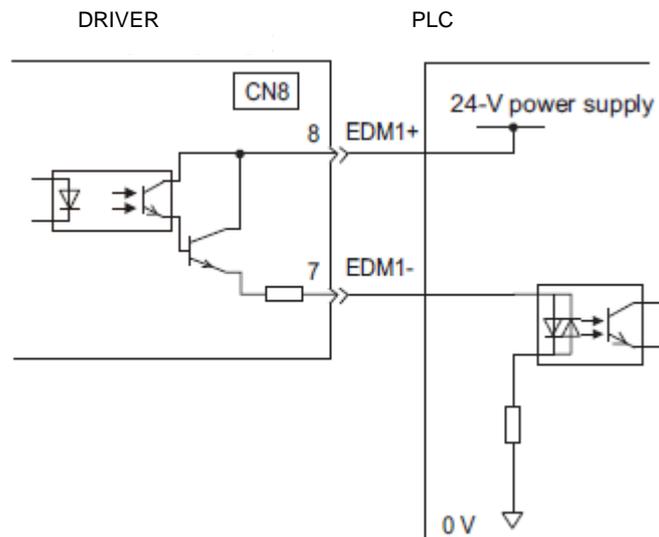
IMPORTANT

For safety function signal connections, the input signal is the 0 V common and the output signal is the source output.

When using the safety function, a safety function device must be connected and the wiring that is necessary to activate the safety function must be done to turn ON the servomotor power. When not using the safety function, use the DRIVER with the Safety Jumper Connector (provided as an accessory) inserted into the CN8.

- (2) Connection Example for output signals

EDM1 output signal is used for source circuit. **It is not able to use the sink output.**



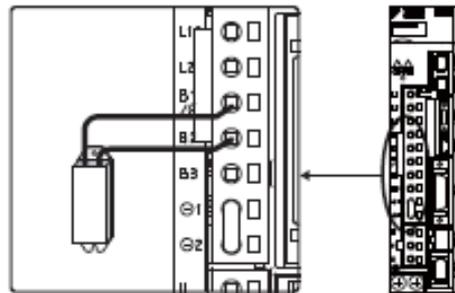
## 2.5 Wiring for external regenerative resistor

Please prepare it in your company when the external regenerative resistor is necessary.  
Refer to the catalog of each actuator for the selection of the external regenerative resistor.

### (1) DRIVERS: Model LECYU2-V5, V7, V8

Connect an external Regenerative resistor between the B1/⊕ and B2 terminals on the DRIVER. After connecting a option, select the capacity. For more information on how to set the capacity of Regenerative resistors, refer to “LECYU Operation Manual (Simplified Edition)”, section 4.6.

Enlarged View

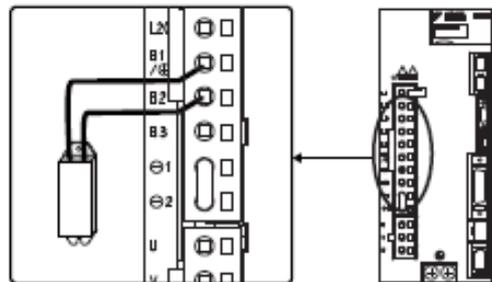


### (2) DRIVER: Model LECYU2-V9

Disconnect the wiring between the DRIVER's B2 and B3 terminals and connect an external Regenerative resistor between the B1/⊕ and B2 terminals. After connecting the option, select the capacity. For more information on how to set the capacity of Regenerative resistors, refer to “LECYU Operation Manual (Simplified Edition)”, section 4.6.

Note: Be sure to take out the lead wire between the B2 and B3 terminals.

Enlarged View

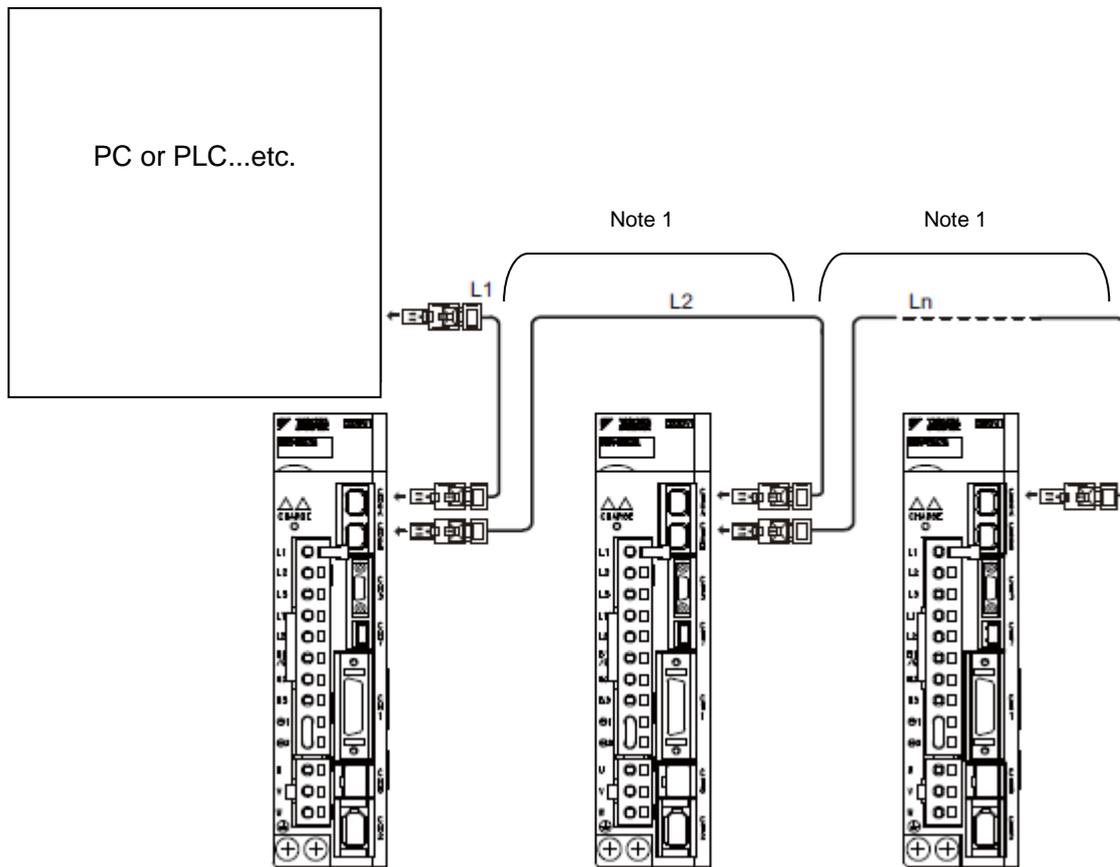


## ⚠ WARNING

Be sure to connect the regenerative resistor correctly. Do not short-circuit between B1/⊕ and B2. Doing so may result in fire or damage to the regenerative resistor or DRIVER.

## 2.6 MECHATROLINK cable wiring

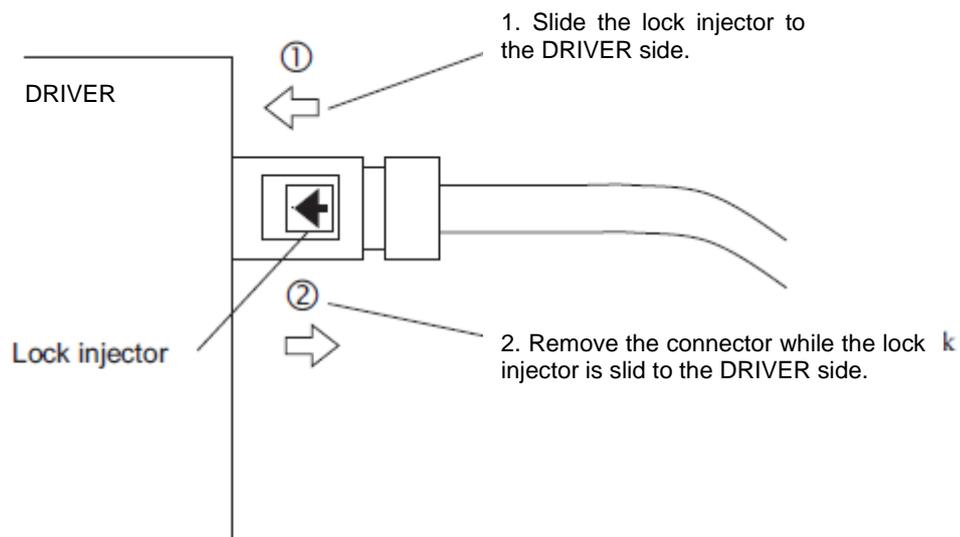
The following diagram shows an example of connections between a PC or PLC...etc and a DRIVER using MECHATROLINK-III communications cables (CN6A, CN6B).



Note 1. The length of the cable between stations (L1, L2 ... Ln) must be 75 m maximum.

For removing the MECHATROLINK-III communications cable connectors from the DRIVER, refer to the following procedure.

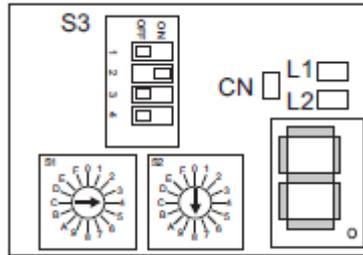
Slide the lock injector of the connector to the DRIVER side to unlock and remove the MECHATROLINK-III communications cable connectors.



Note: The MECHATROLINK-III communications cable connector may be damaged if it is removed without being unlocking.

### 3. Communications Setting

The DIP switch S3 is used to make the settings for MECHATROLINK-III communications.  
The station address is set using the rotary switches S1 and S2.



#### (1) Settings of the Rotary Switches S1 and S2

Set the station address using the rotary switches S1 and S2.

Station Address	S1	S2
00H to 02H: Disabled (Do not use these addresses.)	0	0 to 2
03H (Factory setting)	0	3
04H	0	4
.		
.		
.		
EFH	E	F
F0H to FFH: Disabled (Do not use these addresses.)	F	0 to F

#### (2) Settings of the DIP Switch S3

The following table shows the settings of the DIP switch (S3).

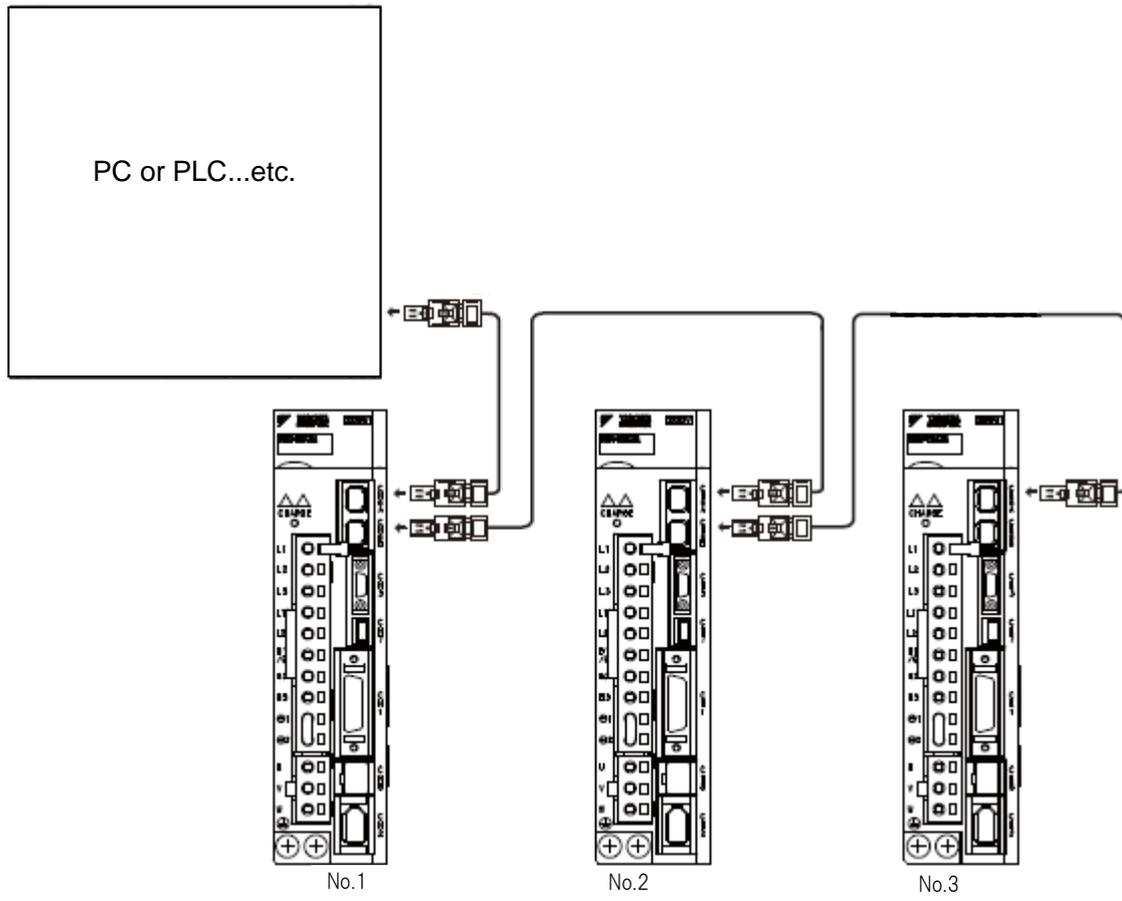
Switch No.	Function	Setting	Description	Factory setting	
Pins 1 and 2	Sets the number of transmission bytes.	1	2	Number of transmission bytes	1: OFF 2: ON
		OFF	OFF	16 byte	
		ON	OFF	32 byte	
		OFF	ON	48 byte	
		ON	ON	Reserved. (Do not change.)	
Pin 3	Reserved. (Do not change.)			OFF	
Pin 4	Reserved. (Do not change.)			OFF	



**IMPORTANT**

- When using the MECHATROLINK-III standard servo profile, set the number of transmission bytes to either 32 or 48.
  - When using the MECHATROLINK-II-compatible profile, set the number of transmission bytes to either 16 or 32.
- Turn the power OFF and then ON again to enable the new settings.

Ex) When you connect three station



Setting the Station Address

	Station Address	S1	S2
No.1	03H	0	3
No.2	04H	0	4
No.3	05H	0	5

## 4. Parameter setting (Driver side)

The setting is a necessary parameter. Please optionally set it. Please refer to "LECYU manual" for a detailed parameter.

Setup software (SigmaWin+) is necessary for the setting of the parameter.

※1 Please download setup software via our website.

※2 Prepare USB cable (LEC-JZ-CVUSB) separately.

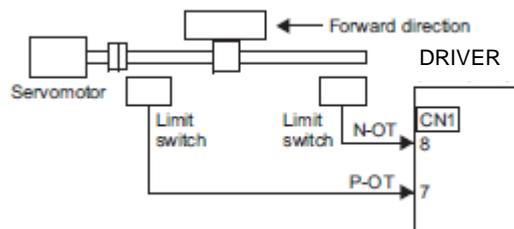
### 4.1 power supply specifications

When using the DRIVER with single-phase, 200 V power input, set parameter Pn00B.2 to 1.

Parameter		Meaning	When Enabled	Classification
Pn00B	n.□0□□ [Factory setting]	Enables use of three-phase power supply for three-phase DRIVER.	After restart	Setup
	n.□1□□	Enables use of single-phase power supply for three-phase DRIVER.		

### 4.2 Overtravel

For machines that move using linear motion, connect limit switches to P-OT and N-OT of CN1 as shown below to prevent machine damage. To prevent a contact fault or disconnection from causing accidents, make sure that the limit switches are normally closed.



Parameters Pn50A and Pn50B can be set to enable or disable the overtravel function.

If the overtravel function is not used, no wiring for overtravel input signals will be required.

Parameter		Meaning	When Enabled	Classification
Pn50A	n.1□□□ [Factory setting]	Inputs the Forward Run Prohibited (P-OT) signal from CN1-7.	After restart	Setup
	n.8□□□	Disables the Forward Run Prohibited (P-OT) signal. Allows constant forward rotation.		
Pn50B	n.□□□2 [Factory setting]	Inputs the Reverse Run Prohibited (N-OT) signal from CN1-8.		
	n.□□□8	Disables the Reverse Run Prohibited (N-OT) signal. Allows constant reverse rotation.		

\*P-OT and N-OT of the factory setting are effective.

Please set it invalidly when you use neither P-OT nor N-OT. (Please set to parameter Pn50A=n.8□□□ and Pn50B=n.□□□8.)

### 4.3 Rotation Direction

The servomotor rotation direction can be reversed with parameter Pn000.0 without changing the polarity of the speed/position reference. This causes the rotation direction of the servomotor to change, but the polarity of the signal, such as encoder output pulses, output from the DRIVER does not change.

Parameter		Forward/ Reverse Reference	Direction of Motor Rotation and Encoder Output Pulse	Applicable Over-travel (OT)
Pn000	n.□□□0 Sets CCW as forward direction. [Factory setting]	Forward Reference		P-OT
		Reverse Reference		N-OT
	n.□□□1 Sets CW as forward direction. (Reverse Rotation Mode)	Forward Reference		P-OT
		Reverse Reference		N-OT

## 4.4 Electronic Gear

It is necessary to set it on the PLC side according to the kind of PLC.

The electronic gear enables the workpiece travel distance per reference unit input from the host PC or PLC...etc. The minimum unit of the position data moving a load is called a reference unit.

Set the electronic gear ratio using Pn20E and Pn210.

Pn20E	Electronic Gear Ratio (Numerator) <span style="float: right;">Position</span>				Classification
	Setting Range	Setting Unit	Factory Setting	When Enabled	
	1 to 1073741824	1	4	After restart	Setup
Pn210	Electronic Gear Ratio (Denominator) <span style="float: right;">Position</span>				Classification
	Setting Range	Setting Unit	Factory Setting	When Enabled	
	1 to 1073741824	1	1	After restart	Setup

$$\begin{aligned} \bullet \text{ Pn20E} &= \frac{M \times P \times (1/1000)}{\text{Actuator lead } L[\text{mm}] \times (n1/n2)} \\ \bullet \text{ Pn210} & \end{aligned}$$

M : Servo motor resolution is 1048576 [Pulse/rev]

P : Travel amount per 1 command pulse [ $\mu\text{m}$ ]

n1/n2 : Pulley ratio \*1

Ex.) To Travel amount per 1 command pulse (P=1 $\mu\text{m}$ ) by actuator lead (L = 6mm) and pulley ratio (n1/n2 = 1/1)

$$\frac{\text{Pn20E}}{\text{Pn210}} = \frac{1048576 \times 1 \times \frac{1}{1000}}{6 \times 1/1}$$

$$\frac{\text{Pn20E}}{\text{Pn210}} = \frac{1048576}{6 \times 1000}$$

$$\frac{\text{Pn20E}}{\text{Pn210}} = \frac{1048576}{6000}$$

$$\frac{\text{Pn20E}}{\text{Pn210}} = \frac{65536}{375}$$

\*1 For pulley ratio, refer to Lead of "LECYU Operation Manual (Simplified Edition)", section 4.4.1. The actuator not described for pulley ratio is calculated by "1/1".



**IMPORTANT**

Electronic gear ratio setting range:  $0.001 \leq \text{Electronic gear ratio (B/A)} \leq 4000$   
If the electronic gear ratio is outside this range, a parameter setting error 1 (A.040) will be output.

#### 4.4.1 List of the electronic gear setting for each actuator

The recommended the electronic gear for each actuator.  
Please change the electronic gear by use of the customer.

Series		Lead symbol	Lead (Including pulley ratio)	Pn20E	Pn210
LEY	LEY25/LEYG25 LEY25D/LEYG25D	A	12	65536	750
		B	6		375
		C	3	131072	375
	LEY32/LEYG32 LEY63D	A	20	65536	1250
		B	10		625
		C	5	131072	625
	LEY32D/LEYG32D	A	16	65536	1000
		B	8		500
		C	4		250
	LEY63	A	20		1250
		B	10		625
		C	5		131072
L		5(2.86) (Pulley ratio 4/7)	229376	625	
LEF	LEFS25	H	20	65536	1250
		A	12		750
		B	6		375
	LEFS32	H	24		1500
		A	16		1000
		B	8		500
	LEFS40	H	30		1875
		A	20		1250
		B	10		625
	LEFB25	S	54		3375
	LEFB32	S			
	LEFB40	S			
LEJ	LEJB40	T	27	131072	3375
	LEJB63	T	42	65536	2625
	LEJS40	H	24		1500
		A	16		1000
		B	8		500
	LEJS63	H	30		1875
		A	20		1250
		B	10		625

\*The travel distance of the actuator per 1 pulse should be 1 [ $\mu\text{m}/\text{pulse}$ ].

## 4.5 Positioning Completed Width

This signal indicates that servomotor movement has been completed during position control.

When the difference between the number of references output by the host PC or PLC...etc and the travel distance of the servomotor (position error) drops below the set value in the parameter, the positioning completion signal will be output.

Note: Use parameter Pn50E.0 to allocate the /COIN signal for use. Refer to the operation manual for Refer to "LECYM Operation Manual", section 3.3.

Pn522	Positioning Completed Width			Position	Classification
	Setting Range	Setting Unit	Factory Setting	When Enabled	
	0 to 1073741824	1 reference unit	7	Immediately	Setup

The positioning completed width setting has no effect on final positioning accuracy.

Note: If the parameter is set to a value that is too large, a positioning completed signal might be output if the position error is low during a low speed operation. This will cause the positioning completed signal to be output continuously. If this signal is output unexpectedly, reduce the set value until it is no longer output.

## 4.6 Regenerative Resistor

Please prepare it in your company when the external regenerative resistor is necessary. Refer to the catalog of each actuator for the selection of the external regenerative resistor.

When using an external Regenerative resistor, set the Pn600 so that the Regenerative resistor capacity is equivalent to the resistor capacity.

	<b>WARNING</b>
<p>If parameter Pn600 is set to 0 while an external Regenerative resistor is connected, the regenerative over-load alarm (A.320) may not be detected. If the regenerative overload alarm (A.320) is not detected correctly, the external Regenerative resistor may be damaged and an injury or fire may result.</p>	

Pn600	Regenerative resistor Capacity			<input type="checkbox"/> Speed	<input type="checkbox"/> Position	<input type="checkbox"/> Torque	Classification
	Setting Range	Unit	Factory Setting	When Enabled			
	0 to DRIVER capacity	10 W	0	Immediately		Setup	

Be sure to set the Regenerative resistor capacity (Pn600) to a value that is in accordance with the allowable capacity of the actual external Regenerative resistor being used.

The setting will vary with the cooling method of external Regenerative resistor:

For natural convection cooling: Set the value to a maximum 20% of the actually installed regenerative option capacity (W).

For forced convection cooling: Set the value to a maximum 50% of the actually installed regenerative option capacity (W).

Example: Set 20 W ( $100 \text{ W} \times 20\%$ ) for the 100-W external Regenerative resistor with natural convection cooling method:  
 $\text{Pn600} = 2$  (unit: 10 W)

- Note 1. If Pn600 is not set to the optimum value, alarm A.320 will occur
2. When set to the factory setting ( $\text{Pn600} = 0$ ), the DRIVER's built-in option has been used.



IMPORTANT

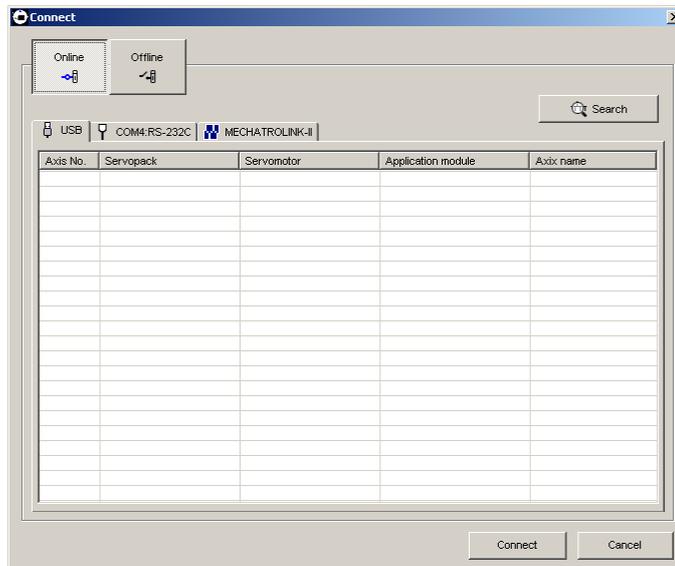
- When the external Regenerative resistors for power are used at the rated load ratio, the resistor temperature increases to between 200 °C and 300 °C. The resistors must be used at or below the rated values. Check with the manufacturer for the resistor's load characteristics.  
For safety, use the external Regenerative resistors with thermostiches.

## 5. Trial Operation (SigmaWin+)

The procedure of the test driving with setup software (SigmaWin+) is shown below. When use the setup software (SigmaWin+), order USB cable (LEC-JZ-CVUSB) separately.

### 5.1 Communications setting for PC

When SigmaWin+ is initially started, the Connect dialog box appears. Enter the settings for communications between SigmaWin+ and the DRIVER by means of a communication port.

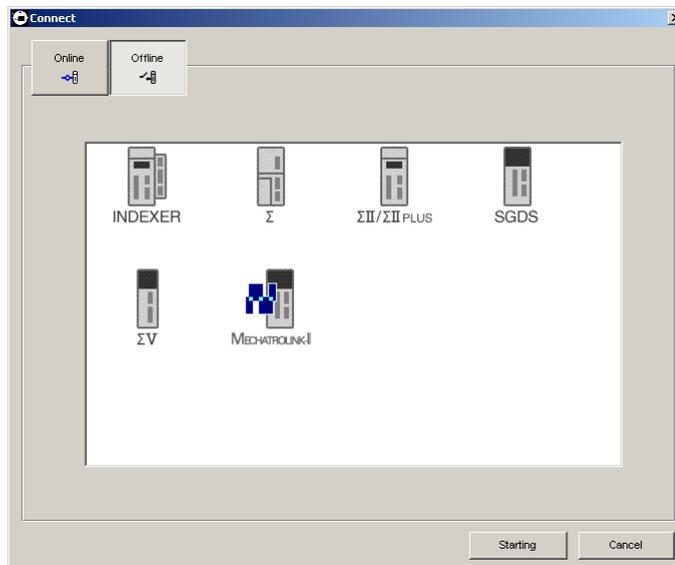


Select the method to set up the DRIVER: online or offline. Online is the default setting.

#### <When Offline is selected>

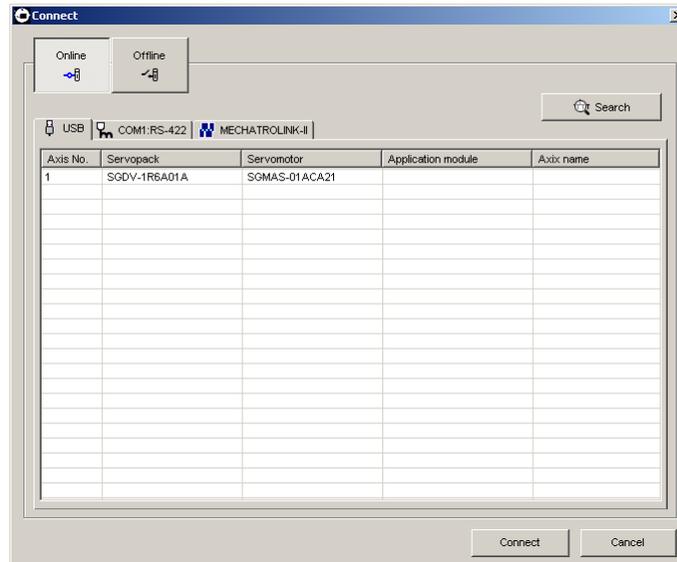
Online: Select when setting up or tuning the servo drive with the DRIVER connected

Offline: Select when editing parameters or checking screens for tracing or mechanical analysis without the DRIVER connected



Select the DRIVER series and click **Starting**. The SigmaWin+ main window will appear.





DRIVER Selection Box

3. Select the DRIVER to be connected and then click **Connect**, or just double-click the DRIVER to be connected. The SigmaWin+ main window will appear.  
Click **Cancel** to close the dialog box.

## 5.2 JOG Operation

This function turns the motor at the set JOG speed. The rotational direction and the speed setting can be verified without connecting a PC or PLC etc.

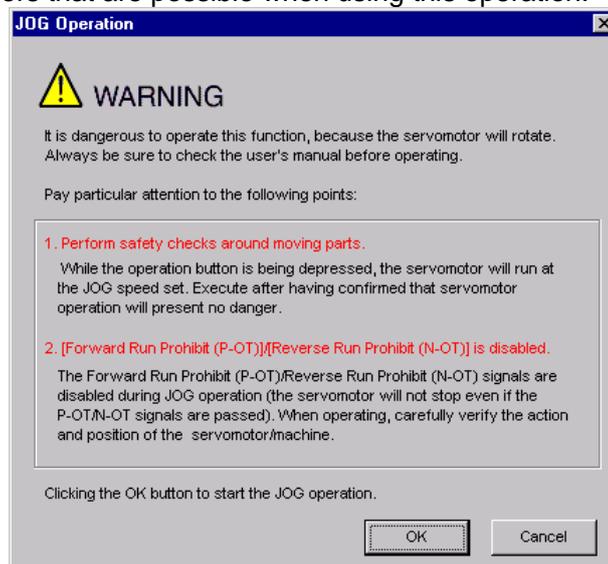
### ! WARNING

Performing JOG operation while the motor is running is dangerous. Be sure to check the user's manual before executing. Pay particular attention to the following.

- Check the safety of the area adjoining the drive unit. The motor runs at the JOG speed, while the Forward or Reverse button is pressed. Make sure that there is no danger in running the motor before execution.
- The Forward Run Prohibit (P-OT) and Reverse Run Prohibit (N-OT) signals are disabled during JOG operation. During operation, make sure to verify the actual operation and position of the motor or machine.

Perform a JOG operation using the following procedure.

1. In the SigmaWin+ main window, click **Test Run**, and then click **Jog**. A warning message appears reminding you of the dangers that are possible when using this operation.



Click **Cancel** to return to the main window without performing JOG operation.

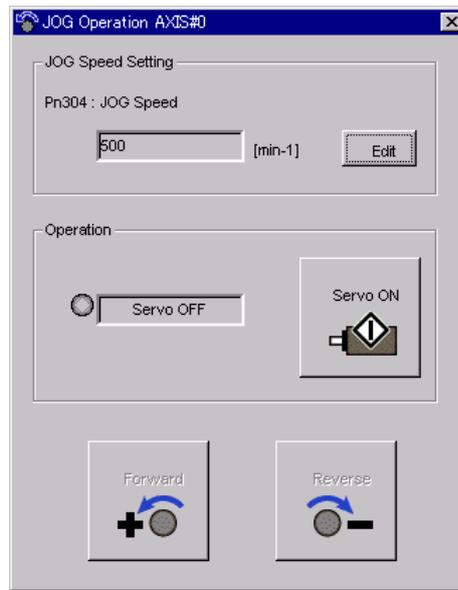
<When the Write Prohibited Setting is ON>

If the write prohibited setting is ON, the following message will appear.



Click **OK**, and set the write prohibited setting to OFF. Refer to “LECYU Operation Manual”, Section 6.12 for details.

2. Click **OK**, and the JOG Operation box appears. If the servo is on, an error message will appear. Make sure that the servo is off.



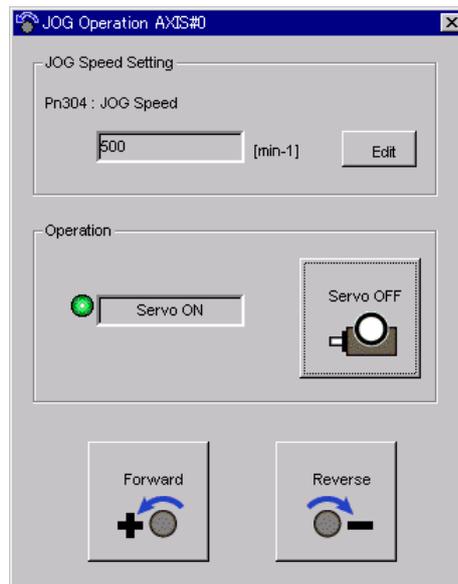
### Pn304: JOG Speed

Parameter Pn304 displays the JOG speed. Click **Edit** to change the JOG speed.

### Operation

On the left, shows if the servo is on or off and the corresponding LED display. On the right, the button changes according to the servo's status. When the servo is off, the **Servo ON** button appears; when the servo is on, **Servo OFF** button appears.

3. Check the JOG speed. To change the JOG speed, click **Edit**.
4. Click **Servo ON**.



5. Press **Forward** or **Reverse**. A JOG operation is performed only while one of these buttons is pressed.

### 5.3 Program JOG Operation

This function allows automatic operation determined by the preset pattern of operation.

#### WARNING

Using the program JOG operation function while the motor is running is dangerous. Be sure to check the user's manual before using this function. Pay particular attention to the following items.

- Check the safety of the area adjoining the drive unit. The motor actually runs based on a preset pattern when this function is used. Make sure that there is no danger in running the motor before actually using it.
- Confirm the position of the machine. Reset the machine position using the Origin Return function before using the program JOG function.

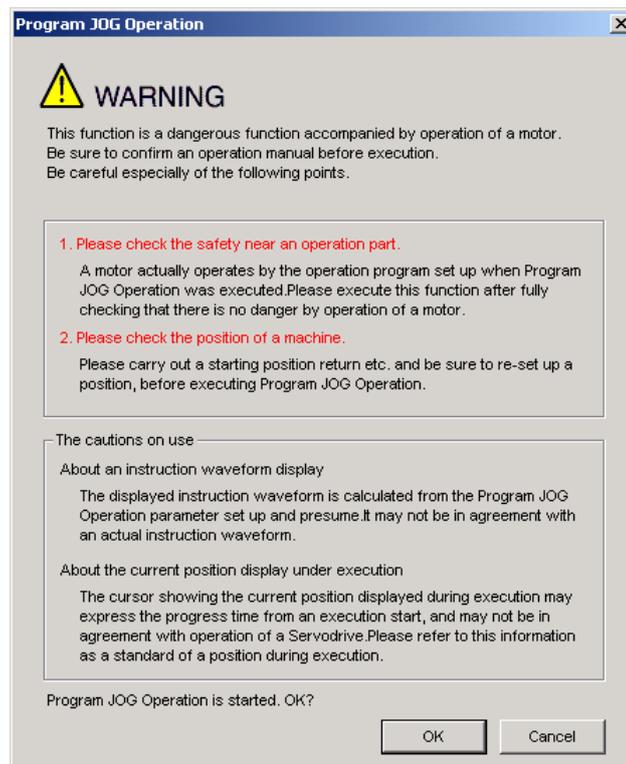
#### CAUTION

Two methods are available to stop program JOG operation while the motor is running, and the motor will stop according to the method selected. Make sure to select the best method for the situation.

- If the Servo OFF button is used, the motor stops according to the stopping method after servo off specified by the parameters.
  - If the Cancel button is used, the motor coasts to a stop and then enters a zero clamp state.
- Note: The Cancel button may not be used with some DRIVERS.

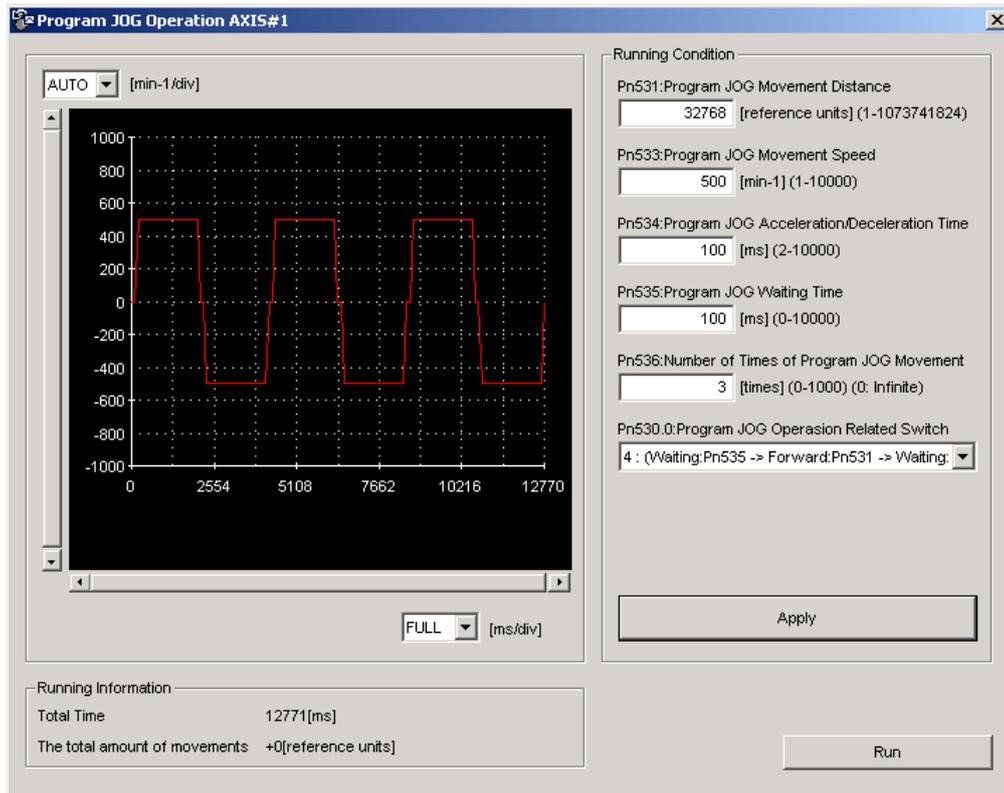
To perform the JOG operation for a particular pattern, use the following procedure.

1. In the SigmaWin+ main window, click **Test Run** and then click **Program JOG Operation**. A warning message appears, reminding you of the possible dangers.

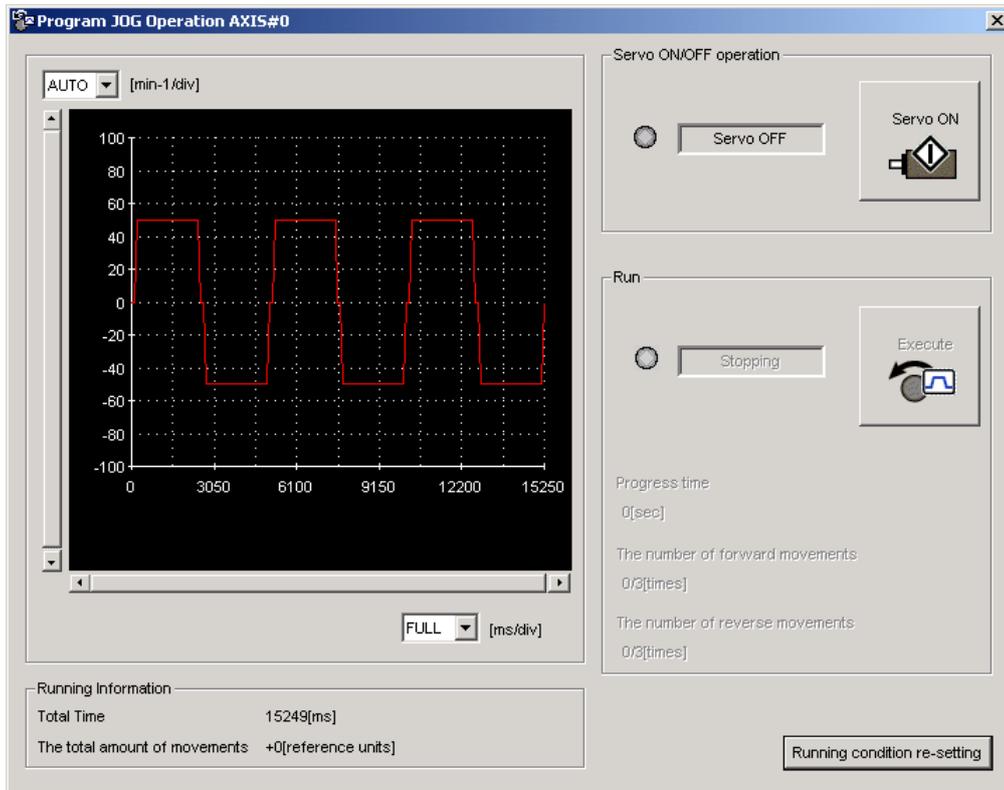


Click **Cancel** to return to the main window without performing program JOG operation.

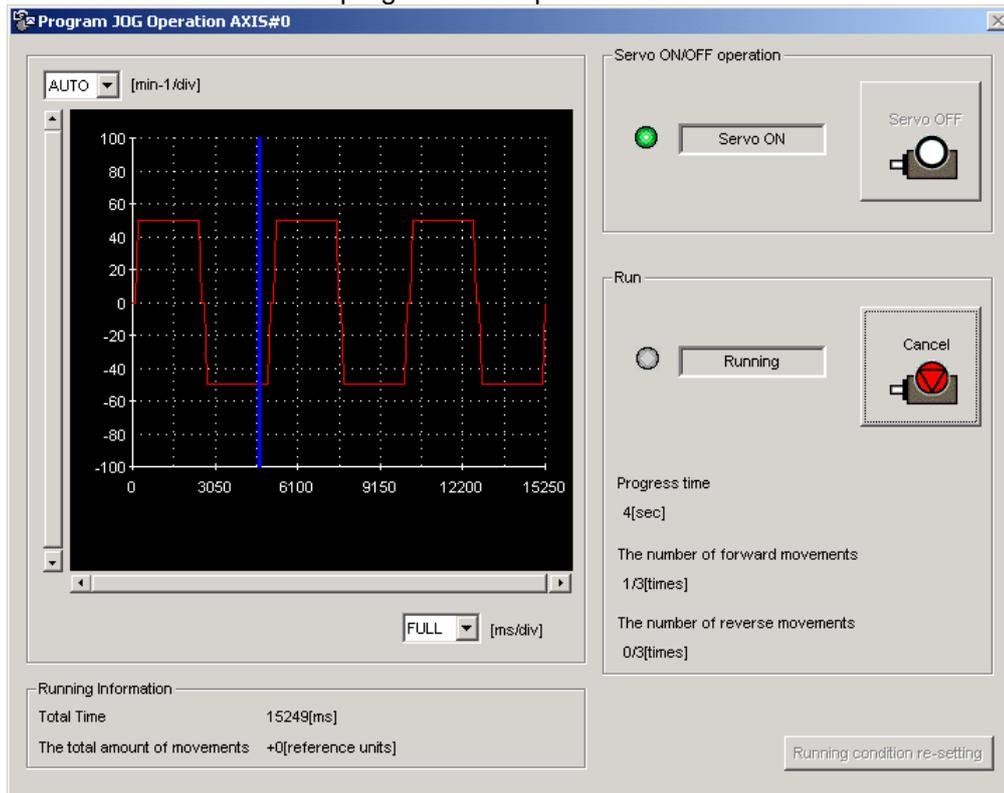
2. Click **OK**, and the Running Condition Setting box appears.



3. Set the running conditions and click **Apply**. The graph for the operation pattern is displayed.
4. Click **Run** and the Program JOG Operation box appears.



5. Click **Servo ON** and **Execute**. The program JOG operation starts.



## 6. The recommended the parameter for each actuator

The recommended the parameter for each actuator. Please change the parameter values by use of the customer. A mechanical resonance may occur depending on the configuration or the mounting orientation of the transferred object. Please change the parameter in the initial setting.

Refer to “LECYU Operation Manual”, Section 4 and Section 5 and Section 10 for details.

### 6.1 The recommended value of the parameter [LEF]

Series			LEFS25			LEFS32			LEFS40		
	Lead symbol		H	A	B	H	A	B	H	A	B
	Lead		20	12	6	24	16	8	30	20	10
Parameter *1,*2	Para. No	Initial value	Recommended value								
Servomotor Rotation Direction can	Pn000	0000	<b>0001</b> (+: Counter motors side)								
Tuning-less Function Related Switch	Pn170	1401	1401								
Electronic Gear Ratio (Numerator) *1	Pn20E	4	<b>65536</b>								
Electronic Gear Ratio (Denominator) *3	Pn210	1	<b>1250</b>	<b>750</b>	<b>375</b>	<b>1500</b>	<b>1000</b>	<b>500</b>	<b>1875</b>	<b>1250</b>	<b>625</b>

Series			LEFS25(L,R)			LEFS32(L,R)			LEFS40(L,R)		
	Lead symbol		H	A	B	H	A	B	H	A	B
	Lead		20	12	6	24	16	8	30	20	10
Parameter *1,*2	Para. No	Initial value	Recommended value								
Servomotor Rotation Direction can	Pn000	0000	0000 (+: Counter motors side)								
Tuning-less Function Related Switch	Pn170	1401	1401								
Electronic Gear Ratio (Numerator) *1	Pn20E	4	<b>65536</b>								
Electronic Gear Ratio (Denominator) *3	Pn210	1	<b>1250</b>	<b>750</b>	<b>375</b>	<b>1500</b>	<b>1000</b>	<b>500</b>	<b>1875</b>	<b>1250</b>	<b>625</b>

Series			LEFB25	LEFB25U	LEFB32	LEFB32U	LEFB40	LEFB40U
	Lead symbol		S					
	Lead		54					
Parameter *1,*2	Para. No	Initial value	Recommended value					
Servomotor Rotation Direction can	Pn000	0000	<b>0001</b> (+: Counter motors side)	0000 (+: Counter motors side)	<b>0001</b> (+: Counter motors side)	0000 (+: Counter motors side)	<b>0001</b> (+: Counter motors side)	0000 (+: Counter motors side)
Tuning-less Function Related Switch	Pn170	1401	1401				<b>2301</b>	
Electronic Gear Ratio (Numerator) *1	Pn20E	4	<b>65536</b>					
Electronic Gear Ratio (Denominator) *3	Pn210	1	<b>3375</b>					

: Different from the initial value.

\*1. Parameter is set to the recommended value. Please set parameter according to customer application.

- \*2. Mechanical resonance may occur depending on the shape or mounting orientation of the work piece. Please change this parameter during initial configuration.  
(Parameter initial configuration ⇒ Set the recommended parameter value ⇒ Operation start)
- \*3. The minimum unit of the travel distance of the actuator should be 1 [μm]. It is necessary to set it on the PLC side according to the kind of PLC.

## 6.2 The recommended value of the parameter [LEJ]

Series				LEJS40			LEJS63			LEJB40	LEJB63
	Lead symbol		H	A	B	H	A	B	T		
	Lead		24	16	8	30	20	10	27	42	
Parameter *1,*2	Para. No	Initial value	Recommended value								
Servomotor Rotation Direction can	Pn000	0000	<b>0001</b> (+ : Counter motors side )						0000 (+ : Counter motors side)		
Tuning-less Function Related Switch	Pn170	1401	1401								
Electronic Gear Ratio (Numerator) *1	Pn20E	4	<b>65536</b>						<b>131072</b>	<b>65536</b>	
Electronic Gear Ratio (Denominator) *3	Pn210	1	<b>1500</b>	<b>1000</b>	<b>500</b>	<b>1875</b>	<b>1250</b>	<b>625</b>	<b>3375</b>	<b>2625</b>	

 : Different from the initial value.

- \*1. Parameter is set to the recommended value. Please set parameter according to customer application.
- \*2. Mechanical resonance may occur depending on the shape or mounting orientation of the work piece. Please change this parameter during initial configuration.  
(Parameter initial configuration ⇒ Set the recommended parameter value ⇒ Operation start)
- \*3. The minimum unit of the travel distance of the actuator should be 1 [μm]. It is necessary to set it on the PLC side according to the kind of PLC.

### 6.3 The recommended value of the parameter [LEY]

Series	LEY25/ LEYG25			LEY25D/ LEYG25D			LEY32/LEYG32			LEY32D/ LEYG32D					
	Lead symbol			A	B	C	A	B	C	A	B	C	A	B	C
	Lead			12	6	3	12	6	3	20	10	5	16	8	4
Parameter *1,*2	Para. No	Initial value	Recommended value												
Servomotor Rotation Direction can *4	Pn000	0000	0000 (+: Counter motors side)			<b>0001</b> (+: Counter motors side)			0000 (+: Counter motors side)			<b>0001</b> (+: Counter motors side)			
Tuning-less Function Related Switch	Pn170	1401	1401												
Electronic Gear Ratio (Numerator) *3	Pn20E	4	<b>65536</b>		131072	<b>65536</b>		131072	<b>65536</b>		131072	<b>65536</b>			
Electronic Gear Ratio (Denominator) *3	Pn210	1	<b>750</b>	<b>375</b>	<b>375</b>	<b>750</b>	<b>375</b>	<b>375</b>	<b>125</b> <b>0</b>	<b>625</b>	<b>62</b> <b>5</b>	<b>100</b> <b>0</b>	<b>500</b>	<b>250</b>	

Series	LEY63						LEY63D					
	Lead symbol						A	B	C	A	B	C
	Lead (Including pulley ratio)						20	10	5	5(2.86) (Pulley ratio 4/7)	20	10
Parameter *1,*2	Para. No	Initial value	Recommended value									
Servomotor Rotation Direction can *4	Pn000	0000	0000 (+: Counter motors side)				<b>0001</b> (+: Counter motors side)					
Tuning-less Function Related Switch	Pn170	1401	1401									
Electronic Gear Ratio (Numerator) *3	Pn20E	4	<b>65536</b>			<b>131072</b>	<b>229376</b>	<b>65536</b>		<b>131072</b>		
Electronic Gear Ratio (Denominator) *3	Pn210	1	<b>1250</b>	<b>625</b>	<b>625</b>	<b>625</b>	<b>1250</b>	<b>625</b>	<b>625</b>			

 : Different from the initial value.

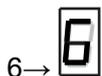
- \*1. Parameter is set to the recommended value. Please set parameter according to customer application.
- \*2. Mechanical resonance may occur depending on the shape or mounting orientation of the work piece. Please change this parameter during initial configuration.  
(Parameter initial configuration ⇒ Set the recommended parameter value ⇒ Operation start)
- \*3. The minimum unit of the travel distance of the actuator should be 1 [μm]. It is necessary to set it on the PLC side according to the kind of PLC.
- \*4. When the motor mounting position is right side parallel (LEFS\*R) or left side parallel (LEFS\*L), the rotation direction selection is 0(+: Counter motors side).

## 7. Troubleshooting

When a fault occurs during operation, the corresponding alarm or warning is displayed. If an alarm or warning occurs, refer to "LECYM Operation Manual", section 9.1.2 or "LECYM Operation Manual", section 9.2.2 and take the appropriate action. When an alarm occurs, ALM turns off.

After removing the cause of the alarm or warning, the alarm or warning can be deactivated in any of the methods marked in the alarm / warning deactivation column.

"6" of the figure, "B" of the alphabet, and "D" are displayed as follows.



### 7.1 Alarms List

This section provides list of alarms.

After its cause has been removed, the alarm can be deactivated in any of the methods marked  in the alarm reset column.

	Alarm Number	Alarm Name	Servo motor Stop ping Method*1	Alarm reset			
				Power OFF ↓ ON	Alarm warning clear command [ALM-CLR]	SigmaWin+ [Alarm]   [Display Alarm]   Reset button	SigmaWin+ [Setup]   [Software Reset]   Execute button
Alarm	A.020	Parameter Checksum Error 1	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.021	Parameter Format Error 1	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.022	System Checksum Error 1	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.030	Main Circuit Detector Error	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.040	Parameter Setting Error 1	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.041	Encoder Output Pulse Setting Error	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.042	Parameter Combination Error	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.044	Semi-closed/Fully-closed Loop Control Parameter Setting Error	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.04A	Parameter Setting Error 2	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.050	Combination Error	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.051	Unsupported Device Alarm	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.0B0	Cancelled Servo ON Command Alarm	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.100	Overcurrent or Heat Sink Overheated	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.300	Regeneration Error	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.320	Regenerative Overload	Gr.2	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.330	Main Circuit Power Supply Wiring Error	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.400	Overvoltage	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.410	Undervoltage	Gr.2	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.450	Main-Circuit Capacitor Overvoltage	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.510	Overspeed	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.511	Overspeed of Encoder Output Pulse Rate	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.520	Vibration Alarm	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.521	Autotuning Alarm	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.710	Overload: High Load	Gr.2	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.720	Overload: Low Load	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.730	Dynamic Brake Overload	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.731	Overload of Surge Current Limit Resistor	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.740	Heat Sink Overheated	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.7A0	Built-in Fan in DRIVER Stopped	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.7AB	Encoder Backup Error	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>
	A.810	Encoder Checksum Error	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
	A.820	Absolute Encoder Battery Error	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>
A.830	Encoder Data Error	Gr.1	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	<input type="radio"/>	
A.840	Encoder Overspeed	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>	
A.850	Encoder Overheated	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>	
A.860	External Encoder Error	Gr.1	<input type="radio"/>	-	-	<input type="radio"/>	

(cont'd)

	Alarm Number	Alarm Name	Servo motor Stop ping Method*1	Alarm reset			
				Power OFF ↓ ON	Alarm warning clear command [ALM-CLR]	SigmaWin+ [Alarm]   [Display Alarm]   Reset button	SigmaWin+ [Setup]   [Software Reset]   Execute button
Alarm	A.8A0	External Encoder Error of Module	Gr.1	○	○	○	○
	A.8A1	External Encoder Error of Sensor	Gr.1	○	○	○	○
	A.8A2	External Encoder Error of Position	Gr.1	○	○	○	○
	A.8A3	External Encoder Overspeed	Gr.1	○	○	○	○
	A.8A5	External Encoder Overheated	Gr.1	○	○	○	○
	A.8A6	Regeneration Error	Gr.1	○	○	○	○
	A.B31	Current Detection Error 1	Gr.1	○	-	-	○
	A.B32	Current Detection Error 2	Gr.1	○	-	-	○
	A.B33	Current Detection Error 3	Gr.1	○	-	-	○
	A.B6A	MECHATROLINK Communications ASIC Error 1	Gr.1	○	-	-	○
	A.B6B	MECHATROLINK Communications ASIC Error 2	Gr.2	○	-	-	○
	A.BF0	System Alarm 0	Gr.1	○	-	-	○
	A.BF1	System Alarm 1	Gr.1	○	-	-	○
	A.BF2	System Alarm 2	Gr.1	○	-	-	○
	A.BF3	System Alarm 3	Gr.1	○	-	-	○
	A.BF4	System Alarm 4	Gr.1	○	-	-	○
	A.C10	Servo Overrun Detected	Gr.1	○	○	○	○
	A.C80	Absolute Encoder Clear Error and Multiturn Limit Setting Error	Gr.1	○	-	-	○
	A.C90	Encoder Communications Error	Gr.1	○	-	-	○
	A.C91	Encoder Communications Position Data Error	Gr.1	○	-	-	○
	A.C92	Encoder Communications Timer Error	Gr.1	○	-	-	○
	A.CA0	Encoder Parameter Error	Gr.1	○	-	-	○
	A.CB0	Encoder Echoback Error	Gr.1	○	-	-	○
	A.CC0	Multiturn Limit Disagreement	Gr.1	○	-	-	○
	A.CF1	Feedback Option Module Communications Error (Reception error)	Gr.1	○	-	-	○
	A.CF2	Feedback Option Module Communications Error (Timer stop)	Gr.1	○	-	-	○
	A.D00	Position Error Overflow	Gr.1	○	○	○	○
	A.D01	Position Error Overflow Alarm at Servo ON	Gr.1	○	○	○	○
	A.D02	Position Error Overflow Alarm by Speed Limit at Servo ON	Gr.2	○	○	○	○
	A.D10	Motor-load Position Error Overflow	Gr.2	○	○	○	○
	A.E02	MECHATROLINK Internal Synchronization Error 1	Gr.1	○	○	○	○
	A.E40	MECHATROLINK Transmission Cycle Setting Error	Gr.2	○	○	○	○
	A.E41	MECHATROLINK Communications Data Size Setting Error	Gr.2	○	○	○	○
	A.E42	MECHATROLINK Station Address Setting Error	Gr.2	○	-	-	○
	A.E50	MECHATROLINK Synchronization Error	Gr.2	○	○	○	○
	A.E51	MECHATROLINK Synchronization Failed	Gr.2	○	○	○	○
	A.E60	MECHATROLINK Communications Error (Reception error)	Gr.2	○	○	○	○
	A.E61	MECHATROLINK Transmission Cycle Error (Synchronization interval error)	Gr.2	○	○	○	○
	A.E62	MECHATROLINK Communications Error (FCS error)	Gr.2	○	○	○	○
	A.E63	MECHATROLINK Synchronization Frame Not Received Alarm	Gr.2	○	○	○	○
A.E71	Safety Option Module Detection Failure	Gr.1	○	-	-	○	
A.E72	Feedback Option Module Detection Failure	Gr.1	○	-	-	○	
A.E74	Unsupported Safety Option Module	Gr.1	○	-	-	○	
A.E75	Unsupported Feedback Option Module	Gr.1	○	-	-	○	
A.EA2	DRV Alarm 2 (DRIVER WDC error)	Gr.2	○	○	○	○	
A.EB1	Safety Function Signal Input Timing Error	Gr.1	○	-	-	○	
A.ED1	Command Execution Timeout	Gr.2	○	○	○	○	
A.F10	Main Circuit Cable Open Phase	Gr.2	○	○	○	○	

(cont'd)

	Alarm Number	Alarm Name	Servo motor Stop ping Method*1	Alarm reset			
				Power OFF ↓ ON	Alarm warning clear command [ALM-CLR]	SigmaWin+ [Alarm]   [Display Alarm]   Reset button	SigmaWin+ [Setup]   [Software Reset]   Execute button
Alarm	FL-1*2	System Alarm	-	○	-	-	-
	FL-2*2		-	○	-	-	-
	CPF00	Digital Operator Transmission Error 1	-	○	-	-	-
	CPF01	Digital Operator Transmission Error 2	-	○	-	-	-
	A.--	Not an error	-	-	-	-	-

\*1 Gr.1: The servomotor is stopped according to the setting in Pn001.0 if an alarm occurs. Pn001.0 is factory-set to stop the servomotor by applying the DB.

Gr.2: The servomotor is stopped according to the setting in Pn00B.1 if an alarm occurs. Pn00B.1 is factory-set to stop the servomotor by setting the speed reference to "0." The servomotor under torque control will always use the Gr.1 method to stop. By setting Pn00B.1 to 1, the servomotor stops using the same method as Gr.1. When coordinating a number of servomotors, use this stopping method to prevent machine damage that may result due to differences in the stop method.

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

## 7.2 WarningAlarms List

This section provides list of warnings.

After its cause has been removed, the warning can be deactivated in any of the methods marked ○ in the warning reset column.

(1) Commands for the MECHATROLINK-III standard servo profile

	Warning Number	Warning Name	Warning reset				
			Automatically <sup>*6</sup>	Power OFF ↓ ON	Alarm warning clear command [ALM-CLR]	SigmaWin+ [Alarm]   [Display Alarm]   Reset button	SigmaWin+ [Setup]   [Software Reset]   Execute button
Warning	A.900 <sup>*3</sup>	Position Error Overflow	-	○	○	○	○
	A.901 <sup>*3</sup>	Position Error Overflow Alarm at Servo ON	-	○	○	○	○
	A.910 <sup>*3</sup>	Overload	-	○	○	○	○
	A.911 <sup>*3</sup>	Vibration	-	○	○	○	○
	A.920 <sup>*3</sup>	Regenerative Overload	-	○	○	○	○
	A.921 <sup>*3</sup>	Dynamic Brake Overload	-	○	○	○	○
	A.930 <sup>*3</sup>	Absolute Encoder Battery Error	-	○	○	○	○
	A.94A <sup>*4</sup>	Data Setting Warning 1 (Parameter Number Error)	○	○	○	○	○
	A.94B <sup>*4</sup>	Data Setting Warning 2 (Out of Range)	○	○	○	○	○
	A.94C <sup>*4</sup>	Data Setting Warning 3 (Calculation Error)	○	○	○	○	○
	A.94D <sup>*4</sup>	Data Setting Warning 4 (Parameter Size)	○	○	○	○	○
	A.94E <sup>*4</sup>	Data Setting Warning 5 (Latch Mode Error)	-	○	○	○	○
	A.95A <sup>*4</sup>	Command Warning 1 (Unsatisfying Command)	○	○	○	○	○
	A.95B <sup>*4</sup>	Command Warning 2 (Non-supported Command)	○	○	○	○	○
	A.95D <sup>*4</sup>	Command Warning 4 (Command Interference)	○	○	○	○	○
	A.95E <sup>*4</sup>	Command Warning 5 (Subcommand Disable)	○	○	○	○	○
	A.95F <sup>*4</sup>	Command Warning 6 (Undefined Command)	○	○	○	○	○
	A.960 <sup>*4</sup>	MECHATROLINK Communications Warning	-	○	○	○	○
	A.962 <sup>*4</sup>	MECHATROLINK Communications Warning (FCS Error)	-	○	○	○	○
	A.963 <sup>*4</sup>	MECHATROLINK Communications Warning (Synchronization Frame Not Received)	-	○	○	○	○
A.971 <sup>*5</sup>	Undervoltage	-	○	○	○	○	
A.97A <sup>*4</sup>	Command Warning 7 (Phase Error)	○	○	○	○	○	
A.97B <sup>*4</sup>	Data Clamp (Out of Range)	○	○	○	○	○	
A.9A0 <sup>*3</sup>	Overtravel	-	○	○	○	○	

\*3. Use Pn008.2 to activate or not the warning detection.

\*4. Use Pn800.1 to activate or not the warning detection.

\*5. Use Pn008.1 to activate or not the warning detection.

\*6. If using the commands for the MECHATROLINK-III standard servo profile, the warning will automatically be cleared after the correct command is received.

(2) Commands for the MECHATROLINK-II-compatible profile

	Warning Number	Warning Name	Warning reset			
			Power OFF ↓ ON	Alarm warning clear command [ALM-CLR]	SigmaWin+ [Alarm]   [Display Alarm]   Reset button	SigmaWin+ [Setup]   [Software Reset]   Execute button
Warning	A.900 <sup>*3</sup>	Position Error Overflow	○	○	○	○
	A.901 <sup>*3</sup>	Position Error Overflow Alarm at Servo ON	○	○	○	○
	A.910 <sup>*3</sup>	Overload	○	○	○	○
	A.911 <sup>*3</sup>	Vibration	○	○	○	○
	A.920 <sup>*3</sup>	Regenerative Overload	○	○	○	○
	A.921 <sup>*3</sup>	Dynamic Brake Overload	○	○	○	○
	A.930 <sup>*3</sup>	Absolute Encoder Battery Error	○	○	○	○
	A.94A <sup>*4</sup>	Data Setting Warning 1 (Parameter Number Error)	○	○	○	○
	A.94B <sup>*4</sup>	Data Setting Warning 2 (Out of Range)	○	○	○	○
	A.94C <sup>*4</sup>	Data Setting Warning 3 (Calculation Error)	○	○	○	○
	A.94D <sup>*4</sup>	Data Setting Warning 4 (Parameter Size)	○	○	○	○
	A.94E <sup>*4</sup>	Data Setting Warning 5 (Latch Mode Error)	○	○	○	○
	A.95A <sup>*4</sup>	Command Warning 1 (Unsatisfying Command)	○	○	○	○
	A.95B <sup>*4</sup>	Command Warning 2 (Non-supported Command)	○	○	○	○
	A.95D <sup>*4</sup>	Command Warning 4 (Command Interference)	○	○	○	○
	A.95E <sup>*4</sup>	Command Warning 5 (Subcommand Disable)	○	○	○	○
	A.95F <sup>*4</sup>	Command Warning 6 (Undefined Command)	○	○	○	○
	A.960 <sup>*4</sup>	MECHATROLINK Communications Warning	○	○	○	○
	A.962 <sup>*4</sup>	MECHATROLINK Communications Warning (FCS Error)	○	○	○	○
	A.963 <sup>*4</sup>	MECHATROLINK Communications Warning (Synchronization Frame Not Received)	○	○	○	○
A.971 <sup>*5</sup>	Undervoltage	○	○	○	○	
A.97A <sup>*4</sup>	Command Warning 7 (Phase Error)	○	○	○	○	
A.97B <sup>*4</sup>	Data Clamp (Out of Range)	○	○	○	○	
A.9A0 <sup>*3</sup>	Overtravel	○	○	○	○	

\*3. Use Pn008.2 to activate or not the warning detection.

\*4. Use Pn800.1 to activate or not the warning detection.

\*5. Use Pn008.1 to activate or not the warning detection.

#### Revision history

No.LEC-OM07501  
Feb./2014 1st printing  
No.LEC-OM07502  
Jul./2014 2nd printing  
No.LEC-OM07503  
Apr./2015 3rd printing  
No.LEC-OM07304 (No.JXC※-OMT0070)  
Nov./2017 4th printing

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Note: Specifications are subject to change without prior notice and any obligation on the part of the manufacturer.  
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