MITSUBISHI ELECTRIC

General-Purpose AC Servo

MELSERVO-J3 Series

SSCNET Ⅲ Compatible

MODEL

MR-J3-□B

SERVO AMPLIFIER

INSTRUCTION MANUAL

● Safety Instructions ●

(Always read these instructions before using the equipment.)

Do not attempt to install, operate, maintain or inspect the servo amplifier and servo motor until you have read through this Instruction Manual, Installation guide, Servo motor Instruction Manual and appended documents carefully and can use the equipment correctly. Do not use the servo amplifier and servo motor until you have a full knowledge of the equipment, safety information and instructions.
In this Instruction Manual, the safety instruction levels are classified into "WARNING" and "CAUTION".

⚠ WARNING	Indicates that incorrect handling may cause hazardous conditions, resulting in death or severe injury.
⚠ CAUTION	Indicates that incorrect handling may cause hazardous conditions, resulting in medium or slight injury to personnel or may cause physical damage.

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.
What must not be done and what must be done are indicated by the following diagrammatic symbols:

⃠: Indicates what must not be done. For example, "No Fire" is indicated by ⃠ .

●: Indicates what must be done. For example, grounding is indicated by ⏚ .

In this Instruction Manual, instructions at a lower level than the above, instructions for other functions, and so on are classified into "POINT".
After reading this installation guide, always keep it accessible to the operator.

1. To prevent electric shock, note the following:

⚠ WARNING

- Before wiring or inspection, switch power off and wait for more than 15 minutes. Then, confirm the voltage is safe with voltage tester. Otherwise, you may get an electric shock.
- Connect the servo amplifier and servo motor to ground.
- Any person who is involved in wiring and inspection should be fully competent to do the work.
- Do not attempt to wire the servo amplifier and servo motor until they have been installed. Otherwise, you may get an electric shock.
- Operate the switches with dry hand to prevent an electric shock.
- The cables should not be damaged, stressed, loaded, or pinched. Otherwise, you may get an electric shock.
- During power-on or operation, do not open the front cover of the servo amplifier. You may get an electric shock.
- Do not operate the servo amplifier with the front cover removed. High-voltage terminals and charging area are exposed and you may get an electric shock.
- Except for wiring or periodic inspection, do not remove the front cover even of the servo amplifier if the power is off. The servo amplifier is charged and you may get an electric shock.

2. To prevent fire, note the following:

⚠ CAUTION

- Do not install the servo amplifier, servo motor and regenerative brake resistor on or near combustibles. Otherwise a fire may cause.
- When the servo amplifier has become faulty, switch off the main servo amplifier power side. Continuous flow of a large current may cause a fire.
- When a regenerative brake resistor is used, use an alarm signal to switch main power off. Otherwise, a regenerative brake transistor fault or the like may overheat the regenerative brake resistor, causing a fire.

3. To prevent injury, note the follow

⚠ CAUTION

- Only the voltage specified in the Instruction Manual should be applied to each terminal, Otherwise, a burst, damage, etc. may occur.
- Connect the terminals correctly to prevent a burst, damage, etc.
- Ensure that polarity (+, −) is correct. Otherwise, a burst, damage, etc. may occur.
- Take safety measures, e.g. provide covers, to prevent accidental contact of hands and parts (cables, etc.) with the servo amplifier heat sink, regenerative brake resistor, servo motor, etc. since they may be hot while power is on or for some time after power-off. Their temperatures may be high and you may get burnt or a parts may damaged.
- During operation, never touch the rotating parts of the servo motor. Doing so can cause injury.

4. Additional instructions

The following instructions should also be fully noted. Incorrect handling may cause a fault, injury, electric shock, etc.

(1) Transportation and installation

⚠ CAUTION

- Transport the products correctly according to their weights.
- Stacking in excess of the specified number of products is not allowed.
- Do not carry the servo motor by the cables, shaft or encoder.
- Do not hold the front cover to transport the servo amplifier. The servo amplifier may drop.
- Install the servo amplifier in a load-bearing place in accordance with the Instruction Manual.
- Do not climb or stand on servo equipment. Do not put heavy objects on equipment.
- The servo amplifier and servo motor must be installed in the specified direction.
- Leave specified clearances between the servo amplifier and control enclosure walls or other equipment.
- Do not install or operate the servo amplifier and servo motor which has been damaged or has any parts missing.
- Provide adequate protection to prevent screws and other conductive matter, oil and other combustible matter from entering the servo amplifier.
- Do not drop or strike servo amplifier or servo motor. Isolate from all impact loads.
- When you keep or use it, please fulfill the following environmental conditions.

Environment			Conditions		
			Servo amplifier	Servo motor	
Ambient temperature	During operation	[℃]	0 to +55 (non-freezing)	0 to +40 (non-freezing)	
		[°F]	32 to 131 (non-freezing)	32 to 104 (non-freezing)	
	In storage	[℃]	−20 to +65 (non-freezing)	−15 to +70 (non-freezing)	
		[°F]	−4 to 149 (non-freezing)	5 to 158 (non-freezing)	
Ambient humidity	In operation		90%RH or less (non-condensing)	80%RH or less (non-condensing)	
	In storage		90%RH or less (non-condensing)		
Ambience			Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt		
Altitude			Max. 1000m (3280 ft) above sea level		
(Note) Vibration	[m/s^2]		5.9 or less	HF-MP Series HF-KP Series	X ▪ Y : 49
				HF-SP 52 to 152 HF-SP 51 ▪ 81	X ▪ Y : 24.5
				HF- SP 202 ▪ 352 HF- SP 121 ▪ 201	X : 24.5 Y : 49
				HF- SP 502 ▪ 702	X : 24.5 Y : 29.5

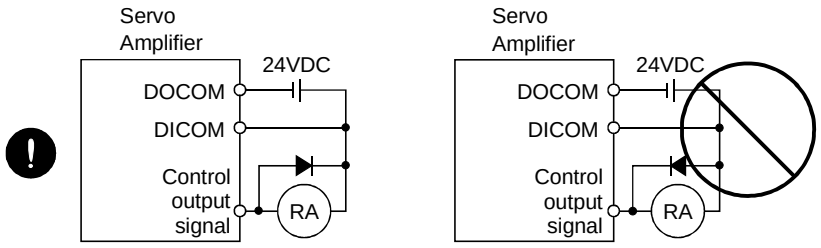
Note. Except the servo motor with reduction gear.

- Securely attach the servo motor to the machine. If attach insecurely, the servo motor may come off during operation.
- The servo motor with reduction gear must be installed in the specified direction to prevent oil leakage.
- Take safety measures, e.g. provide covers, to prevent accidental access to the rotating parts of the servo motor during operation.
- Never hit the servo motor or shaft, especially when coupling the servo motor to the machine. The encoder may become faulty.
- Do not subject the servo motor shaft to more than the permissible load. Otherwise, the shaft may break.
- When the equipment has been stored for an extended period of time, consult Mitsubishi.

(2) Wiring

⚠ CAUTION

- Wire the equipment correctly and securely. Otherwise, the servo motor may misoperate.
- Do not install a power capacitor, surge absorber or radio noise filter (FR-BIF option) between the servo motor and servo amplifier.
- Connect the output terminals (U, V, W) correctly. Otherwise, the servo motor will operate improperly.
- Do not connect AC power directly to the servo motor. Otherwise, a fault may occur.
- The surge absorbing diode installed on the DC output signal relay of the servo amplifier must be wired in the specified direction. Otherwise, the forced stop (EM1) and other protective circuits may not operate.



(3) Test run adjustment

⚠ CAUTION

- Before operation, check the parameter settings. Improper settings may cause some machines to perform unexpected operation.
- The parameter settings must not be changed excessively. Operation will be insatiable.

(4) Usage

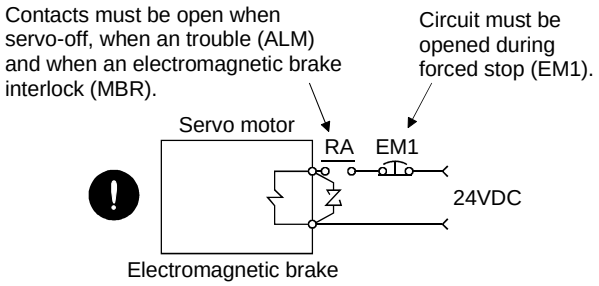
⚠ CAUTION

- Provide an external emergency stop circuit to ensure that operation can be stopped and power switched off immediately.
- Any person who is involved in disassembly and repair should be fully competent to do the work.
- Before resetting an alarm, make sure that the run signal of the servo amplifier is off to prevent an accident. A sudden restart is made if an alarm is reset with the run signal on.
- Do not modify the equipment.
- Use a noise filter, etc. to minimize the influence of electromagnetic interference, which may be caused by electronic equipment used near the servo amplifier.
- Use the servo amplifier with the specified servo motor.
- The electromagnetic brake on the servo motor is designed to hold the motor shaft and should not be used for ordinary braking.
- For such reasons as service life and mechanical structure (e.g. where a ballscrew and the servo motor are coupled via a timing belt), the electromagnetic brake may not hold the motor shaft. To ensure safety, install a stopper on the machine side.

(5) Corrective actions

⚠ CAUTION

- When it is assumed that a hazardous condition may take place at the occur due to a power failure or a product fault, use a servo motor with electromagnetic brake or an external brake mechanism for the purpose of prevention.
- Configure the electromagnetic brake circuit so that it is activated not only by the servo amplifier signals but also by an external forced stop (EM1).



- When any alarm has occurred, eliminate its cause, ensure safety, and deactivate the alarm before restarting operation.
- When power is restored after an instantaneous power failure, keep away from the machine because the machine may be restarted suddenly (design the machine so that it is secured against hazard if restarted).

(6) Maintenance, inspection and parts replacement

⚠ CAUTION

- With age, the electrolytic capacitor of the servo amplifier will deteriorate. To prevent a secondary accident due to a fault, it is recommended to replace the electrolytic capacitor every 10 years when used in general environment.
  Please consult our sales representative.

(7) General instruction

- To illustrate details, the equipment in the diagrams of this Specifications and Instruction Manual may have been drawn without covers and safety guards. When the equipment is operated, the covers and safety guards must be installed as specified. Operation must be performed in accordance with this Specifications and Instruction Manual.

● About processing of waste ●

When you discard servo amplifier, a battery (primary battery), and other option articles, please follow the law of each country (area).

⚠ FOR MAXIMUM SAFETY

- These products have been manufactured as a general-purpose part for general industries, and have not been designed or manufactured to be incorporated in a device or system used in purposes related to human life.
- Before using the products for special purposes such as nuclear power, electric power, aerospace, medicine, passenger movement vehicles or under water relays, contact Mitsubishi.
- These products have been manufactured under strict quality control. However, when installing the product where major accidents or losses could occur if the product fails, install appropriate backup or failsafe functions in the system.

⚠ EEP-ROM life

The number of write times to the EEP-ROM, which stores parameter settings, etc., is limited to 100,000. If the total number of the following operations exceeds 100,000, the servo amplifier and/or converter unit may fail when the EEP-ROM reaches the end of its useful life.

- Write to the EEP-ROM due to parameter setting changes
- Home position setting in the absolute position detection system
- Write to the EEP-ROM due to device changes

Precautions for Choosing the Products

Mitsubishi will not be held liable for damage caused by factors found not to be the cause of Mitsubishi; machine damage or lost profits caused by faults in the Mitsubishi products; damage, secondary damage, accident compensation caused by special factors unpredictable by Mitsubishi; damages to products other than Mitsubishi products; and to other duties.

COMPLIANCE WITH EC DIRECTIVES

1. WHAT ARE EC DIRECTIVES?

The EC directives were issued to standardize the regulations of the EU countries and ensure smooth distribution of safety-guaranteed products. In the EU countries, the machinery directive (effective in January, 1995), EMC directive (effective in January, 1996) and low voltage directive (effective in January, 1997) of the EC directives require that products to be sold should meet their fundamental safety requirements and carry the CE marks (CE marking). CE marking applies to machines and equipment into which servo amplifiers have been installed.

(1) EMC directive

The EMC directive applies not to the servo units alone but to servo-incorporated machines and equipment. This requires the EMC filters to be used with the servo-incorporated machines and equipment to comply with the EMC directive. For specific EMC directive conforming methods, refer to the EMC Installation Guidelines (IB(NA)67310).

(2) Low voltage directive

The low voltage directive applies also to servo units alone. Hence, they are designed to comply with the low voltage directive.

This servo is certified by TUV, third-party assessment organization, to comply with the low voltage directive.

(3) Machine directive

Not being machines, the servo amplifiers need not comply with this directive.

2. PRECAUTIONS FOR COMPLIANCE

(1) Servo amplifiers and servo motors used

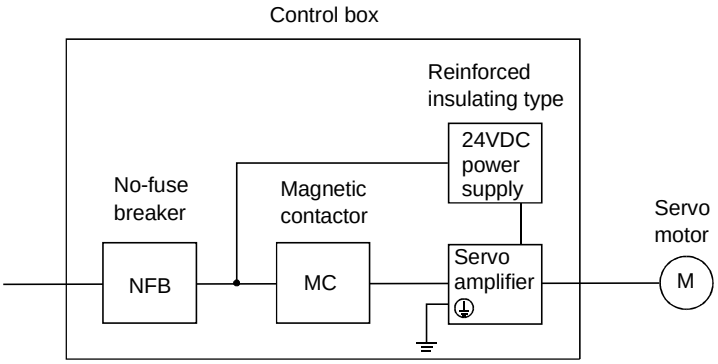
Use the servo amplifiers and servo motors which comply with the standard model.

Servo amplifier :MR-J3-10B to MR-J3-700B
MR-J3-10B1 to MR-J3-40B1

Servo motor :HF-MP□
HF-KP□
HF-SP□

(2) Configuration

The control circuit provide safe separation to the main circuit in the servo amplifier.



(3) Environment

Operate the servo amplifier at or above the contamination level 2 set forth in IEC60664-1. For this purpose, install the servo amplifier in a control box which is protected against water, oil, carbon, dust, dirt, etc. (IP54).

(4) Power supply

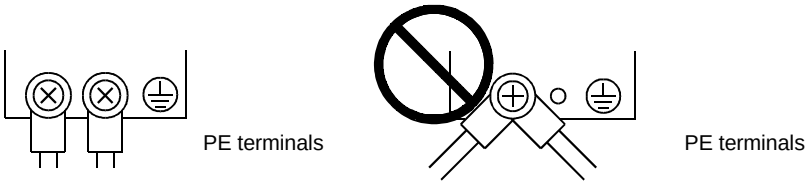
(a) This servo amplifier can be supplied from star-connected supply with earthed neutral point of overvoltage category III set forth in IEC60664-1. However, when using the neutral point of 400V system for single phasesupply, a reinforced reinforced insulating transformer is required in the power input section.

(b) When supplying interface power from external, use a 24VDC power supply which has been insulation-reinforced in I/O.

(5) Grounding

(a) To prevent an electric shock, always connect the protective earth (PE) terminals (marked ⏚) of the servo amplifier to the protective earth (PE) of the control box.

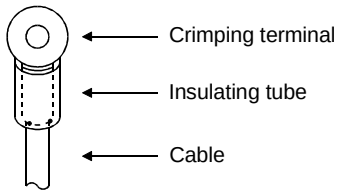
(b) Do not connect two ground cables to the same protective earth (PE) terminal. Always connect the cables to the terminals one-to-one.



(c) If a leakage current breaker is used to prevent an electric shock, the protective earth (PE) terminals of the servo amplifier must be connected to the corresponding earth terminals.

(6) Wiring

(a) The cables to be connected to the terminal block of the servo amplifier must have crimping terminals provided with insulating tubes to prevent contact with adjacent terminals.



(b) Use the servo motor side power connector which complies with the EN Standard. The EN Standard compliant power connector sets are available from us as options. (Refer to Section 11.1)

(7) Auxiliary equipment and options

(a) The no-fuse breaker and magnetic contactor used should be the EN or IEC standard-compliant products of the models described in Section 11.9.

Use a type B (Note) breaker. When it is not used, provide insulation between the servo amplifier and other device by double insulation or reinforced insulation, or install a transformer between the main power supply and servo amplifier.

Note. Type A: AC and pulse detectable

Type B: Both AC and DC detectable

(b) The sizes of the cables described in Section 11.8 meet the following requirements. To meet the other requirements, follow Table 5 and Appendix C in EN60204-1.

- Ambient temperature: 40 (104) [°C (°F)]
- Sheath: PVC (polyvinyl chloride)
- Installed on wall surface or open table tray

(c) Use the EMC filter for noise reduction.

(8) Performing EMC tests

When EMC tests are run on a machine/device into which the servo amplifier has been installed, it must conform to the electromagnetic compatibility (immunity/emission) standards after it has satisfied the operating environment/electrical equipment specifications.

For the other EMC directive guidelines on the servo amplifier, refer to the EMC Installation Guidelines(IB(NA)67310).

CONFORMANCE WITH UL/C-UL STANDARD

(1) Servo amplifiers and servo motors used

Use the servo amplifiers and servo motors which comply with the standard model.

Servo amplifier :MR-J3-10B to MR-J3-700B
MR-J3-10B1 to MR-J3-40B1
Servo motor :HF-MP□
HF-KP□
HF-SP□

(2) Installation

Install a fan of 100CFM (2.8m^3/min) air flow 4 in (10.16 cm) above the servo amplifier or provide cooling of at least equivalent capability.

(3) Short circuit rating

This servo amplifier conforms to the circuit whose peak current is limited to 5000A or less. Having been subjected to the short-circuit tests of the UL in the alternating-current circuit, the servo amplifier conforms to the above circuit.

(4) Capacitor discharge time

The capacitor discharge time is as listed below. To ensure safety, do not touch the charging section for 15 minutes after power-off.

Servo amplifier	Discharge time [min]
MR-J3-10B・20B	1
MR-J3-40B・60B・10B1・20B1	2
MR-J3-70B	3
MR-J3-40B1	4
MR-J3-100B	5
MR-J3-200B・350B	9
MR-J3-500B・700B	10

(5) Options and auxiliary equipment

Use UL/C-UL standard-compliant products.

This servo amplifier is UL/C-UL-listed when using the fuses indicated in the following table. When the servo amplifier must comply with the UL/C-UL Standard, be sure to use these fuses.

Servo amplifier	Fuse		
	Class	Current [A]	Voltage [V]
MR-J3-10B (1)・20B	T	10	AC250
MR-J3-40B・20B1		15	
MR-J3-60B to 100B・40B1		20	
MR-J3-200B		40	
MR-J3-350B		70	
MR-J3-500B		125	
MR-J3-700B		150	

(6) Attachment of a servo motor

For the flange size of the machine side where the servo motor is installed, refer to “CONFORMANCE WITH UL/C-UL STANDARD” in the Servo Motor Instruction Manual (Vol.2).

(7) About wiring protection

For installation in United States, branch circuit protection must be provided, in accordance with the National Electrical Code and any applicable local codes.

For installation in Canada, branch circuit protection must be provided, in accordance with the Canada Electrical Code and any applicable provincial codes.

<<About the manuals>>

This Instruction Manual and the MELSERVO Servo Motor Instruction Manual are required if you use the General-Purpose AC servo MR-J3-B for the first time. Always purchase them and use the MR-J3-B safely.

Relevant manuals

Manual name	Manual No.
MELSERVO-J3 Series To Use the AC Servo Safely	IB(NA)0300077
MELSERVO Servo Motor Instruction Manual Vol.2	SH(NA)030041
EMC Installation Guidelines	IB(NA)67310

MEMO

CONTENTS

1. FUNCTIONS AND CONFIGURATION

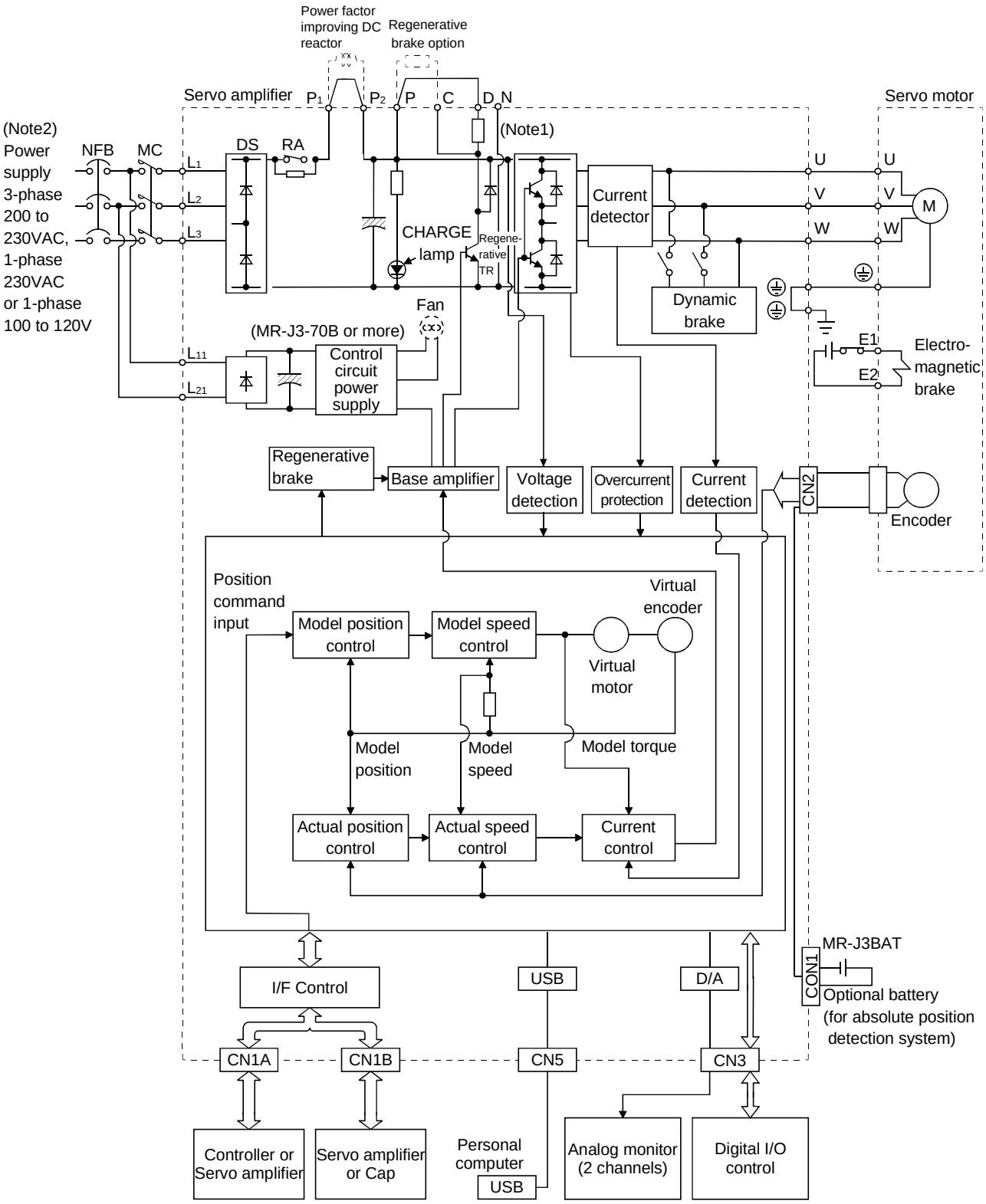
1.1 Introduction

The Mitsubishi MELSERVO-J3 series general-purpose AC servo has further higher performance and higher functions compared to the current MELSERVO-J2-Super series.
The MR-J3-B servo amplifier connects to servo system controller and others via high speed synchronous network and operates by directly reading position data. The rotation speed/direction control of servo motor and the high accuracy positioning are executed with the data from command module. SSCNETⅢ equipped by the MR-J3-B servo amplifier greatly improved its communication speed and noise tolerance by adopting optical communication system compared to the current SSCNET. For wiring distance, 50m of the maximum distance between electrodes is also offered.

The torque limit with clamping circuit is put on the servo amplifier in order to protect the power transistor of main circuit from the overcurrent caused by rapid acceleration/deceleration or overload. In addition, torque limit value can be changed to desired value with parameter.
As this new series has the USB communication function, a servo configuration software-installed personal computer or the like can be used to perform parameter setting, test operation, status display monitoring, gain adjustment, etc.
With real-time auto tuning, you can automatically adjust the servo gains according to the machine.
The MELSERVO-J3 series servo motor is equipped with an absolute position encoder which has the resolution of 262144 pulses/rev to ensure more accurate control as compared to the MELSERVO-J2-Super series. Simply adding a battery to the servo amplifier makes up an absolute position detection system. This makes home position return unnecessary at power-on or alarm occurrence by setting a home position once.

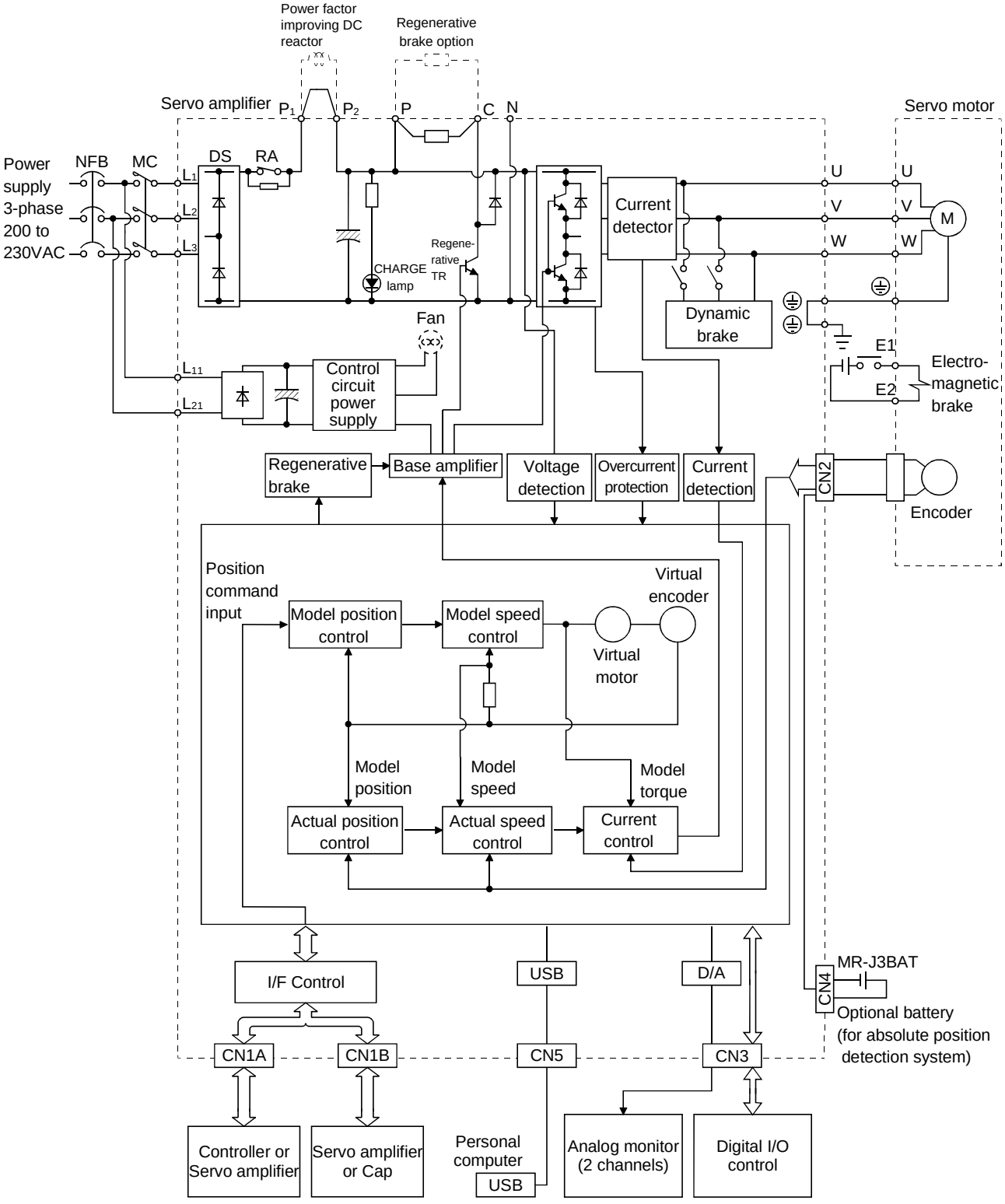
1.2 Function block diagram

The function block diagram of this servo is shown below.
(1) MR-J3-350B or less



Note 1. The built-in regenerative brake resistor is not provided for the MR-J3-10B (1).
2. For 1-phase 230VAC, connect the power supply to L_1,L_2 and leave L_3 open.
There is no L_3 for 1-phase 100 to 120VAC power supply.

(2) MR-J3-500B・MR-J3-700B



1.3 Servo amplifier standard specifications

Item \ Servo Amplifier MR-J3-□				10B	20B	40B	70B	100B	200B	350B	500B	700B	10B1	20B1	40B1
Power supply	Voltage/frequency			3-phase 200 to 230VAC, 50/60Hz or 1-phase 230VAC, 50/60Hz				3-phase 200 to 230VAC, 50/60Hz					1-phase 100V to 120VAC, 50/60Hz		
	Permissible voltage fluctuation			3-phase 200 to 230VAC: 170 to 253VAC 1-phase 230VAC: 207 to 253VAC				3-phase 170 to 253VAC					1-phase 85 to 132VAC		
	Permissible frequency fluctuation			Within ±5%											
	Power supply capacity			Refer to Section 10.2											
	Inrush current			Refer to Section 10.5											
Control circuit power supply	Voltage, frequency			1-phase 200 to 230VAC, 50/60Hz									1-phase 100 to 120VAC, 50/60Hz		
	Permissible voltage fluctuation			1-phase 170 to 253VAC									1-phase 85 to 132VAC		
	Permissible frequency fluctuation			Within ±5%											
	Input			30W							45W		30W		
	Inrush current			Refer to Section 11.5											
Interface power supply	Voltage, frequency			DC24V±10%											
	Power supply capacity			(Note 1) 150mA or more											
Control System				Sine-wave PWM control, current control system											
Dynamic brake				Built-in											
Protective functions				Overcurrent shut-off, regenerative overvoltage shut-off, overload shut-off (electronic thermal relay), servo motor overheat protection, encoder error protection, regenerative brake error protection, undervoltage, instantaneous power failure protection, overspeed protection, excessive error protection											
Structure				Self-cooled, open (IP00)			Force-cooling, open (IP00)						Self-cooled, open (IP00)		
Environment	Ambient temperature	During operation	[°C]	(Note 2) 0 to +55 (non-freezing)											
			[°F]	32 to +131 (non-freezing)											
		In storage	[°C]	−20 to +65 (non-freezing)											
			[°F]	−4 to +149 (non-freezing)											
	Ambient humidity	In operation		90%RH or less (non-condensing)											
		In storage													
	Ambient			Indoors (no direct sunlight) Free from corrosive gas, flammable gas, oil mist, dust and dirt											
	Altitude			Max. 1000m (3280ft) above sea level											
	Vibration			5.9 [m/s^2] or less											
Mass			[kg]	0.8	0.8	1.0	1.4	1.4	2.3	2.3	4.6	6.2	0.8	0.8	1.0
			[lb]	1.8	1.8	2.2	3.1	3.1	5.071	5.071	10.1	13.7	1.8	1.8	2.2

Note 1. 150mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points.
2. When mounting the servo amplifiers closely, operate them at the ambient temperatures of 0 to 45°C or at 75% or a smaller effective load ratio.

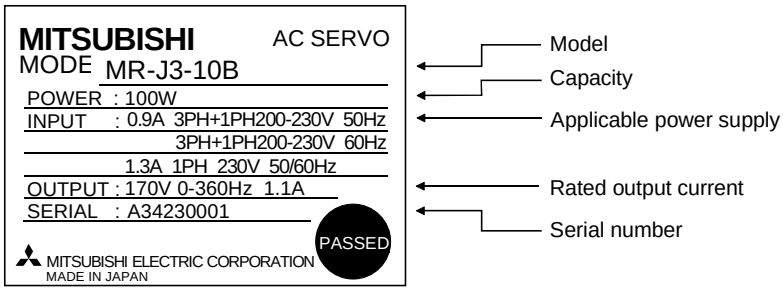
1.4 Function list

The following table lists the functions of this servo. For details of the functions, refer to the reference field.

Function	Description	Reference
High-resolution encoder	High-resolution encoder of 262144 pulses/rev is used as a servo motor encoder.	
Absolute position detection system	Merely setting a home position once makes home position return unnecessary at every power-on.	Chapter 12
Gain changing function	You can switch between gains during rotation and gains during stop or use an external signal to change gains during operation.	Section 7.6
Advanced vibration suppression control	This function suppresses vibration at the arm end or residual vibration.	Section 7.4
Adaptive filter Ⅱ	Servo amplifier detects mechanical resonance and sets filter characteristics automatically to suppress mechanical vibration.	Section 7.2
Low-pass filter	Suppresses high-frequency resonance which occurs as servo system response is increased.	Section 7.5
Machine analyzer function	Analyzes the frequency characteristic of the mechanical system by simply connecting a servo configuration software-installed personal computer and servo amplifier. MR Configurator (servo configuration software) MRZJW3-SETUP221E is necessary for this function.	
Machine simulation	Can simulate machine motions on a personal computer screen on the basis of the machine analyzer results. MR Configurator (servo configuration software) MRZJW3-SETUP221E is necessary for this function.	
Gain search function	Personal computer changes gains automatically and searches for overshoot-free gains in a short time. MR Configurator (servo configuration software) MRZJW3-SETUP221E is necessary for this function.	
Slight vibration suppression control	Suppresses vibration of ±1 pulse produced at a servo motor stop.	Parameters No. PB24
Auto tuning	Automatically adjusts the gain to optimum value if load applied to the servo motor shaft varies. Higher in performance than MR-J2-Super series servo amplifier.	Chapter 6
Brake until	Used when the regenerative brake option cannot provide enough regenerative power. Can be used with the MR-J3-500B・MR-J3-700B.	Section 11.3
Return converter	Used when the regenerative brake option cannot provide enough regenerative power. Can be used with the MR-J3-500B・MR-J3-700B.	Section 11.4
Regenerative brake option	Used when the built-in regenerative brake resistor of the servo amplifier does not have sufficient regenerative capability for the regenerative power generated.	Section 11.2
Alarm history clear	Alarm history is cleared.	Parameter No. PC21
Output signal (DO) forced output	Output signal can be forced on/off independently of the servo status. Use this function for output signal wiring check, etc.	Section 4.5.1 (1) (d)
Test operation mode	JOG operation・positioning operation・ DO forced output. However, MR Configurator (servo configuration software) MRZJW3-SETUP221E is necessary for positioning operation.	Section 4.5
Analog monitor output	Servo status is output in terms of voltage in real time.	Parameter No. PC09
MR configurator (Servo configuration software)	Using a personal computer, parameter setting, test operation, status display, etc. can be performed.	Section 11.6

1.5 Model code definition

(1) Rating plate



(2) Model

MR－J3－□B□

Series

Power supply

Symbol	Power supply
None (Note 1)	3-phase 200 to 230VAC 1-phase 230VAC
(Note 2) 1	1-phase 100 to 120VAC

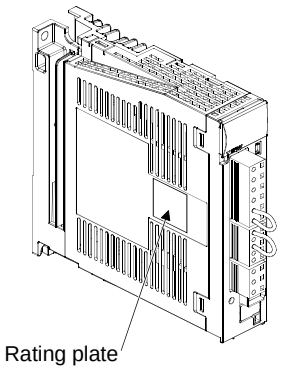
Note 1. 1-phase 230V is supported by the MR-J3-70B or less.
2. No supplied to the servo amplifier of MR-J3-60B or more.

SSCNETⅢ compatible

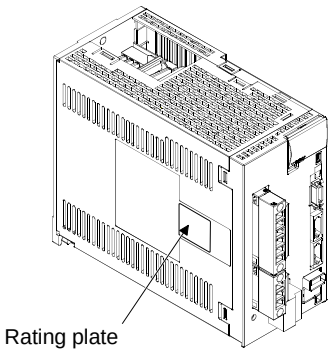
Rated output

Symbol	Rated output [kW]
10	0.1
20	0.2
40	0.4
60	0.6
70	0.75
100	1
200	2
300	3.5
500	5
700	7

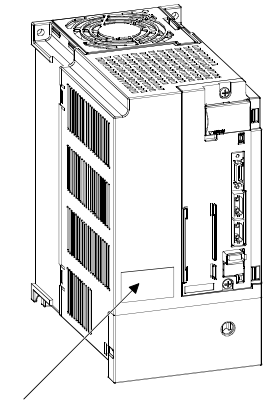
MR-J3-100B or less



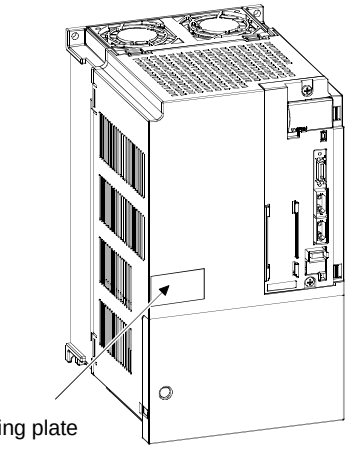
MR-J3-200B･350B



MR-J3-500B



MR-J3-700B



1.6 Combination with servo motor

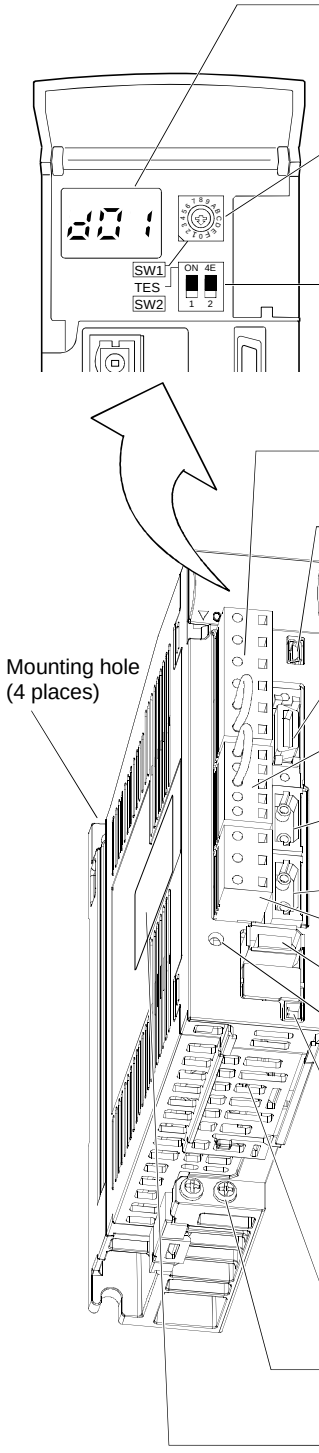
The following table lists combinations of servo amplifiers and servo motors. The same combinations apply to the models with electromagnetic brakes.

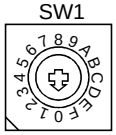
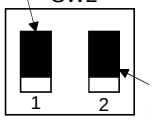
Servo amplifier	Servo motors			
	HF-MP□	HF-KP□	HF-SP□	
			1000r/min	2000r/min
MR-J3-10B (1)	053・13	053・13		
MR-J3-20B (1)	23	23		
MR-J3-40B (1)	43	43		
MR-J3-60B			51	52
MR-J3-70B	73	73		
MR-J3-100B			81	102
MR-J3-200B			121・201	152・202
MR-J3-350B				352
MR-J3-500B				502
MR-J3-700B				702

1.7 Structure

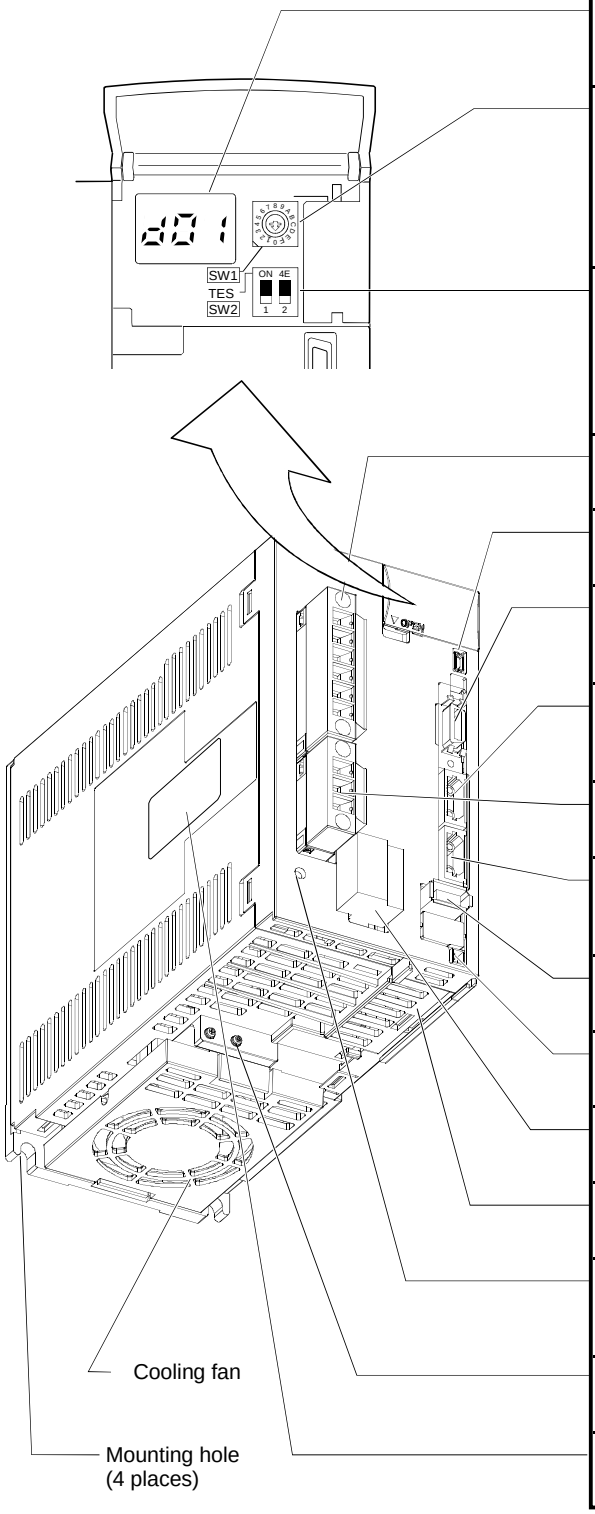
1.7.1 Parts identification

(1) MR-J3-100B or less



Name/Application	Detailed Explanation
Display The 3-digit, seven-segment LED shows the servo status and alarm number.	Chapter 4
Rotary axis setting switch (SW1) SW1  Used to set the axis No. of servo amplifier.	Section 3.13
Test operation select switch (SW2-1) SW2  Used to perform the test operation mode by using MR Configurator (Setup software). Spare (Be sure to set to the "Down" position).	Section 3.13
Main circuit power supply connector (CNP1) Connect the input power supply.	Section 3.1 Section 3.3
USB communication connector (CN5) Connect with the personal computer.	Section 11.5
I/O signal connector (CN3) Used to connect digital I/O signals. More over an analog monitor is output	Section 3.2 Section 3.4
Control circuit connector (CNP2) Connect the control circuit power supply/regenerative brake option.	Section 3.1 Section 3.3
SSCNETⅢ cable connector (CN1A) Used to connect the servo system controller or the front axis servo amplifier.	Section 3.2 Section 3.4
SSCNETⅢ cable connector (CN1B) Used to connect the rear axis servo amplifier. For the final axis, puts a cap.	Section 3.2 Section 3.4
Motor power supply connector (CNP3) Connect the servo motor.	Section 3.1 Section 3.3
Encoder connector (CN2) Connector for connection of the servo motor encoder.	Section 3.4 Section 11.1
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 11.6 Chapter 12
Battery holder Contains the battery for absolute position data backup.	Section 12.3
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Name plate	Section 1.5

(2) MR-J3-200B ▪ MR-J3-350B

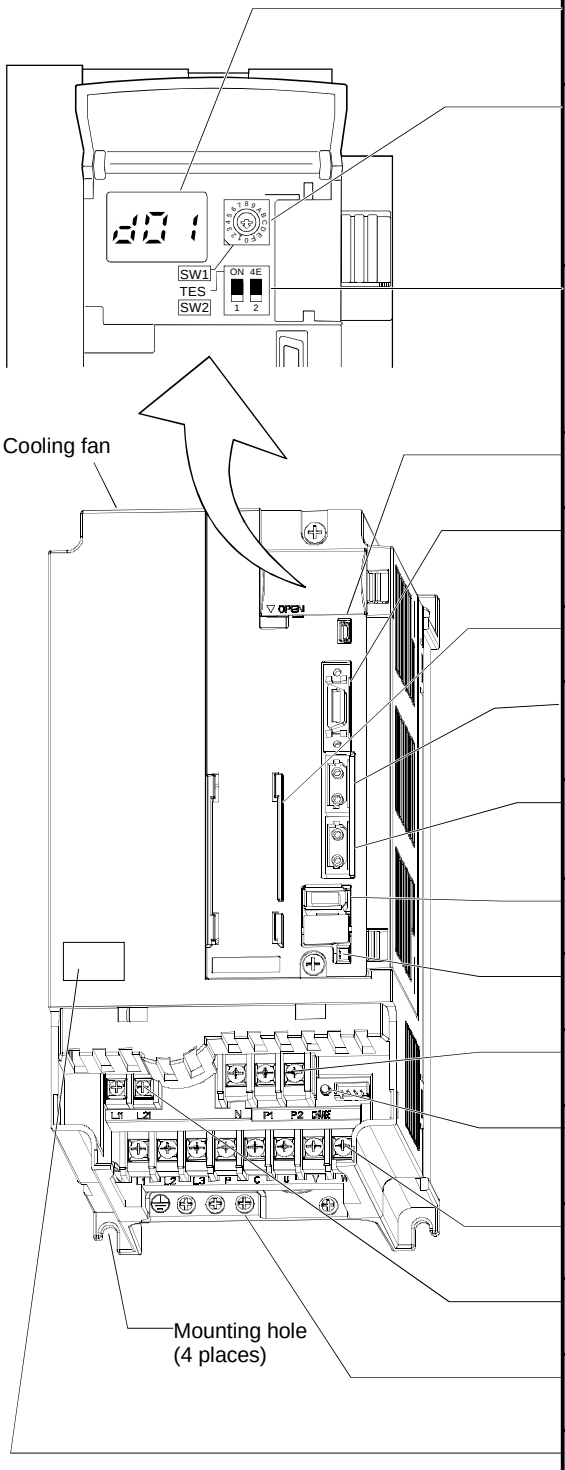


Name/Application	Detailed Explanation
Display The 3-digit, seven-segment LED shows the servo status and alarm number.	Chapter 4
Rotary axis setting switch (SW1) SW1 Used to set the axis No. of servo amplifier.	Section 3.13
Test operation select switch (SW2-1) SW2 Used to perform the test operation mode by using MR Configurator (Setup software). Spare (Be sure to set to the "Down" position).	Section 3.13
Main circuit power supply connector (CNP1) Connect the input power supply.	Section 3.1 Section 3.3
USB communication connector (CN5) Connect with the personal computer.	Section 11.5
I/O signal connector (CN3) Used to connect digital I/O signals. More over an analog monitor is output	Section 3.2 Section 3.4
SSCNET Ⅲ cable connector (CN1A) Used to connect the servo system controller or the front axis servo amplifier.	Section 3.2 Section 3.4
Motor power supply connector (CNP3) Connect the servo motor.	Section 3.1 Section 3.3
SSCNET Ⅲ cable connector (CN1B) Used to connect the rear axis servo amplifier. For the final axis, puts a cap.	Section 3.2 Section 3.4
Encoder connector (CN2) Connector for connection of the servo motor encoder.	Section 3.4 Section 11.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 11.6 Chapter 12
Control circuit connector (CNP2) Connect the control circuit power supply/regenerative brake option.	Section 3.1 Section 3.3
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 11.6 Chapter 12
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Name plate	Section 1.5

(3) MR-J3-500B

POINT

- The servo amplifier is shown without the front cover. For removal of the front cover, refer to Section 1.7.2.

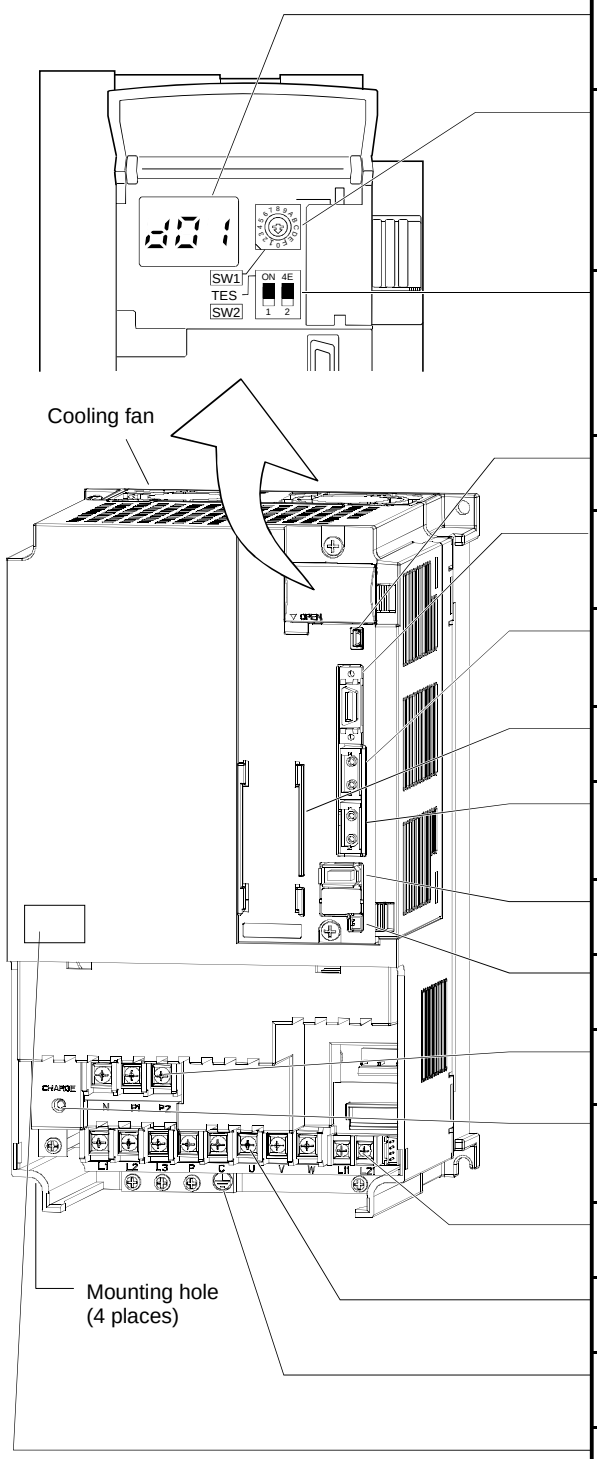


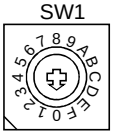
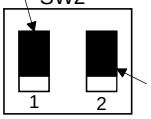
Name/Application	Detailed Explanation
Display The 3-digit, seven-segment LED shows the servo status and alarm number.	Chapter 4
Rotary axis setting switch (SW1) SW1 Used to set the axis No. of servo amplifier.	Section 3.13
Test operation select switch (SW2-1) SW2 Used to perform the test operation mode by using MR Configurator (Setup software). Spare (Be sure to set to the "Down" position).	Section 3.13
USB communication connector (CN5) Connect with the personal computer.	Section 11.5
I/O signal connector (CN3) Used to connect digital I/O signals. More over an analog monitor is output	Section 3.2 Section 3.4
Battery holder Contains the battery for absolute position data backup.	Section 12.3
SSCNET Ⅲ cable connector (CN1A) Used to connect the servo system controller or the front axis servo amplifier.	Section 3.2 Section 3.4
SSCNET Ⅲ cable connector (CN1B) Used to connect the rear axis servo amplifier. For the final axis, puts a cap.	Section 3.2 Section 3.4
Encoder connector (CN2) Connector for connection of the servo motor encoder.	Section 3.4 Section 11.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 11.6 Chapter 12
DC reactor terminal block (TE3) Used to connect the DC reactor.	Section 3.1 Section 3.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Main circuit terminal block (TE1) Used to connect the input power supply and servo motor.	Section 3.1 Section 3.3
Control circuit terminal block (TE2) Used to connect the control circuit power supply.	Section 3.1 Section 3.3
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Name plate	Section 1.5

(4) MR-J3-700B

POINT

- The servo amplifier is shown without the front cover. For removal of the front cover, refer to Section 1.7.2.



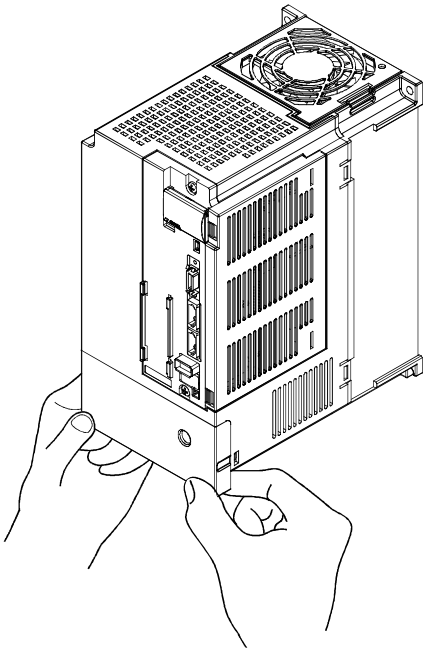
Name/Application	Detailed Explanation
Display The 3-digit, seven-segment LED shows the servo status and alarm number.	Chapter 4
Rotary axis setting switch (SW1) SW1  Used to set the axis No. of servo amplifier.	Section 3.13
Test operation select switch (SW2-1) SW2  Used to perform the test operation mode by using MR Configurator (Setup software). Spare (Be sure to set to the "Down" position).	Section 3.13
USB communication connector (CN5) Connect with the personal computer.	Section 11.5
I/O signal connector (CN3) Used to connect digital I/O signals. More over an analog monitor is output	Section 3.2 Section 3.4
SSCNET Ⅲ cable connector (CN1A) Used to connect the servo system controller or the front axis servo amplifier.	Section 3.2 Section 3.4
Battery holder Contains the battery for absolute position data backup.	Section 12.3
SSCNET Ⅲ cable connector (CN1B) Used to connect the rear axis servo amplifier. For the final axis, puts a cap.	Section 3.2 Section 3.4
Encoder connector (CN2) Connector for connection of the servo motor encoder.	Section 3.4 Section 11.1
Battery connector (CN4) Used to connect the battery for absolute position data backup.	Section 11.6 Chapter 12
DC reactor terminal block (TE3) Used to connect the DC reactor.	Section 3.1 Section 3.3
Charge lamp Lit to indicate that the main circuit is charged. While this lamp is lit, do not reconnect the cables.	
Control circuit terminal block (TE2) Used to connect the control circuit power supply.	Section 3.1 Section 3.3
Main circuit terminal block (TE1) Used to connect the input power supply and servo motor.	Section 3.1 Section 3.3
Protective earth (PE) terminal (⏚) Ground terminal.	Section 3.1 Section 3.3
Name plate	Section 1.5

1.7.2 Removal and reinstallation of the front cover

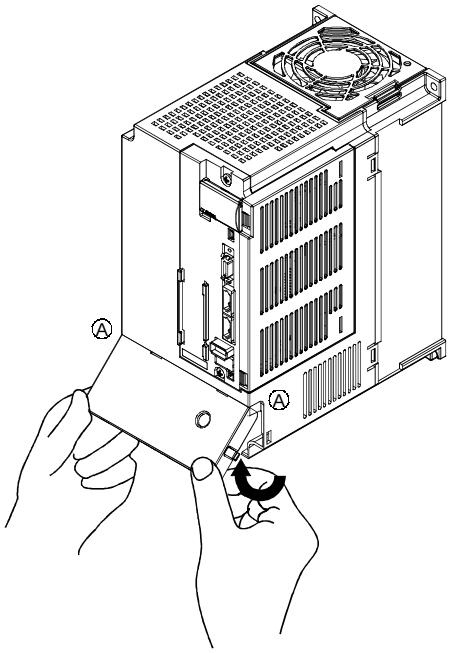
⚠ CAUTION	▪ Before removing or reinstalling the front cover, make sure that the charge lamp is off more than 15 minutes after power off. Otherwise, you may get an electric shock.

For MR-J3-500B or more

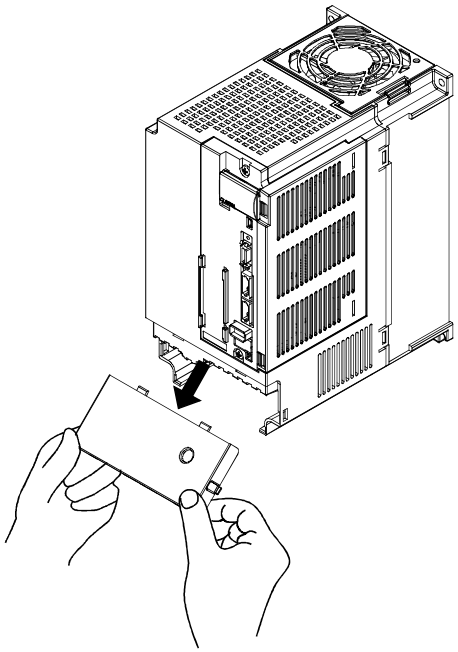
Removal of the front cover



Hold the ends of lower side of the front cover with both hands.

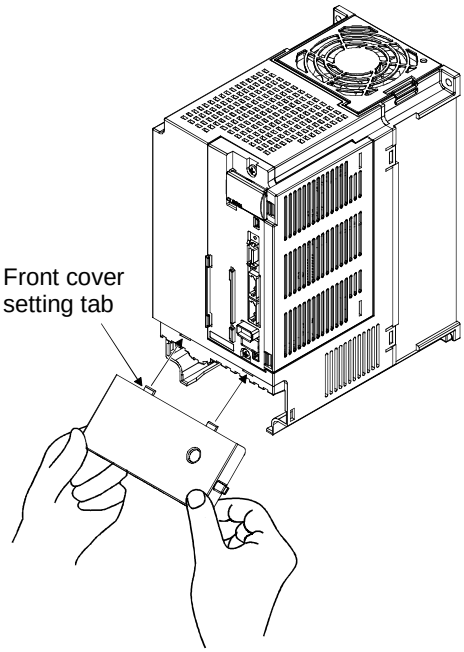


Pull up the cover, supporting at point Ⓐ.

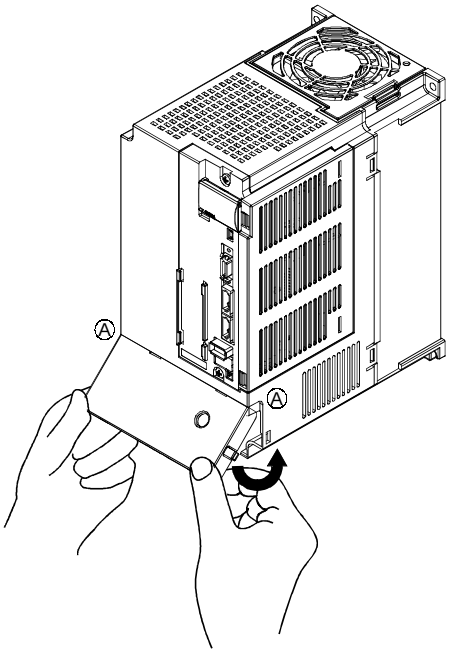


Pull out the front cover to remove.

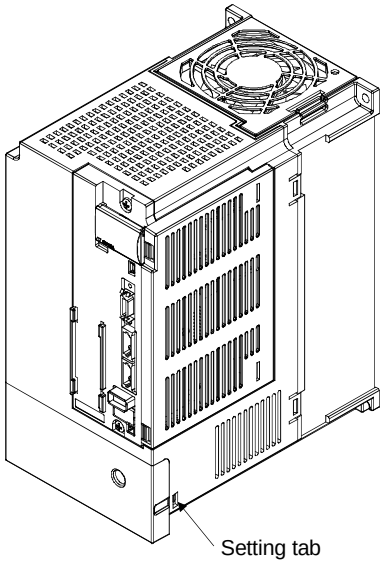
Reinstallation of the front cover



Insert the front cover setting tabs into the sockets of servo amplifier (2 places).



Pull up the cover, supporting at point Ⓐ.



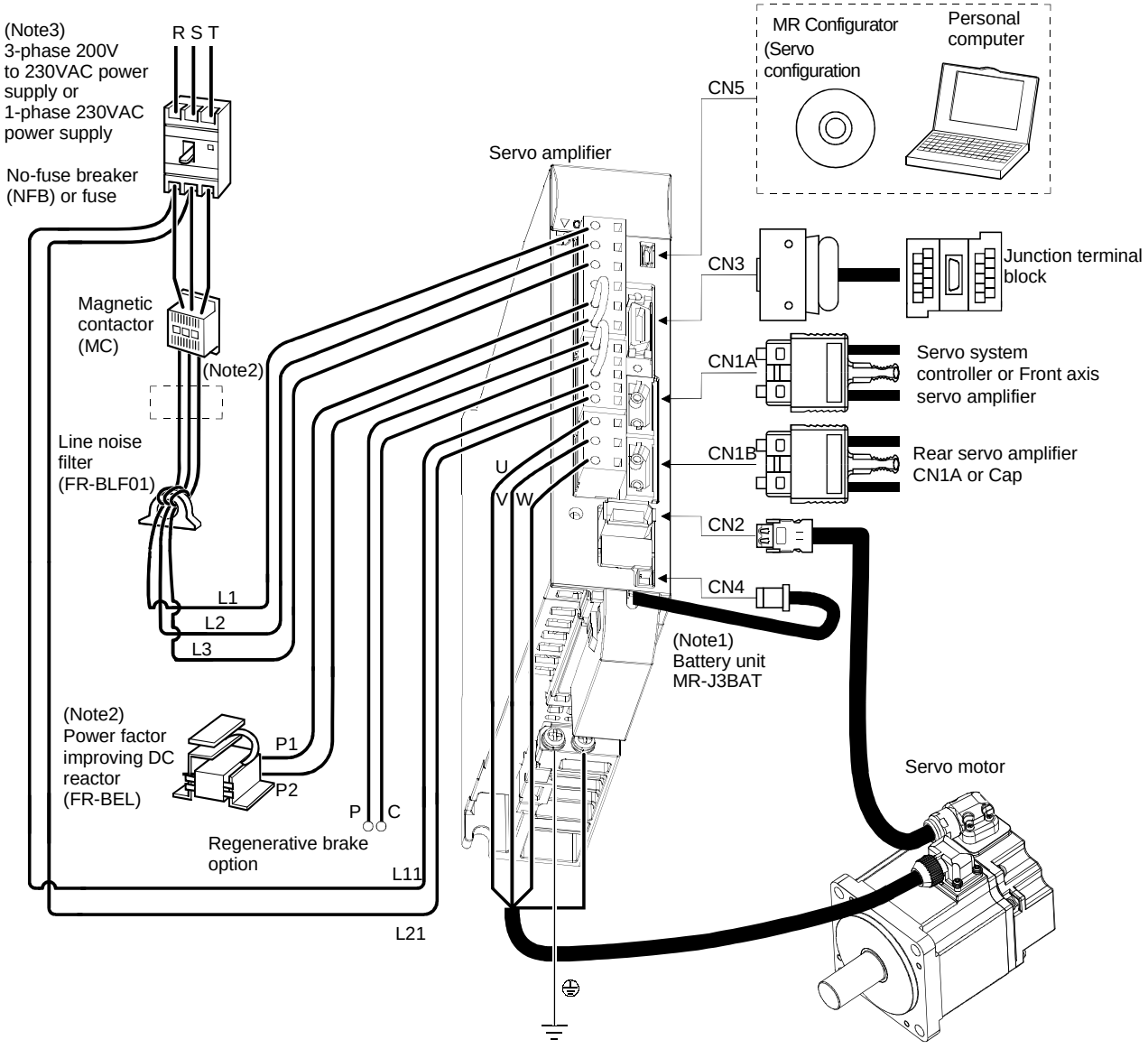
Push the setting tabs until they click.

1.8 Configuration including auxiliary equipment

POINT
・Equipment other than the servo amplifier and servo motor are optional or recommended products.

(1) MR-J3-100B or less

(a) For 3-phase 200V to 230VAC or 1-phase 230VAC

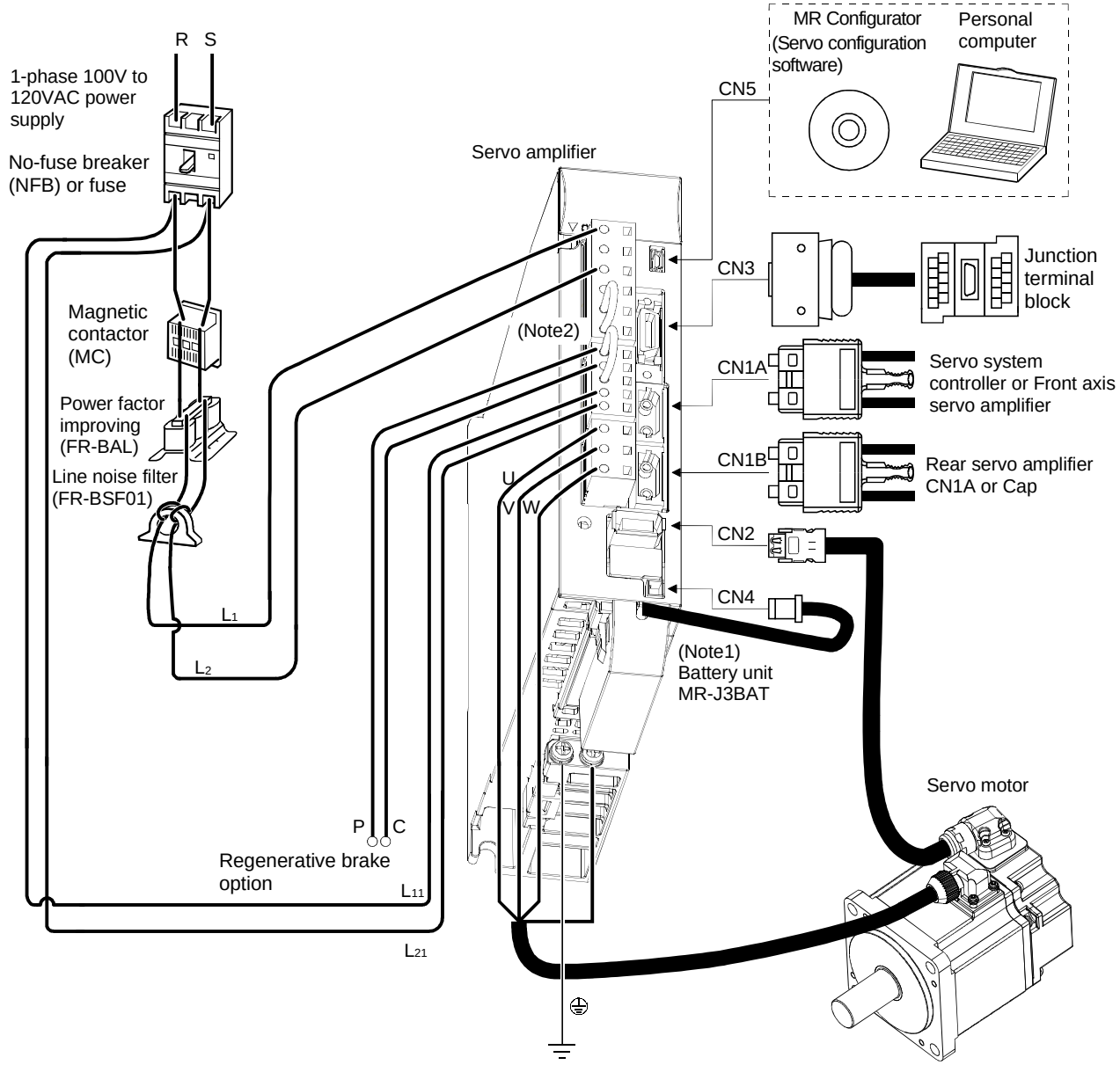


Note 1. The battery unit(option) is used for the absolute position detection system in the position control mode.

2. The AC reactor can also be used. In this case, the DC reactor cannot be used.

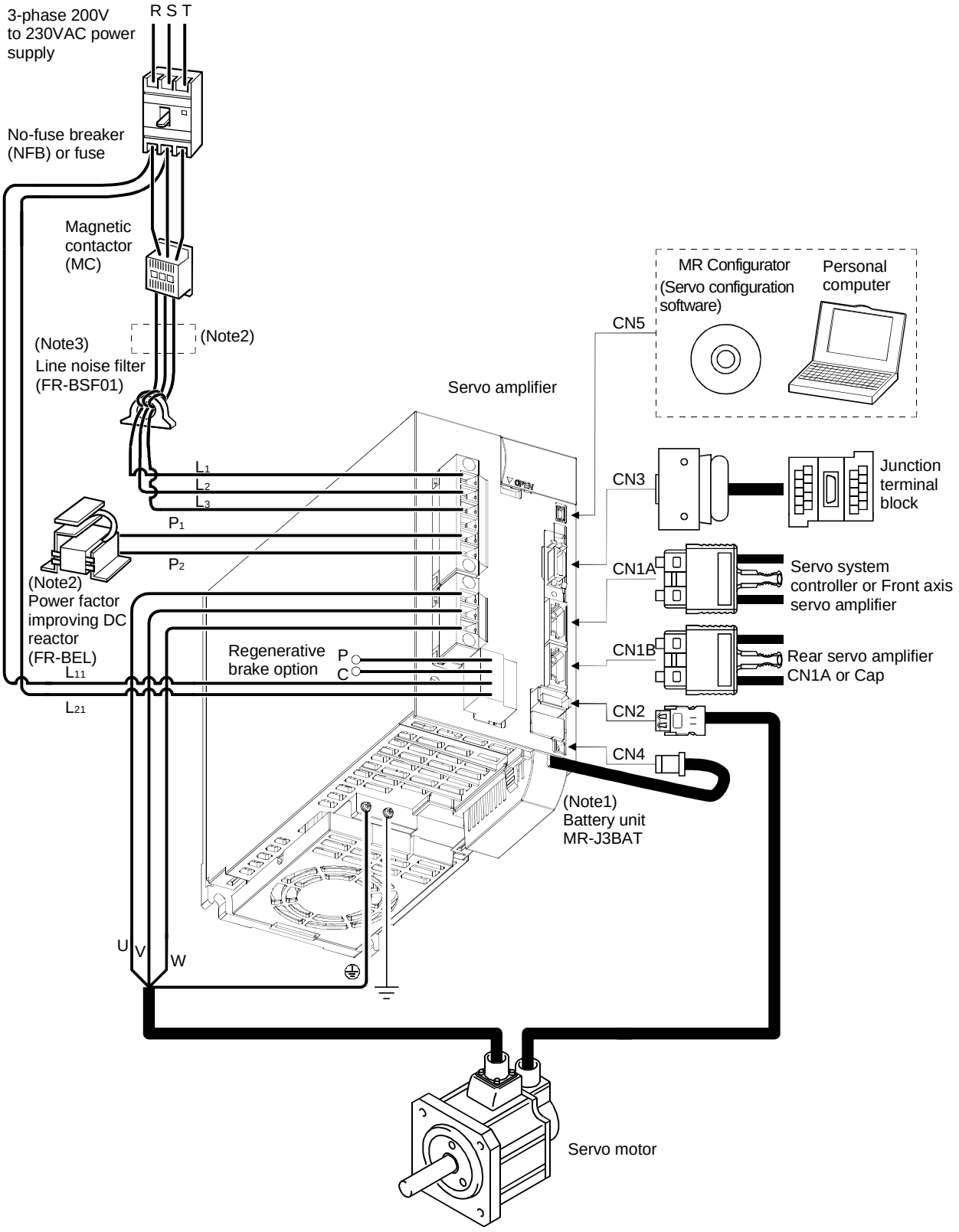
3. A 1-phase 230VAC power supply may be used with the servo amplifier of MR-J3-70B or less.

(b) For 1-phase 100V to 120VAC



Note 1. The battery unit(option) is used for the absolute position detection system in the position control mode.
2. The power factor improving DC reactor cannot be used.

(2) MR-J3-200B ▪ MR-J3-350B

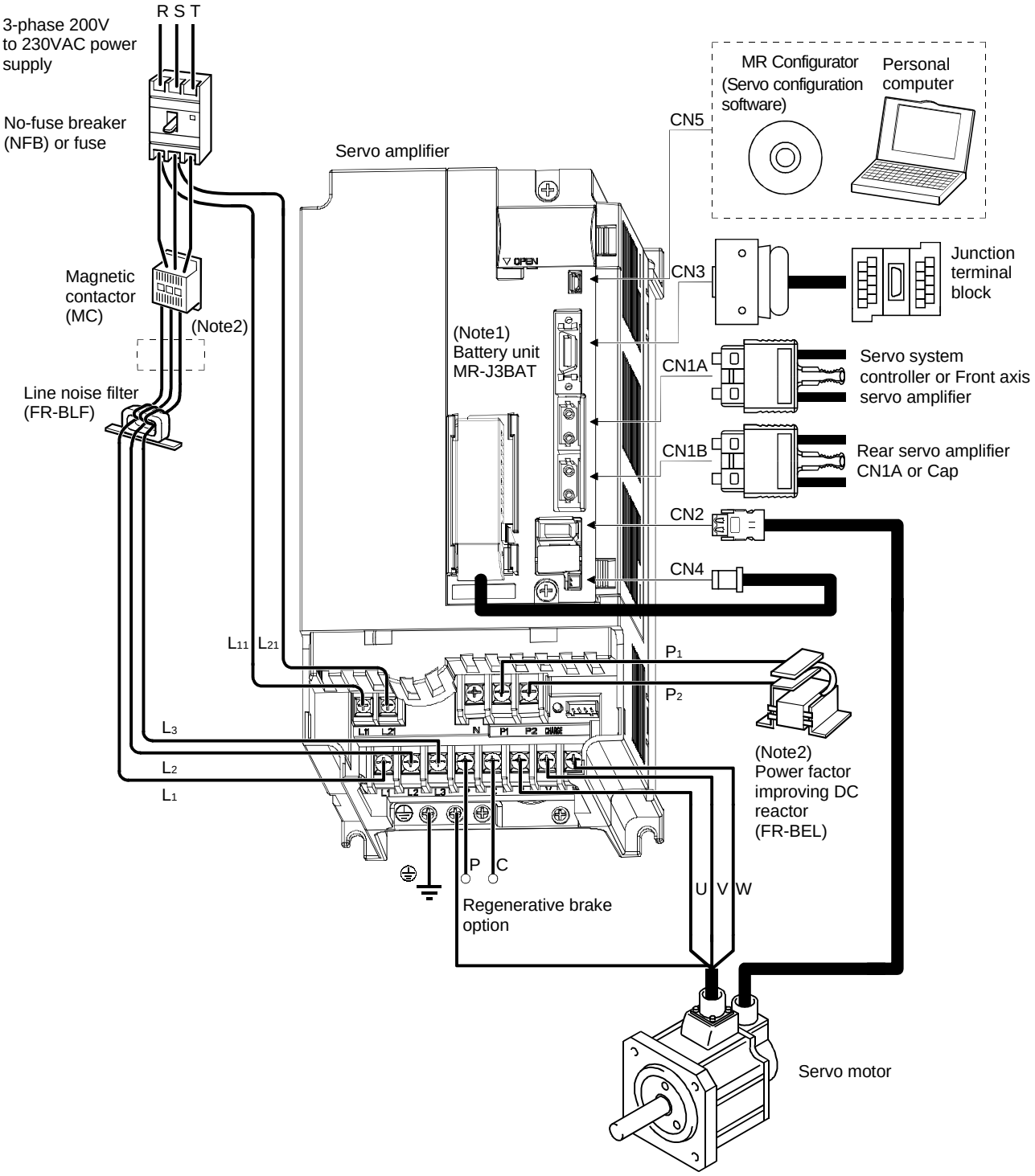


Note 1. The battery unit(option) is used for the absolute position detection system in the position control mode.

2. The AC reactor can also be used. In this case, the DC reactor cannot be used.

3. For MR-J3-350B, use FR-BLF.

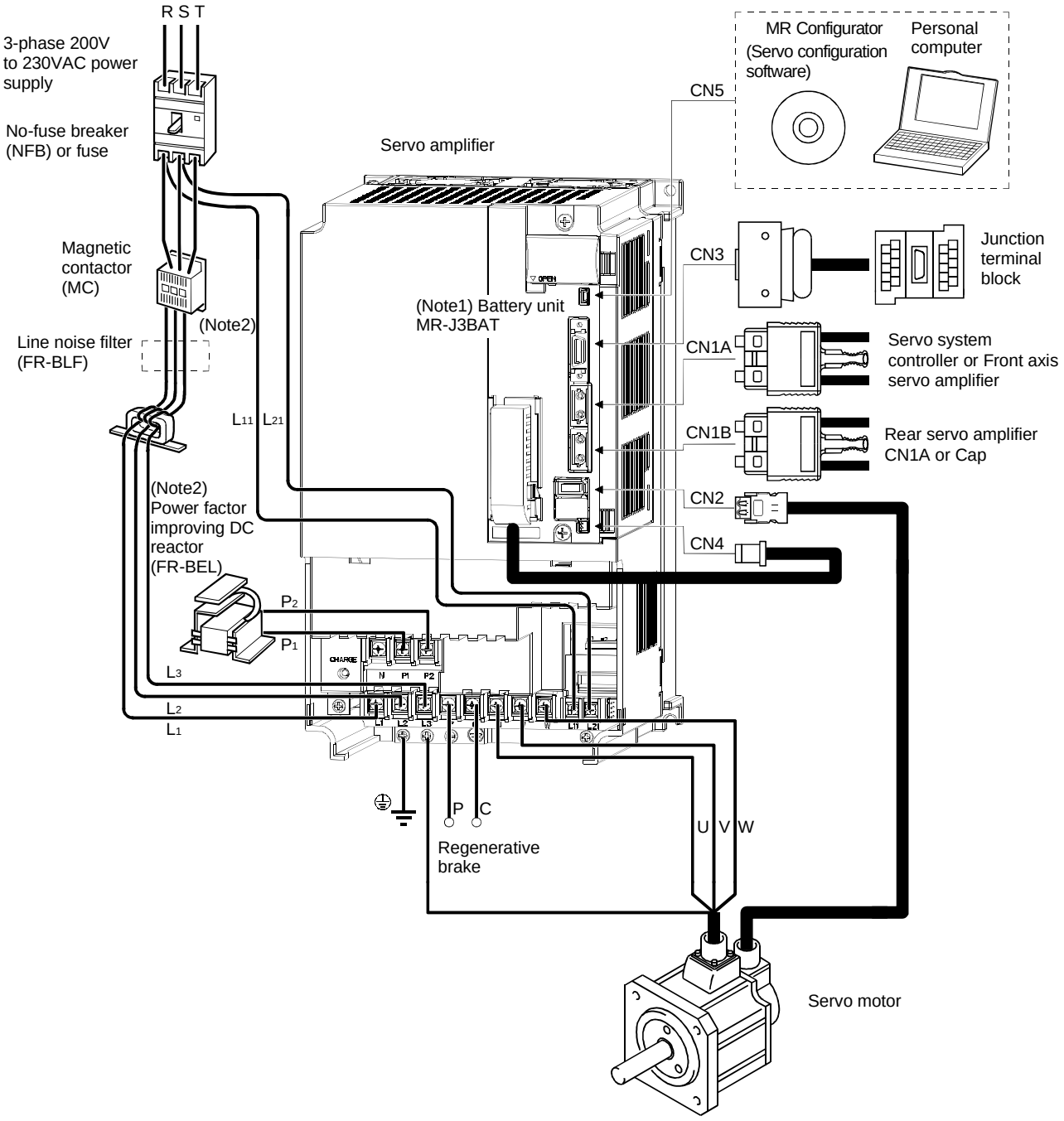
(3) MR-J3-500B



Note 1. The battery unit(option) is used for the absolute position detection system in the position control mode.

2. The AC reactor can also be used. In this case, the DC reactor cannot be used.

(4) MR-J3-700B



Note 1. The battery unit(option) is used for the absolute position detection system in the position control mode.

2. The AC reactor can also be used. In this case, the DC reactor cannot be used.

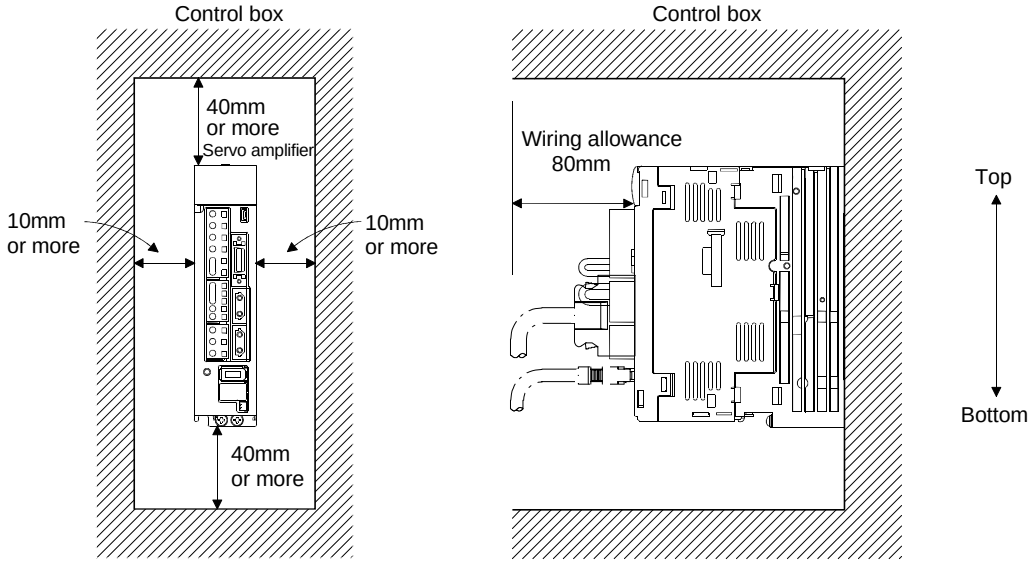
2. INSTALLATION

⚠ CAUTION	・Stacking in excess of the limited number of products is not allowed. ・Install the equipment to incombustibles. Installing them directly or close to combustibles will led to a fire. ・Install the equipment in a load-bearing place in accordance with this Instruction Manual. ・Do not get on or put heavy load on the equipment to prevent injury. ・Use the equipment within the specified environmental condition range. ・Provide an adequate protection to prevent screws, metallic detritus and other conductive matter or oil and other combustible matter from entering the servo amplifier. ・Do not block the intake/exhaust ports of the servo amplifier. Otherwise, a fault may occur. ・Do not subject the servo amplifier to drop impact or shock loads as they are precision equipment. ・Do not install or operate a faulty servo amplifier. ・When the product has been stored for an extended period of time, consult Mitsubishi.

2.1 Installation direction and clearances

⚠ CAUTION	・The equipment must be installed in the specified direction. Otherwise, a fault may occur. ・Leave specified clearances between the servo amplifier and control box inside walls or other equipment.

(1) Installation of one servo amplifier



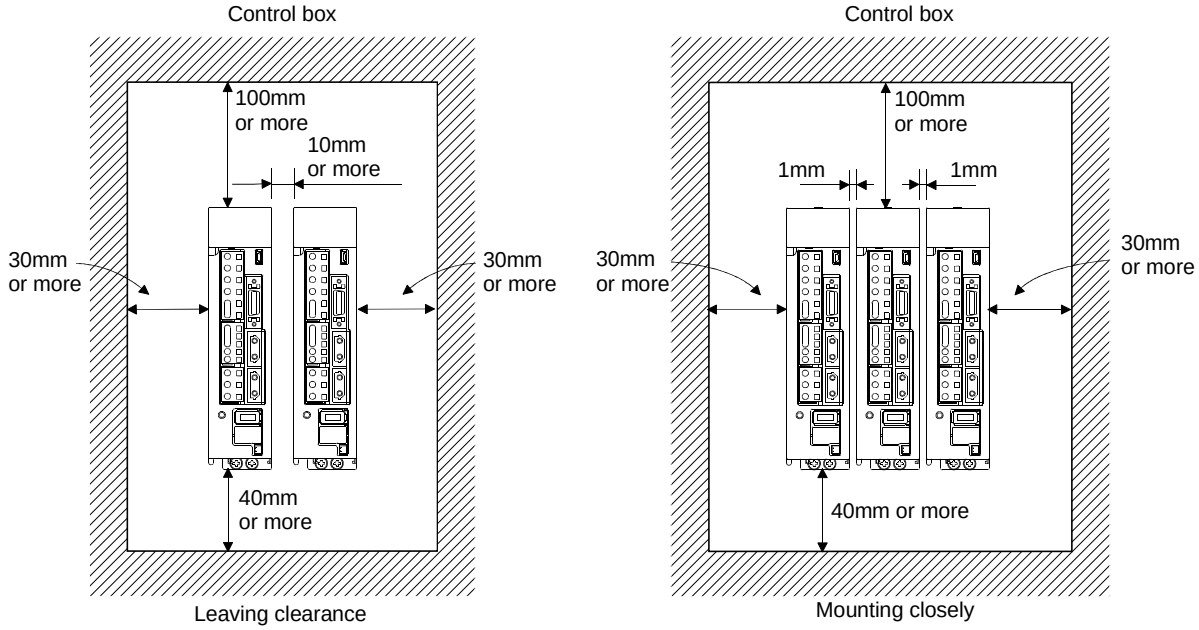
(2) Installation of two or more servo amplifiers

POINT
・Mounting closely is available for a combination of servo amplifiers of 3.5kw or less. The servo amplifiers of 5kw or more can not be mounted closely.

Leave a large clearance between the top of the servo amplifier and the internal surface of the control box, and install a fan to prevent the internal temperature of the control box from exceeding the environmental conditions.

When installing the servo amplifiers closely, leave a clearance of 1mm between the adjacent servo amplifiers in consideration of mounting tolerances.

In this case, bring the ambient temperature within 0 to 45℃, or use it at 75% or a smaller effective load ratio.



(3) Others

When using heat generating equipment such as the regenerative brake option, install them with full consideration of heat generation so that the servo amplifier is not affected.

Install the servo amplifier on a perpendicular wall in the correct vertical direction.

2.2 Keep out foreign materials

(1) When installing the unit in a control box, prevent drill chips and wire fragments from entering the servo amplifier.
(2) Prevent oil, water, metallic dust, etc. from entering the servo amplifier through openings in the control box or a fan installed on the ceiling.
(3) When installing the control box in a place where there are much toxic gas, dirt and dust, conduct an air purge (force clean air into the control box from outside to make the internal pressure higher than the external pressure) to prevent such materials from entering the control box.

2.3 Cable stress

(1) The way of clamping the cable must be fully examined so that flexing stress and cable's own weight stress are not applied to the cable connection.
(2) For use in any application where the servo motor moves, fix the cables (encoder, power supply, brake) supplied with the servo motor, and flex the optional encoder cable or the power supply and brake wiring cables. Use the optional encoder cable within the flexing life range. Use the power supply and brake wiring cables within the flexing life of the cables.
(3) Avoid any probability that the cable sheath might be cut by sharp chips, rubbed by a machine corner or stamped by workers or vehicles.
(4) For installation on a machine where the servo motor will move, the flexing radius should be made as large as possible. Refer to section 10.4 for the flexing life.

2.4 SSCNETⅢ cable laying

SSCNETⅢ cable is made from optical fiber. If optical fiber is added a power such as a major shock, lateral pressure, haul, sudden bending or twist, its inside distorts or breaks, and optical transmission will not be available. Especially, as optical fiber for MR-J3BUS □ M ・ MR-J3BUS □ M-A is made of synthetic resin, it melts down if being left near the fire or high temperature. Therefore, do not make it touched the part, which becomes high temperature, such as radiator or regenerative brake option of servo amplifier.

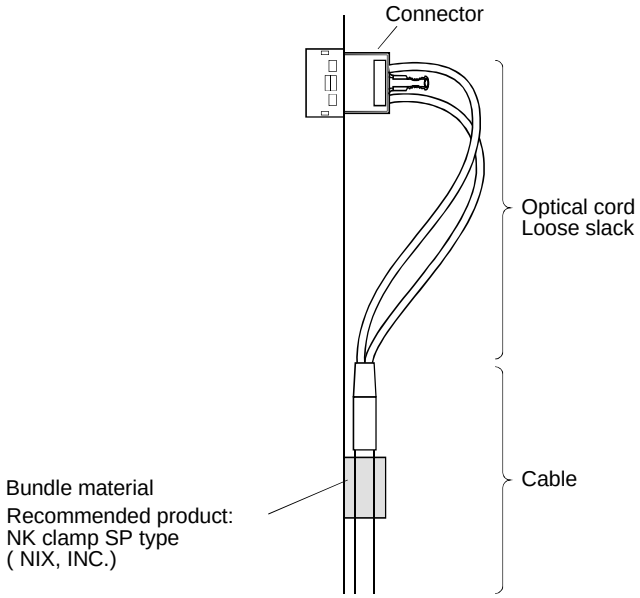
Read described item of this section carefully and handle it with caution.

(1) Minimum bend radius

Make sure to lay the cable with greater radius than the minimum bend radius. Do not press the cable to edges of equipment or others. For SSCNETⅢ cable, the appropriate length should be selected with due consideration for the dimensions and arrangement of servo amplifier. When closing the door of control box, pay careful attention for avoiding the case that SSCNETⅢ cable is hold down by the door and the cable bend becomes smaller than the minimum bend radius.
For the minimum bend radius, refer to Section 11.1.5.

(2) Bundle fixing

Fix the cable at the closest part to the connector with bundle material in order to prevent SSCNETⅢ cable from putting its own weight on CN1A ・ CN1B connector of servo amplifier. Optical cord should be given loose slack to avoid from becoming smaller than the minimum bend radius, and it should not be twisted.



When laying cable, fix and hold it in position with using cushioning such as sponge or rubber which does not contain plasticizing material.
Never use vinyl tape for cord. Plasticizing material in vinyl tape goes into optical fiber and lowers the optical characteristic. At worst, it may cause wire breakage. If using adhesive tape for cable laying, the fire resistant acetate cloth adhesive tape 570F (Teraoka Seisakusho Co., Ltd) is recommended.
If laying with other wires, do not make the cable touched wires or cables made from soft polyvinyl chloride (PVC), polyethylene resin (PE), teflon (Fluorocarbon resin) or nylon which contains plasticizing material.

(3) Tension

If tension is added on optical cable, the increase of transmission loss occurs because of external force which concentrates on the fixing part of optical fiber or the connecting part of optical connector. At worst, the breakage of optical fiber or damage of optical connector may occur. For cable laying, handle without putting forced tension. For the tension strength, refer to Section 11.1.5.

(4) Lateral pressure

If lateral pressure is added on optical cable, the optical cable itself distorts, internal optical fiber gets stressed, and then transmission loss will increase. At worst, the breakage of optical cable may occur. As the same condition also occurs at cable laying, do not tighten up optical cable with a thing such as nylon band (TY-RAP).

Do not trample it down or tuck it down with the door of control box or others.

(5) Twisting

If optical fiber is twisted, it will become the same stress added condition as when local lateral pressure or bend is added. Consequently, transmission loss increases, and the breakage of optical fiber may occur at worst.

(6) Disposal

When incinerating optical cable (cord) used for SSCNETⅢ, hydrogen fluoride gas or hydrogen chloride gas which is corrosive and harmful may be generated. For disposal of optical fiber, request for specialized industrial waste disposal services who has incineration facility for disposing hydrogen fluoride gas or hydrogen chloride gas.

2.5 Inspection Items

⚠WARNING	・Before starting maintenance and/or inspection, make sure that the charge lamp is off more than 15 minutes after power-off. Then, confirm that the voltage is safe in the tester or the like. Otherwise, you may get an electric shock. ・Any person who is involved in inspection should be fully competent to do the work. Otherwise, you may get an electric shock. For repair and parts replacement, contact your safes representative.

POINT
・Do not test the servo amplifier with a megger (measure insulation resistance), or it may become faulty. ・Do not disassemble and/or repair the equipment on customer side.

It is recommended to make the following checks periodically:

(a) Check for loose terminal block screws. Retighten any loose screws.

(b) Check the cables and the like for scratches and cracks. Perform periodic inspection according to operating conditions.

2.6 Parts Having Service Lives

The following parts must be changed periodically as listed below. If any part is found faulty, it must be changed immediately even when it has not yet reached the end of its life, which depends on the operating method and environmental conditions. For parts replacement, please contact your sales representative.

Part name		Life guideline
Servo amplifier	Smoothing capacitor	10 years
	Relay	Number of power-on and number of emergency stop times : 100,000 times
	Cooling fan	10,000 to 30,000hours (2 to 3 years)
	Absolute position battery	Refer to Section 12.2

(a) Smoothing capacitor

Affected by ripple currents, etc. and deteriorates in characteristic. The life of the capacitor greatly depends on ambient temperature and operating conditions. The capacitor will reach the end of its life in 10 years of continuous operation in normal air-conditioned environment.

(b) Relays

Their contacts will wear due to switching currents and contact faults occur. Relays reach the end of their life when the cumulative number of power-on and emergency stop times is 100,000, which depends on the power supply capacity.

(c) Servo amplifier cooling fan

The cooling fan bearings reach the end of their life in 10,000 to 30,000 hours. Normally, therefore, the fan must be changed in a few years of continuous operation as a guideline.

It must also be changed if unusual noise or vibration is found during inspection.

MEMO

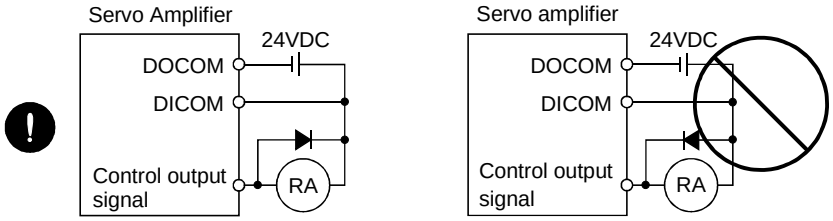
3. SIGNALS AND WIRING

⚠ WARNING

- Any person who is involved in wiring should be fully competent to do the work.
- Before starting wiring, switch power off, then wait for more than 15 minutes, and after the charge lamp has gone off, make sure that the voltage is safe in the tester or like. Otherwise, you may get an electric shock.
- Ground the servo amplifier and the servo motor securely.
- Do not attempt to wire the servo amplifier and servo motor until they have been installed. Otherwise, you may get an electric shock.
- The cables should not be damaged, stressed excessively, loaded heavily, or pinched. Otherwise, you may get an electric shock.

⚠ CAUTION

- Wire the equipment correctly and securely. Otherwise, the servo motor may misoperate, resulting in injury.
- Connect cables to correct terminals to prevent a burst, fault, etc.
- Ensure that polarity (+, −) is correct. Otherwise, a burst, damage, etc. may occur.
- The surge absorbing diode installed to the DC relay designed for control output should be fitted in the specified direction. Otherwise, the signal is not output due to a fault, disabling the forced stop (EM1) and other protective circuits.



- Use a noise filter, etc. to minimize the influence of electromagnetic interference, which may be given to electronic equipment used near the servo amplifier.
- Do not install a power capacitor, surge suppressor or radio noise filter (FR-BIF option) with the power line of the servo motor.
- When using the regenerative brake resistor, switch power off with the alarm signal. Otherwise, a transistor fault or the like may overheat the regenerative brake resistor, causing a fire.
- Do not modify the equipment.

3.1 Input power supply circuit

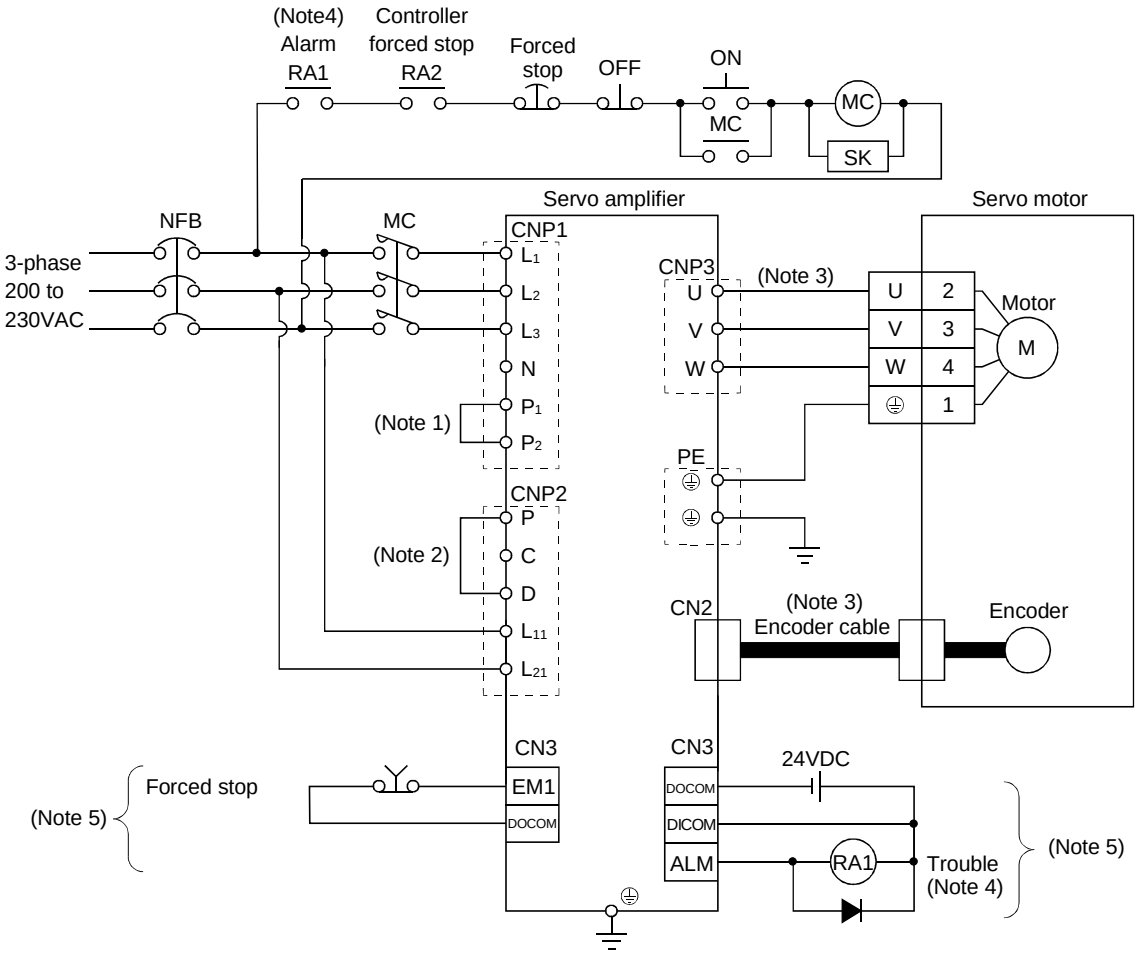
⚠ CAUTION	▪ When the servo amplifier has become faulty, switch power off on the servo amplifier power side. Continuous flow of a large current may cause a fire. ▪ Use the trouble signal to switch main circuit power supply off. Otherwise, a regenerative brake transistor fault or the like may overheat the regenerative brake resistor, causing a fire.

POINT

▪ Even if alarm has occurred, do not switch off the control circuit power supply. When the control circuit power supply has been switched off, optical module does not operate, and optical transmission of SSCNETⅢ communication is interrupted. Therefore, the servo amplifier on the rear axis displays "AA" at the indicator and turns into base circuit shut-off. The servo amplifier stops with starting dynamic brake.

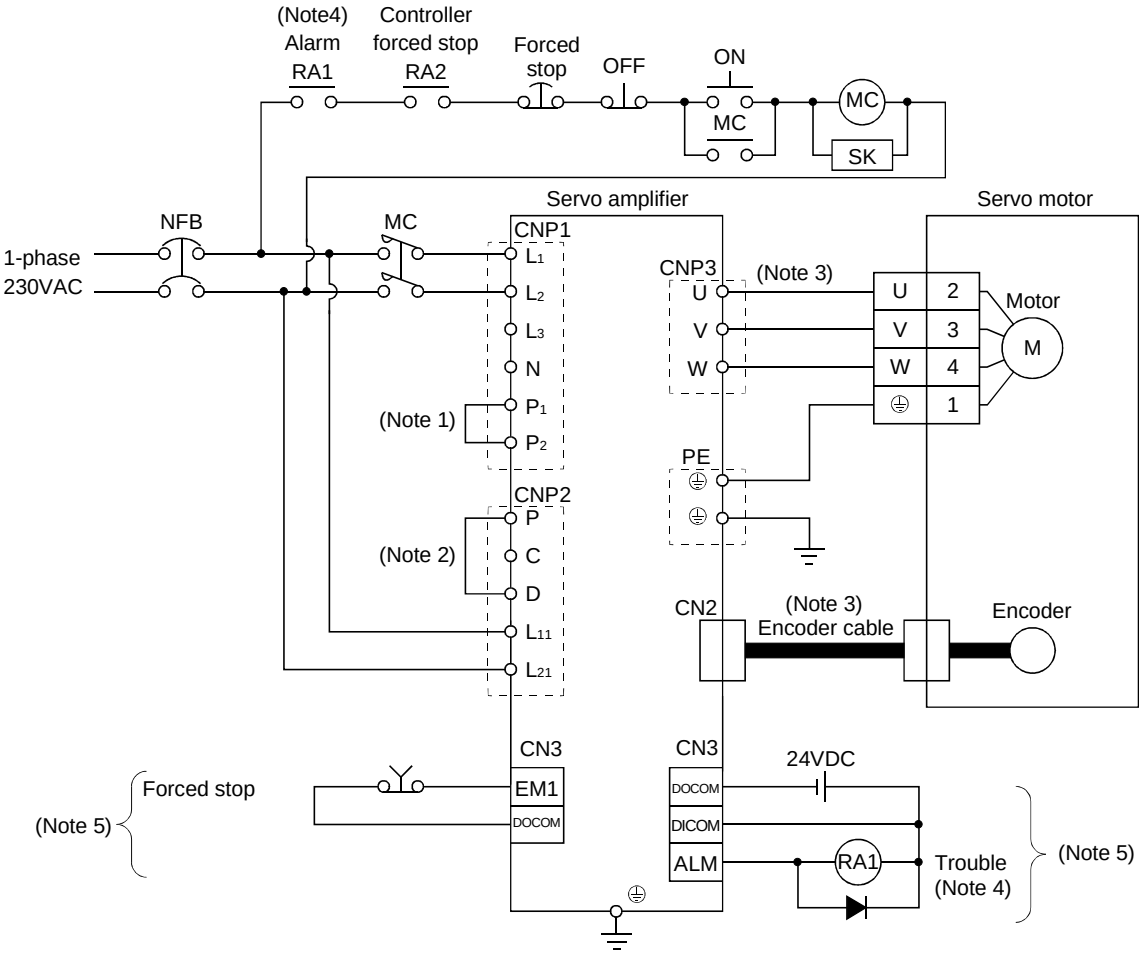
Wire the power supply/main circuit as shown below so that power is shut off and the servo-on command turned off as soon as an alarm occurs, a servo forced stop is made valid, or a controller forced stop is made valid. A no-fuse breaker (NFB) must be used with the input cables of the main circuit power supply.

(1) For 3-phase 200 to 230VAC power supply to MR-J3-10B to MR-J3-350B



Note 1. Always connect P_1-P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to Section 11.10.
2. Always connect P-D. (Factory-wired.) When using the regenerative brake option, refer to Section 11.2.
3. For connection of the servo amplifier and servo motor, use of the option cable is recommended. Refer to Section 11.1 for selection of the cable.
4. If deactivating output of trouble (ALM) with parameter change, configure up the power supply circuit which switches off the magnetic contactor after detection of alarm occurrence on the controller side.
5. For the sink I/O interface. For the source I/O interface, refer to Section 3.7.3.

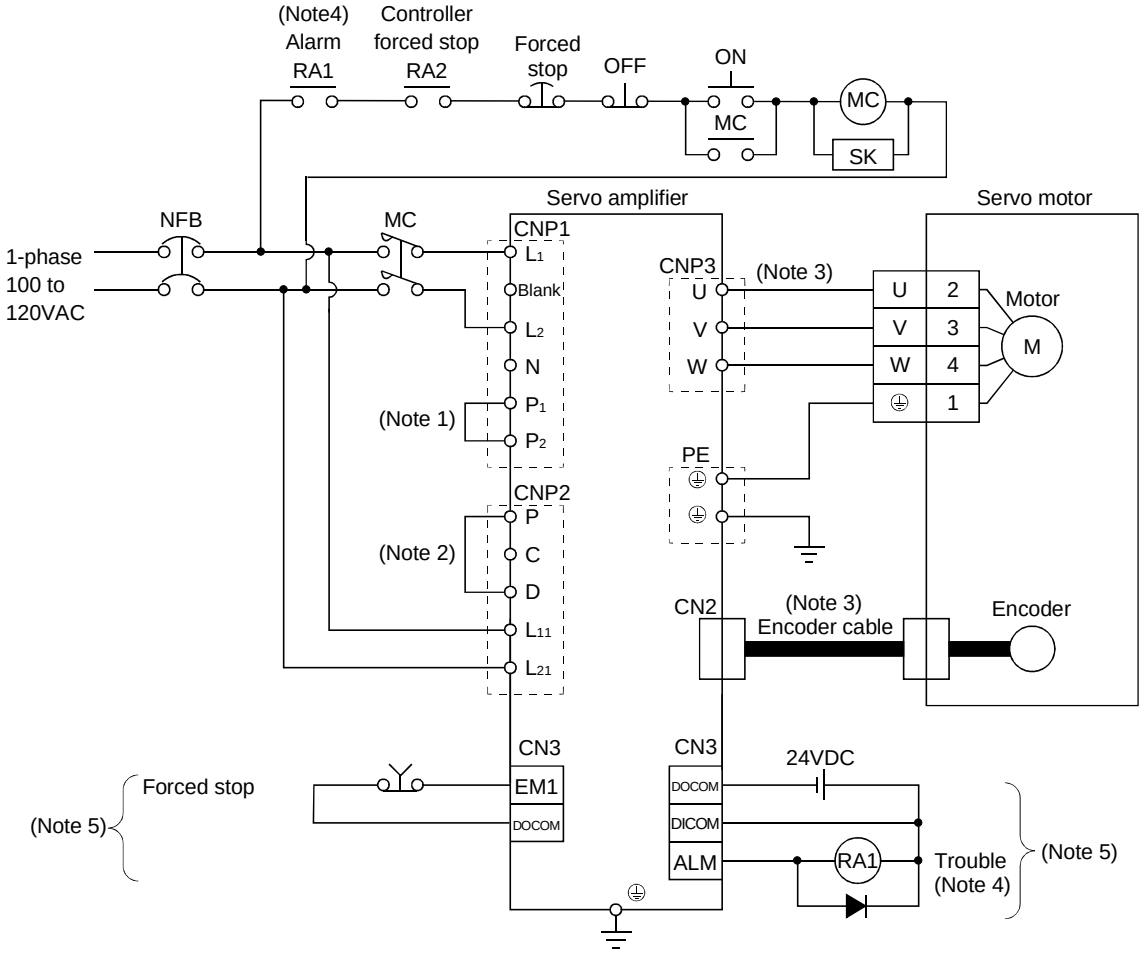
(2) For 1-phase 230VAC power supply to MR-J3-10B to MR-J3-70B



Note 1. Always connect P_1-P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to Section 11.10.

2. Always connect P-D. (Factory-wired.) When using the regenerative brake option, refer to Section 11.2.
3. For connection of the servo amplifier and servo motor, use of the option cable is recommended. Refer to Section 11.1 for selection of the cable.
4. If deactivating output of trouble (ALM) with parameter change, configure up the power supply circuit which switches off the magnetic contactor after detection of alarm occurrence on the controller side.
5. For the sink I/O interface. For the source I/O interface, refer to Section 3.7.3.

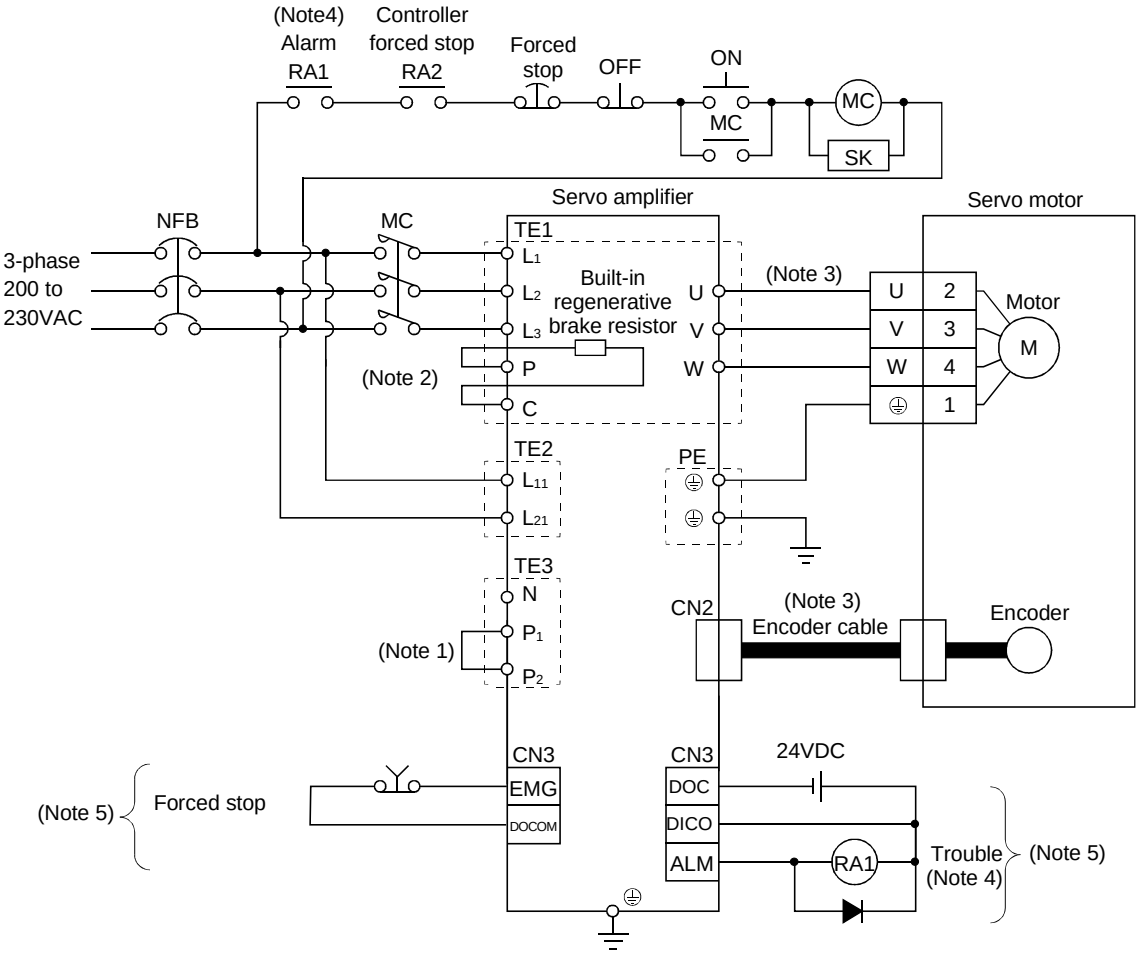
(3) For MR-J3-10B1 to MR-J3-40B1



Note 1. Always connect P_1-P_2. (Factory-wired.) The power factor improving DC reactor cannot be used.

2. Always connect P-D. (Factory-wired.) When using the regenerative brake option, refer to Section 11.2.
3. For connection of the servo amplifier and servo motor, use of the option cable is recommended. Refer to Section 11.1 for selection of the cable.
4. If deactivating output of trouble (ALM) with parameter change, configure up the power supply circuit which switches off the magnetic contactor after detection of alarm occurrence on the controller side.
5. For the sink I/O interface. For the source I/O interface, refer to Section 3.7.3.

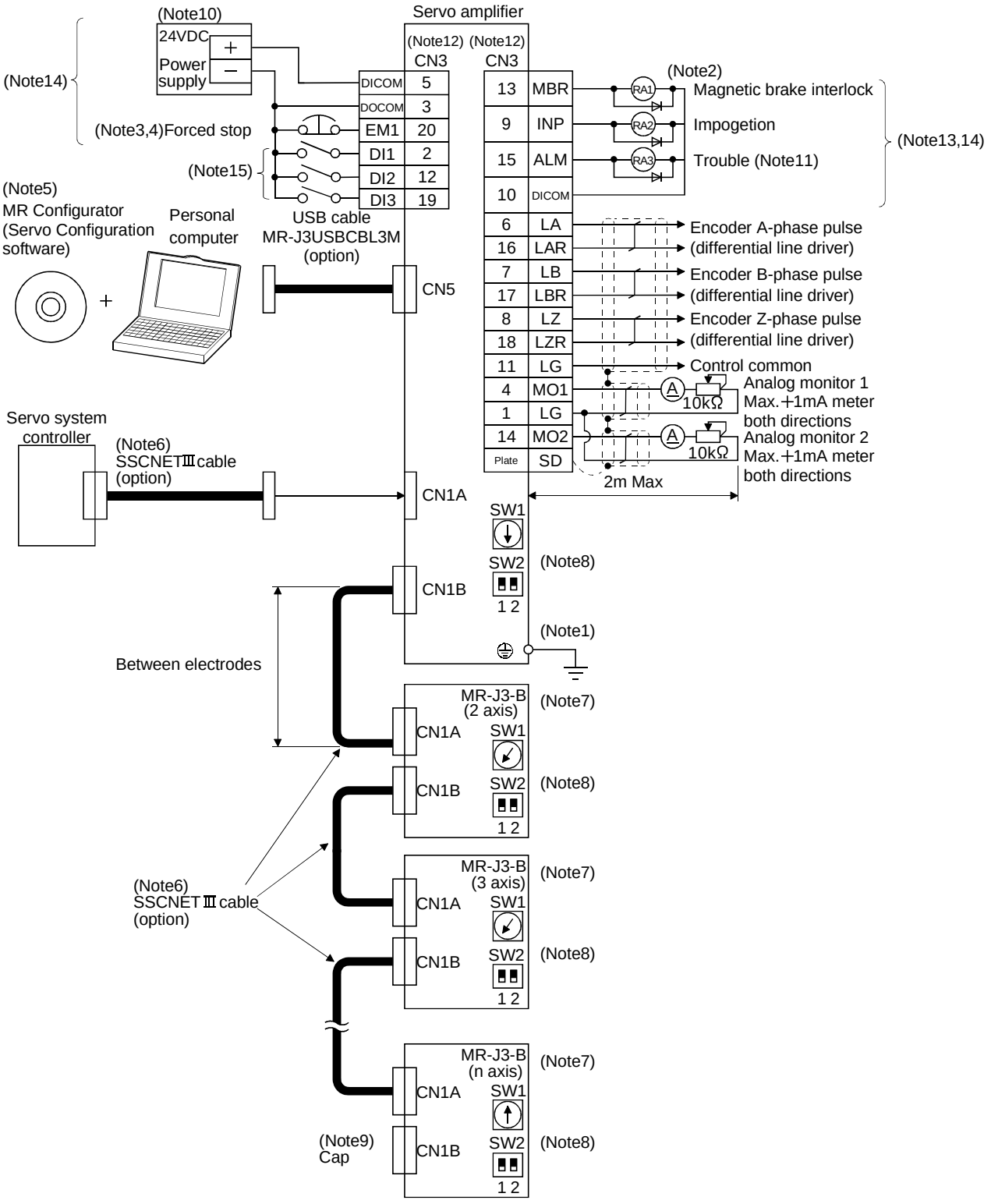
(4) MR-J3-500B · MR-J3-700B



Note 1. Always connect P_1-P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to Section 11.10.

2. When using the regenerative brake option, refer to Section 11.2.
3. For connection of the servo amplifier and servo motor, use of the option cable is recommended. Refer to Section 11.1 for selection of the cable.
4. If deactivating output of trouble (ALM) with parameter change, configure up the power supply circuit which switches off the magnetic contactor after detection of alarm occurrence on the controller side.
5. For the sink I/O interface. For the source I/O interface, refer to Section 3.7.3.

3.2 I/O signal Connection Example



Note 1 To prevent an electric shock, always connect the protective earth (PE) terminal (terminal marked ⏚) of the servo amplifier to the protective earth (PE) of the control box.

2. Connect the diode in the correct direction. If it is connected reversely, the servo amplifier will be faulty and will not output signals, disabling the forced stop (EM1) and other protective circuits.
3. If the controller does not have an forced stop (EM1) function, always install a forced stop switch (Normally closed).
4. When starting operation, always turn on the forced stop (EM1). (Normally closed contacts) By setting "□1□□ " in DRU parameter No.PA04 of the drive unit, the forced stop (EM1) can be made invalid.
5. Use MRZJW3-SETUP 221E.
6. For the distance between electrodes of SSCNETⅢ cable, refer to the following table.

Cable	Cable model name	Cable length	Distance between electrodes
Standard code inside panel	MR-J3BUS □ M	0.15m to 3m	20m
Standard cable outside panel	MR-J3BUS □ M-A	5m to 20m	
Long-distance cable	MR-J3BUS □ M-B	30m to 50m	50m

7. The wiring of the second and subsequent axes is omitted.
8. Up to eight axes (n = 1 to 8) may be connected. Refer to Section 3.13 for setting of axis selection.
9. Make sure to put a cap on the unused CN1A・CN1B.
10. Supply 24VDC±10% 150mA current for interfaces from the outside. 150mA is the value applicable when all I/O signals are used. The current capacity can be decreased by reducing the number of I/O points. Refer to Section 3.7.2 (1) that gives the current value necessary for the interface.
11. Trouble (ALM) turns on in normal alarm-free condition. When this signal is switched off (at occurrence of an alarm), the output of the programmable controller should be stopped by the sequence program.
12. The pins with the same signal name are connected in the servo amplifier.
13. The signal can be changed by parameter No.PD07, PD08, PD09.
14. For the sink I/O interface. For the source I/O interface, refer to Section 3.7.3.
15. Devices can be assigned for DI1・DI2・DI3 with controller setting. For devices that can be assigned, refer to the controller instruction manual. The following devices can be assigned for Q172HCPU・Q173HCPU・QD75MH.
    DI1: upper stroke limit (FLS)
    DI2: lower stroke limit (RLS)
    DI3: near-point dog (DOG)

3.3 Explanation of Power Supply System

3.3.1 Signal explanations

POINT

・For the layout of connector and terminal block, refer to outline drawings in Chapter 9.

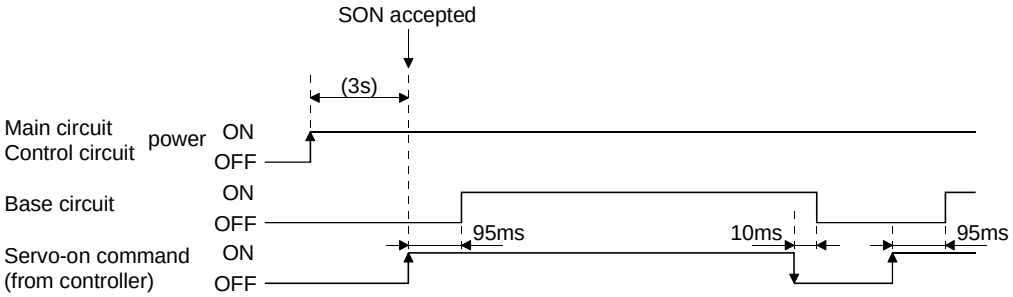
<table>
<tr><th>Abbreviation</th><th>Connection Target (Application)</th><th>Description</th></tr>
<tr><td>L_1
L_2
L_3</td><td>Main circuit power supply</td><td>Supply the following power to L_1, L_2, L_3. For the 1-phase 230VAC power supply, connect the power supply to L_1, L_2, and keep L_3 open.
<table>
<tr><th>Servo amplifier / Power supply</th><th>MR-J3-10B to 70B</th><th>MR-J3-100B to 700B</th><th>MR-J3-10B1 to 40B1</th></tr>
<tr><td>3-phase 200 to 230VAC, 50/60Hz</td><td colspan="2">L_1・L_2・L_3</td><td></td></tr>
<tr><td>1-phase 230VAC, 50/60Hz</td><td>L_1・L_2</td><td></td><td></td></tr>
<tr><td>1-phase 100 to 120VAC, 50/60Hz</td><td></td><td></td><td>L_1・L_2</td></tr>
</table></td></tr>
<tr><td>P_1
P_2</td><td>Power factor improving DC reactor</td><td>When not using the power factor improving DC reactor, connect P_1-P_2. (Factory-wired.)
When using the power factor improving DC reactor, disconnect the wiring across P_1-P_2 and connect the power factor improving DC reactor across P_1-P_2. (Refer to Section 11.10.)</td></tr>
<tr><td>P
C
D</td><td>Regenerative brake option</td><td>1) MR-J3-350B or less
When using servo amplifier built-in regenerative brake resistor, connect between P-D terminals. (Wired by default)
When using regenerative brake option, disconnect between P-D terminals and connect regenerative brake option to P terminal and C terminal.
2) MR-J3-500B.700B
MR-J3-500B and 700B do not have D terminal.
When using servo amplifier built-in regenerative brake resistor, connect P terminal and C terminal. (Wired by default)
When using regenerative brake option, disconnect P terminal and C terminal and connect regenerative brake option to P terminal and C terminal. (Refer to Section 11.2)</td></tr>
<tr><td>L_{11}
L_{21}</td><td>Control circuit power supply</td><td>
<table>
<tr><th>Servo amplifier / Power supply</th><th>MR-J3-10B to 700B</th><th>MR-J3-10B1 to 40B1</th></tr>
<tr><td>1-phase 200 to 230VAC, 50/60Hz</td><td>L_{11}・L_{21}</td><td></td></tr>
<tr><td>1-phase 100 to 120VAC, 50/60Hz</td><td></td><td>L_{11}・L_{21}</td></tr>
</table></td></tr>
<tr><td>U
V
W</td><td>Servo motor power</td><td>Connect to the servo motor power supply terminals (U, V, W).</td></tr>
<tr><td>N</td><td>Return converter
Brake unit</td><td>When using return converter/brake unit, connect to P terminal and N terminal.
Do not connect to servo amplifier MR-J3-350B or less.
For details, refer to Section 11.3, 11.4.</td></tr>
<tr><td>⏚</td><td>Protective earth (PE)</td><td>Connect to the earth terminal of the servo motor and to the protective earth (PE) of the control box to perform grounding.</td></tr>
</table>

3.3.2 Power-on sequence

(1) Power-on procedure

1) Always wire the power supply as shown in above Section 3.1 using the magnetic contactor with the main circuit power supply (three-phase 200V: L_1, L_2, L_3, single-phase 230V・signal-phase 100V: L_1, L_2). Configure up an external sequence to switch off the magnetic contactor as soon as an alarm occurs.
2) Switch on the control circuit power supply L11, L21 simultaneously with the main circuit power supply or before switching on the main circuit power supply. If the main circuit power supply is not on, the display shows the corresponding warning. However, by switching on the main circuit power supply, the warning disappears and the servo amplifier will operate properly.
3) The servo amplifier can accept the servo-on command within 3s the main circuit power supply is switched on. (Refer to paragraph (2) in this section.)

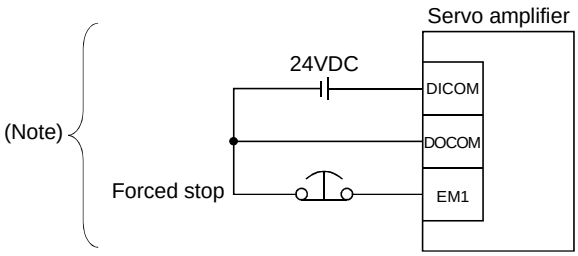
(2) Timing chart



(3) Forced stop

> **CAUTION** ・Install an forced stop circuit externally to ensure that operation can be stopped and power shut off immediately.

If the controller does not have an forced stop function, make up a circuit that switches off main circuit power as soon as EM1 is turned off at a forced stop. When EM1 is turned off, the dynamic brake is operated to stop the servo motor. At this time, the display shows the servo forced stop warning (E6).
During ordinary operation, do not use forced stop (EM1) to alternate stop and run. The service life of the servo amplifier may be shortened.



Note. For the sink I/O interface. For the source I/O interface, refer to Section 3.7.3.

3.3.3 CNP1, CNP2, CNP3 wiring method

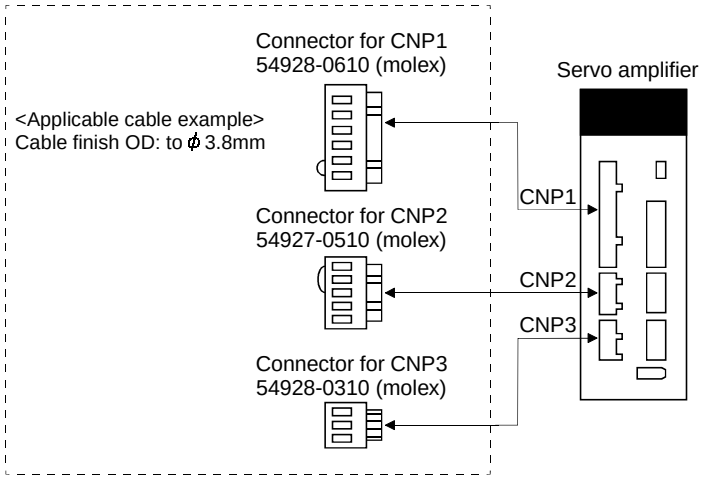
> **POINT**
> - Refer to Table 11.1 in Section 11.8 for the wire sizes used for wiring.
> - MR-J3-500B or more does not have these connectors.

Use the supplied servo amplifier power supply connectors for wiring of CNP1, CNP2 and CNP3.

(1) MR-J3-100B or less

(a) Servo amplifier power supply connectors

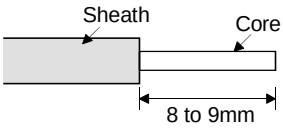
(Note)
Servo amplifier power supply connectors



Note. These connectors are of insert type. As the crimping type, the following connectors (molex) are recommended.
For CNP1: 51241-0600 (connector), 56125-0118 (terminal)
For CNP2: 51240-0500 (connector), 56125-0118 (terminal)
For CNP3: 51241-0300 (connector), 56125-0118 (terminal)
Crimping tool: CNP57349-5300
<Connector applicable cable example>
Cable finish OD: to ϕ3.8mm

(b) Termination of the cables

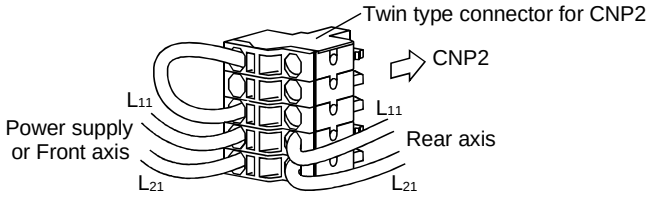
Solid wire: After the sheath has been stripped, the cable can be used as it is.



Twisted wire: Use the cable after stripping the sheath and twisting the core. At this time, take care to avoid a short caused by the loose wires of the core and the adjacent pole. Do not solder the core as it may cause a contact fault. Alternatively, a bar terminal may be used to put the wires together.

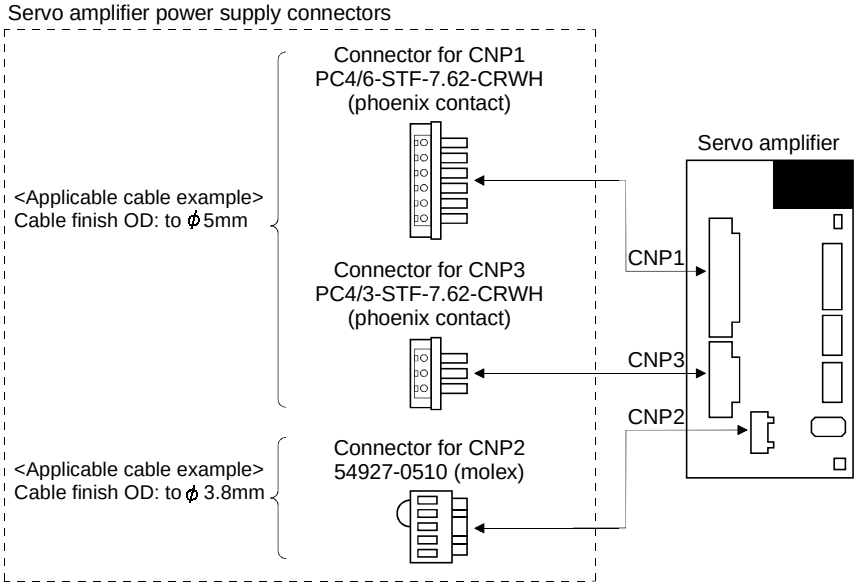
Cable size		Bar terminal type		Crimping tool	Maker
[mm^2]	AWG	For 1 cable	For 2 cables		
1.25	16	BT1.25-9-1		NH1	NICHIFU
		TUB-1.25		YHT-2210	JST
1.5	16	AI1.5-8BK	AI-TWIN2 × 1.5-8BK	CRIMPFOX-UD6	Phoenix Contact
			AI-TWIN2 × 1.5-12BK		
2	14	BT2-9-1		NH1	NICHIFU
		TUB-2		YHT-2210	JST

(c) The twin type connector for CNP2 (L_{11} ・ L_{21}): 721-2105/026-000 (WAGO)
it is used for control circuit power supply wiring.
Refer to Appendix 3 for details of connector.



(2) MR-J3-200B ・ MR-J3-350B

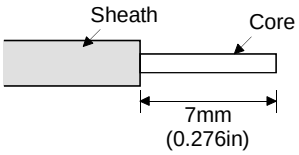
(a) Servo amplifier power supply connectors



(b) Termination of the cables

1) CNP1 · CNP3

Solid wire: After the sheath has been stripped, the cable can be used as it is.



Twisted wire: Use the cable after stripping the sheath and twisting the core. At this time, take care to avoid a short caused by the loose wires of the core and the adjacent pole. Do not solder the core as it may cause a contact fault. Alternatively, a bar terminal may be used to put the wires together.

Cable size		Bar terminal type		Crimping tool	Maker
[mm^2]	AWG	For 1 cable	For 2 cables		
0.34	22	AI0.34-8TQ		CRIMPFOX-ZA3	Phoenix Contact
0.5	20	AI0.5-8WH	AI-TWIN2 × 0.5-8WH		
0.75	18	AI0.75-8GY	AI-TWIN2 × 0.75-8GY		
1	18	AI1-8RD	AI-TWIN2 × 1-8RD		
1.5	16	AI1.5-8BK	AI-TWIN2 × 1.5-8BK		
2.5	14	AI2.5-8BU	AI-TWIN2 × 2.5-8BU		

2) CNP2

CNP2 is the same as MR-J3-100B or smaller capacities. Refer to (1) (b) in this section.

(c) As twin type connector for CNP2 (L_{11}, L_{21}) is the same as MR-J3-100B or smaller.

Refer to (1) (C) in this section.

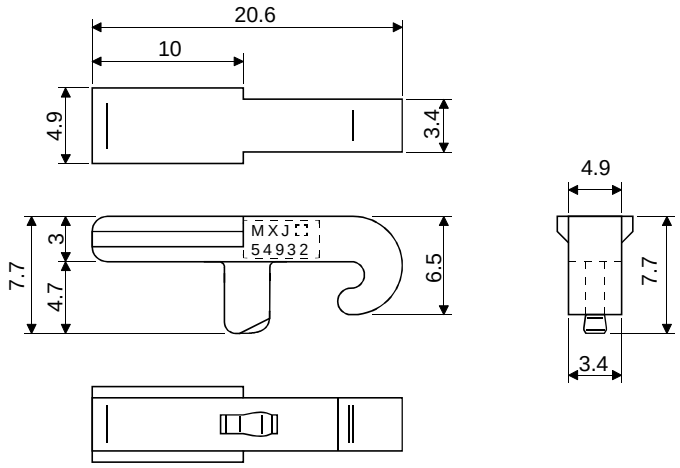
(3) Insertion of cable into 54928-0610 · 54927-0510 and 54928-0310 (Molex)

How to connect a cable to the servo amplifier power supply connector is shown below.

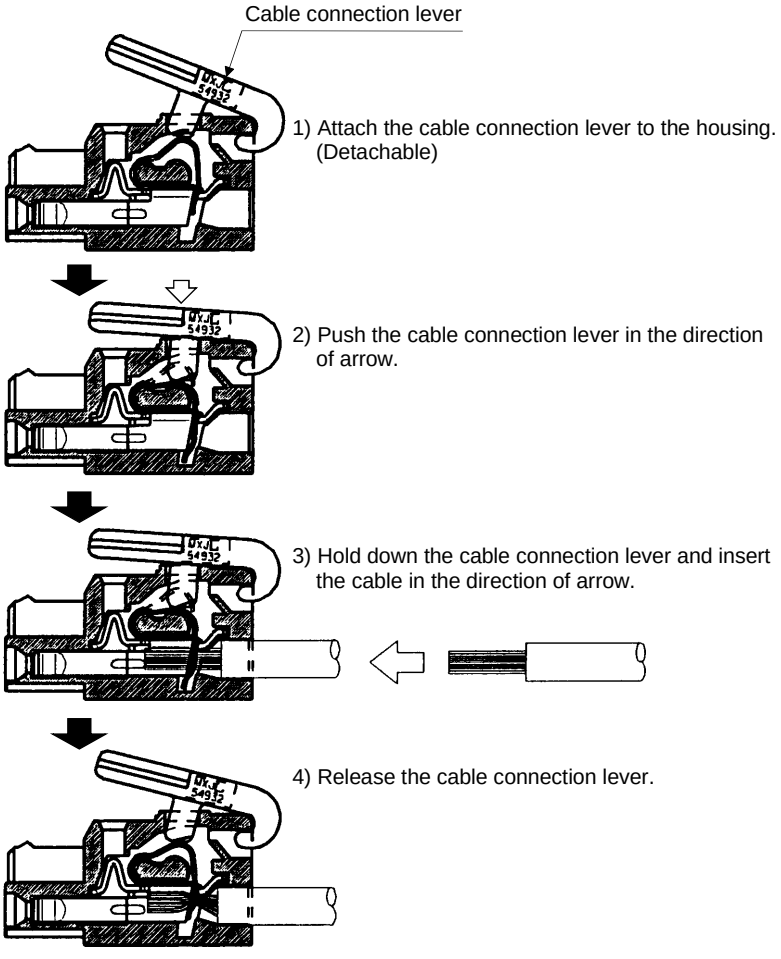
(a) When using the supplied cable connection lever

1) The servo amplifier is packed with the cable connection lever 54932-0000 (Molex).

[Unit: mm]



2) Cable connection procedure

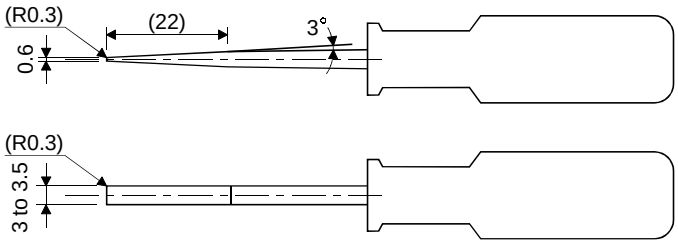


(b) Inserting the cable into the connector

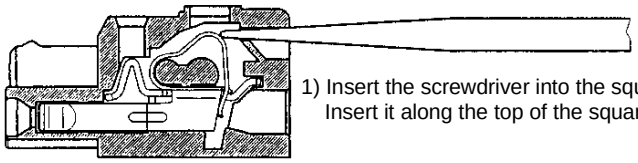
1) Applicable flat-blade screwdriver dimensions

Always use the screwdriver shown here to do the work.

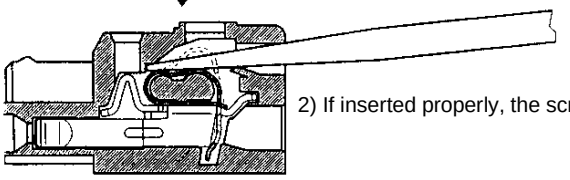
[Unit: mm]



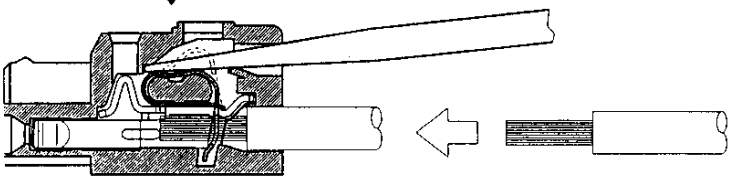
2) When using the flat-blade screwdriver - part 1



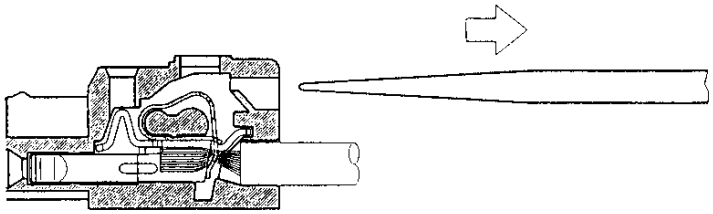
1) Insert the screwdriver into the square hole.
Insert it along the top of the square hole to insert it smoothly.



2) If inserted properly, the screwdriver is held.

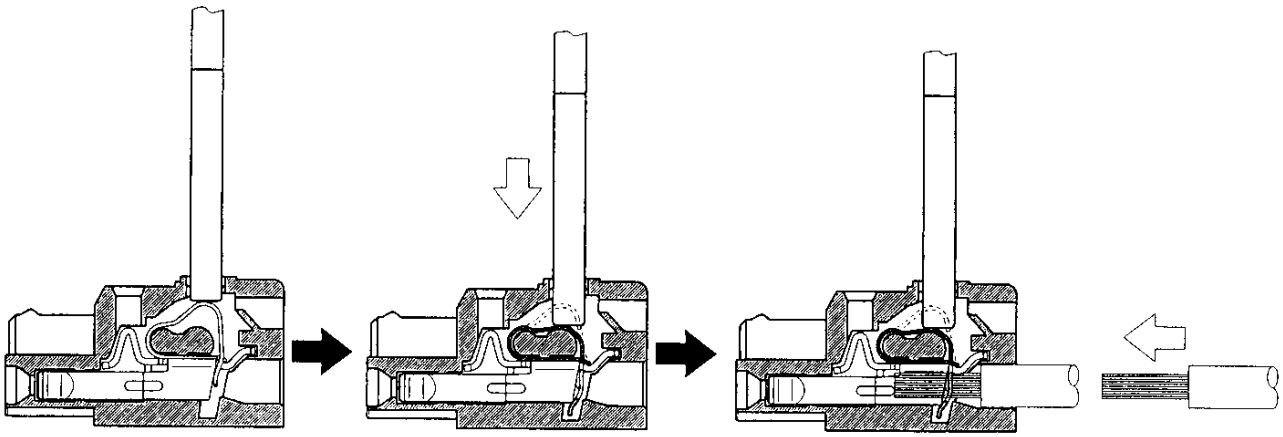


3) With the screwdriver held, insert the cable in the direction of arrow. (Insert the cable as far as it will go.)



4) Releasing the screwdriver connects the cable.

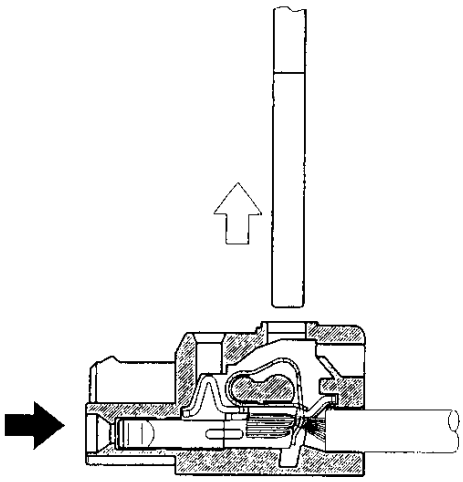
3) When using the flat-blade screwdriver - part 2



1) Insert the screwdriver into the square window at top of the connector.

2) Push the screwdriver in the direction of arrow.

3) With the screwdriver pushed, insert the cable in the direction of arrow. (Insert the cable as far as it will go.)

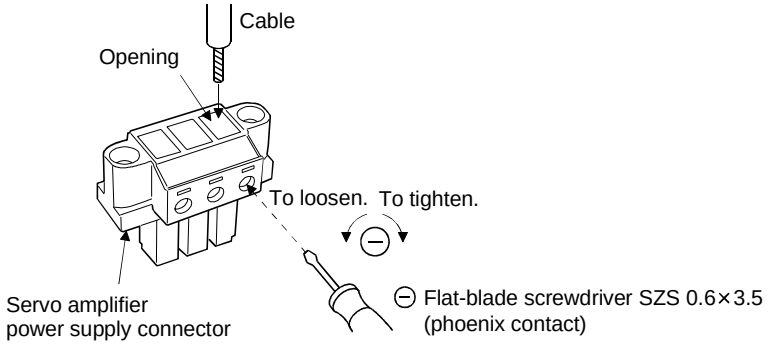


4) Releasing the screwdriver connects the cable.

(4) How to insert the cable into PC4/6-STF-7.62-CRWH or PC4/3-STF-7.62-CRWH connector

Insert the core of the cable into the opening and tighten the screw with a flat-blade screwdriver so that the cable does not come off. (Tightening torque: 0.5 to 0.6N m(4.425 to 5.31 lb in)) Before inserting the cable into the opening, make sure that the screw of the terminal is fully loose.

When using a cable of 1.5mm^2 or less, two cables may be inserted into one opening.

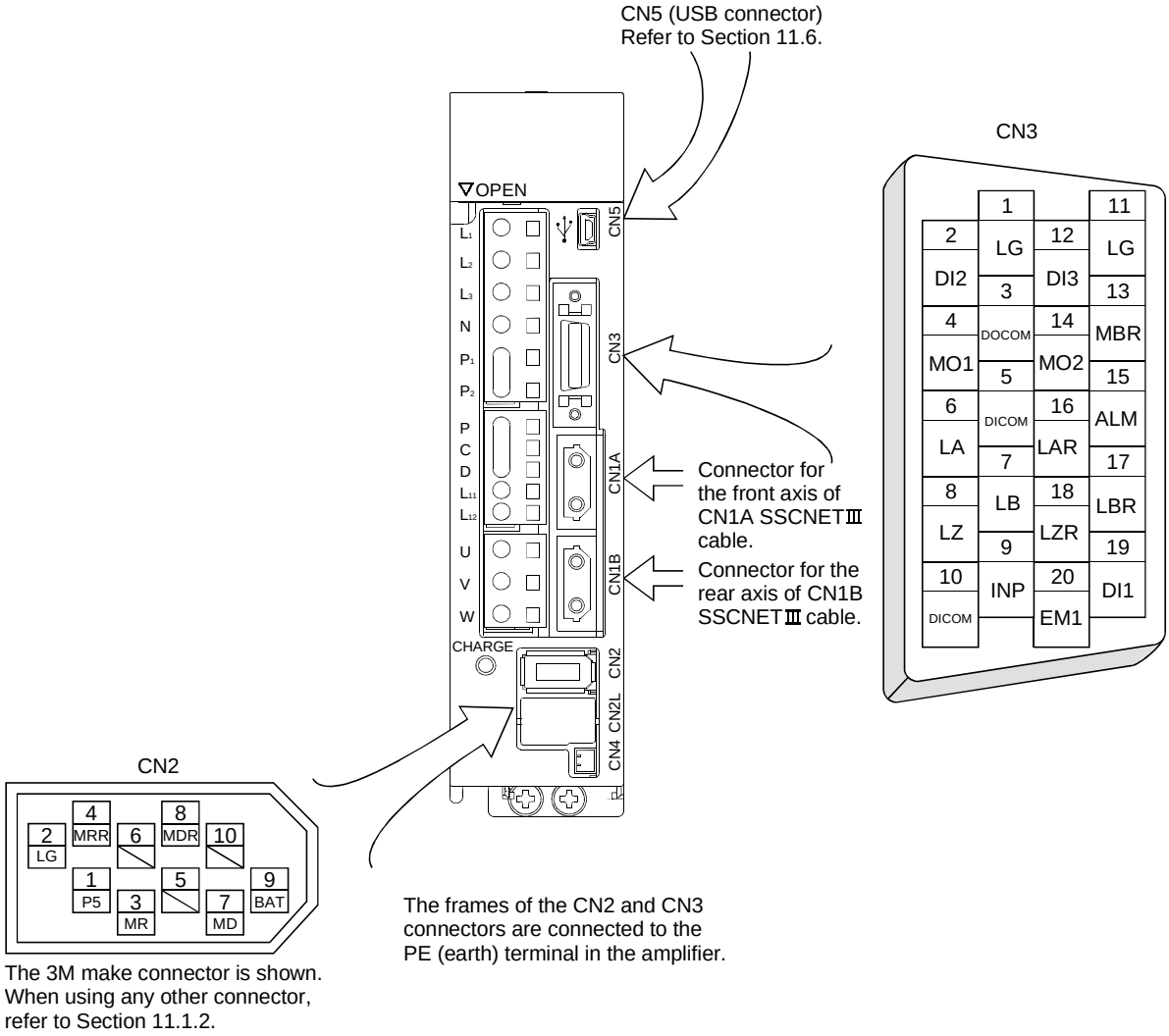


3.4 Connectors and signal arrangements

POINT
▪ The pin configurations of the connectors are as viewed from the cable connector wiring section.

(1) Signal arrangement

The servo amplifier front view shown is that of the MR-J3-20B or less. Refer to Chapter 9 Outline Drawings for the appearances and connector layouts of the other servo amplifiers.



3.5 Signal (device) explanations

For the I/O interfaces (symbols in I/O division column in the table), refer to Section 3.7.2.
In the control mode field of the table
The pin No.s in the connector pin No. column are those in the initial status.

(1) Connector applications

Connector	Name	Function/Application
CN1A	Connector for bus cable from preceding axis.	Used for connection with the controller or preceding-axis servo amplifier.
CN1B	Connector for bus cable to next axis	Used for connection with the next-axis servo amplifier or for connection of the cap.
CN2	Encoder connector	Used for connection with the servo motor encoder.
CN4	Battery connection connector	When using as absolute position detection system, connect to battery (MR-J3BAT). For setting battery, make sure that charge lamp is off more than 15 minutes after main circuit power is switched off. Then, confirm that the voltage between P-N terminals in the tester or the like. Replace the battery with main circuit power OFF and with control circuit power ON. Replacing the battery with the control circuit power OFF results in loosing absolute position data.
CN5	Communication connector	The personal computer is connected.

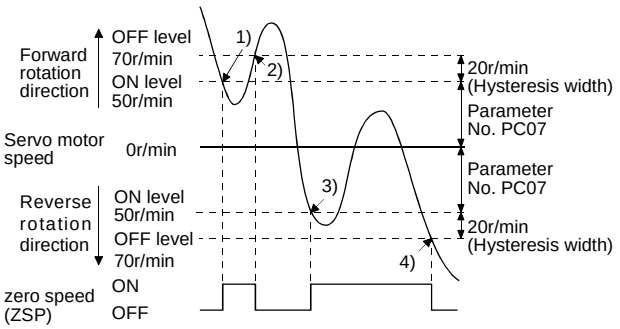
(2) I/O device

(a) Input device

Device	Symbol	Connector Pin No.	Function/Application	I/O division
Forced stop	EM1	CN3-20	Turn EM1 off (open between commons) to bring the motor to an forced stop state, in which the base circuit is shut off and the dynamic brake is operated. Turn EM1 on (short between commons) in the forced stop state to reset that state. When parameter No.PA.04 is set to " □1□□ ", automatically ON (always ON) can be set inside.	DI-1
	DI1	CN3-19	Devices can be assigned for DI1 DI2 DI3 with controller setting. For devices that can be assigned, refer to the controller instruction manual. The following devices can be assigned for Q172HCPU Q173HCPU QD75MH. DI1: upper stroke limit (FLS) DI2: lower stroke limit (RLS) DI3: near-point dog (DOG)	DI-1
	DI2	CN3-2		DI-1
	DI3	CN3-12		DI-1

(b) Output device

Device	Symbol	Connector Pin No.	Function/Application	I/O division
Trouble	ALM	CN3-15	ALM turns off when power is switched off or the protective circuit is activated to shut off the base circuit. Without alarm occurring, ALM turns on within about 1.5s after power-on.	DO-1
Electromagnetic brake interlock	MBR	CN3-13	When using this signal, set operation delay time of the electromagnetic brake in parameter No.PC02. In the servo-off or alarm status, MBR turns off.	DO-1
In-position (Positioning completed)	INP	CN3-9	INP turns on when the number of droop pulses is in the preset in-position range. The in-position range can be changed using parameter No. PA10. When the in-position range is increased, INP may be on conductive status during low-speed rotation. INP turns on when servo on turns on. This signal cannot be used in the speed loop mode.	DO-1
Ready	RD		When using the signal, make it usable by the setting of parameter No.PD07 to PD09. RD turns on when the servo is switched on and the servo amplifier is ready to operate.	DO-1

Device	Symbol	Connector Pin No.	Function/Application	I/O division
Speed reached	SA		When using this signal, make it usable by the setting of parameter No.PD07 to PD09. When the servo is off, SA will be turned OFF. When servo motor rotation speed becomes approximately setting speed, SA will be turned ON. When the preset speed is 20r/min or less, SA always turns on. This signal cannot be used in position loop mode.	DO-1
Limiting torque	TLC		When using this signal, make it usable by the setting of parameter No.PD07 to PD09. When torque is produced level of torque set with controller, TLC will be turned ON. When the servo is off, TLC will be turned OFF.	DO-1
Zero speed	ZSP		When using this signal, make it usable by the setting of parameter No.PD07 to PD09. When the servo is off, SA will be turned OFF. ZSP turns on when the servo motor speed is zero speed (50r/min) or less. Zero speed can be changed using parameter No. PC07. Example Zero speed is 50r/min  ZPS turns on 1) when the servo motor is decelerated to 50r/min, and ZPS turns off 2) when the servo motor is accelerated to 70r/min again. ZPS turns on 3) when the servo motor is decelerated again to -50r/min, and turns off 4) when the servo motor speed has reached -70r/min. The range from the point when the servo motor speed has reached ON level, and ZPS turns on, to the point when it is accelerated again and has reached OFF level is called hysteresis width. Hysteresis width is 20r/min for the MR-J3-B servo amplifier.	DO-1
Warning	WNG		When using this signal, make it usable by the setting of parameter No.PD07 to PD09. When warning has occurred, WNG turns on. When there is no warning, WNG turns off within about 1.5s after power-on.	DO-1
Battery warning	BWNG		When using this signal, make it usable by the setting of parameter No.PD07 to PD09. BWNG turns on when battery cable breakage warning (92) or battery warning (9F) has occurred. When there is no battery warning, BWNG turns off within about 1.5s after power-on.	DO-1
Variable gain selection	CDPS		When using this signal, make it usable by the setting of parameter No.PD07 to PD09. CDPS is on during variable gain.	DO-1
Absolute position erasing	ABSV		When using this signal, make it usable by the setting of parameter No.PD07 to PD09. ABSV turns on when the absolute position erased. This signal cannot be used in position loop mode.	DO-1

(C) Output signals

Signal name	Symbol	Connector Pin No.	Function/Application
Encoder A-phase pulse (Differential line driver)	LA LAR	CN3-6 CN3-16	Outputs pulses per servo motor revolution set in parameter No. PA15 in the differential line driver system. In CCW rotation of the servo motor, the encoder B-phase pulse lags the encoder A-phase pulse by a phase angle of π/2. The relationships between rotation direction and phase difference of the A- and B-phase pulses can be changed using parameter No. PC03. Output pulse specification and dividing ratio setting can be set. (Refer to Section 5.1.9.)
Encoder B-phase pulse (Differential line driver)	LB LBR	CN3-7 CN3-17	
Encoder Z-phase pulse (Differential line driver)	LZ LZR	CN3-8 CN3-18	Outputs the zero-point signal in the differential line driver system of the encoder. One pulse is output per servo motor revolution. turns on when the zero-point position is reached. The minimum pulse width is about 400μs. For home position return using this pulse, set the creep speed to 100r/min. or less.
Analog monitor 1	MO1	CN3-4	Used to output the data set in parameter No. PC09 to across MO1-LG in terms of voltage. Resolution 10 bits
Analog monitor 2	MO2	CN3-14	Used to output the data set in parameter No. PC10 to across MO2-LG in terms of voltage. Resolution 10 bits

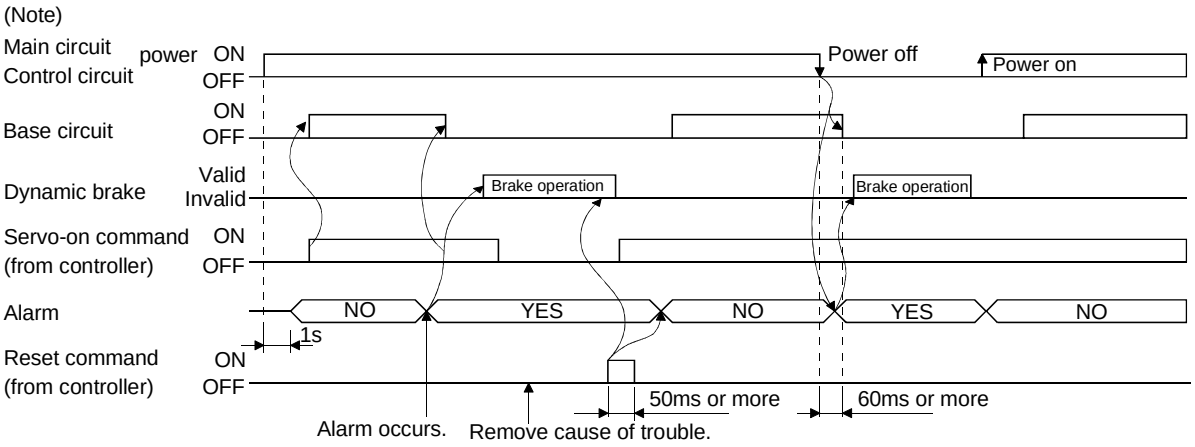
(d) Power supply

Signal name	Symbol	Connector Pin No.	Function/Application
Digital I/F power supply input	DICOM	CN3-5 CN3-10	Used to input 24VDC (150mA) for input interface. The power supply capacity changes depending on the number of I/O interface points to be used. Connect the positive terminal of the 24VDC external power supply. 24VDC±10% Pins are connected internally.
Digital I/F common	DOCOM	CN1-46 CN1-47	Connect ⊖ of DC24V external power supply. Common terminal for input signals such as EM1. Pins are connected internally. Separated from LG.
Monitor common	LG	CN3-1 CN3-11	Common terminal of M01 · M02 Pins are connected internally.
Shield	SD	Plate	Connect the external conductor of the shield cable.

3.6 Alarm occurrence timing chart

⚠ CAUTION	▪ When an alarm has occurred, remove its cause, make sure that the operation signal is not being input, ensure safety, and reset the alarm before restarting operation. ▪ As soon as an alarm occurs, make the Servo off status and interrupt the main circuit power.

When an alarm occurs in the servo amplifier, the base circuit is shut off and the servo motor is coated to a stop. Switch off the main circuit power supply in the external sequence. To deactivate the alarm, power the control circuit off, then on or give the error reset or CPU reset command from the servo system controller. However, the alarm cannot be deactivated unless its cause is removed.



Note. Switch off the main circuit power as soon as an alarm occurs.

(1) Overcurrent, overload 1 or overload 2

If operation is repeated by switching control circuit power off, then on to reset the overcurrent (32), overload 1 (50) or overload 2 (51) alarm after its occurrence, without removing its cause, the servo amplifier and servo motor may become faulty due to temperature rise. Securely remove the cause of the alarm and also allow about 30 minutes for cooling before resuming operation.

(2) Regenerative alarm

If operation is repeated by switching control circuit power off, then on to reset the regenerative (30) alarm after its occurrence, the external regenerative brake resistor will generate heat, resulting in an accident.

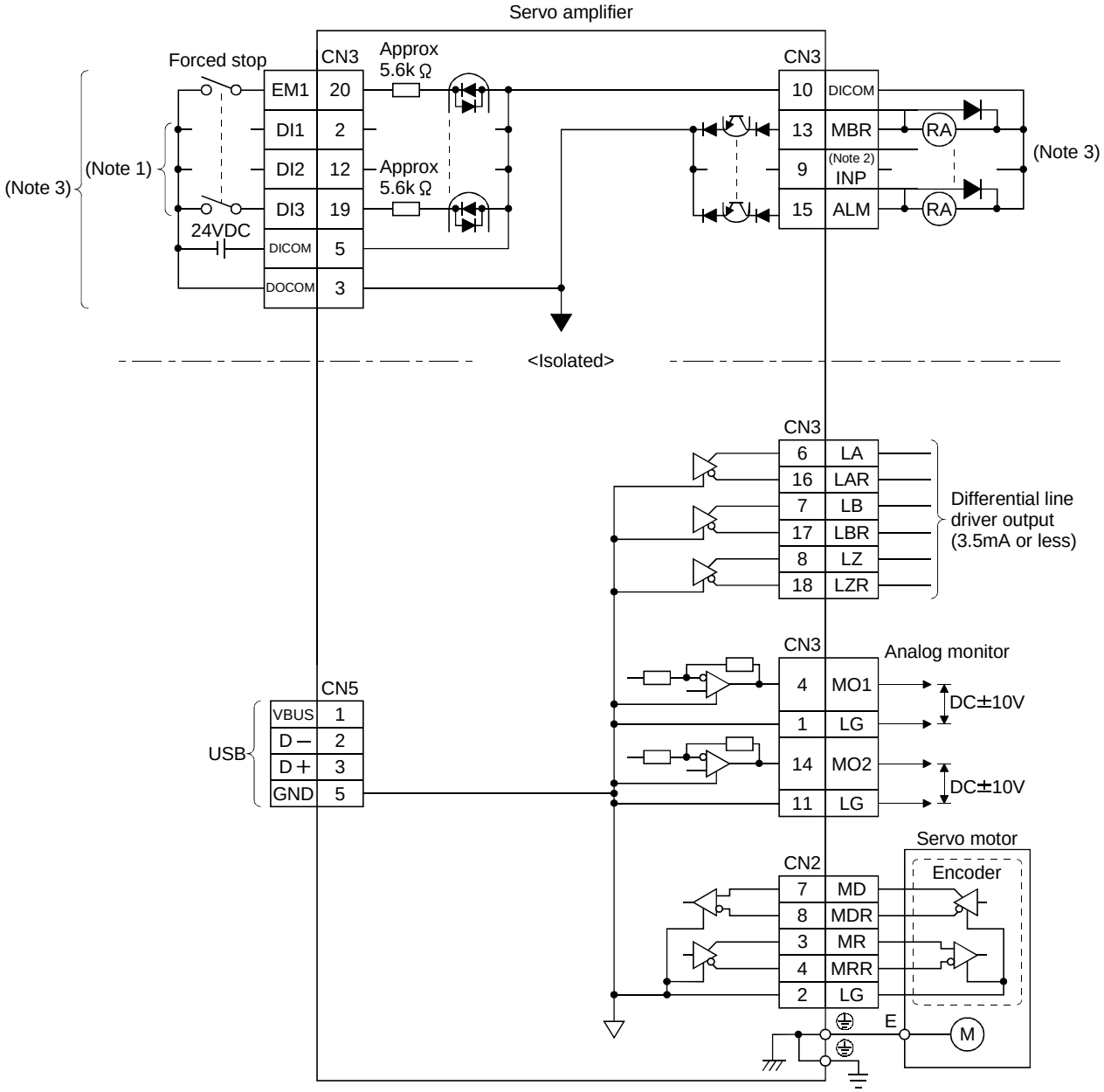
(3) Instantaneous power failure

Undervoltage (10) occurs when the input power is in either of the following statuses.

- A power failure of the control circuit power supply continues for 60ms or longer and the control circuit is not completely off.
- The bus voltage dropped to 200VDC or less for the MR-J3-□B, or to 158VDC or less for the MR-J3-□B1.

3.7 Interfaces

3.7.1 Internal connection diagram



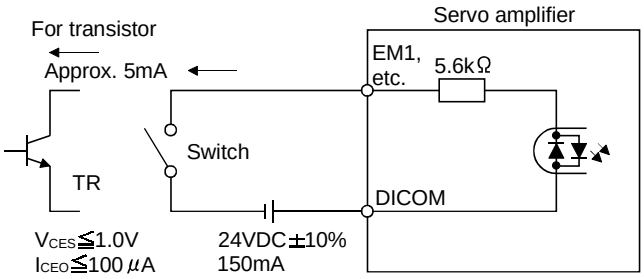
Note 1. Signal can be assigned for these pins with host controller setting.
For contents of signals, refer to the instruction manual of host controller.
2. This signal cannot be used with speed loop mode.
3. For the sink I/O interface. For the source I/O interface, refer to Section 3.7.3.

3.7.2 Detailed description of interfaces

This section provides the details of the I/O signal interfaces (refer to the I/O division in the table) given in Section 3.5. Refer to this section and make connection with the external equipment.

(1) Digital input interface DI-1

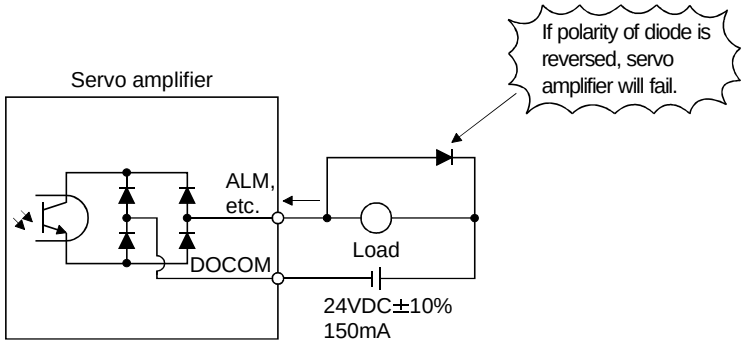
Give a signal with a relay or open collector transistor. Refer to Section 3.7.3 for the source input.



(2) Digital output interface DO-1

A lamp, relay or photocoupler can be driven. Install a diode (D) for an inductive load, or install an inrush current suppressing resistor (R) for a lamp load. (Permissible current: 40mA or less, inrush current: 100mA or less) A maximum of 2.6V voltage drop occurs in the servo amplifier.

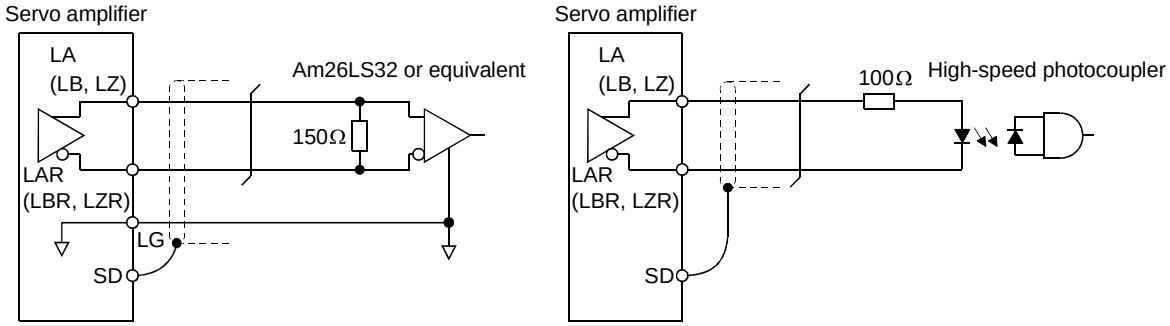
Refer to Section 3.7.3 for the source output.



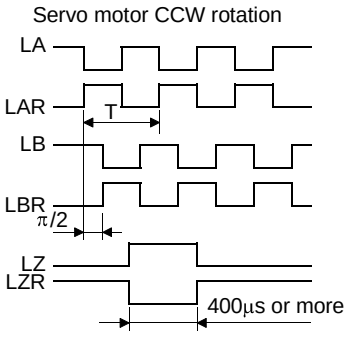
(3) Encoder pulse output DO-2 (Differential line driver system)

(a) Interface

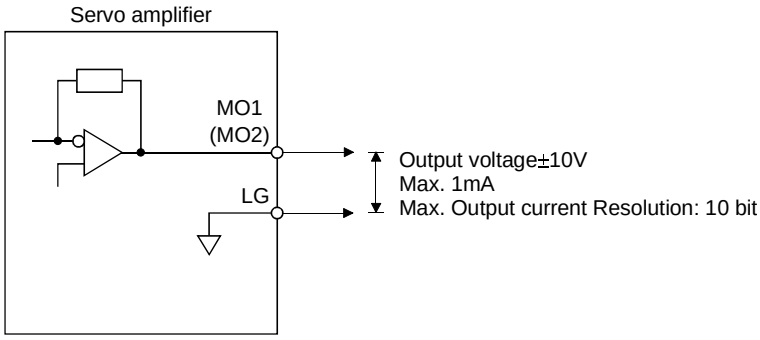
Max. output current: 35mA



b) Output pulse



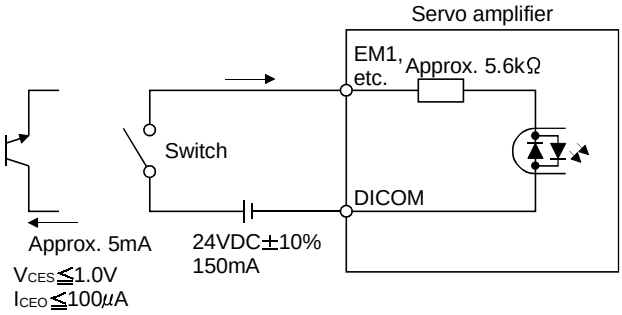
(4) Analog output



3.7.3 Source I/O interfaces

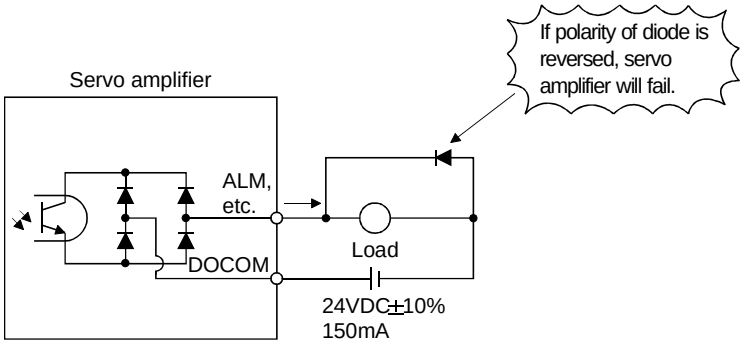
In this servo amplifier, source type I/O interfaces can be used. In this case, all DI-1 input signals and DO-1 output signals are of source type. Perform wiring according to the following interfaces.

(1) Digital input interface DI-1



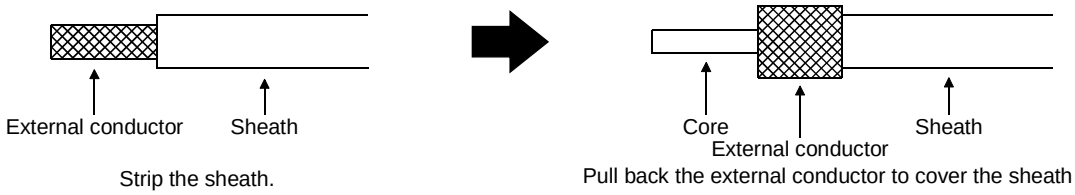
(2) Digital output interface DO-1

A maximum of 2.6V voltage drop occurs in the servo amplifier.



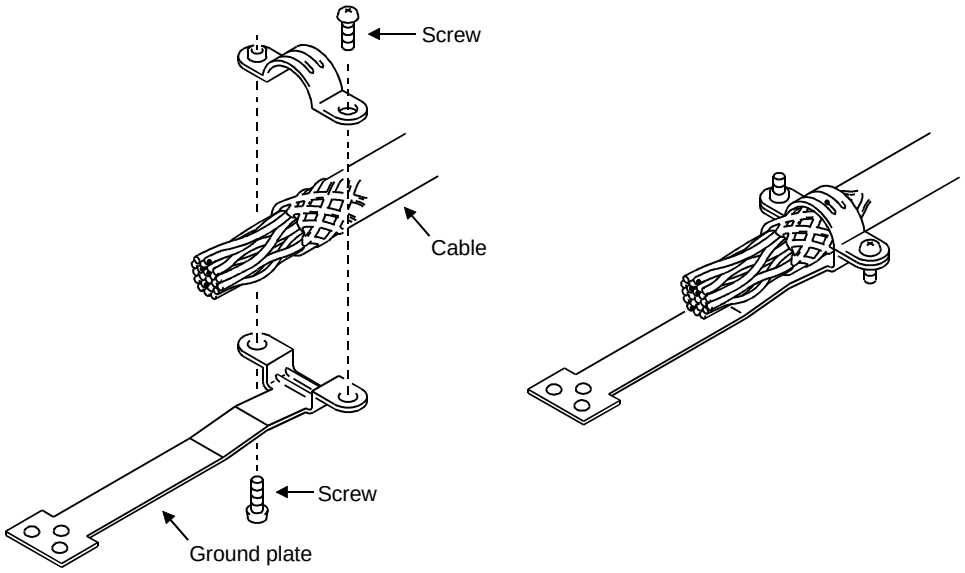
3.8 Instructions for the 3M connector

In the case of the CN3 connector, securely connect the shielded external conductor of the cable to the ground plate as shown in this section and fix it to the connector shell.



Strip the sheath.

Pull back the external conductor to cover the sheath

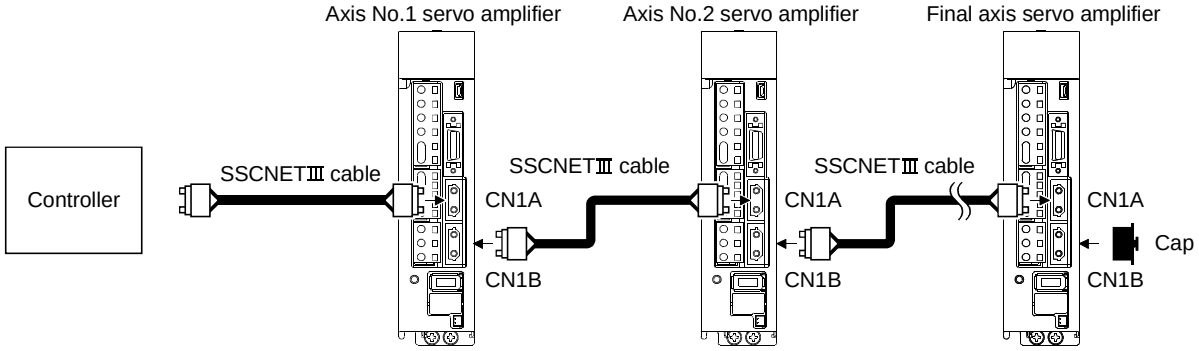


3.9 SSCNETⅢ cable connection

POINT
・Do not see directly the light generated from CN1A・CN1B connector of servo amplifier or the end of SSCNETⅢ cable. When the light gets into eye, may feel something is wrong for eye. (The light source of SSCNETⅢ corresponds to class1 defined in JISC6802 or IEC60825-1.)

(1) SSCNETⅢ cable connection

For CN1A connector, connect SSCNETⅢ cable connected to controller in host side or servo amplifier.
For CN1B, connect SSCNETⅢ cable connected to servo amplifier in lower side.
For CN1B connector of the final axis, put a cap came with servo amplifier.



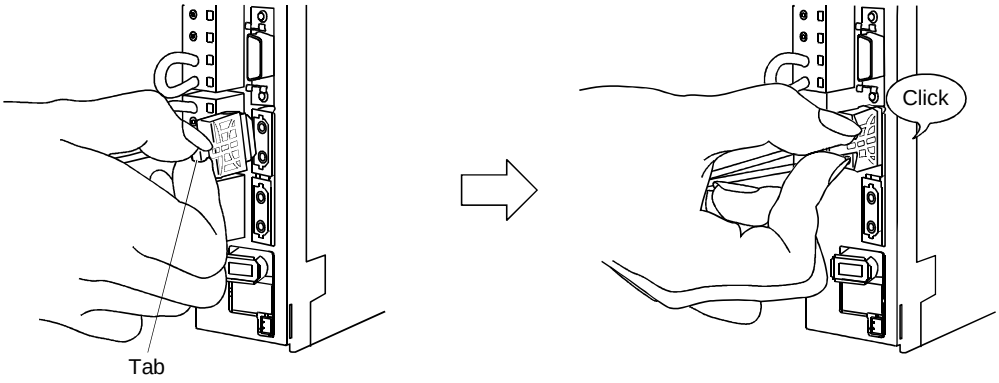
(2) How to connect/disconnect cable.

POINT
・CN1A・CN1B connector is put a cap to protect light device inside connector from dust. For this reason, do not remove a cap until just before mounting SSCNETⅢ cable. Then, when removing SSCNETⅢ cable, make sure to put a cap. ・Keep the cap for CN1A・CN1B connector and the tube for protecting light code end of SSCNETⅢ cable in a plastic bag with a zipper of SSCNETⅢ cable to prevent them from becoming dirty. ・When asking repair of servo amplifier for some troubles, make sure to put a cap on CN1A・CN1B connector. When the connector is not put a cap, the light device may be damaged at the transit. In this case, exchange and repair of light device is required.

(a) Mounting

1) For SSCNETⅢ cable in the shipping status, the tube for protect light code end is put on the end of connector. Remove this tube.
2) Remove the CN1A・CN1B connector cap of servo amplifier.

3) With holding a tab of SSCNETⅢ cable connector, make sure to insert it into CN1A・CN1B connector of servo amplifier until you hear the click.
If the end face of optical code tip is dirty, optical transmission is interrupted and it may cause malfunctions.
If it becomes dirty, wipe with a bonded textile, etc.
Do not use solvent such as alcohol.



(b) Removal

With holding a tab of SSCNETⅢ cable connector, pull out the connector.
When pulling out the SSCNETⅢ cable from servo amplifier, be sure to put the cap on the connector parts of servo amplifier to prevent it from becoming dirty.
For SSCNETⅢ cable, attach the tube for protection optical code's end face on the end of connector.

3.10 Connection of servo amplifier and servo motor

3.10.1 Connection instructions

⚠ WARNING	・Insulate the connections of the power supply terminals to prevent an electric shock.

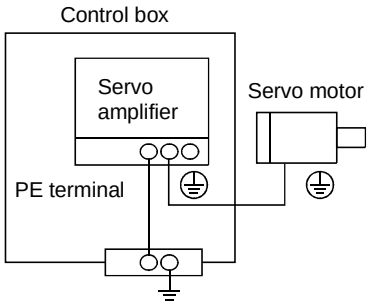
⚠ CAUTION	・Connect the wires to the correct phase terminals (U, V, W) of the servo amplifier and servo motor. Otherwise, the servo motor will operate improperly. ・Do not connect AC power supply directly to the servo motor. Otherwise, a fault may occur.

POINT

・Refer to Section 11.1 for the selection of the encoder cable.

This section indicates the connection of the motor power supply (U, V, W). Use of the optional cable and connector set is recommended for connection between the servo amplifier and servo motor. When the options are not available, use the recommended products. Refer to Section 11.1 for details of the options.

(1) For grounding, connect the earth cable of the servo motor to the protective earth (PE) terminal of the servo amplifier and connect the ground cable of the servo amplifier to the earth via the protective earth of the control box. Do not connect them directly to the protective earth of the control panel.

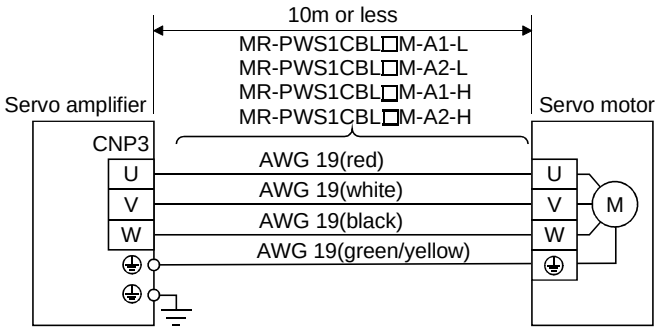


(2) Do not share the 24VDC interface power supply between the interface and electromagnetic brake. Always use the power supply designed exclusively for the electromagnetic brake.

3.10.2 Power supply cable wiring diagrams

(1) HF-MP service · HF-KP series servo motor

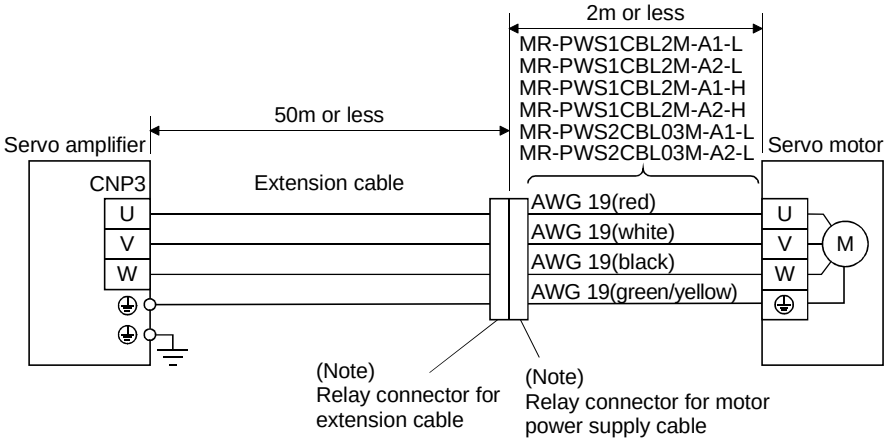
(a) When cable length is 10m or less



(b) When cable length exceeds 10m

When the cable length exceeds 10m, fabricate an extension cable as shown below. In this case, the motor power supply cable pulled from the servo motor should be within 2m long.

Refer to Section 11.8 for the wire used for the extension cable.



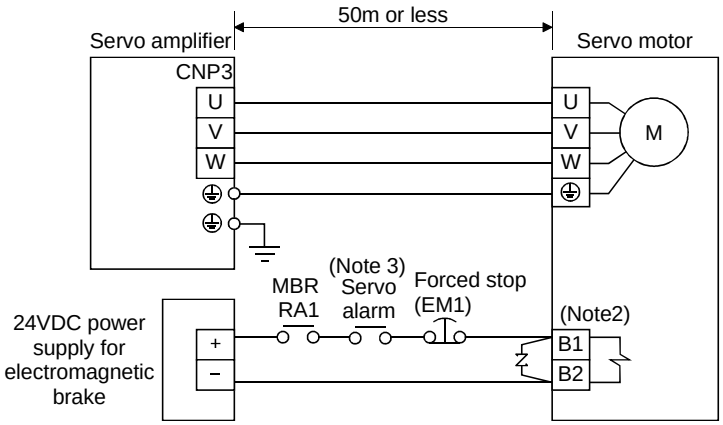
Note. Use of the following connectors is recommended when ingress protection (IP65) is necessary.

Relay Connector	Description	Protective Structure
Relay connector for extension cable	Connector: RM15WTP-4P Cord clamp: RM-15WTP-CP(5) (Hirose Electric) └ Numeral changes depending on the cable OD	IP65
Relay connector for motor power supply cable	Connector: RM15WTJA-4S Cord clamp: RM-15WTP-CP(8) (Hirose Electric) └ Numeral changes depending on the cable OD	IP65

(2) HF-SP series servo motor

(a) Wiring diagrams

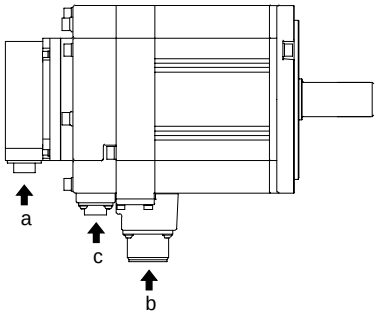
Refer to Section 11.8 for the cables used for wiring.



Note 1. Shut off the circuit upon detection of a servo alarm.
2. There is no polarity in electromagnetic brake terminals B1 and B2.
3. Configure up the power supply circuit in which the dynamic brake acts after detection of alarm occurrence on the controller side.

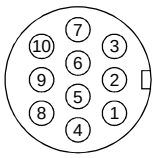
(b) Connector and signal allotment

The connector fitting the servomotor is prepared as optional equipment. Refer to Section 11.1. For types other than those prepared as optional equipment, refer to Section 3 in Servomotor Technical Reference, Vol. 2 to select.



Servo motor	Servo motor side connectors		
	Encoder	Power supply	Electromagnetic brake
HF-SP52 to 152	CN10-R10P (DDK)	MS3102A18-10P	CM10-R2P (DDK)
HF-SP51 ▪ 81			
HF-SP202 to 502		MS3102A22-22P	
HF-SP121 ▪ 201			
HF-SP702		CE05-2A32-17RD-B	

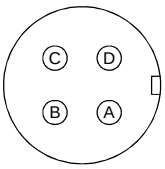
Detector connector signal allotment
CN10-R10P



View a

Terminal No.	Signal
1	MR
2	MRR
3	
4	BAT
5	LG
6	
7	
8	P5
9	
10	SHD

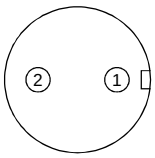
Power supply connector signal allotment
MS3102A18-10P
MS3102A22-22P
CE05-2A32-17PD-B



View b

Terminal No.	Signal
A	U
B	V
C	W
D	⏚

Brake connector signal allotment
CM10-R2P



View c

Terminal No.	Signal
1	B1 (Note)
2	B2 (Note)

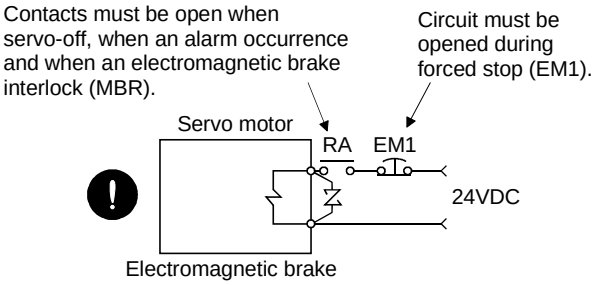
Note. For the motor with electromagnetic brake, supply electromagnetic brake power (24VDC). There is no polarity.

3.11 Servo motor with electromagnetic brake

3.11.1 Safety precautions

CAUTION

- Configure the electromagnetic brake circuit so that it is activated not only by the interface unit signals but also by a forced stop (EM1).



- The electromagnetic brake is provided for holding purpose and must not be used for ordinary braking.

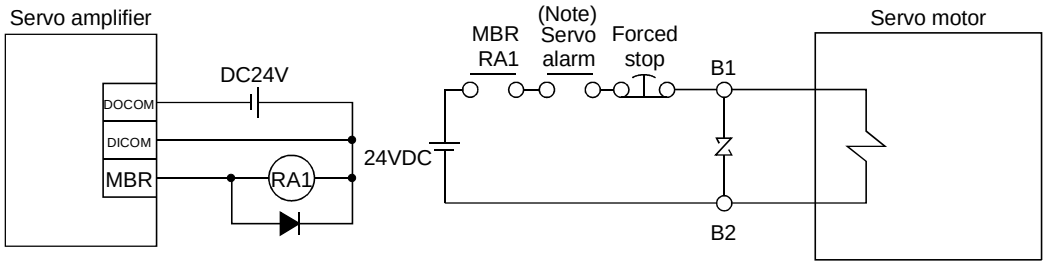
POINT

- Refer to the Servo Motor Instruction Manual for specifications such as the power supply capacity and operation delay time of the electromagnetic brake.

Note the following when the servo motor equipped with electromagnetic brake is used :

1) Do not share the 24VDC interface power supply between the interface and electromagnetic brake. Always use the power supply designed exclusively for the electromagnetic brake.
2) The brake will operate when the power (24VDC) switches off.
3) Switch off the servo-on command after the servo motor has stopped.

(1) Connection diagram



Note. Configure up the power supply circuit in which the dynamic brake acts after detection of alarm occurrence on the controller side.

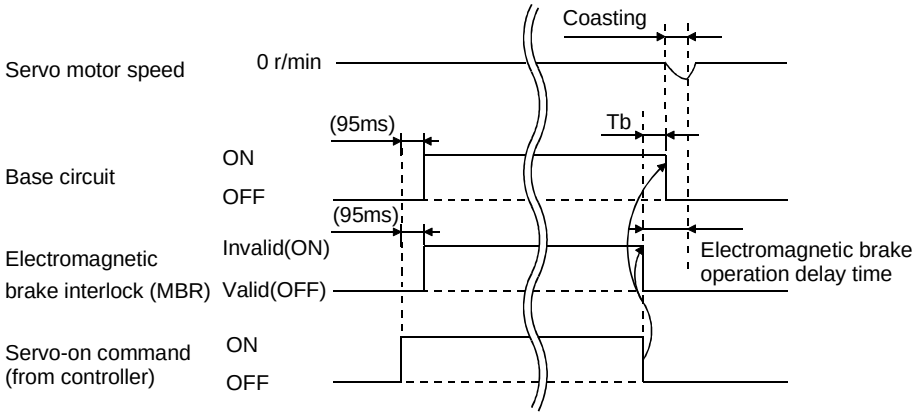
(2) Setting

In parameter No.PC02 (electromagnetic brake sequence output), set the time delay (Tb) from electromagnetic brake operation to base circuit shut-off at a servo off time as in the timing chart in 3.11.2 in this section.

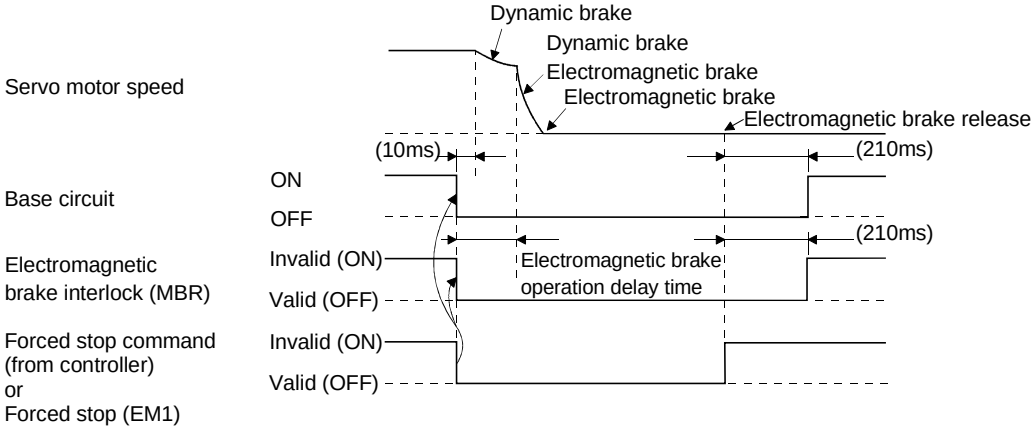
3.11.2 Timing charts

(1) Servo-on command (from controller) ON/OFF

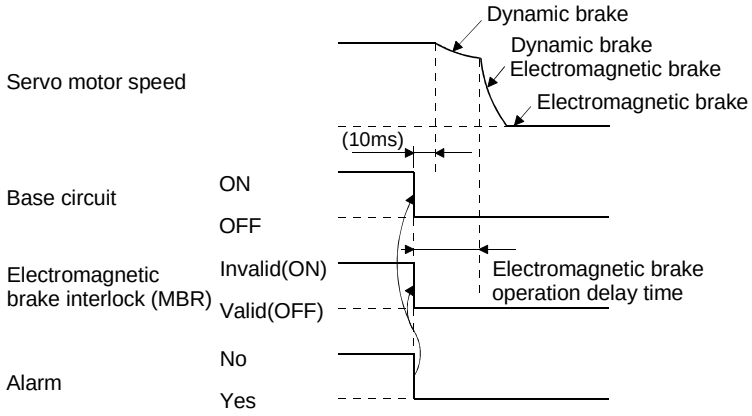
Tb [ms] after the servo-on is switched off, the servo lock is released and the servo motor coasts. If the electromagnetic brake is made valid in the servo lock status, the brake life may be shorter. Therefore, when using the electromagnetic brake in a vertical lift application or the like, set delay time (Tb) to about the same as the electromagnetic brake operation delay time to prevent a drop.



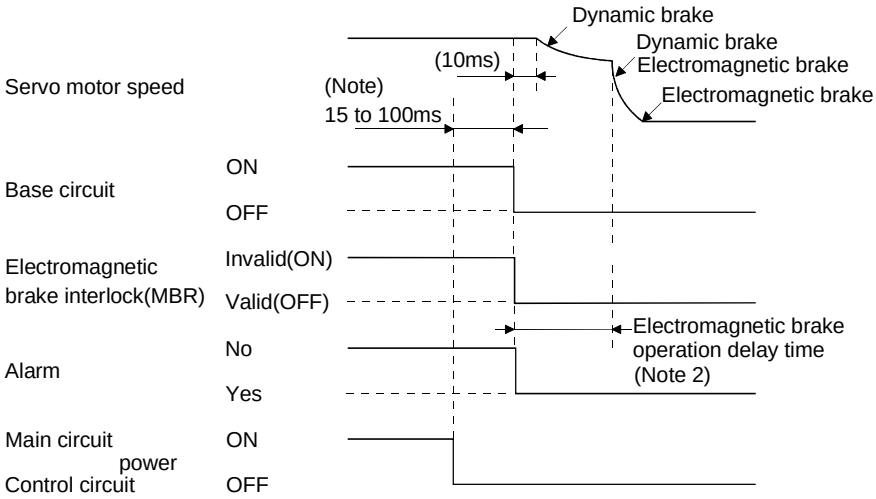
(2) Forced stop command (from controller) or forced stop (EM1) ON/OFF



(3) Alarm occurrence

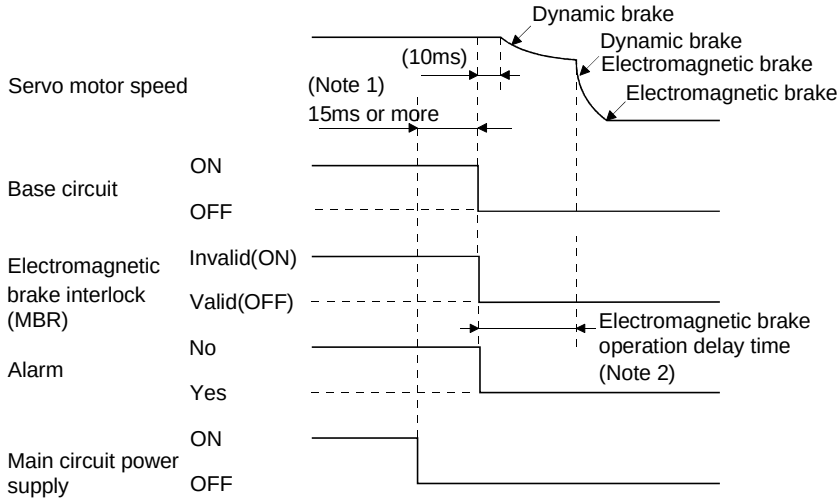


(4) Both main and control circuit power supplies off



Note: Changes with the operating status.

(5) Only main circuit power supply off (control circuit power supply remains on)



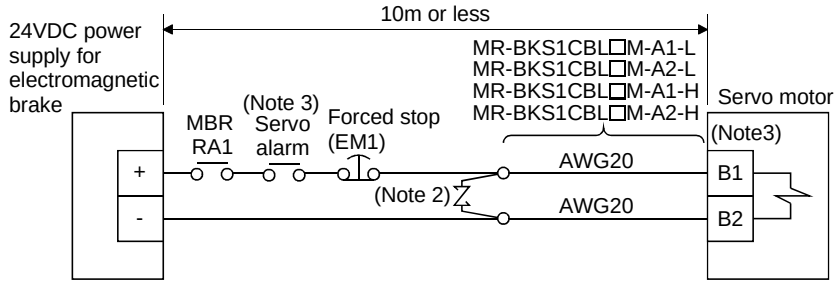
Note: 1. Changes with the operating status.

2. When the main circuit power supply is off in a motor stop status, the main circuit off warning (E9) occurs and the alarm (ALM) does not turn off.

3.11.3 Wiring diagrams (HF-MP series · HF-KP series servo motor)

POINT
· For HF-SP series servo motors, refer to Section 3.10.2 (2).

(1) When cable length is 10m or less



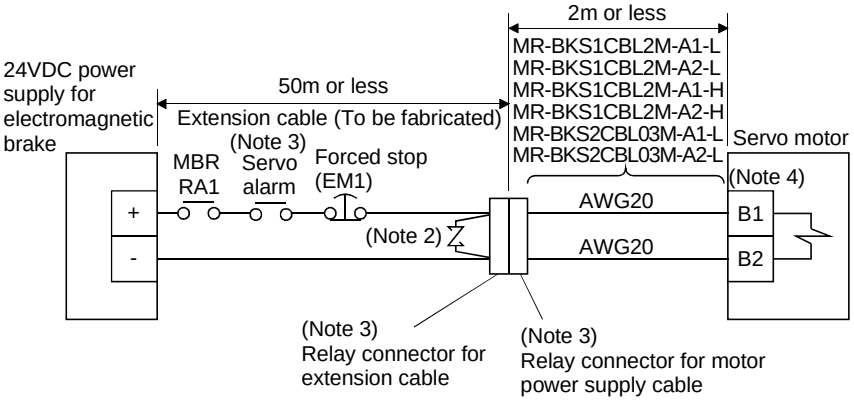
Note 1. Shut off the circuit on detection of the servo amplifier alarm.
2. Connect a surge absorber as close to the servo motor as possible.
3. There is no polarity in electromagnetic brake terminals (B1 and B2).

When fabricating the motor brake cable MR-BKS1CBL-□M-H, refer to Section 11.1.4.

(2) When cable length exceeds 10m

When the cable length exceeds 10m, fabricate an extension cable as shown below on the customer side. In this case, the motor power supply cable pulled from the servo motor should be within 2m long.

Refer to Section 11.8 for the wire used for the extension cable.



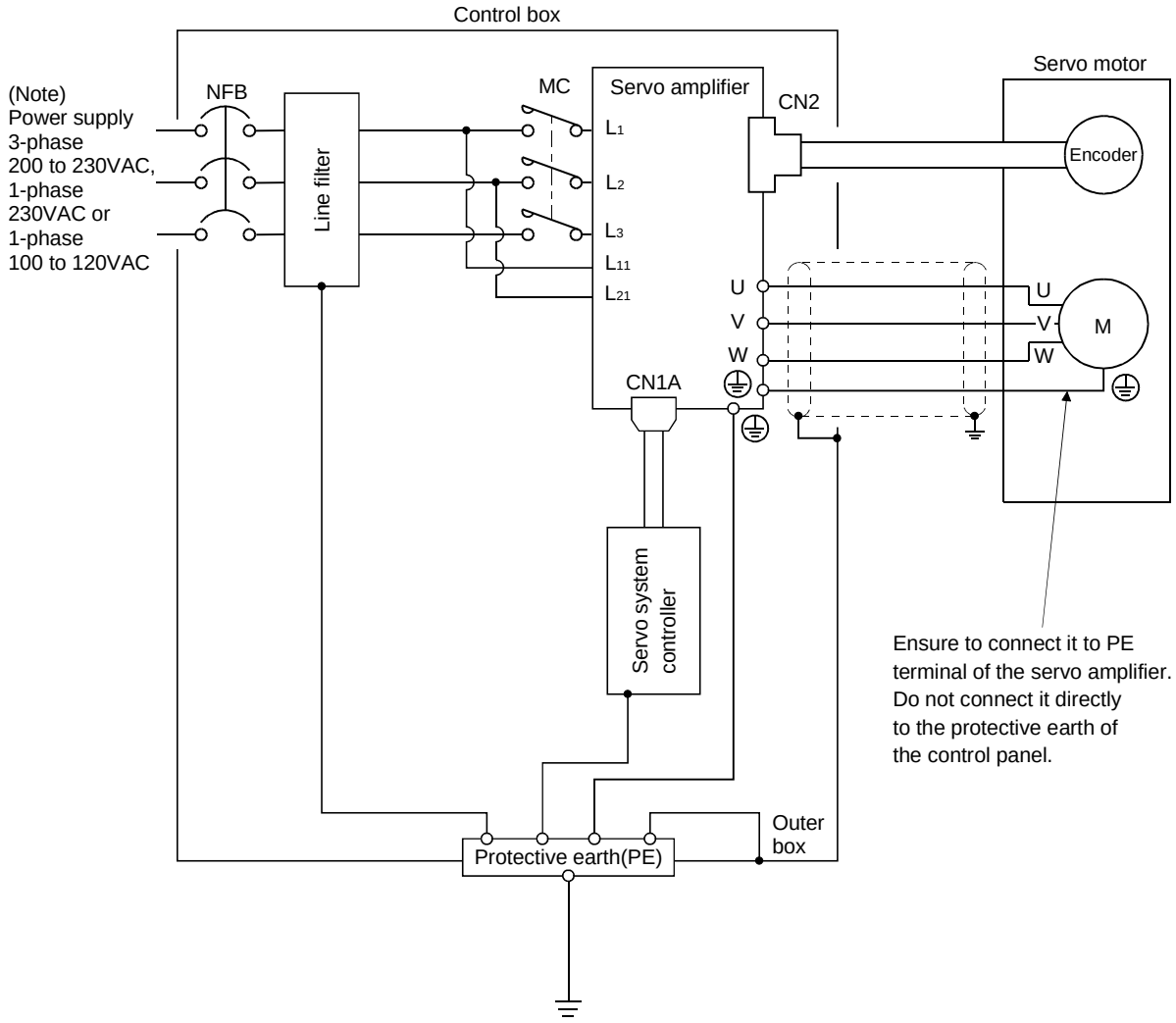
Note 1. Shut off the circuit on detection of the servo amplifier alarm.
2. Connect a surge absorber as close to the servo motor as possible.
3. Use of the following connectors is recommended when ingress protection (IP65) is necessary.
4. There is no polarity in electromagnetic brake terminals (B1 and B2).

Relay Connector	Description	Protective Structure
Relay connector for extension cable	CM10-CR2P-* (DDK) ┗ Wire size: S, M, L	IP65
Relay connector for motor power supply cable	CM10-SP2S-* (DDK) ┗ Wire size: S, M, L	IP65

3.12 Grounding

> **WARNING**
> - Ground the servo amplifier and servo motor securely.
> - To prevent an electric shock, always connect the protective earth (PE) terminal of the servo amplifier with the protective earth (PE) of the control box.

The servo amplifier switches the power transistor on-off to supply power to the servo motor. Depending on the wiring and ground cablerouting, the servo amplifier may be affected by the switching noise (due to di/dt and dv/dt) of the transistor. To prevent such a fault, refer to the following diagram and always ground.
To conform to the EMC Directive, refer to the EMC Installation Guidelines (IB(NA)67310).



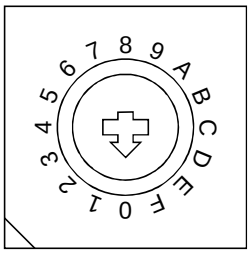
Note: For 1-phase 230VAC, connect the power supply to L_1 ・ L_2 and leave L_3 open.
There is no L_3 for 1-phase 100 to 120VAC power supply.

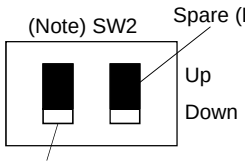
3.13 Control axis selection

POINT
▪ The control axis number set to rotary axis setting switch (SW1) should be the same as the one set to the servo system controller.

Use the rotary axis setting switch (SW1) to set the control axis number for the servo. If the same numbers are set to different control axes in a single communication system, the system will not operate properly. The control axes may be set independently of the SSCNET Ⅲ cable connection sequence.

Rotary axis setting switch (SW1)





Test operation select switch (SW2-1)
Set the test operation select switch to the "Up" position, when performing the test operation mode by using MR Configurator (Servo configuration).

Note. This table indicates the status when the switch is set to "Down".
(Default)

Spare	Rotary axis setting switch (SW1)	Description	Display
Down (Be sure to set to the "Down" position.)	0	Axis No.1	01
	1	Axis NO.2	02
	2	Axis NO.3	03
	3	Axis NO.4	04
	4	Axis NO.5	05
	5	Axis NO.6	06
	6	Axis NO.7	07
	7	Axis NO.8	08
	8	Axis NO.9	09
	9	Axis NO.10	10
	A	Axis NO.11	11
	B	Axis NO.12	12
	C	Axis NO.13	13
	D	Axis NO.14	14
	E	Axis NO.15	15
	F	Axis NO.16	16

4. STARTUP

⚠ WARNING	・Do not operate the switches with wet hands. You may get an electric shock.

⚠ CAUTION	・Before starting operation, check the parameters. Some machines may perform unexpected operation. ・Take safety measures, e.g. provide covers, to prevent accidental contact of hands and parts (cables, etc.) with the servo amplifier heat sink, regenerative brake resistor, servo motor, etc. since they may be hot while power is on or for some time after power-off. Their temperatures may be high and you may get burnt or a parts may damaged. ・During operation, never touch the rotating parts of the servo motor. Doing so can cause injury.

4.1 Switching power on for the first time

When switching power on for the first time, follow this section to make a startup.

4.1.1 Startup procedure

Wiring check	Check whether the servo amplifier and servo motor are wired correctly using visual inspection, DO forced output function (Section 4.5.1), etc. (Refer to Section 4.1.2.)
↓	
Surrounding environment check	Check the surrounding environment of the servo amplifier and servo motor. (Refer to Section 4.1.3.)
↓	
Axis No. settings	Confirm that the axis No. settings for rotary axis setting switch (SW1) and servo system controller are consistent. (Refer to Section 3.12)
↓	
Parameter setting	Set the parameters as necessary, such as the used control mode and regenerative brake option selection. (Refer to Chapter 5)
↓	
Test operation of servo motor alone in test operation mode	With the servo motor disconnected from the machine, check whether the servo motor rotates correctly. (Refer to Sections 4.5)
↓	
Test operation of servo motor alone by commands	With the servo motor disconnected from the machine, give commands to the servo amplifier and check whether the servo motor rotates correctly.
↓	
Test operation with servo motor and machine connected	Connect the servo motor with the machine, give operation commands from the host command device, and check machine motions.
↓	
Gain adjustment	Make gain adjustment to optimize the machine motions. (Refer to Chapter 6.)
↓	
Actual operation	
↓	
Stop	Stop giving commands and stop operation.

4.1.2 Wiring check

(1) Power supply system wiring

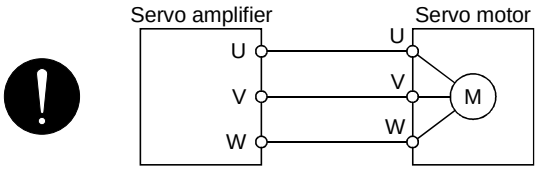
Before switching on the main circuit and control circuit power supplies, check the following items.

(a) Power supply system wiring

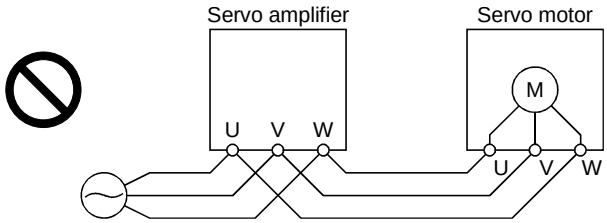
The power supplied to the power input terminals (L_1, L_2, L_3, L_{11}, L_{21}) of the servo amplifier should satisfy the defined specifications. (Refer to Section 1.3.)

(b) Connection of servo amplifier and servo motor

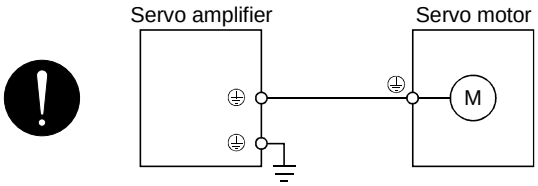
1) The servo motor power supply terminals (U, V, W) of the servo amplifier match in phase with the power input terminals (U, V, W) of the servo motor.



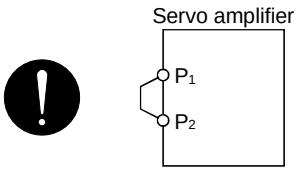
2) The power supplied to the servo amplifier should not be connected to the servo motor power supply terminals (U, V, W). To do so will fail the connected servo amplifier and servo motor.



3) The earth terminal of the servo motor is connected to the PE terminal of the servo amplifier.



4) P_1-P_2 should be connected.



(c) When option and auxiliary equipment are used

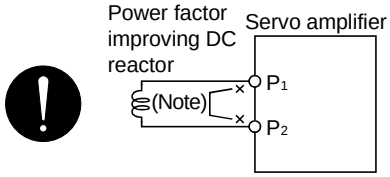
1) When regenerative brake option is used under 3.5kW

- The lead between P terminal and D terminal of CNP2 connector should not be connected.
- The generative brake option should be connected to P terminal and C terminal.
- A twisted cable should be used. (Refer to Section 11.2)

2) When regenerative brake option is used over 5kW
- The lead of built-in regenerative brake resistor connected to P terminal and D terminal of TE1 terminal block should not be connected.
- The generative brake option should be connected to P terminal and C terminal.
- A twisted cable should be used when wiring is over 5m and under 10m. (Refer to Section 11.2)

3) When brake unit and power supply return converter are used over 5kW
- The lead of built-in regenerative brake resistor connected to P terminal and D terminal of TE1 terminal block should not be connected.
- Brake unit or power supply return converter should be connected to P terminal and N terminal. (Refer to Section 11.3 and 11.4)

4) The power factor improving DC reactor should be connected across P_1-P_2. (Refer to Section 11.10.)



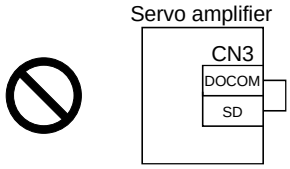
Note. Always disconnect the wiring across P_1-P_2.

(2) I/O signal wiring

(a) The I/O signals should be connected correctly.
Use DO forced output to forcibly turn on/off the pins of the CN3 connector. This function can be used to perform a wiring check. In this case, switch on the control circuit power supply only.

(b) 24VDC or higher voltage is not applied to the pins of connectors CN3.

(c) SD and DOCOM of connector CN3 is not shorted.



4.1.3 Surrounding environment

(1) Cable routing

(a) The wiring cables are free from excessive force.

(b) The encoder cable should not be used in excess of its flex life. (Refer to Section 11.4.)

(c) The connector part of the servo motor should not be strained.

(2) Environment

Signal cables and power cables are not shorted by wire offcuts, metallic dust or the like.

4.2 Start up

Connect the servo motor with a machine after confirming that the servo motor operates properly alone.

(1) Power on

When the main and control circuit power supplies are switched on, "b01" (for the first axis) appears on the servo amplifier display.

In the absolute position detection system, first power-on results in the absolute position lost (25) alarm and the servo system cannot be switched on.

The alarm can be deactivated by then switching power off once and on again.

Also in the absolute position detection system, if power is switched on at the servo motor speed of 500r/min or higher, position mismatch may occur due to external force or the like. Power must therefore be switched on when the servo motor is at a stop.

(2) Parameter setting

Set the parameters according to the structure and specifications of the machine. Refer to Chapter 5 for the parameter definitions.

Parameter No.	Name	Setting	Description
PA14	Rotation direction setting	0	Increase in positioning address rotates the motor in the CCW direction.
PA08	Auto tuning mode	□□□1	Used.
PA09	Auto tuning response	12	Slow response (initial value) is selected.

After setting the above parameters, switch power off once. Then switch power on again to make the set parameter values valid.

(3) Servo-on

Switch the servo-on in the following procedure:

1) Switch on main circuit/control circuit power supply.
2) The controller transmits the servo-on command.

When placed in the servo-on status, the servo amplifier is ready to operate and the servo motor is locked.

(4) Home position return

Always perform home position return before starting positioning operation.

(5) Stop

If any of the following situations occurs, the servo amplifier suspends the running of the servo motor and brings it to a stop.

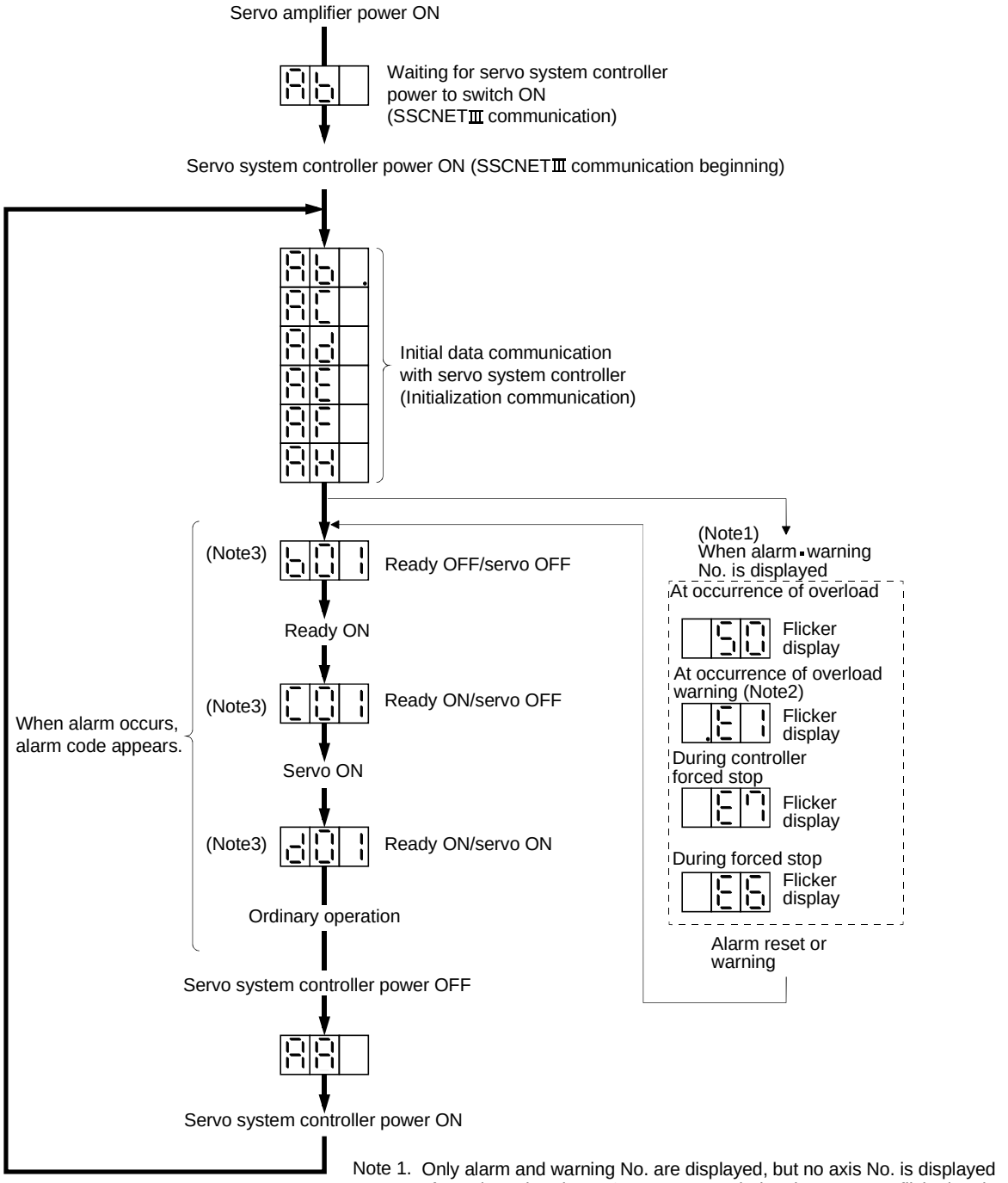
When the servo motor is equipped with an electromagnetic brake, refer to Section 3.10.

	Operation/command	Stopping condition
Servo system controller	Servo off command	The base circuit is shut off and the servo motor coasts.
	Forced stop command	The base circuit is shut off and the dynamic brake operates to bring the servo motor to stop. The controller forced stop warning (E7) occurs.
Servo amplifier	Alarm occurrence	The base circuit is shut off and the dynamic brake operates to bring the servo motor to stop.
	Forced stop (EM1) OFF	The base circuit is shut off and the dynamic brake operates to bring the servo motor to stop. The servo forced stop warning (E6) occurs.

4.3 Servo amplifier display

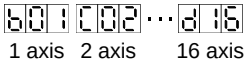
On the servo amplifier display (three-digit, seven-segment display), check the status of communication with the servo system controller at power-on, check the axis number, and diagnose a fault at occurrence of an alarm.

(1) Display sequence



Note 1. Only alarm and warning No. are displayed, but no axis No. is displayed

2. If warning other than E6 or E7 occurs during the servo on, flickering the second place of decimal point indicates that it is during the servo on.
3. The right-hand segments of b01, c02 and d16 indicate the axis number. (Below example indicates Axis1)



(2) Indication list

Indication	Status	Description
Ab	Initializing	・Power of the servo amplifier was switched on at the condition that the power of servo system controller is OFF. ・The axis No. set to the servo system controller does not match the axis No. set with the rotary axis setting switch (SW1) of the servo amplifier. ・A servo amplifier fault occurred or an error took place in communication with the servo system controller. In this case, the indication changes: "Ab " → "AC " → "Ad " → "Ab " ・The servo system controller is faulty.
Ab.	Initializing	During initial setting for communication specifications
AC	Initializing	Initial setting for communication specifications completed, and then it became a waiting status for synchronizing with servo system controller.
Ad	Initializing	During initial parameter setting communication with servo system controller
AE	Initializing	During motor・encoder information and telecommunication with servo system controller
AF	Initializing	During initial signal data communication with servo system controller
AH	Initializing completion	During the completion process for initial data communication with servo system controller
AA	Initializing standby	The power supply of servo system controller is turned off during the power supply of servo amplifier is on.
(Note 1) b##	Ready OFF	The ready off signal from the servo system controller was received.
(Note 1) d##	Servo ON	The ready off signal from the servo system controller was received.
(Note 1) C##	Servo OFF	The ready off signal from the servo system controller was received.
(Note 2) **	Alarm・Warning	The alarm No./warning No. that occurred is displayed. (Refer to Section 9.1.)
888	CPU Error	CPU watchdog error has occurred.
(Note 3) b00.	(Note 3) Test operation mode	JOG operation, positioning operation, programmed operation, DO forced output.
(Note 1) b##. d##. C##.		Motor-less operation

Note: 1. ## denotes any of numerals 00 to 16 and what it means is listed below:

#	Description
0	Set to the test operation mode.
1	First axis
2	Second axis
3	Third axis
4	Fourth axis
5	Fifth axis
6	Sixth axis
7	Seventh axis
8	Eighth axis
9	Ninth axis
10	Tenth axis
11	Eleventh axis
12	Twelfth axis
13	Thirteenth axis
14	Fourteenth axis
15	Fifteenth axis
16	Sixteenth axis

2. ** indicates the warning/alarm No.

3. Requires the MR Configurator (servo configuration software).

4.4 Test operation

Before starting actual operation, perform test operation to make sure that the machine operates normally.
Refer to Section 4.2 for the power on and off methods of the servo amplifier.

> **POINT**
>
> ▪ If necessary, verify controller program by using motorless operation.
> Refer to Section 4.5.2 for the motorless operation.

Test operation of servo motor alone in JOG operation of test operation mode

In this step, confirm that the servo amplifier and servo motor operate normally.
With the servo motor disconnected from the machine, use the test operation mode and check whether the servo motor rotates correctly. Refer to Section 4.5 for the test operation mode.

↓

Test operation of servo motor alone by commands

In this step, confirm that the servo motor rotates correctly under the commands from the controller.
Make sure that the servo motor rotates in the following procedure.
Give a low speed command at first and check the rotation direction, etc. of the servo motor.
If the servo motor does not operate in the intended direction, check the input signal.

↓

Test operation with servo motor and machine connected

In this step, connect the servo motor with the machine and confirm that the machine operates normally under the commands from the command device.
Make sure that the servo motor rotates in the following procedure.
Give a low speed command at first and check the operation direction, etc. of the machine. If the machine does not operate in the intended direction, check the input signal. In the status display, check for any problems of the servo motor speed, command pulse frequency, load ratio, etc.
Then, check automatic operation with the program of the command device.

4.5 Test operation mode

CAUTION

- The test operation mode is designed for servo operation confirmation and not for machine operation confirmation. Do not use this mode with the machine. Always use the servo motor alone.
- If an operation fault occurred, use the forced stop (EM1) to make a stop.

POINT

- Always install a forced stop switch to enable a stop at occurrence of an alarm.
- The content described in this section indicates the environment that servo amplifier and personal computer are directly connected.

By using a personal computer and the MR Configurator (servo configuration software MRZJW3-SETUP121E), you can execute jog operation, positioning operation, DO forced output and motor-less operation without connecting the motion controller.

4.5.1 Test operation mode in MR Configurator

(1) Test operation mode

(a) Jog operation

Jog operation can be performed without using the servo system controller. Use this operation with the forced stop reset. This operation may be used independently of whether the servo is on or off and whether the servo system controller is connected or not.

Exercise control on the jog operation screen of the MR Configurator (servo configuration software).

1) Operation pattern

Item	Initial value	Setting range
Speed [r/min]	200	0 to max. speed
Acceleration/deceleration time constant [ms]	1000	0 to 50000

2) Operation method

Operation	Screen control
Forward rotation start	Click the "Forward" button.
Reverse rotation start	Click the "Reverse" button.
Stop	Click the "Stop" button.

(b) Positioning operation

Positioning operation can be performed without using the servo system controller. Use this operation with the forced stop reset. This operation may be used independently of whether the servo is on or off and whether the servo system controller is connected or not.

Exercise control on the positioning operation screen of the MR Configurator (servo configuration software).

1) Operation pattern

Item	Initial value	Setting range
Travel [pulse]	100000	0 to 99999999
Speed [r/min]	200	0 to max. speed
Acceleration/deceleration time constant [ms]	1000	0 to 50000

2) Operation method

Operation	Screen control
Forward rotation start	Click the "Forward" button.
Reverse rotation start	Click the "Reverse" button.
Pause	Click the "Pause" button.

(c) Program operation

Positioning operation can be performed in two or more operation patterns combined, without using the servo system controller. Use this operation with the forced stop reset. This operation may be used independently of whether the servo is on or off and whether the servo system controller is connected or not.

Exercise control on the programmed operation screen of the MR Configurator (servo configuration software). For full information, refer to the MR Configurator (Servo Configuration Software) Installation Guide.

Operation	Screen control
Start	Click the "Start" button.
Stop	Click the "Reset" button.

(d) Output signal (DO) forced output

Output signals can be switched on/off forcibly independently of the servo status. Use this function for output signal wiring check, etc.

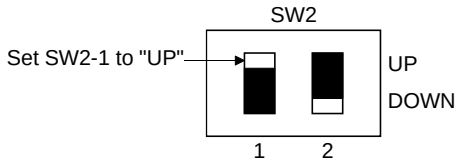
Exercise control on the DO forced output screen of the MR Configurator (servo configuration software).

(2) Operation procedure

(a) Jog operation, positioning operation, program operation, DO forced output.

1) Switch power off.

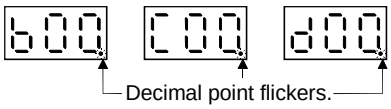
2) Set SW2-1 to "UP".



When SW1 and SW2-1 is set to the axis number and operation is performed by the servo system controller, the test operation mode screen is displayed on the personal computer, but no function is performed.

3) Switch servo amplifier power on.

When initialization is over, the display shows the following screen:



4) Perform operation with the personal computer.

4.5.2 Motorless operation in controller

POINT
・ Use motor-less operation which is available by making the servo system controller parameter setting. ・ Motorless operation is done while connected with the servo system controller.

(1) Motorless operation

Without connecting the servo motor, output signals or status displays can be provided in response to the servo system controller commands as if the servo motor is actually running. This operation may be used to check the servo system controller sequence. Use this operation with the forced stop reset. Use this operation with the servo amplifier connected to the servo system controller.

For stopping the motorless operation, set the selection of motorless operation to [Invalid] in servo parameter setting of servo system controller. Motorless operation will be invalid condition after switching on power supply next time.

(a) Load conditions

Load Item	Condition
Load torque	0
Load inertia moment ratio	Same as servo motor inertia moment

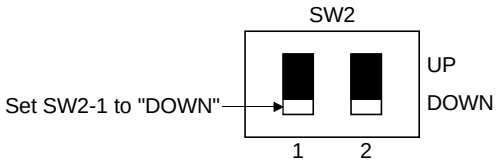
(b) Alarms

The following alarms and warning do not occur. However, the other alarms and warnings occur as when the servo motor is connected:

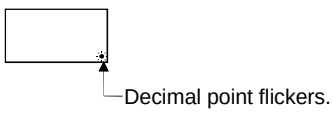
・Encoder error 1 (16)
・Encoder error 2 (20)
・Absolute position erasure (25)
・Battery cable breakage warning (92)

(2) Operating procedure

1) Switch off servo amplifier
2) Set parameter No.PC05 to "1", change test operation mode switch (SW2-1) to normal condition side "Down", and then turn on the power supply.



3) Perform motor-less operation with the personal computer.
The display shows the following screen:



5. PARAMETERS

> **CAUTION** ・Never adjust or change the parameter values extremely as it will make operation instable.

In the MR-J3-B servo amplifier, the parameters are classified into the following groups on a function basis.

Parameter Group	Main Description
Basic setting parameters (No. PA ☐☐)	When using this servo amplifier in the position control mode, make basic setting with these parameters.
Gain/filter parameters (No. PB ☐☐)	Use these parameters when making gain adjustment manually.
Extension setting parameters (No. PC ☐☐)	When changing settings such as analog monitor output signal or encoder electromagnetic brake sequence output, use these parameters.
I/O setting parameters (No. PD ☐☐)	Use these parameters when changing the I/O signals of the servo amplifier.

When using this servo in the position control mode, mainly setting the basic setting parameters (No. PA☐☐) allows the setting of the basic parameters at the time of introduction.

5.1 Basic Setting Parameters (No.PA☐☐)

> POINT
> ・Parameter whose symbol is preceded by * is made valid with the following conditions.
> * : Set the parameter value, switch power off once after setting, and then switch it on again, or perform the controller reset.
> **: Set the parameter value, switch power off once, and then switch it on again.
> ・Never change parameters for manufacturer setting.

5.1.1 Parameter list

No.	Symbol	Name	Initial Value	Unit
PA01		For manufacturer setting	0000h	
PA02	**REG	Regenerative brake option	0000h	
PA03	*ABS	Absolute position detection system	0000h	
PA04	*AOP1	Function selection A-1	0000h	
PA05		For manufacturer setting	0	
PA06			1	
PA07			1	
PA08	ATU	Auto tuning	0001h	
PA09	RSP	Auto tuning response	12	
PA10	INP	In-position range	100	pulse
PA11		For manufacturer setting	1000.0	%
PA12			1000.0	%
PA13			0000h	
PA14	*POL	Rotation direction selection	0	
PA15	*ENR	Encoder output pulses	4000	pulse/rev
PA16		For manufacturer setting	0	
PA17			0000h	
PA18			0000h	
PA19	*BLK	Parameter write inhibit	000Bh	

5.1.2 Parameter write inhibit

Parameter			Initial Value	Unit	Setting Range
No.	Symbol	Name			
PA19	*BLK	Parameter write inhibit	000Bh		Refer to the text.

POINT

- This parameter is made valid when power is switched off, then on after setting, or when the controller reset has been performed.

In the factory setting, this servo amplifier allows changes to the basic setting parameter, gain/filter parameter and extension setting parameter settings. With the setting of parameter No. PA19, write can be disabled to prevent accidental changes.

The following table indicates the parameters which are enabled for reference and write by the setting of parameter No. PA19. Operation can be performed for the parameters marked ○.

Parameter No. PA19 Setting	Setting Operation	Basic Setting Parameters No. PA □□	Gain/Filter Parameters No. PB □□	Extension Setting Parameters No. PC □□	I/O Setting Parameters No. PD □□
0000h	Reference	○			
	Write	○			
000Bh (initial value)	Reference	○	○	○	
	Write	○	○	○	
000Ch	Reference	○	○	○	○
	Write	○	○	○	○
100Bh	Reference	○			
	Write	Parameter No. PA19 only			
100Ch	Reference	○	○	○	○
	Write	Parameter No. PA19 only			

5.1.3 Selection of regenerative brake option

Parameter			Initial Value	Unit	Setting Range
No.	Symbol	Name			
PA02	**REG	Regenerative brake option	0000h		Refer to the text.

POINT

- This parameter value and switch power off once, then switch it on again to make that parameter setting valid.
- Wrong setting may cause the regenerative brake option to burn.
- If the regenerative brake option selected is not for use with the servo amplifier, parameter error (37) occurs.

Set this parameter when using the regenerative brake option.

Parameter No. PA02

0	0		

Selection of regenerative brake option
00: Regenerative brake option is not used
- For MR-J3-10B, regenerative brake resistor is not used.
- For MR-J3-20B or more, built-in regenerative brake resistor is used.

01: FR-BU・FR-RC
02: MR-RB032
03: MR-RB12
04: MR-RB32
05: MR-RB30
06: MR-RB50
08: MR-RB31
09: MR-RB51

5.1.4 Using absolute position detection system

Parameter			Initial Value	Unit	Setting Range
No.	Symbol	Name			
PA03	*ABS	Absolute position detection system	0000h		Refer to the text.

POINT

- This parameter is made valid when power is switched off, then on after setting, or when the controller reset has been performed.
- This parameter cannot be used in the speed control mode.

Set this parameter when using the absolute position detection system in the position control mode.

Parameter No. PA03

0	0	0	

Selection of absolute position detection system (refer to Chapter 12)
0: Used in incremental system
1: Used in absolute position detection system

5.1.5 Forced stop input selection

Parameter			Initial Value	Unit	Setting Range
No.	Symbol	Name			
PA04	*AOP1	Function selection A-1	0000h		Refer to the text.

POINT
・This parameter is made valid when power is switched off, then on after setting, or when the controller reset has been performed.

The servo forced stop function is voidable.

Parameter No.PA04

0		0	0

Selection of servo forced stop
0: Valid (Forced stop (EM1) is used.)
1: Invalid (Forced stop (EM1) is not used.)

When not using the forced stop (EM1) of servo amplifier, set the selection of servo forced stop to Invalid (□ □ □ 1). At this time, the forced stop (EM1) automatically turns on inside the servo amplifier.

5.1.6 Auto tuning

Parameter			Initial Value	Unit	Setting Range
No.	Symbol	Name			
PA08	ATU	Auto tuning mode	0001h		Refer to the text.
PA09	RSP	Auto tuning response	12		1 to 32

Make gain adjustment using auto tuning. Refer to Section 6.2 for details.

(1) Auto tuning mode (parameter No. PA08)

Select the gain adjustment mode.

Parameter No. PA08

0	0	0	

Gain adjustment mode setting

Setting	Gain adjustment mode	Automatically set parameter No. (Note)
0	Interpolation mode	PB06・PB08・PB09・PB10
1	Auto tuning mode 1	PB06・PB07・PB08・PB09・PB10
2	Auto tuning mode 2	PB07・PB08・PB09・PB10
3	Manual mode	

Note. The parameters have the following names.

Parameter No.	Name
PB06	Ratio of load inertia moment to servo motor inertia moment
PB07	Model loop gain
PB08	Position loop gain
PB09	Speed loop gain
PB10	Speed integral compensation

(2) Auto tuning response (parameter No. PA09)

If the machine hunts or generates large gear sound, decrease the set value. To improve performance, e.g. shorten the settling time, increase the set value.

Setting	Response	Guideline for Machine Resonance Frequency [Hz]
1	Low response	10.0
2	↑	11.3
3		12.7
4		14.3
5		16.1
6		18.1
7		20.4
8		23.0
9		25.9
10		29.2
11		32.9
12		37.0
13		41.7
14		47.0
15	↓	52.9
16	Middle response	59.6

Setting	Response	Guideline for Machine Resonance Frequency [Hz]
17	Low response	67.1
18	↑	75.6
19		85.2
20		95.9
21		108.0
22		121.7
23		137.1
24		154.4
25		173.9
26		195.9
27		220.6
28		248.5
29		279.9
30		315.3
31	↓	355.1
32	Middle response	400.0

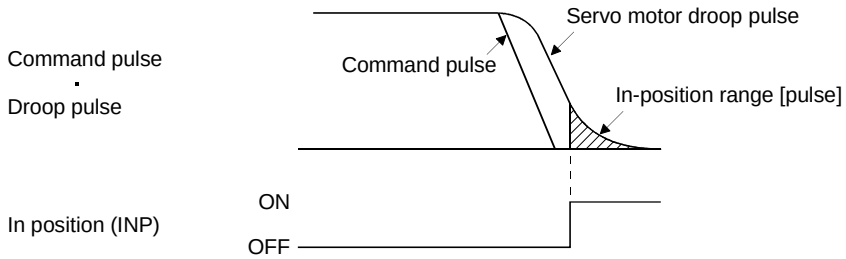
5.1.7 In-position range

Parameter			Initial Value	Unit	Setting Range
No.	Symbol	Name			
PA10	INP	In-position range	100	pulse	0 to 50000

POINT

- This parameter cannot be used in the speed control mode.

Set the range, where In position (INP) is output, in the command pulse unit.



5.1.8 Selection of servo motor rotation direction

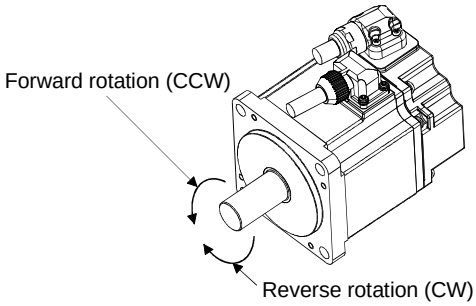
Parameter			Initial Value	Unit	Setting Range
No.	Symbol	Name			
PA14	*POL	Rotation direction selection	0		0 ▪ 1

POINT

- This parameter is made valid when power is switched off, then on after setting, or when the controller reset has been performed.
- This parameter cannot be used in the speed control mode.

Select servo motor rotation direction relative.

Parameter No. PA14 Setting	Servo Motor Rotation Direction	
	When positioning address increases	When positioning address decreases
0	CCW	CW
1	CW	CCW



5.1.9 Encoder output pulse

Parameter			Initial Value	Unit	Setting Range
No.	Symbol	Name			
PA15	*ENR	Encoder output pulse	4000	pulse/rev	1 to 65535

POINT

- This parameter is made valid when power is switched off, then on after setting, or when the controller reset has been performed.

Used to set the encoder pulses (A-phase, B-phase) output by the servo amplifier.
Set the value 4 times greater than the A-phase or B-phase pulses.
You can use parameter No. PC03 to choose the output pulse setting or output division ratio setting.
The number of A/B-phase pulses actually output is 1/4 times greater than the preset number of pulses.
The maximum output frequency is 4.6Mpps (after multiplication by 4). Use this parameter within this range.

(1) For output pulse designation

Set "☐☐0☐" (initial value) in parameter No. PC03.

Set the number of pulses per servo motor revolution.

Output pulse = set value [pulses/rev]

For instance, set "5600" to Parameter No. pa15, the actually output A/B-phase pulses are as indicated below:

$$\text{A·B-phase output pulses} = \frac{5600}{4} = 1400\text{[pulse]}$$

(2) For output division ratio setting

Set "☐☐1☐" in parameter No. PC03.

The number of pulses per servo motor revolution is divided by the set value.

$$\text{Output pulse} = \frac{\text{Resolution per servo motor revolution}}{\text{Set value}}\ \text{[pulses/rev]}$$

For instance, set "8" to Parameter No. pa15, the actually output A/B-phase pulses are as indicated below:

$$\text{A·B-phase output pulses} = \frac{262144}{8} \cdot \frac{1}{4} = 8192\text{[pulse]}$$

5.2 Gain/Filter Parameters (No. PB□□)

POINT

- Parameter whose symbol is preceded by * is made valid with the following conditions.
  * : Set the parameter value, switch power off once after setting, and then switch it on again, or perform the controller reset.

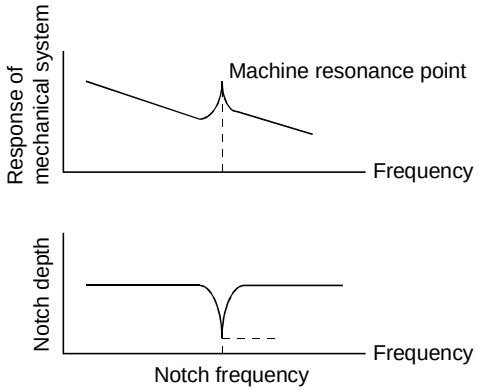
5.2.1 Parameter list

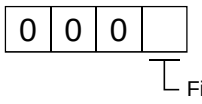
No.	Symbol	Name	Initial Value	Unit
PB01	FILT	Adaptive tuning mode (Adaptive filter II)	0000h	
PB02	VRFT	Vibration suppression control filter tuning mode (Advanced vibration suppression control)	0000h	
PB03		For manufacturer setting	0	
PB04	FFC	Feed forward gain	0	%
PB05		For manufacturer setting	500	
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	7.0	times
PB07	PG1	Model loop gain	24	rad/s
PB08	PG2	Position loop gain	37	rad/s
PB09	VG2	Speed loop gain	823	rad/s
PB10	VIC	Speed integral compensation	33.7	ms
PB11	VDC	Speed differential compensation	980	
PB12		For manufacturer setting	0	
PB13	NH1	Machine resonance suppression filter 1	4500	Hz
PB14	NHQ1	Notch form selection 1	0000h	
PB15	NH2	Machine resonance suppression filter 2	4500	Hz
PB16	NHQ2	Notch form selection 2	0000h	
PB17		For manufacturer setting	0000	
PB18	LPF	Low-pass filter	3141	rad/s
PB19	VRF1	Vibration suppression control vibration frequency setting	100.0	Hz
PB20	VRF2	Vibration suppression control resonance frequency setting	100.0	Hz
PB21		For manufacturer setting	0.00	
PB22			0.00	
PB23	VFBF	Low-pass filter selection	0000h	
PB24	*MVS	Slight vibration suppression control selection	0000h	
PB25		For manufacturer setting	0000h	
PB26	*CDP	Gain changing selection	0000h	
PB27	CDL	Gain changing condition	10	
PB28	CDT	Gain changing time constant	1	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	7.0	times
PB30	PG2B	Gain changing position loop gain	37	rad/s
PB31	VG2B	Gain changing speed loop gain	823	rad/s
PB32	VICB	Gain changing speed integral compensation	33.7	ms
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	100.0	Hz
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	100.0	Hz
PB35		For manufacturer setting	0.00	
PB36			0.00	
PB37			100	
PB38			0.0	
PB39			0.0	
PB40			0.0	
PB41			1125	

No.	Symbol	Name	Initial Value	Unit
PB42		For manufacturer setting	1125	
PB43			0004h	
PB44			0.0	
PB45			0000h	

5.2.2 Detail list

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range
PB01	FILT	Adaptive tuning mode (adaptive filter Ⅱ) Select the setting method for filter tuning. Setting this parameter to "□□□1" (filter tuning mode 1) automatically changes the machine resonance suppression filter 1 (parameter No. PB13) and notch shape selection (parameter No. PB14).	0000h		

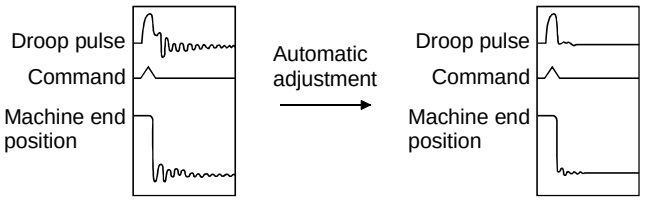


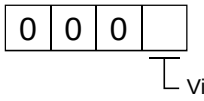


Setting	Filter adjustment mode	Automatically set parameter
0	Filter OFF	(Note)
1	Filter tuning mode	Parameter No. PB13 Parameter No. PB14
2	Manual mode	

Note. Parameter No. PB13 and PB14 are fixed to the initial values.

When this parameter is set to "□□□1", the tuning is completed after positioning is done the predetermined number or times for the predetermined period of time, and the setting changes to "□□□2". When the filter tuning is not necessary, the setting changes to "□□□0". When this parameter is set to "□□□0", the initial values are set to the machine resonance suppression filter 1 and notch shape selection. However, this does not occur when the servo off.

<table>
<tr><th>No.</th><th>Symbol</th><th>Name and Function</th><th>Initial Value</th><th>Unit</th><th>Setting Range</th></tr>
<tr><td>PB02</td><td>VRFT</td><td>Vibration suppression control tuning mode (advanced vibration suppression control)
This parameter cannot be used in the speed control mode.
The vibration suppression is valid when the parameter No. PA08 (auto tuning) setting is "☐☐☐2" or "☐☐☐3". When PA08 is "☐☐☐1", vibration suppression is always invalid.
Select the setting method for vibration suppression control tuning. Setting this parameter to "☐☐☐1" (vibration suppression control tuning mode) automatically changes the vibration suppression control - vibration frequency (parameter No. PB19) and vibration suppression control - resonance frequency (parameter No. PB20) after positioning is done the predetermined number of times.
 

<table><tr><th>Setting</th><th>Vibration suppression control tuning mode</th><th>Automatically set parameter</th></tr><tr><td>0</td><td>Vibration suppression control OFF</td><td>(Note)</td></tr><tr><td>1</td><td>Vibration suppression control tuning mode (Advanced vibration suppression control)</td><td>Parameter No. PB19
Parameter No. PB20</td></tr><tr><td>2</td><td>Manual mode</td><td></td></tr></table>Note. Parameter No. PB19 and PB20 are fixed to the initial values.

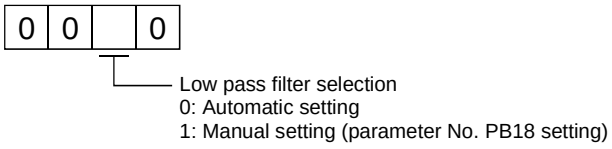
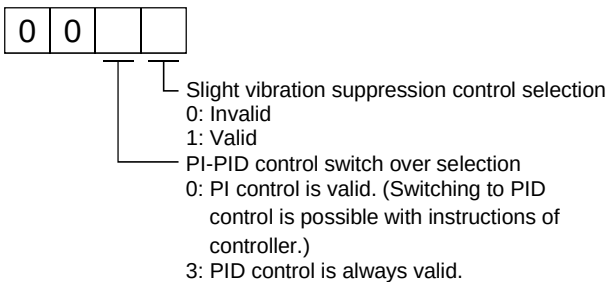
When this parameter is set to "☐☐☐1", the tuning is completed after positioning is done the predetermined number or times for the predetermined period of time, and the setting changes to "☐☐☐2". When the vibration suppression control tuning is not necessary, the setting changes to "☐☐☐0". When this parameter is set to "☐☐☐0", the initial values are set to the vibration suppression control - vibration frequency and vibration suppression control - resonance frequency. However, this does not occur when the servo off.</td><td>0000h</td><td></td><td></td></tr>
<tr><td>PB03</td><td></td><td>For manufacturer setting
Do not change this value by any means.</td><td>0</td><td></td><td></td></tr>
<tr><td>PB04</td><td>FFC</td><td>Feed forward gain
This parameter cannot be used in the speed control mode.
Set the feed forward gain. When the setting is 100%, the droop pulses during operation at constant speed are nearly zero. However, sudden acceleration/deceleration will increase the overshoot. As a guideline, when the feed forward gain setting is 100%, set 1s or more as the acceleration/deceleration time constant up to the rated speed.</td><td>0</td><td>%</td><td>0
to
100</td></tr>
<tr><td>PB05</td><td></td><td>For manufacturer setting
Do not change this value by any means.</td><td>500</td><td></td><td></td></tr>
</table>

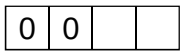
No.	Symbol	Name and Function	Initial Value	Unit	Setting Range
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment Used to set the ratio of the load inertia moment to the servo motor shaft inertia moment. When auto tuning mode 1 and interpolation mode is selected, the result of auto tuning is automatically used. (Refer to section 6.1.1) In this case, it varies between 0 and 100.0. When parameter No. PA08 is set to "☐☐☐2" or "☐☐☐3", this parameter can be set manually.	7.0	times	0 to 300.0
PB07	PG1	Model loop gain This parameter cannot be used in the speed control mode. Set the response gain up to the target position. Increase the gain to improve trackability in response to the position command. When auto turning mode 1,2 is selected, the result of auto turning is automatically used. When parameter No. PA08 is set to "☐☐☐1" or "☐☐☐3", this parameter can be set manually.	24	rad/s	1 to 2000
PB08	PG2	Position loop gain This parameter cannot be used in the speed control mode. Used to set the gain of the position loop. Set this parameter to increase the position response to level load disturbance. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1,2 and interpolation mode is selected, the result of auto tuning is automatically used. When parameter No. PA08 is set to "☐☐☐3", this parameter can be set manually.	37	rad/s	1 to 1000
PB09	VG2	Speed loop gain Set this parameter when vibration occurs on machines of low rigidity or large backlash. Higher setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1・2, manual mode and interpolation mode is selected, the result of auto tuning is automatically used. When parameter No. PA08 is set to "☐☐☐3", this parameter can be set manually.	823	rad/s	20 to 50000
PB10	VIC	Speed integral compensation Used to set the integral time constant of the speed loop. Lower setting increases the response level but is liable to generate vibration and/or noise. When auto tuning mode 1・2 and interpolation mode is selected, the result of auto tuning is automatically used. When parameter No. PA08 is set to "☐☐☐3", this parameter can be set manually.	33.7	ms	0.1 to 1000.0
PB11	VDC	Speed differential compensation Used to set the differential compensation. When parameter No. PB24 is set to "☐☐3☐", this parameter is made valid. When parameter No. PA08 is set to "☐☐0☐", this parameter is made valid by instructions of controller.	980		0 to 1000
PB12		For manufacturer setting Do not change this value by any means.	0		
PB13	NH1	Machine resonance suppression filter 1 Set the notch frequency of the machine resonance suppression filter 1. Setting parameter No. PB01 (filter tuning mode 1) to "☐☐☐1" automatically changes this parameter. When the parameter No. PB01 setting is "☐☐☐0", the setting of this parameter is ignored.	4500	Hz	100 to 4500

<table>
<tr><th>No.</th><th>Symbol</th><th>Name and Function</th><th>Initial Value</th><th>Unit</th><th>Setting Range</th></tr>
<tr><td>PB14</td><td>NHQ1</td><td>Notch shape selection 1
Used to selection the machine resonance suppression filter 1.
 

Notch depth selection
<table><tr><th>Setting value</th><th>Depth</th><th>Gain</th></tr><tr><td>0</td><td rowspan="4">Deep
to
Shallow</td><td>-40dB</td></tr><tr><td>1</td><td>-14dB</td></tr><tr><td>2</td><td>-8dB</td></tr><tr><td>3</td><td>-4dB</td></tr></table>
Notch width
<table><tr><th>Setting value</th><th>Width</th><th>α</th></tr><tr><td>0</td><td>Standard</td><td>2</td></tr><tr><td>1</td><td rowspan="2">to</td><td>3</td></tr><tr><td>2</td><td>4</td></tr><tr><td>3</td><td>Wide</td><td>5</td></tr></table>
Setting parameter No. PB01 (filter tuning mode 1) to "□□□1" automatically changes this parameter.
When the parameter No. PB01 setting is "□□□0", the setting of this parameter is ignored.</td><td>0000h</td><td></td><td>Refer to Name and function column.</td></tr>
<tr><td>PB15</td><td>NH2</td><td>Machine resonance suppression filter 2
Set the notch frequency of the machine resonance suppression filter 2.
Set parameter No. PB16 (notch shape selection 2) to "□□□1" to make this parameter valid.</td><td>4500</td><td>Hz</td><td>100
to
4500</td></tr>
<tr><td>PB16</td><td>NHQ2</td><td>Notch shape selection 2
Select the shape of the machine resonance suppression filter 2.
 

Machine resonance suppression filter 2 selection
0: Invalid
1: Valid
Notch depth selection
<table><tr><th>Setting value</th><th>Depth</th><th>Gain</th></tr><tr><td>0</td><td rowspan="4">Deep
to
Shallow</td><td>-40dB</td></tr><tr><td>1</td><td>-14dB</td></tr><tr><td>2</td><td>-8dB</td></tr><tr><td>3</td><td>-4dB</td></tr></table>
Notch width
<table><tr><th>Setting value</th><th>Width</th><th>α</th></tr><tr><td>0</td><td>Standard</td><td>2</td></tr><tr><td>1</td><td rowspan="2">to</td><td>3</td></tr><tr><td>2</td><td>4</td></tr><tr><td>3</td><td>Wide</td><td>5</td></tr></table></td><td>0000h</td><td></td><td>Refer to Name and function column.</td></tr>
<tr><td>PB17</td><td></td><td>For manufacturer setting
Automatically set depending on the machine condition.</td><td>0000</td><td></td><td></td></tr>
</table>

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range
PB18	LPF	Low pass filter setting Set the low pass filter. Setting parameter No. PB23 (low pass filter selection) to "□□0□" automatically changes this parameter. When parameter No. PB23 is set to "□□1□", this parameter can be set manually.	3141	rad/s	100 to 18000
PB19	VRF1	Vibration suppression control - vibration frequency setting This parameter cannot be used in the speed control mode. Set the vibration frequency for vibration suppression control to suppress low-frequency machine vibration, such as enclosure vibration. (Refer to Section 7.4.(4)) Setting parameter No. PB02 (vibration suppression control tuning mode) to "□□□1" automatically changes this parameter. When parameter No. PB02 is set to "□□□2", this parameter can be set manually.	100.0	Hz	0.1 to 100.0
PB20	VRF2	Vibration suppression control - resonance frequency setting This parameter cannot be used in the speed control mode. Set the resonance frequency for vibration suppression control to suppress low-frequency machine vibration, such as enclosure vibration. (Refer to Section 7.4.(4)) Setting parameter No. PB02 (vibration suppression control tuning mode) to "□□□1" automatically changes this parameter. When parameter No. PB02 is set to "□□□2", this parameter can be set manually.	100.0	Hz	0.1 to 100.0
PB21		For manufacturer setting	0.00		
PB22		Do not change this value by any means.	0.00		
PB23	VFBF	Low pass filter selection Select the low pass filter.  When automatic setting has been selected, select the filter that has the band width close to the one calculated with $\frac{VG2 \cdot 10}{1 + GD2}$ [rad/s]	0000h		Refer to Name and function column.
PB24	*MVS	Slight vibration suppression control selection Select the slight vibration suppression control and PI-PID change. When parameter No. PA08 (auto tuning mode) is set to "□□□3", this parameter is made valid. (Slight vibration suppression control cannot be used in the speed control mode.)  	0000h		Refer to Name and function column.
PB25		For manufacturer setting Do not change this value by any means.	0000h		

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range
PB26	*CDP	Gain changing selection Select the gain changing condition. (Refer to Section 7.6.)  Gain changing selection Under any of the following conditions, the gains change on the basis of the parameter No. PB29 to PB32 settings. 0: Invalid 1: Control instructions from a controller. 2: Command frequency (Parameter No.PB27 setting) 3: Droop pulse value (Parameter No.PB27 setting) 4: Servo motor speed (Parameter No.PB27 setting) Gain changing condition 0: Valid at more than condition (For control instructions from a controller, valid with ON) 1: Valid at less than condition (For control instructions from a controller, valid with OFF)	0000h		Refer to Name and function column.
PB27	CDL	Gain changing condition Used to set the value of gain changing condition (command frequency, droop pulses, servo motor speed) selected in parameter No. PB26.The set value unit changes with the changing condition item. (Refer to Section 7.6.)	10	kpps pulse r/min	0 to 9999
PB28	CDT	Gain changing time constant Used to set the time constant at which the gains will change in response to the conditions set in parameters No. PB26 and PB27. (Refer to Section 7.6.)	1	ms	0 to 100
PB29	GD2B	Gain changing - ratio of load inertia moment to servo motor inertia moment Used to set the ratio of load inertia moment to servo motor inertia moment when gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: ☐☐☐3).	7.0	times	0 to 300.0
PB30	PG2B	Gain changing - position loop gain This parameter cannot be used in the speed control mode. Set the position loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: ☐☐☐3).	37	rad/s	1 to 2000
PB31	VG2B	Gain changing - speed loop gain Set the speed loop gain when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: ☐☐☐3).	823	rad/s	20 to 20000
PB32	VICB	Gain changing - speed integral compensation Set the speed integral compensation when the gain changing is valid. This parameter is made valid when the auto tuning is invalid (parameter No. PA08: ☐☐☐3).	33.7	ms	0.1 to 5000.0
PB33	VRF1B	Gain changing - vibration suppression control - vibration frequency setting This parameter cannot be used in the speed control mode. Set the vibration frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No. PB02 setting is "☐☐☐2" and the parameter No. PB26 setting is "☐☐☐1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range
PB34	VRF2B	Gain changing - vibration suppression control - resonance frequency setting This parameter cannot be used in the speed control mode. Set the resonance frequency for vibration suppression control when the gain changing is valid. This parameter is made valid when the parameter No. PB02 setting is "□□□2" and the parameter No. PB26 setting is "□□□1". When using the vibration suppression control gain changing, always execute the changing after the servo motor has stopped.	100.0	Hz	0.1 to 100.0
PB35		For manufacturer setting Do not change this value by any means.	0.00		
PB36			0.00		
PB37			100		
PB38			0		
PB39			0		
PB40			0		
PB41			1125		
PB42			1125		
PB43			0004h		
PB44			0.0		
PB45			0000h		

5.3 Extension Setting Parameters (No. PC□□)

POINT

- Parameter whose symbol is preceded by * is made valid with the following conditions.
  * : Set the parameter value, switch power off once after setting, and then switch it on again, or perform the controller reset.
  **: Set the parameter value, switch power off once, and then switch it on again.

5.3.1 Parameter list

No.	Symbol	Name	Initial Value	Unit
PC01	*ERZ	Error excessive alarm level	3	rev
PC02	MBR	Electromagnetic brake sequence output	0	ms
PC03	*ENRS	Encoder output pulses selection	0000h	
PC04	**COP1	Function selection C-1	0000h	
PC05	** COP2	Function selection C-2	0000h	
PC06		For manufacturer setting	0000h	
PC07	ZSP	Zero speed	50	r/min
PC08		For manufacturer setting	0	
PC09	MOD1	Analog monitor output 1	0000h	
PC10	MOD2	Analog monitor output 2	0001h	
PC11	MO1	Analog monitor 1 offset	0	mV
PC12	MO2	Analog monitor 2 offset	0	mV
PC13		For manufacturer setting	0	
PC14			0	
PC15			0	
PC16			0000h	
PC17	** COP4	Function selection C-4	0000h	
PC18		For manufacturer setting	0000h	
PC19			0000h	
PC20			0000h	
PC21	*BPS	Alarm history clear	0000h	
PC22		For manufacturer setting	0000h	
PC23			0000h	
PC24			0000h	
PC25			0000h	
PC26			0000h	
PC27			0000h	
PC28			0000h	
PC29			0000h	
PC30			0000h	
PC31			0000h	
PC32			0000h	

5.3.2 List of details

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range
PC01	*ERZ	Error excessive alarm level This parameter cannot be used in the speed control mode. Set error excessive alarm level with rotation amount of servo motor.	3	rev	1 to 200
PC02	MBR	Electromagnetic brake sequence output Used to set the delay time (Tb) between electronic brake interlock (MBR) and the base drive circuit is shut-off.	0	ms	0 to 1000
PC03	*ENRS	Encoder output pulse selection Use to select the, encoder output pulse direction and encoder pulse output setting. 0 0 ☐ ☐ Encoder pulse output phase changing Changes the phases of A, B-phase encoder pulses output . Set value: 0 — A phase / B phase: CCW: ↑↓↑↓↑↓↑↓, CW: ↓↑↓↑↓↑↓↑ Set value: 1 — A phase / B phase: CCW: ↑↓↑↓↑↓↑↓, CW: ↓↑↓↑↓↑↓↑ Encoder output pulse setting selection (refer to parameter No. PA15) 0: Output pulse designation 1: Division ratio setting	0000h		Refer to Name and function column.
PC04	**COP1	Function selection C-1 Select the encoder cable communication system selection. ☐ 0 0 0 Encoder cable communication system selection 0: Two-wire type 1: Four-wire type The following encoder cables are of 4-wire type. MR-EKCBL30M-L MR-EKCBL30M-H MR-EKCBL40M-H MR-EKCBL50M-H The other encoder cables are all of 2-wire type. Incorrect setting will result in an encoder alarm 1 (16) or encoder alarm 2 (20).	0000h		Refer to Name and function column.
PC05	**COP2	Function selection C-2 Motor-less operation select. 0 0 0 ☐ Motor-less operation select. 0: Valid 1: Invalid	0000h		Refer to Name and function column.
PC06		For manufacturer setting Do not change this value by any means.	0000h		
PC07	ZSP	Zero speed Used to set the output range of the zero speed (ZSP). Zero speed signal detection has hysteresis width of 20r/min (Refer to Section 3.5 (2) (b))	50	r/min	0 to 10000
PC08		For manufacturer setting Do not change this value by any means.	0		

<table>
<tr><th>No.</th><th>Symbol</th><th>Name and Function</th><th>Initial Value</th><th>Unit</th><th>Setting Range</th></tr>
<tr><td>PC09</td><td>MOD1</td><td>Analog monitor 1 output
Used to selection the signal provided to the analog monitor 1 (MO1) output. (Refer to Section 5.3.3)
0 0 0 □
└ Analog monitor 1 (MO1) output selection
<table>
<tr><th>Setting</th><th>Item</th></tr>
<tr><td>0</td><td>Servo motor speed (±8V/max. speed)</td></tr>
<tr><td>1</td><td>Torque (±8V/max. torque) (Note 2)</td></tr>
<tr><td>2</td><td>Servo motor speed (+8V/max. speed)</td></tr>
<tr><td>3</td><td>Torque (+8V/max. torque) (Note 2)</td></tr>
<tr><td>4</td><td>Current command (±8V/max. current command)</td></tr>
<tr><td>5</td><td>Speed command (±8V/max. current command)</td></tr>
<tr><td>6</td><td>Droop pulses (±10V/100 pulses) (Note 1)</td></tr>
<tr><td>7</td><td>Droop pulses (±10V/1000 pulses) (Note 1)</td></tr>
<tr><td>8</td><td>Droop pulses (±10V/10000 pulses) (Note 1)</td></tr>
<tr><td>9</td><td>Droop pulses (±10V/100000 pulses) (Note 1)</td></tr>
<tr><td>A</td><td>Feedback position (±10V/1 Mpulses) (Note 1, 3)</td></tr>
<tr><td>B</td><td>Feedback position (±10V/10 Mpulses) (Note 1, 3)</td></tr>
<tr><td>C</td><td>Feedback position (±10V/100 Mpulses) (Note 1, 3)</td></tr>
<tr><td>D</td><td>Bus voltage (±8V/400V)</td></tr>
</table>
Note1. Encoder pulse unit.
2. 8V is outputted at the maximum torque.
3. It can be used by the absolute position detection system.</td><td>0000h</td><td></td><td>Refer to Name and function column.</td></tr>
<tr><td>PC10</td><td>MOD2</td><td>Analog monitor 2 output
Used to selection the signal provided to the analog monitor 2 (MO2) output. (Refer to Section 5.3.3)
0 0 0 □
└ Analog monitor 2 (MO2) output selection
<table>
<tr><th>Setting</th><th>Item</th></tr>
<tr><td>0</td><td>Servo motor speed (±8V/max. speed)</td></tr>
<tr><td>1</td><td>Torque (±8V/max. torque) (Note 2)</td></tr>
<tr><td>2</td><td>Servo motor speed (+8V/max. speed)</td></tr>
<tr><td>3</td><td>Torque (+8V/max. torque) (Note 2)</td></tr>
<tr><td>4</td><td>Current command (±8V/max. current command)</td></tr>
<tr><td>5</td><td>Speed command (±8V/max. current command)</td></tr>
<tr><td>6</td><td>Droop pulses (±10V/100 pulses) (Note 1)</td></tr>
<tr><td>7</td><td>Droop pulses (±10V/1000 pulses) (Note 1)</td></tr>
<tr><td>8</td><td>Droop pulses (±10V/10000 pulses) (Note 1)</td></tr>
<tr><td>9</td><td>Droop pulses (±10V/100000 pulses) (Note 1)</td></tr>
<tr><td>A</td><td>Feedback position (±10V/1 Mpulses) (Note 1, 3)</td></tr>
<tr><td>B</td><td>Feedback position (±10V/10 Mpulses) (Note 1, 3)</td></tr>
<tr><td>C</td><td>Feedback position (±10V/100 Mpulses) (Note 1, 3)</td></tr>
<tr><td>D</td><td>Bus voltage (±8V/400V)</td></tr>
</table>
Note1. Encoder pulse unit.
2. 8V is outputted at the maximum torque.
3. It can be used by the absolute position detection system.</td><td>0001h</td><td></td><td>Refer to Name and function column.</td></tr>
<tr><td>PC11</td><td>MO1</td><td>Analog monitor 1 offset
Used to set the offset voltage of the analog monitor1 (MO1) output.</td><td>0</td><td>mV</td><td>-999 to 999</td></tr>
</table>

No.	Symbol	Name and Function	Initial Value	Unit	Setting Range
PC12	MO2	Analog monitor 2 offset Used to set the offset voltage of the analog monitor2 (MO2) output.	0	mV	-999 to 999
PC13		For manufacturer setting Do not change this value by any means.	0		
PC14			0		
PC15			0		
PC16			0000h		
PC17	**COP4	Function Selection C-4 Home position setting condition in the absolute position detection system can be selected. 0 0 0 [ ] └ Selection of home position setting condition 0: Need to pass motor Z phase after the power supply is switched on. 1: Not need to pass motor Z phase after the power supply is switched on.	0000h		Refer to Name and function column.
PC18		For manufacturer setting Do not change this value by any means.	0000h		
PC19			0000h		
PC20			0000h		
PC21	*BPS	Alarm history clear Used to clear the alarm history. 0 0 0 [ ] └ Alarm history clear 0: Invalid 1: Valid When alarm history clear is made valid, the alarm history is cleared at next power-on. After the alarm history is cleared, the setting is automatically made invalid (reset to 0).	0000h		Refer to Name and function column.
PC22		For manufacturer setting Do not change this value by any means.	0000h		
PC23			0000h		
PC24			0000h		
PC25			0000h		
PC26			0000h		
PC27			0000h		
PC28			0000h		
PC29			0000h		
PC30			0000h		
PC31			0000h		
PC32			0000h		

5.3.3 Analog monitor

The servo status can be output to two channels in terms of voltage. Use this function when using an ammeter to monitor the servo status or synchronizing the torque/speed with the other servo.

(1) Setting

Change the following digits of parameter No. PC09, PC10:

Parameter No. PC09

0	0	0	

Analog monitor (MO1) output selection
(Signal output to across MO1-LG)

Parameter No. PC10

0	0	0	

Analog monitor (MO2) output selection
(Signal output to across MO2-LG)

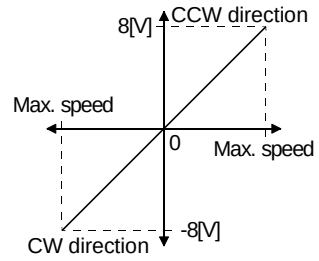
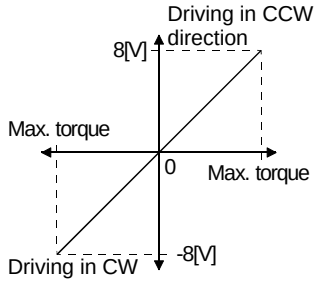
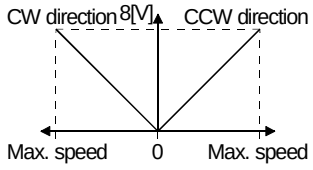
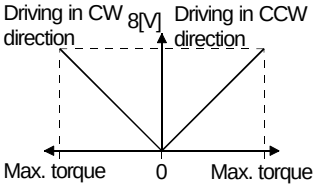
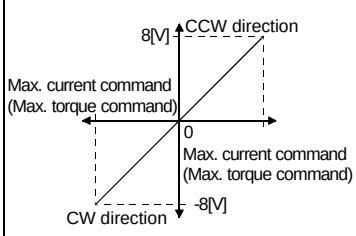
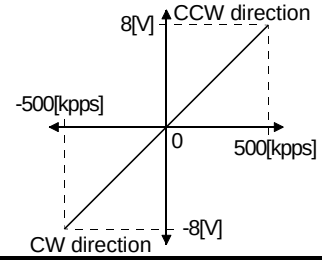
Parameters No. PC11 and PC12 can be used to set the offset voltages to the analog output voltages. The setting range is between −999 and 999mV.

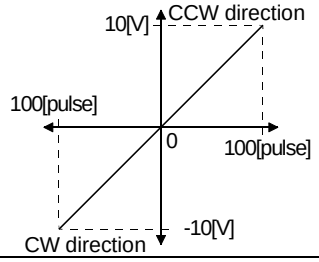
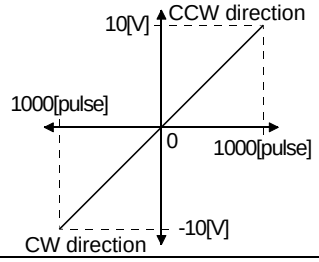
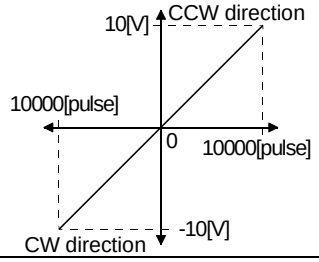
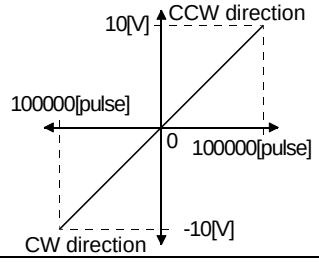
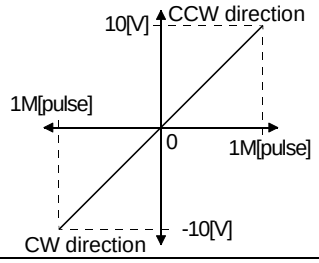
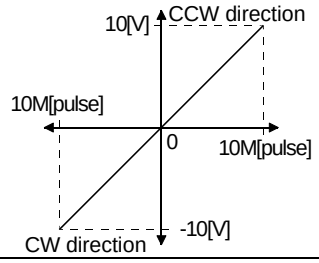
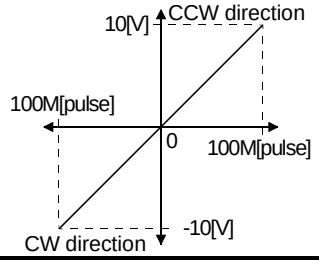
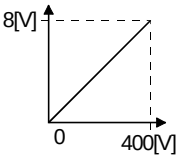
Parameter No.	Description	Setting range [mV]
PC11	Used to set the offset voltage for the analog monitor 1 (MO1).	−999 to 999
PC12	Used to set the offset voltage for the analog monitor 2 (MO2).	

(2) Set content

The servo amplifier is factory-set to output the servo motor speed to analog monitor 1 (MO1) and the torque to analog monitor (MO2). The setting can be changed as listed below by changing the parameter No. PC14 and PC12 value:

Refer to (3) for the measurement point.

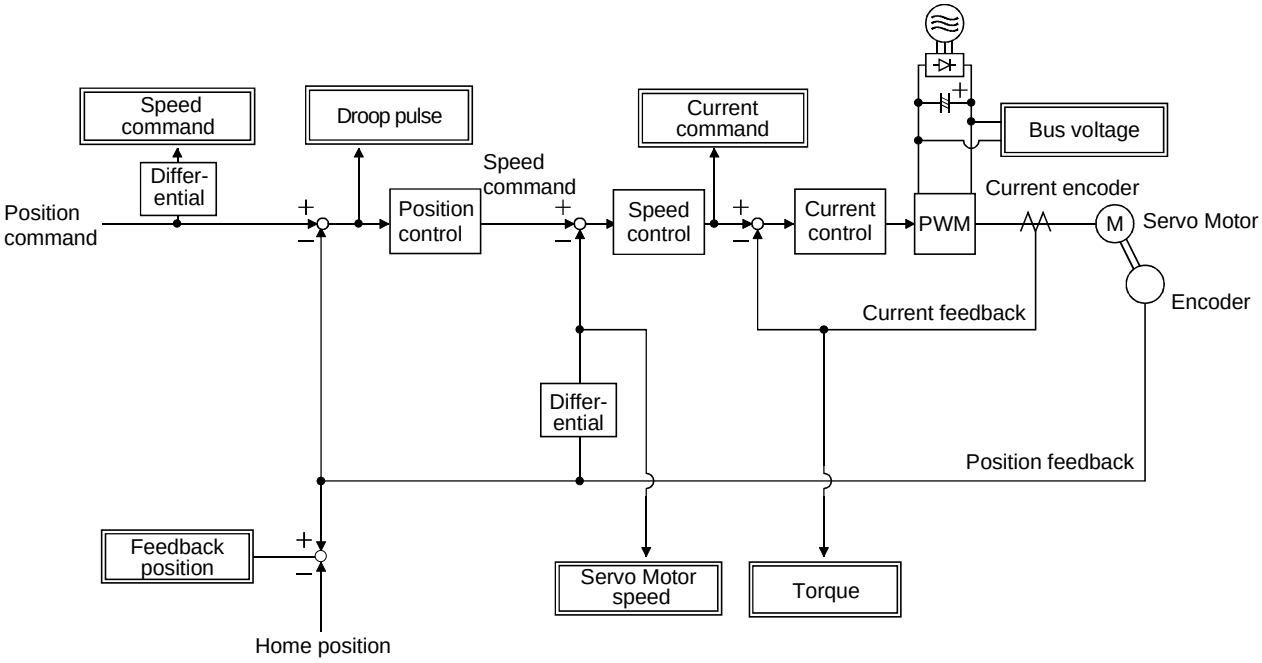
Setting	Output item	Description	Setting	Output item	Description
0	Servo motor speed		1	Torque	
2	Servo motor speed		3	Torque	
4	Current command		5	Speed command	

Setting	Output item	Description	Setting	Output item	Description
6	Droop pulses (Note) (±10V/100 pulses)		7	Droop pulses (Note) (±10V/1000 pulses)	
8	Droop pulses (Note 1) (±10V/10000 pulses)		9	Droop pulses (Note 1) (±10V/100000 pulses)	
A	Feedback position (Note 1,2) (±10V/1 Mpulses)		B	Feedback position (Note 1,2) (±10V/10 Mpulses)	
C	Feedback position (Note 1,2) (±10V/100 Mpulses)		D	Bus voltage	

Note 1. Encoder pulse unit.

2. Available in position control mode

(3) Analog monitor block diagram

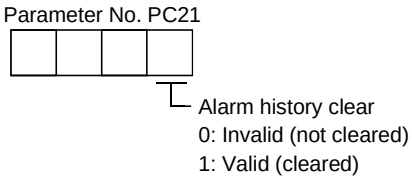


5.3.4 Alarm history clear

The servo amplifier stores one current alarm and five past alarms from when its power is switched on first. To control alarms which will occur during operation, clear the alarm history using parameter No. PC21 before starting operation.

Clearing the alarm history automatically returns to "□□□0".

After setting, this parameter is made valid by switch power from OFF to ON.



5.4 I/O Setting Parameters (No. PD□□)

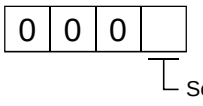
POINT

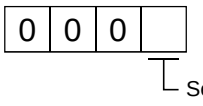
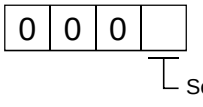
- Parameter whose symbol is preceded by * is made valid with the following conditions.
  * : Set the parameter value, switch power off once after setting, and then switch it on again, or perform the controller reset.

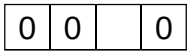
5.4.1 Parameter list

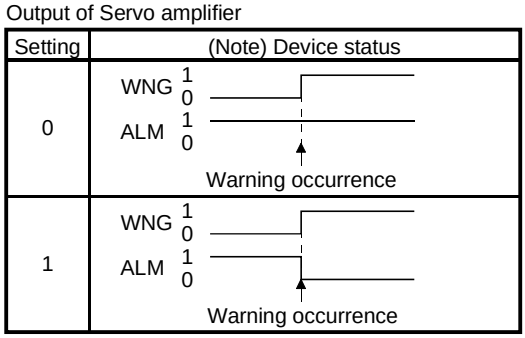
No.	Symbol	Name	Initial Value	Unit
PD01		For manufacturer setting	0000h	
PD02			0000h	
PD03			0000h	
PD04			0000h	
PD05			0000h	
PD06			0000h	
PD07	*D01	Output signal device selection 1 (CN3-pin 13)	0005h	
PD08	*D02	Output signal device selection 2 (CN3-pin 9)	0004h	
PD09	*D03	Output signal device selection 3 (CN3-pin 15)	0003h	
PD10		For manufacturer setting	0000h	
PD11			0004h	
PD12			0000h	
PD13			0000h	
PD14	*D0P3	Function selection D-3	0000h	
PD15		For manufacturer setting	0000h	
PD16			0000h	
PD17			0000h	
PD18			0000h	
PD19			0000h	
PD20			0000h	
PD21			0000h	
PD22			0000h	
PD23			0000h	
PD24			0000h	
PD25			0000h	
PD26			0000h	
PD27			0000h	
PD28			0000h	
PD29			0000h	
PD30			0000h	
PD31			0000h	
PD32			0000h	

5.4.2 List of details

<table>
<tr><th>No.</th><th>Symbol</th><th>Name and Function</th><th>Initial Value</th><th>Unit</th><th>Setting Range</th></tr>
<tr><td>PD01</td><td rowspan="6"></td><td rowspan="6">For manufacturer setting
Do not change this value by any means.</td><td>0000h</td><td rowspan="6"></td><td rowspan="6"></td></tr>
<tr><td>PD02</td><td>0000h</td></tr>
<tr><td>PD03</td><td>0000h</td></tr>
<tr><td>PD04</td><td>0000h</td></tr>
<tr><td>PD05</td><td>0000h</td></tr>
<tr><td>PD06</td><td>0000h</td></tr>
<tr><td>PD07</td><td>*DO1</td><td>Output signal device selection 1 (CN3-13)
Any input signal can be assigned to the CN3-13 pin.
Note that the signal that can be assigned change depending on the control mode.
 

The devices that can be assigned in each control mode are those that have the symbols indicated in the following table. If any other device is set, it is invalid.
<table><tr><th>Setting</th><th>Device</th></tr><tr><td>00</td><td>Always OFF</td></tr><tr><td>01</td><td>For manufacturer setting (Note 3)</td></tr><tr><td>02</td><td>RD</td></tr><tr><td>03</td><td>ALM</td></tr><tr><td>04</td><td>INP (Note 1)</td></tr><tr><td>05</td><td>MBR</td></tr><tr><td>06</td><td>DB</td></tr><tr><td>07</td><td>TLC</td></tr><tr><td>08</td><td>WNG</td></tr><tr><td>09</td><td>BWNG</td></tr></table><table><tr><th>Setting</th><th>Device</th></tr><tr><td>0A</td><td>Always OFF (Note 2)</td></tr><tr><td>0B</td><td>For manufacturer setting (Note 3)</td></tr><tr><td>0C</td><td>ZSP</td></tr><tr><td>0D</td><td>For manufacturer setting (Note 3)</td></tr><tr><td>0E</td><td>For manufacturer setting (Note 3)</td></tr><tr><td>0F</td><td>CDPS</td></tr><tr><td>10</td><td>For manufacturer setting (Note 3)</td></tr><tr><td>11</td><td>ABSV (Note 1)</td></tr><tr><td>12 to 1F</td><td>For manufacturer setting (Note 3)</td></tr><tr><td>20 to 3F</td><td>For manufacturer setting (Note 3)</td></tr></table>Note 1. It becames always OFF in speed control mode.
Note 2. It becames SA in speed control mode.
Note 3. For manufacturer setting
Never change this setting.</td><td>0005h</td><td></td><td>Refer to Name and function column.</td></tr>
<tr><td>PD08</td><td>*DO2</td><td>Output signal device selection 2 (CN3-9)
Any input signal can be assigned to the CN3-9 pin.
The devices that can be assigned and the setting method are the same as in parameter No. PD07.
 
</td><td>0004h</td><td></td><td>Refer to Name and function column.</td></tr>
<tr><td>PD09</td><td>*DO3</td><td>Output signal device selection 3 (CN3-15)
Any input signal can be assigned to the CN3-15 pin.
The devices that can be assigned and the setting method are the same as in parameter No. PD07.
 
</td><td>0003h</td><td></td><td>Refer to Name and function column.</td></tr>
</table>

<table>
<tr><th>No.</th><th>Symbol</th><th>Name and Function</th><th>Initial Value</th><th>Unit</th><th>Setting Range</th></tr>
<tr><td>PD10</td><td rowspan="4"></td><td rowspan="4">For manufacturer setting
Do not change this value by any means.</td><td>0000h</td><td rowspan="4"></td><td rowspan="4"></td></tr>
<tr><td>PD11</td><td>0004h</td></tr>
<tr><td>PD12</td><td>0000h</td></tr>
<tr><td>PD13</td><td>0000h</td></tr>
<tr><td>PD14</td><td>*DOP3</td><td>Function selection D-3
Set the ALM output signal at warning occurrence.
 

Selection of output device at warning occurrence
Select the warning (WNG) and trouble (ALM) output status at warning occurrence.
Output of Servo amplifier
 

Note. 0: off
1: on</td><td>0000h</td><td></td><td>Refer to Name and function column.</td></tr>
<tr><td>PD15</td><td rowspan="18"></td><td rowspan="18">For manufacturer setting
Do not change this value by any means.</td><td>0000h</td><td rowspan="18"></td><td rowspan="18"></td></tr>
<tr><td>PD16</td><td>0000h</td></tr>
<tr><td>PD17</td><td>0000h</td></tr>
<tr><td>PD18</td><td>0000h</td></tr>
<tr><td>PD19</td><td>0000h</td></tr>
<tr><td>PD20</td><td>0000h</td></tr>
<tr><td>PD21</td><td>0000h</td></tr>
<tr><td>PD22</td><td>0000h</td></tr>
<tr><td>PD23</td><td>0000h</td></tr>
<tr><td>PD24</td><td>0000h</td></tr>
<tr><td>PD25</td><td>0000h</td></tr>
<tr><td>PD26</td><td>0000h</td></tr>
<tr><td>PD27</td><td>0000h</td></tr>
<tr><td>PD28</td><td>0000h</td></tr>
<tr><td>PD29</td><td>0000h</td></tr>
<tr><td>PD30</td><td>0000h</td></tr>
<tr><td>PD31</td><td>0000h</td></tr>
<tr><td>PD32</td><td>0000h</td></tr>
</table>

6. GENERAL GAIN ADJUSTMENT

6.1 Different adjustment methods

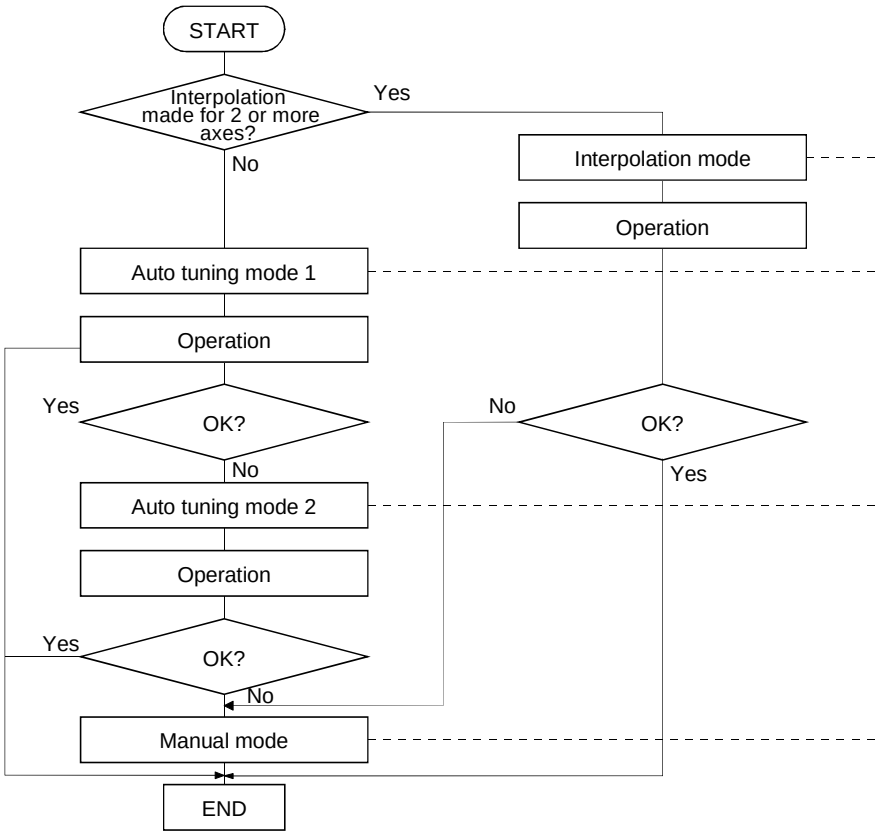
6.1.1 Adjustment on a single servo amplifier

The gain adjustment in this section can be made on a single servo amplifier. For gain adjustment, first execute auto tuning mode 1. If you are not satisfied with the results, execute auto tuning mode 2 and manual mode in this order.

(1) Gain adjustment mode explanation

Gain adjustment mode	Parameter No. PA08 setting	Estimation of load inertia moment ratio	Automatically set parameters	Manually set parameters
Auto tuning mode 1 (initial value)	0001	Always estimated	GD2 (parameter No. PB06) PG2 (parameter No. PB08) PG1 (parameter No. PB07) VG2 (parameter No. PB09) VIC (parameter No. PB10)	Response level setting of parameter No. 2
Auto tuning mode 2	0002	Fixed to parameter No. PB06 value	PG2 (parameter No. PB08) PG1 (parameter No. PB07) VG2 (parameter No. PB09) VIC (parameter No. PB10)	GD2 (parameter No. PB06) Response level setting of parameter No. PA09
Manual mode	0003			PG1 (parameter No. PB07) GD2 (parameter No. PB06) VG2 (parameter No. PB09) VIC (parameter No. PB10)
Interpolation mode	0000	Always estimated	GD2 (parameter No. PB06) PG2 (parameter No. PB08) VG2 (parameter No. PB09) VIC (parameter No. PB10)	PG1 (parameter No. PB07)

(2) Adjustment sequence and mode usage



Usage
Used when you want to match the position gain (PG1) between 2 or more axes. Normally not used for other purposes.
Allows adjustment by merely changing the response level setting. First use this mode to make adjustment.
Used when the conditions of auto tuning mode 1 are not met and the load inertia moment ratio could not be estimated properly, for example.
You can adjust all gains manually when you want to do fast settling or the like.

6.1.2 Adjustment using servo configuration software

This section gives the functions and adjustment that may be performed by using the servo amplifier with the servo configuration software which operates on a personal computer.

Function	Description	Adjustment
Machine analyzer	With the machine and servo motor coupled, the characteristic of the mechanical system can be measured by giving a random vibration command from the personal computer to the servo and measuring the machine response.	・You can grasp the machine resonance frequency and determine the notch frequency of the machine resonance suppression filter. ・You can automatically set the optimum gains in response to the machine characteristic. This simple adjustment is suitable for a machine which has large machine resonance and does not require much settling time.
Gain search	Executing gain search under to-and-fro positioning command measures settling characteristic while simultaneously changing gains, and automatically searches for gains which make settling time shortest.	・You can automatically set gains which make positioning settling time shortest.
Machine simulation	Response at positioning settling of a machine can be simulated from machine analyzer results on personal computer.	・You can optimize gain adjustment and command pattern on personal computer.

6.2 Auto tuning

6.2.1 Auto tuning mode

The servo amplifier has a real-time auto tuning function which estimates the machine characteristic (load inertia moment ratio) in real time and automatically sets the optimum gains according to that value. This function permits ease of gain adjustment of the servo amplifier.

(1) Auto tuning mode 1

The servo amplifier is factory-set to the auto tuning mode 1.

In this mode, the load inertia moment ratio of a machine is always estimated to set the optimum gains automatically.

The following parameters are automatically adjusted in the auto tuning mode 1.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

POINT

- The auto tuning mode 1 may not be performed properly if the following conditions are not satisfied.
- Time to reach 2000r/min is the acceleration/deceleration time constant of 5s or less.
- Speed is 150r/min or higher.
- The ratio of load inertia moment to servo motor inertia moment is 100 times or less.
- The acceleration/deceleration torque is 10% or more of the rated torque.
- Under operating conditions which will impose sudden disturbance torque during acceleration/deceleration or on a machine which is extremely loose, auto tuning may not function properly, either. In such cases, use the auto tuning mode 2 or manual mode to make gain adjustment.

(2) Auto tuning mode 2

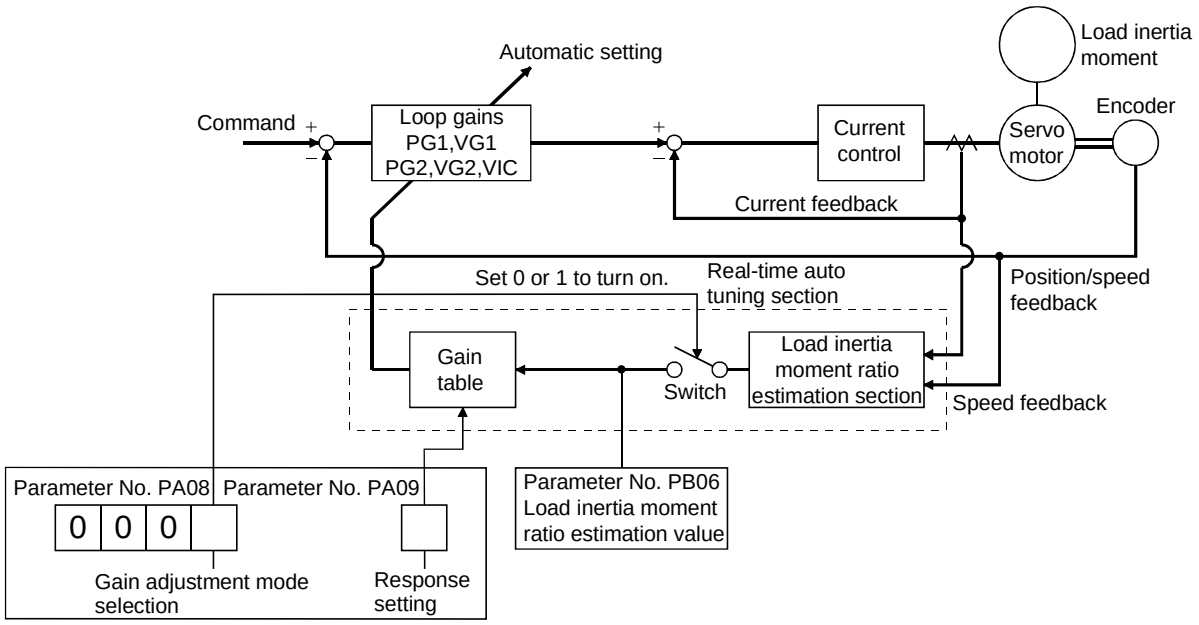
Use the auto tuning mode 2 when proper gain adjustment cannot be made by auto tuning mode 1. Since the load inertia moment ratio is not estimated in this mode, set the value of a correct load inertia moment ratio (parameter No. PB06).

The following parameters are automatically adjusted in the auto tuning mode 2.

Parameter No.	Abbreviation	Name
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

6.2.2 Auto tuning mode operation

The block diagram of real-time auto tuning is shown below.



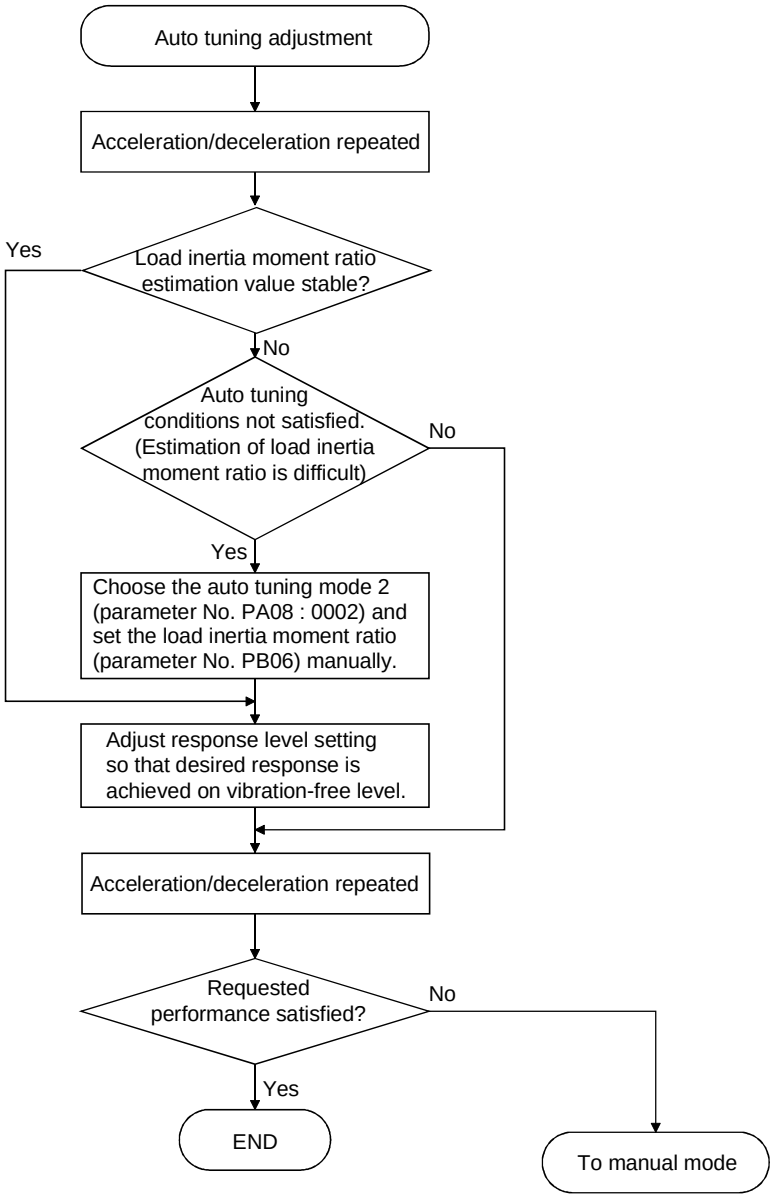
When a servo motor is accelerated/decelerated, the load inertia moment ratio estimation section always estimates the load inertia moment ratio from the current and speed of the servo motor. The results of estimation are written to parameter No. PB06 (the ratio of load inertia moment to servo motor). These results can be confirmed on the status display screen of the servo configuration software section.
If the value of the load inertia moment ratio is already known or if estimation cannot be made properly, chose the "auto tuning mode 2" (parameter No. PA08: 0002) to stop the estimation of the load inertia moment ratio (Switch in above diagram turned off), and set the load inertia moment ratio (parameter No. 34) manually.
From the preset load inertia moment ratio (parameter No. PB06) value and response level (parameter No. PA09), the optimum loop gains are automatically set on the basis of the internal gain tale.
The auto tuning results are saved in the EEP-ROM of the servo amplifier every 60 minutes since power-on. At power-on, auto tuning is performed with the value of each loop gain saved in the EEP-ROM being used as an initial value.

POINT

- If sudden disturbance torque is imposed during operation, the estimation of the inertia moment ratio may malfunction temporarily. In such a case, choose the "auto tuning mode 2" (parameter No. PA08: 0002) and set the correct load inertia moment ratio in parameter No. PB06.
- When any of the auto tuning mode 1 and auto tuning mode settings is changed to the manual mode 2 setting, the current loop gains and load inertia moment ratio estimation value are saved in the EEP-ROM.

6.2.3 Adjustment procedure by auto tuning

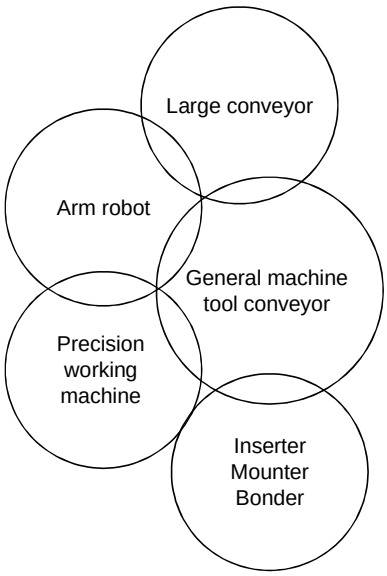
Since auto tuning is made valid before shipment from the factory, simply running the servo motor automatically sets the optimum gains that match the machine. Merely changing the response level setting value as required completes the adjustment. The adjustment procedure is as follows.



6.2.4 Response level setting in auto tuning mode

Set the response (The first digit of parameter No. PA09) of the whole servo system. As the response level setting is increased, the trackability and settling time for a command decreases, but a too high response level will generate vibration. Hence, make setting until desired response is obtained within the vibration-free range.
If the response level setting cannot be increased up to the desired response because of machine resonance beyond 100Hz, filter tuning mode (parameter No. PB01) or machine resonance suppression filter (parameter No. PB13 to PB16) may be used to suppress machine resonance. Suppressing machine resonance may allow the response level setting to increase. Refer to Section 7.1 for filter tuning mode and machine resonance suppression filter.

Setting of parameter No. PA09

Response level setting	Machine characteristic		
	Machine rigidity	Machine resonance frequency guideline	Guideline of corresponding machine
1	Low	10.0	
2		11.3	
3		12.7	
4		14.3	
5		16.1	
6		18.1	
7		20.4	
8		23.0	
9		25.9	
10		29.2	
11		32.9	
12		37.0	
13		41.7	
14		47.0	
15		52.9	
16	Middle	59.6	
17		67.1	
18		75.6	
19		85.2	
20		95.9	
21		108.0	
22		121.7	
23		137.1	
24		154.4	
25		173.9	
26		195.9	
27		220.6	
28		248.5	
29		279.9	
30		315.3	
31		355.1	
32	High	400.0	

6.3 Manual mode 1 (simple manual adjustment)

If you are not satisfied with the adjustment of auto tuning, you can make simple manual adjustment with three parameters.

> POINT
> - If machine resonance occurs, filter tuning mode (parameter No. PB01) or machine resonance suppression filter (parameter No. PB13 to PB16) may be used to suppress machine resonance. (Refer to Section 7.1.)

(1) For speed control

(a) Parameters

The following parameters are used for gain adjustment:

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Brief-adjust with auto tuning. Refer to Section 6.2.3.	
2	Change the setting of auto tuning to the manual mode (Parameter No.PA08: 0003).	
3	Set an estimated value to the ratio of load inertia moment to servo motor inertia moment. (If the estimate value with auto tuning is correct, setting change is not required.)	
4	Set a slightly smaller value to the model loop gain Set a slightly larger value to the speed integral compensation.	
5	Increase the speed loop gain within the vibration- and unusual noise-free range, and return slightly if vibration takes place.	Increase the speed loop gain.
6	Decrease the speed integral compensation within the vibration-free range, and return slightly if vibration takes place.	Decrease the time constant of the speed integral compensation.
7	Increase the model loop gain, and return slightly if overshooting takes place.	Increase the model loop gain.
8	If the gains cannot be increased due to mechanical system resonance or the like and the desired response cannot be achieved, response may be increased by suppressing resonance with filter tuning mode or machine resonance suppression filter and then executing steps 2 and 3.	Suppression of machine resonance. Refer to Section 7.2, 7.3.
9	While checking the settling characteristic and rotational status, fine-adjust each gain.	Fine adjustment

(c)Adjustment description

1) Speed loop gain (parameter No. PB09)

This parameter determines the response level of the speed control loop. Increasing this value enhances response but a too high value will make the mechanical system liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression:

$$\text{Speed loop response frequency(Hz)} = \frac{\text{Speed loop gain setting}}{(1+\text{ratio of load inertia moment to servo motor inertia moment})\times 2\pi}$$

2) Speed integral compensation (VIC: parameter No. PB10)

To eliminate stationary deviation against a command, the speed control loop is under proportional integral control. For the speed integral compensation, set the time constant of this integral control. Increasing the setting lowers the response level. However, if the load inertia moment ratio is large or the mechanical system has any vibratory element, the mechanical system is liable to vibrate unless the setting is increased to some degree. The guideline is as indicated in the following expression:

$$\text{Speed integral compensation setting(ms)} \geq \frac{2000 \text{ to } 3000}{\text{Speed loop gain setting}/\ (1+\text{ratio of load inertia moment to servo motor inertia moment setting}\times 0.1)}$$

3) Model loop gain (PG1: Parameter No.PB07)

This parameter determines the response level to a position command. Increasing the model loop gain improves track ability to a position command, but a too high value will make overshooting liable to occur at the time of setting.

$$\text{Model loop gain guideline} \leq \frac{\text{Speed loop gain setting}}{(1+\text{ratio of load inertia moment to servo mortar inertia moment})}\times\left(\frac{1}{4}\text{ to }\frac{1}{8}\right)$$

(2) For position control

(a) Parameters

The following parameters are used for gain adjustment:

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	VG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Adjustment procedure

Step	Operation	Description
1	Brief-adjust with auto tuning. Refer to Section 6.2.3.	
2	Change the setting of auto tuning to the manual mode (Parameter No.PA08: 0003).	
3	Set an estimated value to the ratio of load inertia moment to servo motor inertia moment. (If the estimate value with auto tuning is correct, setting change is not required.)	
4	Set a slightly smaller value to the model loop gain and the position loop gain. Set a slightly larger value to the speed integral compensation.	
5	Increase the speed loop gain within the vibration- and unusual noise-free range, and return slightly if vibration takes place.	Increase the speed loop gain.
6	Decrease the speed integral compensation within the vibration-free range, and return slightly if vibration takes place.	Decrease the time constant of the speed integral compensation.
7	Increase the position loop gain, and return slightly if vibration takes place.	Increase the position loop gain.
8	Increase the model loop gain, and return slightly if overshooting takes place.	Increase the position loop gain.
9	If the gains cannot be increased due to mechanical system resonance or the like and the desired response cannot be achieved, response may be increased by suppressing resonance with filter tuning mode or machine resonance suppression filter and then executing steps 3 to 5.	Suppression of machine resonance. Refer to Section 7.1.
10	While checking the settling characteristic and rotational status, fine-adjust each gain.	Fine adjustment

(c) Adjustment description

1) Speed loop gain (VG2: parameter No. PB09)

This parameter determines the response level of the speed control loop. Increasing this value enhances response but a too high value will make the mechanical system liable to vibrate. The actual response frequency of the speed loop is as indicated in the following expression:

$$\text{Speed loop response frequency(Hz)} = \frac{\text{Speed loop gain 2 setting}}{(1+\text{ratio of load inertia moment to servo motor inertia moment})\times 2\pi}$$

2) Speed integral compensation (VIC: parameter No. PB10)

To eliminate stationary deviation against a command, the speed control loop is under proportional integral control. For the speed integral compensation, set the time constant of this integral control. Increasing the setting lowers the response level. However, if the load inertia moment ratio is large or the mechanical system has any vibratory element, the mechanical system is liable to vibrate unless the setting is increased to some degree. The guideline is as indicated in the following expression:

$$\text{Speed integral compensation setting(ms)} \geq \frac{\text{2000 to 3000}}{\text{Speed loop gain 2 setting}/(1+\text{ratio of load inertia moment to servo motor inertia moment 2 setting})}$$

3) Model loop gain (PG1: Parameter No.PB07)

This parameter determines the response level to a position command. Increasing the model loop gain improves track ability to a position command, but a too high value will make overshooting liable to occur at the time of setting.

$$\text{Model loop gain guideline} \leq \frac{\text{Speed loop gain setting}}{(1+\text{ratio of load inertia moment to servo mortar inertia moment})} \times \left(\frac{1}{4}\text{ to }\frac{1}{8}\right)$$

4) Model loop gain (PG1: parameter No. PB07)

This parameter determines the response level to a position command. Increasing position loop gain 1 improves track ability to a position command but a too high value will make overshooting liable to occur at the time of settling.

$$\text{Model loop gain guideline} \leq \frac{\text{Speed loop gain 2 setting}}{(1+\text{ratio of load inertia moment to servo motor inertia moment})} \times \left(\frac{1}{4}\text{ to }\frac{1}{8}\right)$$

6.4 Interpolation mode

The interpolation mode is used to match the position loop gains of the axes when performing the interpolation operation of servo motors of two or more axes for an X-Y table or the like. In this mode, the model loop gain and speed loop gain which determine command trackability are set manually and the other parameter for gain adjustment are set automatically.

(1) Parameter

(a) Automatically adjusted parameters

The following parameters are automatically adjusted by auto tuning.

Parameter No.	Abbreviation	Name
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation

(b) Manually adjusted parameters

The following parameters are adjustable manually.

Parameter No.	Abbreviation	Name
PB07	PG1	Model loop gain

(2) Adjustment procedure

Step	Operation	Description
1	Set to the auto tuning mode.	Select the auto tuning mode 1.
2	During operation, increase the response level setting (parameter No. PA09), and return the setting if vibration occurs.	Adjustment in auto tuning mode 1.
3	Check the values of model loop gain.	Check the upper setting limits.
4	Set the interpolation mode (parameter No. PA08: 0000).	Select the interpolation mode.
5	Using the model loop gain value checked in step 3 as the guideline of the upper limit, set in PG1 the value identical to the position loop gain of the axis to be interpolated.	Set position loop gain.
6	Looking at the interpolation characteristic and rotation status, fine-adjust the gains and response level setting.	Fine adjustment.

(3) Adjustment description

(a) Model loop gain (parameter No. PB07)

This parameter determines the response level of the position control loop. Increasing model loop gain improves trackability to a position command but a too high value will make overshooting liable to occur at the time of settling. The droop pulse value is determined by the following expression.

$$\text{Droop pulse value (pulse)} = \frac{\frac{\text{Rotation speed (r/min)}}{60} \times 262144\text{(pulse)}}{\text{Model loop gain setting}}$$

6.5 Differences in auto tuning between MELSERVO-J2 and MELSERVO-J2-Super

To meet higher response demands, the MELSERVO-J3 series has been changed in response level setting range from the MELSERVO-J2S-Super series. The following table lists comparison of the response level setting.

MELSERVO-J2-Super		MELSERVO-J3	
Parameter No. 9 Setting	Guideline for Machine Resonance Frequency [Hz]	Parameter No. PA09 Setting	Guideline for Machine Resonance Frequency [Hz]
		1	10.0
		2	11.3
		3	12.7
1	15	4	14.3
		5	16.1
		6	18.1
2	20	7	20.4
		8	23.0
3	25	9	25.9
4	30	10	29.2
		11	32.9
5	35	12	37.0
		13	41.7
6	45	14	47.0
7	55	15	52.9
		16	59.6
8	70	17	67.1
		18	75.6
9	85	19	85.2
		20	95.9
A	105	21	108.0
		22	121.7
B	130	23	137.1
C	160	24	154.4
		25	173.9
D	200	26	195.9
		27	220.6
E	240	28	248.5
		29	279.9
F	300	30	315.3
		31	355.1
		32	400.0

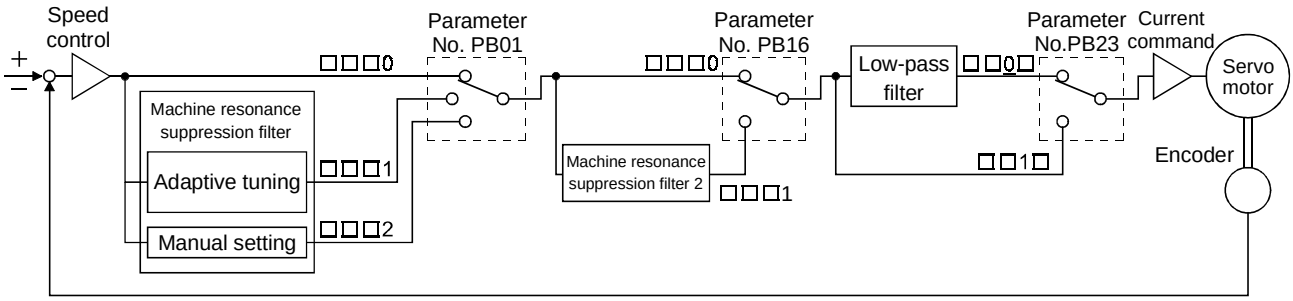
Note that because of a slight difference in gain adjustment pattern, response may not be the same if the resonance frequency is set to the same value.

7. SPECIAL ADJUSTMENT FUNCTIONS

> **POINT**
>
> ・The functions given in this chapter need not be used generally. Use them if you are not satisfied with the machine status after making adjustment in the methods in Chapter 7.

If a mechanical system has a natural resonance point, increasing the servo system response level may cause the mechanical system to produce resonance (vibration or unusual noise) at that resonance frequency.
Using the machine resonance suppression filter and adaptive tuning can suppress the resonance of the mechanical system.

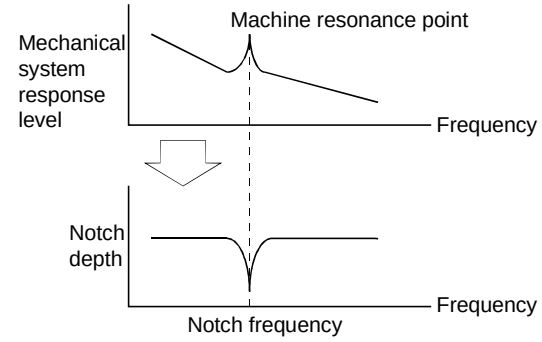
7.1 Function block diagram



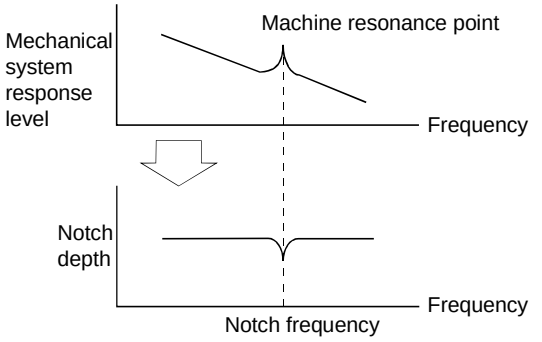
7.2 Adaptive filter Ⅱ

(1) Function

Adaptive filter Ⅱ (adaptive tuning) is a function in which the servo amplifier detects machine vibration for a predetermined period of time and sets the filter characteristics automatically to suppress mechanical system vibration. Since the filter characteristics (frequency, depth) are set automatically, you need not be conscious of the resonance frequency of a mechanical system.



When machine resonance is large and frequency is low

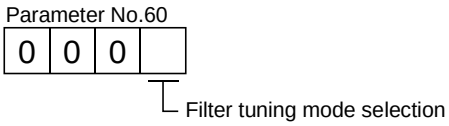


When machine resonance is small and frequency is high

> **POINT**
>
> ・The machine resonance frequency which adaptive tuning mode can respond to is about 100 to 2.25kHz. Adaptive vibration suppression control has no effect on the resonance frequency outside this range.
>
> ・Adaptive vibration suppression control may provide no effect on a mechanical system which has complex resonance characteristics.

(2) Parameters

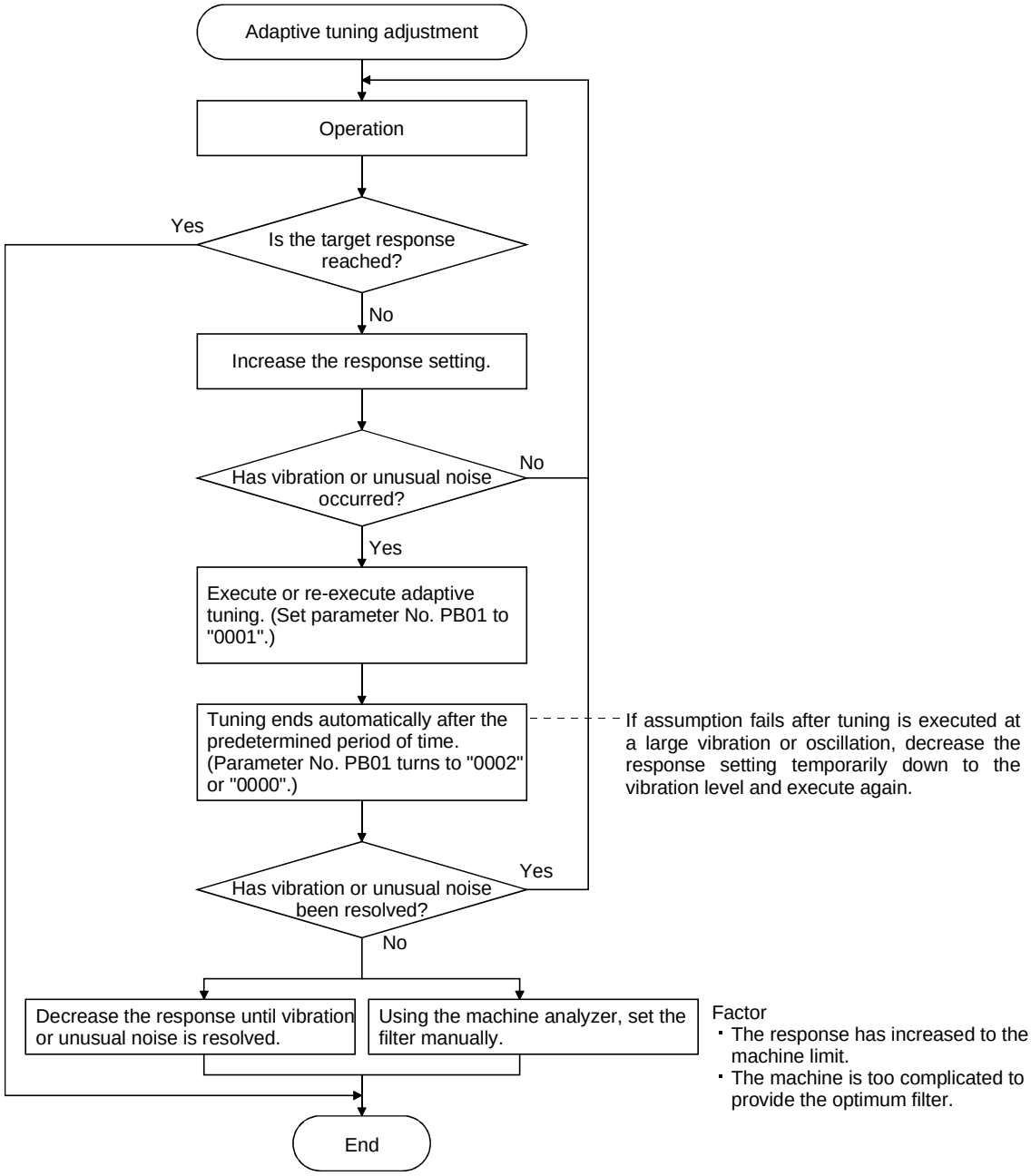
The operation of adaptive tuning mode (parameter No. PB01).



Setting	Filter adjustment mode	Automatically set parameter
0	Filter OFF	(Note)
1	Filter tuning mode	Parameter No. PB13 Parameter No. PB14
2	Manual mode	

Note. Parameter No. PB19 and PB20 are fixed to the initial values.

(3) Adaptive tuning mode procedure



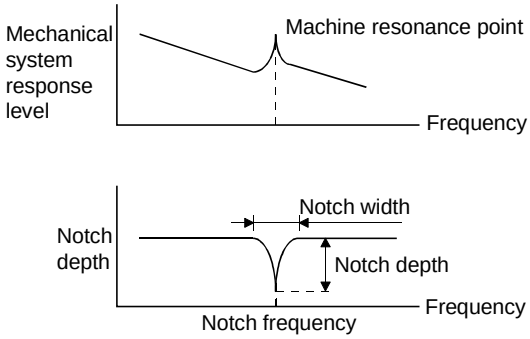
POINT

- "Filter OFF" enables a return to the factory-set initial value.
- When adaptive tuning is executed, vibration sound increases as an excitation signal is forcibly applied for several seconds.
- When adaptive tuning is executed, machine resonance is detected for a maximum of 10 seconds and a filter is generated. After filter generation, the adaptive tuning mode automatically shifts to the manual mode.
- Adaptive tuning generates the optimum filter with the currently set control gains. If vibration occurs when the response setting is increased, execute adaptive tuning again.
- During adaptive tuning, a filter having the best notch depth at the set control gain is generated. To allow a filter margin against mechane resonance, increase the notch depth in the manual mode.

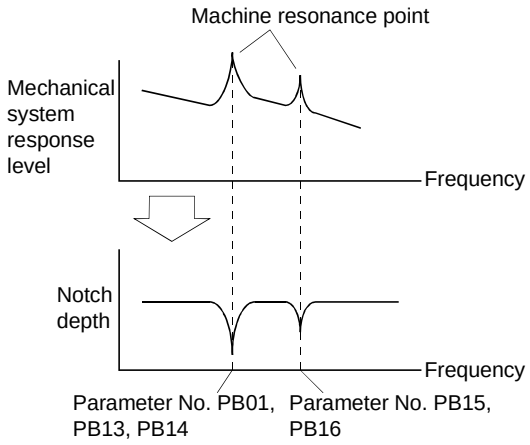
7.3 Machine resonance suppression filter

(1) Function

The machine resonance suppression filter is a filter function (notch filter) which decreases the gain of the specific frequency to suppress the resonance of the mechanical system. You can set the gain decreasing frequency (notch frequency), gain decreasing depth and width.



You can use the machine resonance suppression filter 1 (parameter No. PB13, PB14) and machine resonance suppression filter 2 (parameter No. PB15, PB16) to suppress the vibration of two resonance frequencies. Execution of adaptive tuning in the filter tuning mode automatically adjusts the machine resonance suppression filter. When adaptive tuning is ON, the adaptive tuning mode shifts to the manual mode after the predetermined period of time. The manual mode enables manual setting using the machine resonance suppression filter 1.



(2) Parameters

(a) Machine resonance suppression filter 1 (parameter No. PB13, PB14)

Set the notch frequency, notch depth and notch width of the machine resonance suppression filter 1 (parameter No. PB13, PB14)

When you have made adaptive filter tuning mode (parameter No. PB01) "manual mode", set up the machine resonance suppression filter 1 becomes effective.

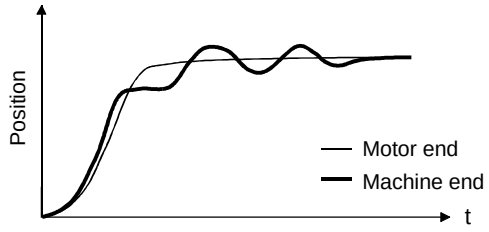
POINT

- The machine resonance suppression filter is a delay factor for the servo system. Hence, vibration may increase if you set a wrong resonance frequency or a too deep notch.
- If the frequency of machine resonance is unknown, decrease the notch frequency from higher to lower ones in order. The optimum notch frequency is set at the point where vibration is minimal.
- A deeper notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.
- A deeper notch has a higher effect on machine resonance suppression but increases a phase delay and may increase vibration.
- The machine characteristic can be grasped beforehand by the machine analyzer on the MR Configurator (Servo configuration software). This allows the required notch frequency and depth to be determined.

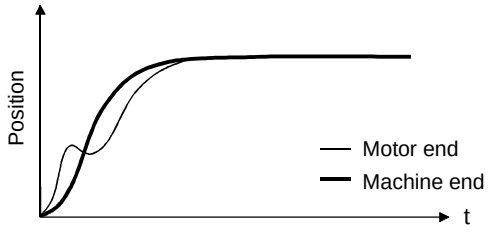
7.4 Advanced Vibration Suppression Control

(1) Operation

Vibration suppression control is used to further suppress machine end vibration, such as workpiece end vibration and base shake. The motor side operation is adjusted for positioning so that the machine does not shake.



Vibration suppression control OFF
(Normal control)



Vibration suppression control ON

When the advanced vibration suppression control (vibration suppression control tuning mode parameter No. PB02) is executed, the vibration frequency at machine end can automatically be estimated to suppress machine end vibration.

In the vibration suppression control tuning mode, this mode shifts to the manual mode after operation is performed the predetermined number of times. The manual mode enables manual setting using the vibration suppression control vibration frequency setting (parameter No. PB19) and vibration suppression control resonance frequency setting (parameter No. PB20).

(2) Parameter

Select the operation of the vibration suppression control tuning mode (parameter No. PB02).

Parameter No. PB02

0	0	0	

Vibration suppression control tuning mode

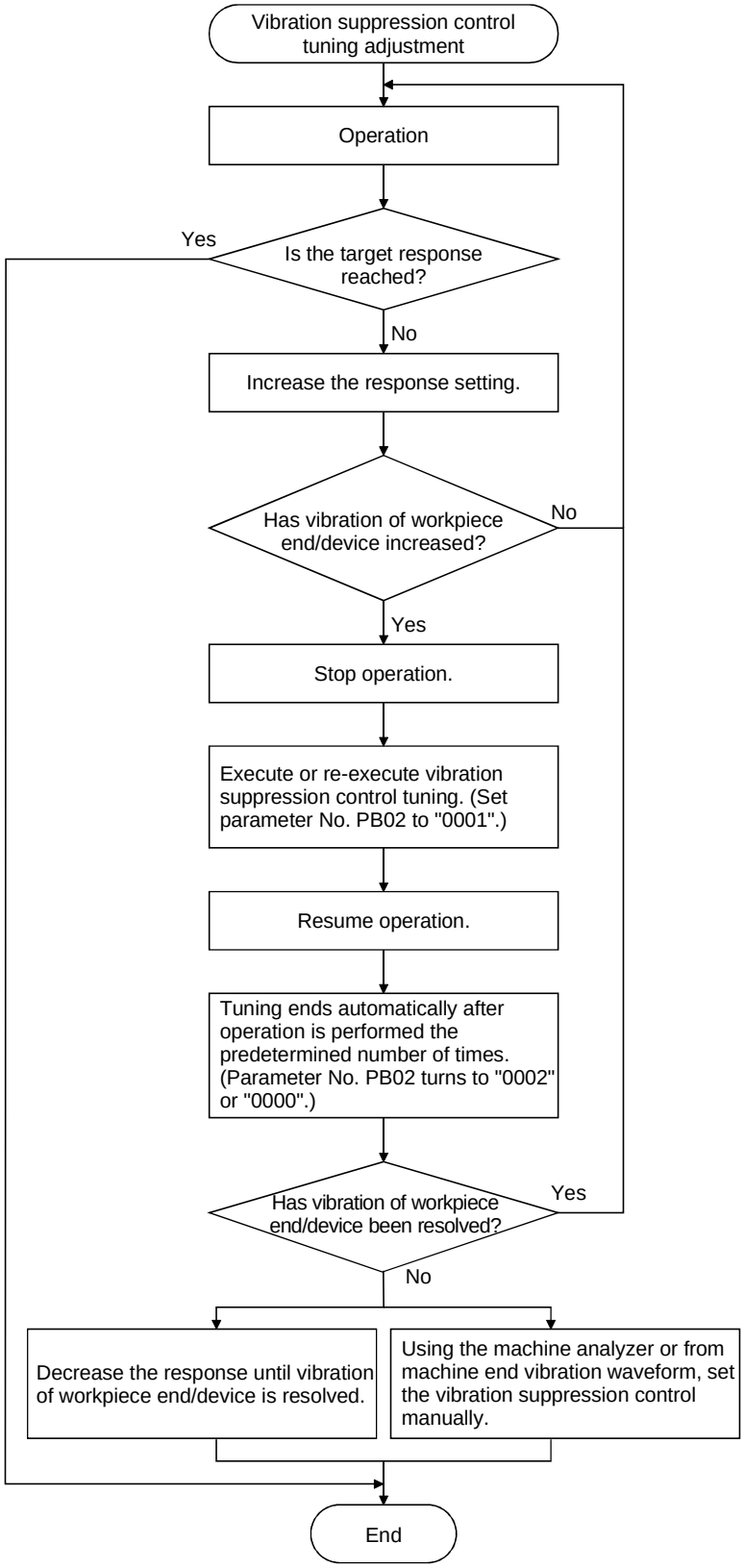
Setting	Vibration Suppression Control Tuning Mode	Automatically Set Parameter
0	Vibration suppression control OFF	(Note)
1	Vibration suppression control tuning mode (Advanced vibration suppression control)	Parameter No. PB19 Parameter No. PB20
2	Manual mode	

Note. Parameter No. PB19 and PB20 are fixed to the initial values.

POINT

- The function is made valid when the auto tuning mode (parameter No. PA08) is the auto tuning mode 2 ("0002") or manual mode ("0003").
- The machine resonance frequency supported in the vibration suppression control tuning mode is 1.0Hz to 100.0Hz. The function is not effective for vibration outside this range.
- Stop the motor before changing the vibration suppression control-related parameters (parameter No. PB02, PB19, PB20, PB33, PB34). A failure to do so will cause a shock.
- For positioning operation during execution of vibration suppression control tuning, provide a stop time to ensure a stop after full vibration damping.
- Vibration suppression control tuning may not make normal estimation if the residual vibration at the motor end is small.
- Vibration suppression control tuning sets the optimum parameter with the currently set control gains. When the response setting is increased, set vibration suppression control tuning again.

(3) Vibration suppression control tuning mode procedure

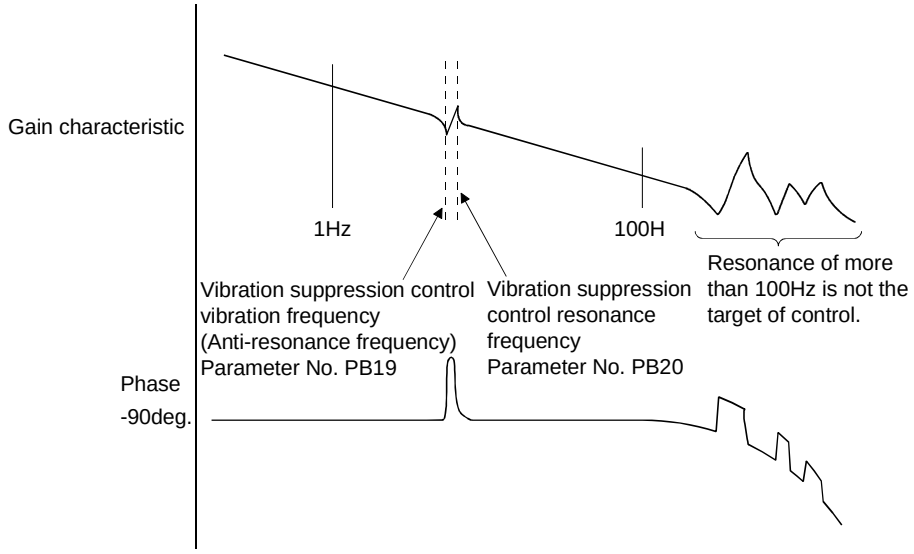


Factor
- Estimation cannot be made as machine end vibration has not been transmitted to the motor end.
- The response of the model loop gain has increased to the machine end vibration frequency (vibration suppression control limit).

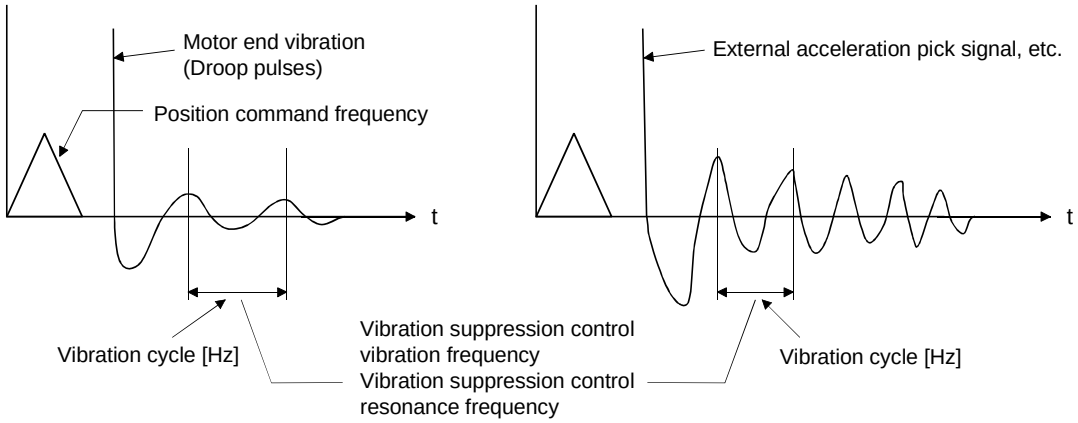
(4) Vibration suppression control manual mode

Measure work end vibration and device shake with the machine analyzer or external measuring instrument, and set the vibration suppression control vibration frequency (parameter No. PB19) and vibration suppression control resonance frequency (parameter No. PB20) to set vibration suppression control manually.

(a) When a vibration peak can be confirmed using MR Configurator, machine analyzer or external FFT equipment



(b) When vibration can be confirmed using monitor signal or external sensor



POINT

- When machine end vibration does not show up in motor end vibration, the setting of the motor end vibration frequency does not produce an effect.
- When the anti-resonance frequency and resonance frequency can be confirmed using the machine analyzer or external FFT device, do not set the same value but set different values to improve the vibration suppression performance.
- A vibration suppression control effect is not produced if the relationship between the model loop gain (parameter No. PB07) value and vibration frequency is as indicated below. Make setting after decreasing PG1, e.g. reduce the response setting.

$$\frac{1}{2\pi}(1.5 \times PG1) > \text{vibration frequency}$$

7.5 Low-pass filter

(1) Function

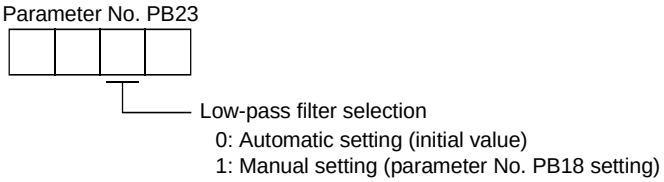
When a ballscrew or the like is used, resonance of high frequency may occur as the response level of the servo system is increased. To prevent this, the low-pass filter is factory-set to be valid for a torque command. The filter frequency of this low-pass filter is automatically adjusted to the value in the following expression:

$$\text{Filter frequency(rad/s)} = \frac{VG2}{1 + GD2} \times 10$$

When parameter No. PB23 is set to "☐☐1☐", manual setting can be made with parameter No. PB18.

(2) Parameter

Set the operation of the low-pass filter selection (parameter No. PB23.)



7.6 Gain changing function

This function can change the gains. You can change between gains during rotation and gains during stop or can use an external signal to change gains during operation.

7.6.1 Applications

This function is used when:

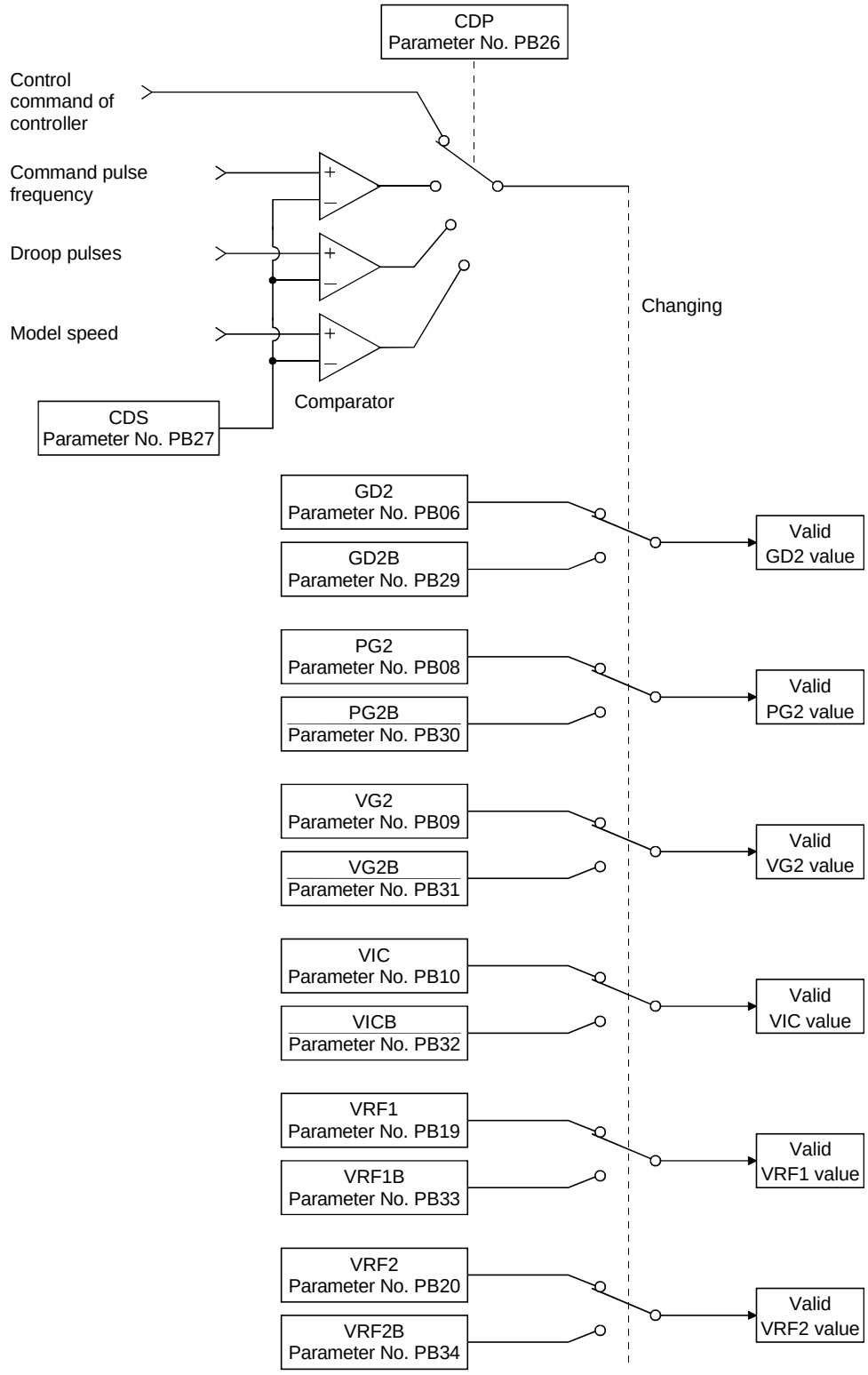
(1) You want to increase the gains during servo lock but decrease the gains to reduce noise during rotation.

(2) You want to increase the gains during settling to shorten the stop settling time.

(3) You want to change the gains using an external signal to ensure stability of the servo system since the load inertia moment ratio varies greatly during a stop (e.g. a large load is mounted on a carrier).

7.6.2 Function block diagram

The valid loop gains PG2, VG2, VIC and GD2 of the actual loop are changed according to the conditions selected by gain changing selection CDP (parameter No. PB26) and gain changing condition CDS (parameter No. PB27).



7.6.3 Parameters

When using the gain changing function, always set "□□□3" in parameter No. PA08 (auto tuning) to choose the manual mode of the gain adjustment modes. The gain changing function cannot be used in the auto tuning mode.

Parameter No.	Abbreviation	Name	Unit	Description
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	times	Control parameters before changing
PB07	PG1	Model loop gain	rad/s	Position and speed gains of a model used to set the response level to a command. Always valid.
PB08	PG2	Position loop gain	rad/s	
PB09	VG2	Speed loop gain	rad/s	
PB10	VIC	Speed integral compensation	ms	
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	times	Used to set the ratio of load inertia moment to servo motor inertia moment after changing.
PB30	PG2B	Gain changing position loop gain 2	rad/s	Used to set the value of the after-changing position loop gain 2.
PB31	VG2B	Gain changing speed loop gain 2	rad/s	Used to set the value of the after-changing speed loop gain.
PB32	VICB	Gain changing speed integral compensation	ms	Used to set the value of the after-changing speed integral compensation.
PB26	CDP	Gain changing selection		Used to select the changing condition.
PB27	CDS	Gain changing condition	kpps pulser/min	Used to set the changing condition values.
PB28	CDT	Gain changing time constant	ms	You can set the filter time constant for a gain change at changing.
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	Hz	Used to set the value of the after-changing vibration suppression control vibration frequency setting.
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	Hz	Used to set the value of the after-changing vibration suppression control resonance frequency setting.

(1) Parameters No. PB06 to PB10

These parameters are the same as in ordinary manual adjustment. Gain changing allows the values of ratio of load inertia moment to servo motor inertia moment, position loop gain, speed loop gain and speed integral compensation to be changed.

(2) Gain changing ratio of load inertia moment to servo motor inertia moment (GD2B: parameter No. PB29)

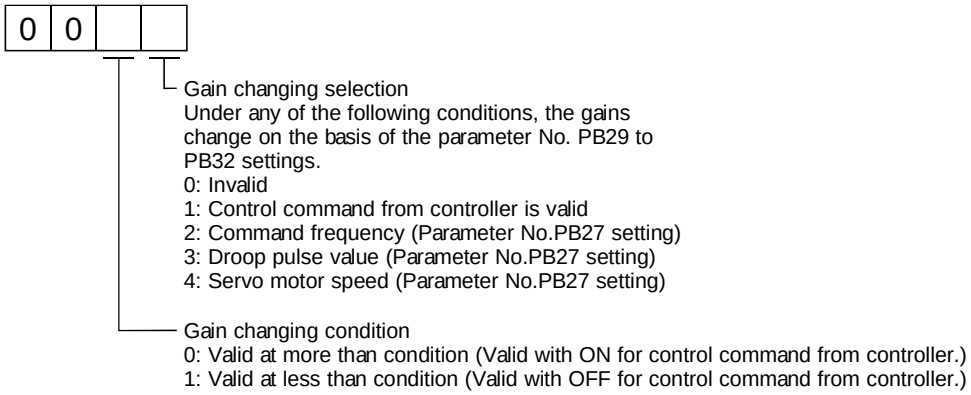
Set the ratio of load inertia moment to servo motor inertia moment after changing. If the load inertia moment ratio does not change, set it to the same value as ratio of load inertia moment to servo motor inertia moment (parameter No. PB06).

(3) Gain changing position loop gain (parameter No. PB30), Gain changing speed loop gain (parameter No. PB31), Gain changing speed integral compensation (parameter No. PB32)

Set the values of after-changing position loop gain, speed loop gain and speed integral compensation.

(4) Gain changing selection (parameter No. PB26)

Used to set the gain changing condition. Choose the changing condition in the first digit and second digit. If you set "1" in the first digit here, you can use the control command from controller is valid for gain changing.



(5) Gain changing condition (parameter No. PB27)

When you selected "command frequency", "droop pulses" or "servo motor speed" in gain changing selection (parameter No. PB26), set the gain changing level.

The setting unit is as follows:

Gain changing condition	Unit
Command frequency	kpps
Droop pulses	pulse
Servo motor speed	r/min

(6) Gain changing time constant (parameter No. PB28)

You can set the primary delay filter to each gain at gain changing. This parameter is used to suppress shock given to the machine if the gain difference is large at gain changing, for example.

7.6.4 Gain changing operation

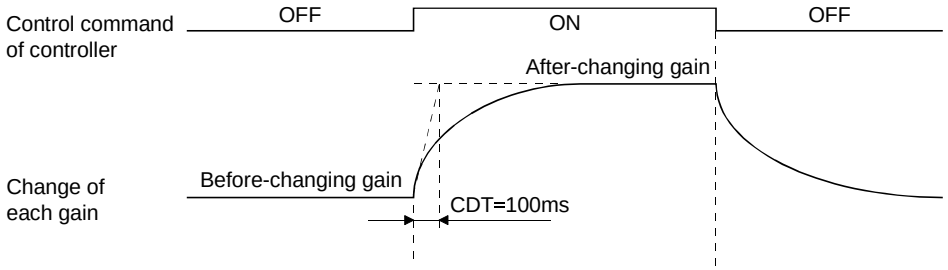
This operation will be described by way of setting examples.

(1) When you choose changing by external input

(a) Setting

Parameter No.	Abbreviation	Name	Setting	Unit
PB07	PG1	Model loop gain	100	rad/s
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	4.0	times
PB08	PG2	Position loop gain	120	rad/s
PB09	VG2	Speed loop gain	3000	rad/s
PB10	VIC	Speed integral compensation	20	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	10.0	times
PB30	PG2B	Gain changing position loop gain	84	rad/s
PB31	VG2B	Gain changing speed loop gain	4000	rad/s
PB32	VICB	Gain changing speed integral compensation	50	ms
PB26	CDP	Gain changing selection	0001 (Changed by ON/OFF of Input signal)	
PB28	CDT	Gain changing time constant	100	ms
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting	Used to set the value of the after-changing vibration suppression control vibration frequency setting.	Hz
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting	Used to set the value of the after-changing vibration suppression control resonance frequency setting.	Hz

(b) Changing operation



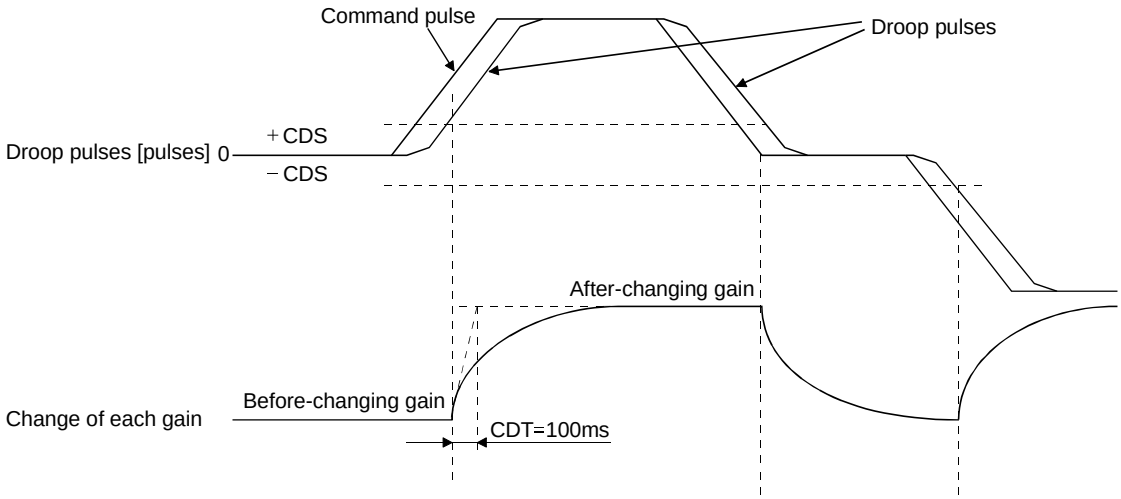
Model loop gain 1	100				
Ratio of load inertia moment to servo motor inertia moment	4.0	→	10.0	→	4.0
Position loop gain	120	→	84	→	120
Speed loop gain	3000	→	4000	→	3000
Speed integral compensation	20	→	50	→	20

(2) When you choose changing by droop pulses

(a) Setting

Parameter No.	Abbreviation	Name	Setting	Unit
PB07	PG1	Model loop gain	100	rad/s
PB06	GD2	Ratio of load inertia moment to servo motor inertia moment	4.0	times
PB08	PG2	Position loop gain	120	rad/s
PB09	VG2	Speed loop gain 2	3000	rad/s
PB10	VIC	Speed integral compensation	20	ms
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment	10.0	times
PB30	PG2B	Gain changing position loop gain	84	rad/s
PB31	VG2B	Gain changing speed loop gain	4000	rad/s
PB32	VICB	Gain changing speed integral compensation	50	ms
PB26	CDP	Gain changing selection	0003 (Changed by droop pulses)	
PB27	CDS	Gain changing condition	50	pulse
PB28	CDT	Gain changing time constant	100	ms

(b) Changing operation



Model loop gain	100						
Ratio of load inertia moment to servo motor inertia moment	4.0	→	10.0	→	4.0	→	10.0
Position loop gain	120	→	84	→	120	→	84
Speed loop gain	3000	→	4000	→	3000	→	4000
Speed integral compensation	20	→	50	→	20	→	50

MEMO

8. TROUBLESHOOTING

POINT
▪ As soon as an alarm occurs, make the Servo off status and interrupt the main circuit power.

If an alarm/warning has occurred, refer to this chapter and remove its cause.

8.1 Alarms and warning list

When a fault occurs during operation, the corresponding alarm or warning is displayed. If any alarm or warning has occurred, refer to Section 8.2 or 8.3 and take the appropriate action
After its cause has been removed, the alarm can be deactivated in any of the methods marked ○ in the alarm deactivation column.

	Display	Name	Alarm deactivation		
			Power OFF→ON	Error reset	CPU reset
Alarms	10	Undervoltage	○	○	○
	12	Memory error1 (RAM)	○		
	13	Clock error	○		
	15	Memory error2 (EEP-ROM)	○		
	16	Encoder error1 (At power on)	○		
	17	Board error	○		
	19	Memory error3 (Flash-ROM)	○		
	1A	Motor combination error	○		
	20	Encoder error2	○		
	24	Main circuit error	○	○	○
	25	Absolute position erase	○		
	30	Regenerative error	(Note1) ○	(Note1) ○	(Note1) ○
	31	Overspeed	○	○	○
	32	Overcurrent	○		
	33	Overvoltage	○	○	○
	34	Receive error1	○	(Note2) ○	○
	35	Command frequency alarm	○	○	○
	36	Receive error2	○	○	○
	37	Parameter error	○		
	45	Main circuit device overheat	(Note1) ○	(Note1) ○	(Note1) ○
	46	Servo motor overheat	(Note1) ○	(Note1) ○	(Note1) ○
	47	Cooling fan alarm	○		
	50	Overload1	(Note1) ○	(Note1) ○	(Note1) ○
	51	Overload2	(Note1) ○	(Note1) ○	(Note1) ○
	52	Error excessive	○	○	○
	8A	USB communication time-out	○	○	○
	8E	USB communication error	○	○	○
	888	Watchdog	○		

	Display	Name
Warnings	92	Open battry cable warning
	96	Home position setting error
	9F	Battery warning
	E0	Excessive regeneration warning
	E1	Overload warning 1
	E3	Absolute position counter warning
	E4	Parameter warning
	E6	Servo forced stop warning
	E8	Cooling fan speed reduction warning
	E9	Main circuit off warning
	E7	Controller forced stop warning
	EC	Overload warning 2
	ED	Output watt excess warning

Note1. Deactivate the alarm about 30 minutes of cooling time after removing the cause of occurrence.
2. In some controller communication status, the alarm factor may not be removed.

8.2 Remedies for alarms

⚠ CAUTION	・When any alarm has occurred, eliminate its cause, ensure safety, then reset the alarm, and restart operation. Otherwise, injury may occur. ・If an absolute position erase (25) occurred, always make home position setting again. Otherwise, misoperation may occur. ・As soon as an alarm occurs, mark Servo-off and power off the main circuit and control circuit.

POINT

・When any of the following alarms has occurred, do not deactivate the alarm and resume operation repeatedly. To do so will cause the servo amplifier/servo motor to fail. Remove the cause of occurrence, and leave a cooling time of more than 30 minutes before resuming operation. To protect the main circuit elements, any of these servo alarms cannot be deactivated from the servo system controller until the specified time elapses after its occurrence. Judging the load changing condition until the alarm occurs, the servo amplifier calculates this specified time automatically.
・Regenerative error (30)
・Overload 1 (50)
・Overload 2 (51)
・The alarm can be deactivated by switching power off, then on or by the error reset command・CPU reset from the servo system controller. For details, refer to Section 8.1.

When an alarm occurs, the trouble (ALM) switches off and the dynamic brake is operated to stop the servomotor. At this time, the display indicates the alarm No.
The servo motor comes to a stop. Remove the cause of the alarm in accordance with this section. MR Configulator (servo configuration software) may be used to refer to the cause.

Display	Name	Definition	Cause	Action
10	Undervoltage	Power supply voltage dropped. MR-J3-□B: 160VAC or less MR-J3-□B1: 83VAC or less	1. Power supply voltage is low.	Review the power supply.
			2. There was an instantaneous control power failure of 60ms or longer.	
			3. Shortage of power supply capacity caused the power supply voltage to drop at start, etc.	
			4. The bus voltage dropped to the following value or less. MR-J3-□B: 200VDC MR-J3-□B1: 158VDC	
			5. Faulty parts in the servo amplifier Checking method Alarm (10) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	Change the servo amplifier.

Display	Name	Definition	Cause	Action
12	Memory error 1 (RAM)	RAM, memory fault	Faulty parts in the servo amplifier Checking method Alarm (any of 12 and 13) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	Change the servo amplifier.
13	Clock error	Printed board fault		
		Clock error transmitted from the controller	Faulty controller Checking method Alarm(13) occurs, if servo controller is used in multiple CPU system.	Change the servo system controller.
15	Memory error 2 (EEP-ROM)	EEP-ROM fault	1. Faulty parts in the servo amplifier Checking method Alarm (15) occurs if power is switched on after disconnection of all cables but the control circuit power supply cables.	Change the servo amplifier.
			2. The number of write times to EEP-ROM exceeded 100,000.	
16	Encoder error 1 (At power on)	Communication error occurred between encoder and servo amplifier.	1. Encoder connector (CN2) disconnected.	Connect correctly.
			2. Encoder fault	Change the servo motor.
			3. Encoder cable faulty (Wire breakage or shorted)	Repair or change cable.
			4. Encoder cable type (2-wire, 4-wire) selection was wrong in parameter setting.	Correct the setting in the fourth digit of parameter No. PC04.
17	Board error 2	CPU/parts fault	Faulty parts in the servo amplifier Checking method Alarm (17 or 19) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable.	Change the servo amplifier.
19	Memory error 3 (Flash ROM)	ROM memory fault		
1A	Motor combination error	Wrong combination of servo anplifier and servo motor.	Wrong combination of servo amplifier and servo motor connected.	Use correct combination.
20	Encoder error 2	Communication error occurred between encoder and servo amplifier.	1. Encoder connector (CN2) disconnected.	Connect correctly.
			2. Encoder cable faulty (Wire breakage or shorted)	Repair or change the cable.
			3. Encoder fault	Change the servo motor.
24	Main circuit error	Ground fault occurred at the servo motor power (U,V and W phases) of the servo amplififer.	1. Power input wires and servo motor power wires are in contact.	Connect correctly.
			2. Sheathes of servo motor power cables deteriorated, resulting in ground fault.	Change the cable.
			3. Main circuit of servo amplifier failed. Checking method (24) occurs if the servo is switched on after disconnecting the U, V, W power cables from the servo amplifier.	Change the servo amplifier.
25	Absolute position erase	Absolute position data in error	1. Voltage drop in encoder (Battery disconnected.)	After leaving the alarm occurring for a few minutes, switch power off, then on again. Always make home position setting again.
			2. Battery voltage low	Change battery. Always make home position setting again.
			3. Battery cable or battery is faulty.	
		Power was switched on for the first time in the absolute position detection system.	4. Home position not set.	After leaving the alarm occurring for a few minutes, switch power off, then on again. Always make home position setting again.

Display	Name	Definition	Cause	Action
30	Regenerative alarm	Permissible regenerative power of the built-in regenerative brake resistor or regenerative brake option is exceeded.	1. Wrong setting of parameter No. PA02	Set correctly.
			2. Built-in regenerative brake resistor or regenerative brake option is not connected.	Connect correctly
			3. High-duty operation or continuous regenerative operation caused the permissible regenerative power of the regenerative brake option to be exceeded. Checking method Call the status display and check the regenerative load ratio.	1. Reduce the frequency of positioning. 2. Use the regenerative brake option of larger capacity. 3. Reduce the load.
			4. Power supply voltage is abnormal. MR-J3-□B:260VAC or more MR-J3-□B1:More than 135VAC	Review power supply
			5. Built-in regenerative brake resistor or regenerative brake option faulty.	Change servo amplifier or regenerative brake option.
		Regenerative transistor fault	6. Regenerative transistor faulty. Checking method 1) The regenerative brake option has overheated abnormally. 2) The alarm occurs even after removal of the built-in regenerative brake resistor or regenerative brake option.	Change the servo amplifier.
31	Overspeed	Speed has exceeded the instantaneous permissible speed.	1. Small acceleration/deceleration time constant caused overshoot to be large.	Increase acceleration/deceleration time constant.
			2. Servo system is instable to cause overshoot.	1. Re-set servo gain to proper value. 2. If servo gain cannot be set to proper value: 1) Reduce load inertia moment ratio; or 2) Reexamine acceleration/ deceleration time constant.
			3. Encoder faulty.	Change the servo motor.
32	Overcurrent	Current that flew is higher than the permissible current of the servo amplifier.	1. Short occurred in servo motor power (U, V, W).	Correct the wiring.
			2. Transistor (IPM) of the servo amplifier faulty. Checking method Alarm (32) occurs if power is switched on after U,V and W are disconnected.	Change the servo amplifier.
			3. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.
			4. External noise caused the overcurrent detection circuit to misoperate.	Take noise suppression measures.

Display	Name	Definition	Cause	Action
33	Overvoltage	Converter bus voltage exceeded 400VDC.	1. Regenerative brake option is not used.	Use the regenerative brake option.
			2. Though the regenerative brake option is used, the parameter No.PA02 setting is "□□00 (not used)".	Setcorrectly.
			3. Lead of built-in regenerative brake resistor or regenerative brake option is open or disconnected.	1. Change lead. 2. Connect correctly.
			4. Regenerative transistor faulty.	Change servo amplifier
			5. Wire breakage of built-in regenerative brake resistor or regenerative brake option	1. For wire breakage of built-in regenerative brake resistor, change servo amplifier. 2. For wire breakage of regenerative brake option, change regenerative brake option.
			6. Capacity of built-in regenerative brake resistor or regenerative brake option is insufficient.	Add regenerative brake option or increase capacity.
			7. Power supply voltage high.	Review the power supply.
			8. Ground fault occurred in servo motor power (U, V, W).	Correct the wiring.
34	Receive error 1	SSCNETⅢ communication error (Continuously communication error with about 3.5ms interval.)	1. The SSCNETⅢ cable is disconnected.	Connect it after turning off the control circuit power supply for servo amplifier.
			2. The surface at the end of SSCNETⅢ cable got dirty.	Wipe dirt at the surface away. (Refer to section 3.9)
			3. The SSCNETⅢ cable is broken or severed.	Change the cable.
			4. Noise entered the servo amplifier.	Take noise suppression measures.
35	Command frequency error	Input pulse frequency of command pulse is too high.	1. Command given is greater than the maximum speed of the servo motor.	Review opration program
			2. Servo system controller failure.	Change the servo system controller.
			3. Noise entered the servo amplifier.	Take noise of I/O signal suppression measures.
			4. Noise entered the controller.	Take noise from the controller suppression measures.
36	Receive error2	SSCNETⅢ communication error (Intermittently communication error with about 70ms interval.)	1. The SSCNETⅢ cable is disconnected.	Connect it after turning off the control circuit power supply for servo amplifier.
			2. The surface at the end of SSCNETⅢ cable got dirty.	Wipe dirt away from the surface. (Refer to section 3.9)
			3. The SSCNETⅢ cable is broken or severed.	Change the cable.
			4. Noise entered the servo amplifier.	Take noise suppression measures
37	Parameter error	Parameter setting is wrong.	1. Servo amplifier fault caused the parameter setting to be rewritten.	Change the servo amplifier.
			2. There is a parameter whose value was set to outside the setting range by the controller.	Change the parameter value to within the setting range.
			3. The number of write times to EEP-ROM exceeded 100,000 due to parameter write, etc.	Change the servo amplifier.

Display	Name	Definition	Cause	Action
45	Main circuit device overheat	Main circuit device overheat	1. Servo amplifier faulty.	Change the servo amplifier.
			2. The power supply was turned on and off continuously by overloaded status.	The drive method is reviewed.
			3. Air cooling fan of servo amplifier stops.	1. Exchange the cooling fan or the servo amplifier. 2. Reduce ambient temperature.
			4. Used beyond the specifications of close mounting.	Use within the range of specifications.
46	Servo motor overheat	Servo motor temperature rise actuated the thermal sensor.	1. Ambient temperature of servo motor is over 40°C.	Review environment so that ambient temperature is 0 to 40°C.
			2. Servo motor is overloaded.	1. Reduce load. 2. Review operation pattern. 3. Use servo motor that provides larger output.
			3. Thermal sensor in encoder is faulty.	Change servo motor.
47	Cooling fan alarm	The cooling fan of the servo amplifier stopped, or its speed decreased to or below the alarm level.	Cooling fan life expiration (Refer to Section 2.5.)	Change the cooling fan of the servo amplifier.
			Foreign matter caught in the fan stopped rotation.	Remove the foreign matter.
			The power supply of the cooling fan failed.	Change servo amplifier.
50	Overload 1	Load exceeded overload protection characteristic of servo amplifier.	1. Servo amplifier is used in excess of its continuous output current.	1. Reduce load. 2. Review operation pattern. 3. Use servo motor that provides larger output.
			2. Servo system is instable and hunting.	1. Repeat acceleration/ deceleration to execute auto tuning. 2. Change auto tuning response setting. 3. Set auto tuning to OFF and make gain adjustment manually.
			3. Machine struck something.	1. Review operation pattern. 2. Install limit switches.
			4. Wrong connection of servo motor. Servo amplifier's output terminals U, V, W do not match servo motor's input terminals U, V, W.	Connect correctly.
			5. Encoder faulty. Checking method When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.	Change the servo motor.
51	Overload 2	Machine collision or the like caused max. output current to flow successively for several seconds. Servo motor locked: 1s or more During rotation: 2.5s or more	1. Machine struck something.	1. Review operation pattern. 2. Install limit switches.
			2. Wrong connection of servo motor. Servo amplifier's output terminals U, V, W do not match servo motor's input terminals U, V, W.	Connect correctly.
			3. Servo system is instable and hunting.	1. Repeat acceleration/deceleration to execute auto tuning. 2. Change auto tuning response setting. 3. Set auto tuning to OFF and make gain adjustment manually.
			4. Encoder faulty. Checking method When the servo motor shaft is rotated with the servo off, the cumulative feedback pulses do not vary in proportion to the rotary angle of the shaft but the indication skips or returns midway.	Change the servo motor.

Display	Name	Definition	Cause	Action
52	Error excessive	The deviation between the model position and the actual servo motor position exceeds the parameter No.PC01 setting value (initial value: 3 revolutions).	1. Acceleration/deceleration time constant is too small.	Increase the acceleration/deceleration time constant.
			2. Torque limit value set with controller is too small.	Increase the torque limit value.
			3. Motor cannot be started due to torque shortage caused by power supply voltage drop.	1. Review the power supply capacity. 2. Use servo motor which provides larger output.
			4. Model loop gain 1 (parameter No.PB07) value is small.	Increase set value and adjust to ensure proper operation.
			5. Servo motor shaft was rotated by external force.	1. When torque is limited, increase the limit value. 2. Reduce load. 3. Use servo motor that provides larger output.
			6. Machine struck something.	1. Review operation pattern. 2. Install limit switches.
			7. Encoder faulty	Change the servo motor.
			8. Wrong connection of servo motor. Servo amplifier's output terminals U, V, W do not match servo motor's input terminals U, V, W.	Connect correctly.
			9. SSCNETⅢ cable fault	Change the SSCNETⅢ cable.
8A	USB communication time-out error	Communication with MR Configurator in test operation mode stopped for longer than the specified time.	1. USB cable breakage.	Change the USB cable.
8E	USB communication error	Serial communication error occurred between servo amplifier and communication device (e.g. personal computer).	1. USB cable fault (Open cable or short circuit)	Change the USB cable.
			2. Communication device (e.g. personal computer) faulty	Change the communication device (e.g. personal computer).
(Note) 888	Watchdog	CPU, parts faulty	Fault of parts in servo amplifier Checking method Alarm (888) occurs if power is switched on after disconnection of all cables but the control circuit power supply cable.	Change servo amplifier.

Note. At power-on, "888" appears instantaneously, but it is not an error.

8.3 Remedies for warnings

> ⚠ CAUTION
> - If an absolute position counter warning (E3) occurred, always make home position setting again. Otherwise, misoperation may occur.

If E6, E7 or E9 occurs, the servo off status is established. If any other warning occurs, operation can be continued but an alarm may take place or proper operation may not be performed. Use the optional servo configuration software to refer to the cause of warning.

Remove the cause of warning according to this section. Use the optional MR Configulator (servo configuration software) to refer to a factor of warning occurrence.

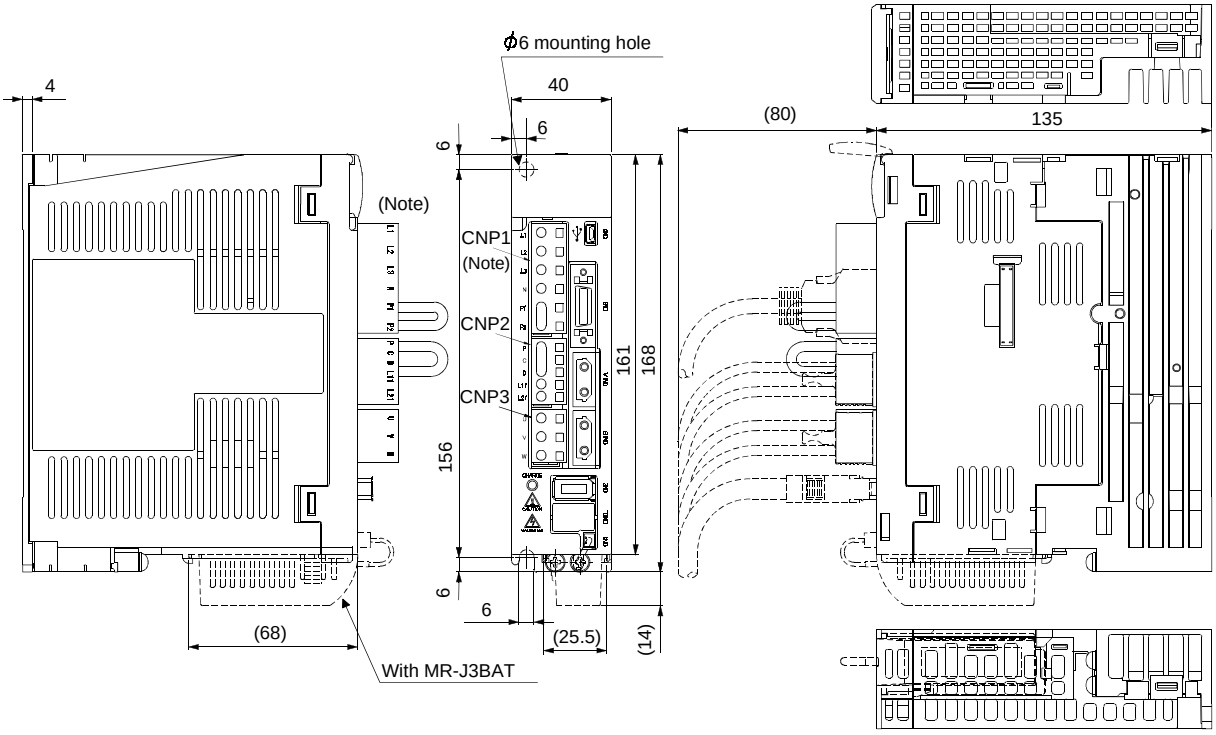
Display	Name	Definition	Cause	Action
92	Open battery cable warning	Absolute position detection system battery voltage is low.	1. Battery cable is open.	Repair cable or changed.
			2. Battery voltage supplied from the servo amplifier to the encoder fell to about 3V or less. (Detected with the encoder)	Change battery.
96	Home position setting warning	Home position setting could not be made.	1. Droop pulses remaining are greater than the in-position range setting.	Remove the cause of droop pulse occurrence
			2. Command pulse entered after clearing of droop pulses.	Do not enter command pulse after clearing of droop pulses.
			3. Creep speed high.	Reduce creep speed.
9F	Battery warning	Voltage of battery for absolute position detection system reduced.	Battery voltage fell to 3.2V or less. (Detected with the servo amplifier)	Change the battery.
E0	Excessive regenerative warning	There is a possibility that regenerative power may exceed permissible regenerative power of built-in regenerative brake resistor or regenerative brake option.	Regenerative power increased to 85% or more of permissible regenerative power of built-in regenerative brake resistor or regenerative brake option. Checking method Call the status display and check regenerative load ratio.	1. Reduce frequency of positioning. 2. Change regenerative brake option for the one with larger capacity. 3. Reduce load.
E1	Overload warning 1	There is a possibility that overload alarm 1 or 2 may occur.	Load increased to 85% or more of overload alarm 1 or 2 occurrence level. Cause, checking method Refer to 50,51.	Refer to 50, 51.
E3	Absolute position counter warning	Absolute position encoder pulses faulty.	1. Noise entered the encoder.	Take noise suppression measures.
			2. Encoder faulty.	Change servo motor.
		The multi-revolution counter value of the absolute position encoder exceeded the maximum revolution range.	3. The movement amount from the home position exceeded a 32767 rotation or -37268 rotation in succession.	Make home position setting again.
E4	Parameter warning	Parameter outside setting range	Parameter value set from servo system controller is outside setting range	Set it correctly.
E6	Servo forced stop warning	EM1 is off.	External forced stop was made valid. (EM1 was turned off.)	Ensure safety and deactivate forced stop.
E7	Controller forced stop warning		Forced stop signal was entered into the servo system controller.	Ensure safety and deactivate forced stop.
E8	Cooling fan speed reduction warning	The speed of the servo amplifier decreased to or below the warning level. This warning is not displayed with MR-J3-70B/100B among servo amplifiers equipped with a cooling fan.	Cooling fan life expiration (Refer to Section 2.5.)	Change the cooling fan of the servo amplifier.
			The power supply of the cooling fan is broken.	Change servo amplifier.
E9	Main circuit off warning	Servo-on command was issued with main circuit power off.		Switch on main circuit power.
EC	Overload warning 2	Operation, in which a current exceeding the rating flew intensively in any of the U, V and W phases of the servo motor, was repeated.	During a stop, the status in which a current flew intensively in any of the U, V and W phases of the servo motor occurred repeatedly, exceeding the warning level.	1. Reduce the positioning frequency at the specific positioning address. 2. Reduce the load. 3. Replace the servo amplifier/ servo motor with the one of larger capacity.
ED	Output watt excess warning	The status, in which the output wattage (speed × torque) of the servo motor exceeded the rated output, continued steadily.	Continuous operation was performed with the output wattage (speed × torque) of the servo motor exceeding 150% of the rated output.	1. Reduce the servo motor speed. 2. Reduce the load.

9. OUTLINE DRAWINGS

9.1 Servo Amplifier

(1) MR-J3-10B ▪ MR-J3-20B
MR-J3-10B1 ▪ MR-J3-20B1

[Unit: mm]



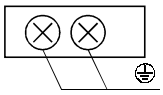
Note. This data applies to the 3-phase 200 to 230VAC and 1-phase 230VAC power supply models.
For a single-phase, 100 to 120VAC power supply, refer to the terminal signal layout.

Mass: 0.8 [kg] (1.76 [lb])

Terminal signal layout

	For 1-phase 100 to 120VAC	For 3-phase 200 to 230VAC and 1-phase 230VAC
CNP1	L_1	L_1
		L_2
	L_2	L_3
	N	N
	P_1	P_1
	P_2	P_2
CNP2	P	P
	C	C
	D	D
	L_{11}	L_{11}
	L_{21}	L_{21}
CNP3	U	U
	V	V
	W	W

PE terminal



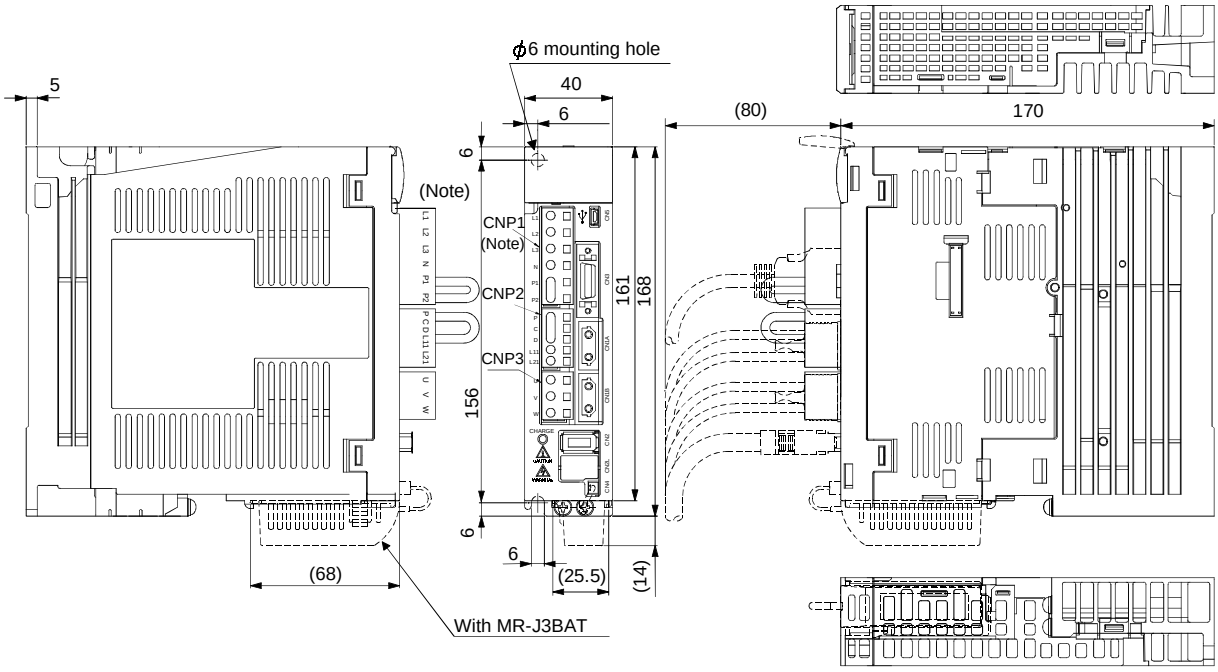
Screw size: M4
Tightening torque: 1.2 [N ▪ m] (10 [lb ▪ in])

Mounting screw
Screw size: M5
Tightening torque: 3.24 [N ▪ m] (28.7 [lb ▪ in])

(2) MR-J3-40B・MR-J3-60B

MR-J3-40B1

[Unit: mm]



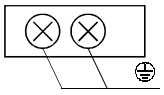
Note. This data applies to the 3-phase 200 to 230VAC and 1-phase 230VAC power supply models.
For a single-phase, 100 to 120VAC power supply, refer to the terminal signal layout.

Mass: 1.0 [kg] (2.21 [lb])

Terminal signal layout

	For 1-phase 100 to 120VAC	For 3-phase 200 to 230VAC and 1-phase 230VAC
CNP1	L_1	L_1
		L_2
	L_2	L_3
	N	N
	P_1	P_1
	P_2	P_2
CNP2	P	P
	C	C
	D	D
	L_{11}	L_{11}
	L_{21}	L_{21}
CNP3	U	U
	V	V
	W	W

PE terminal

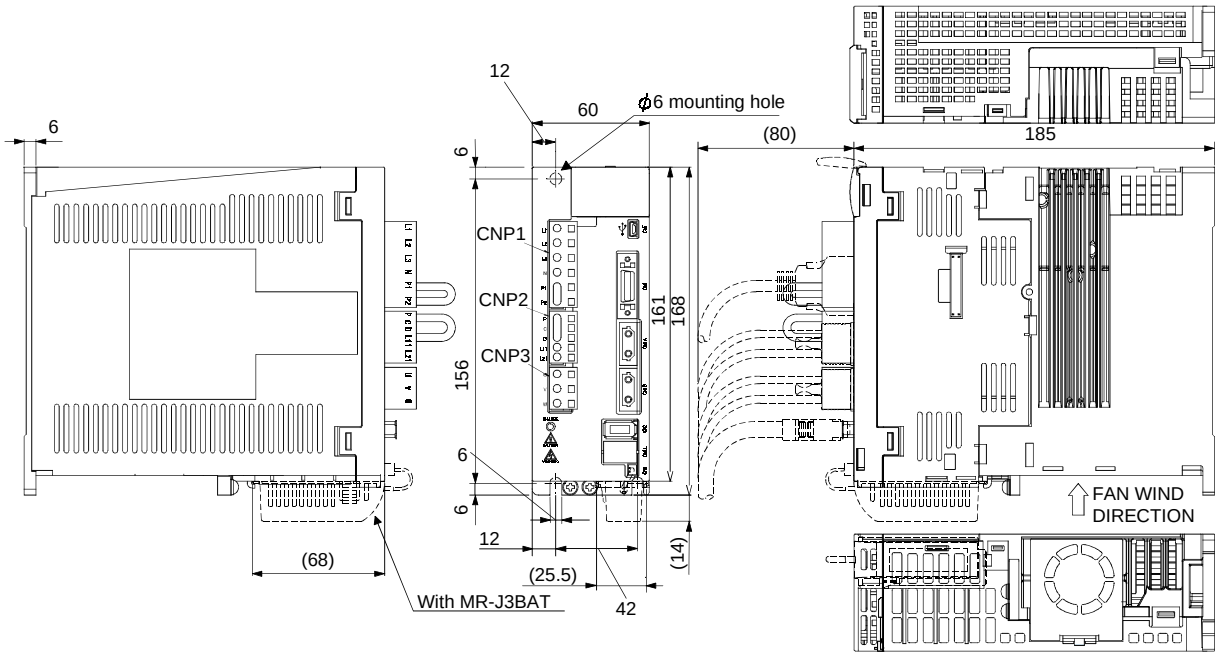


Screw size: M4
Tightening torque: 1.2 [N・m] (10 [lb・in])

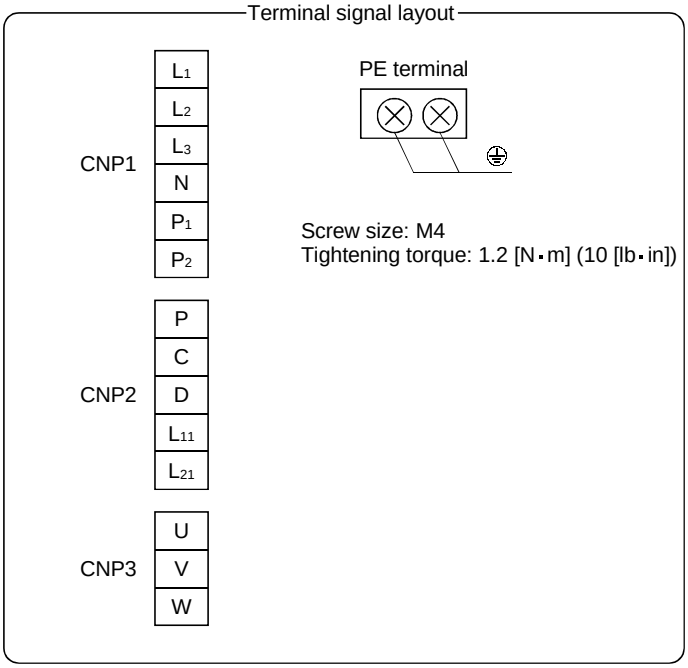
Mounting screw
Screw size: M5
Tightening torque: 3.24 [N・m] (28.7 [in])

(3) MR-J3-70B ▪ MR-J3-100B

[Unit: mm]



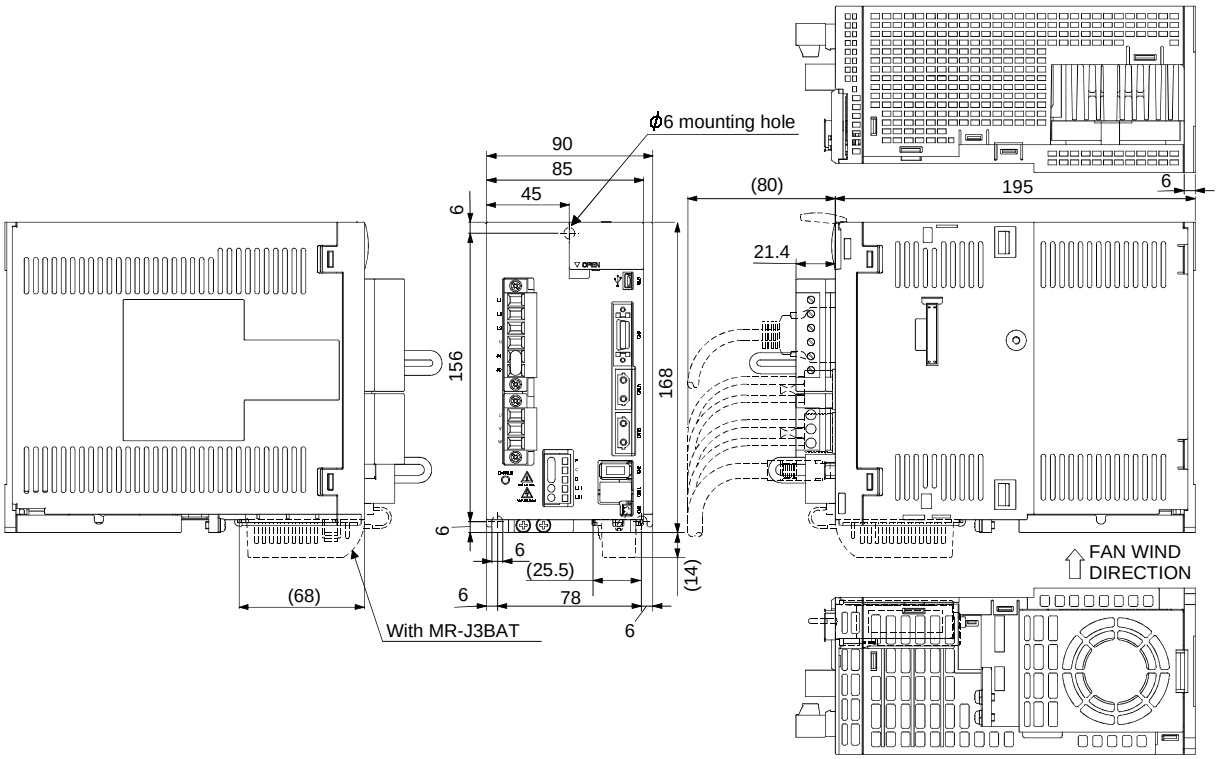
Mass: 1.4 [kg] (3.09 [lb])



Mounting screw
Screw size: M5
Tightening torque: 3.24 [N▪m] (28.7 [lb▪in])

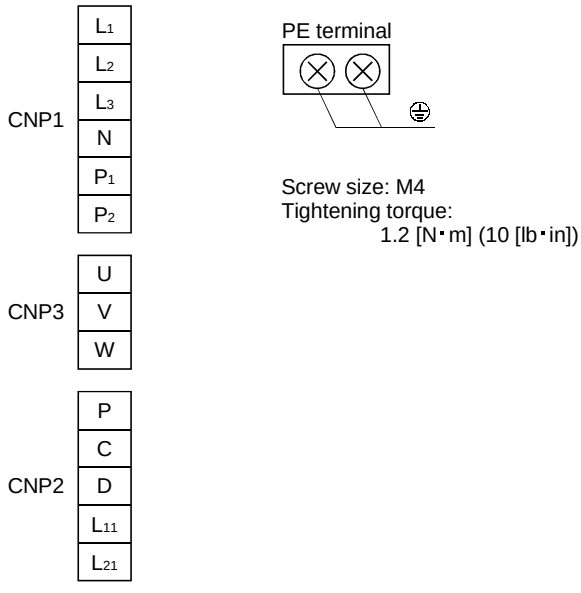
(4) MR-J3-200B ▪ MR-J3-350B

[Unit: mm]



Mass: 1.4 [kg] (3.09 [lb])

Terminal signal layout

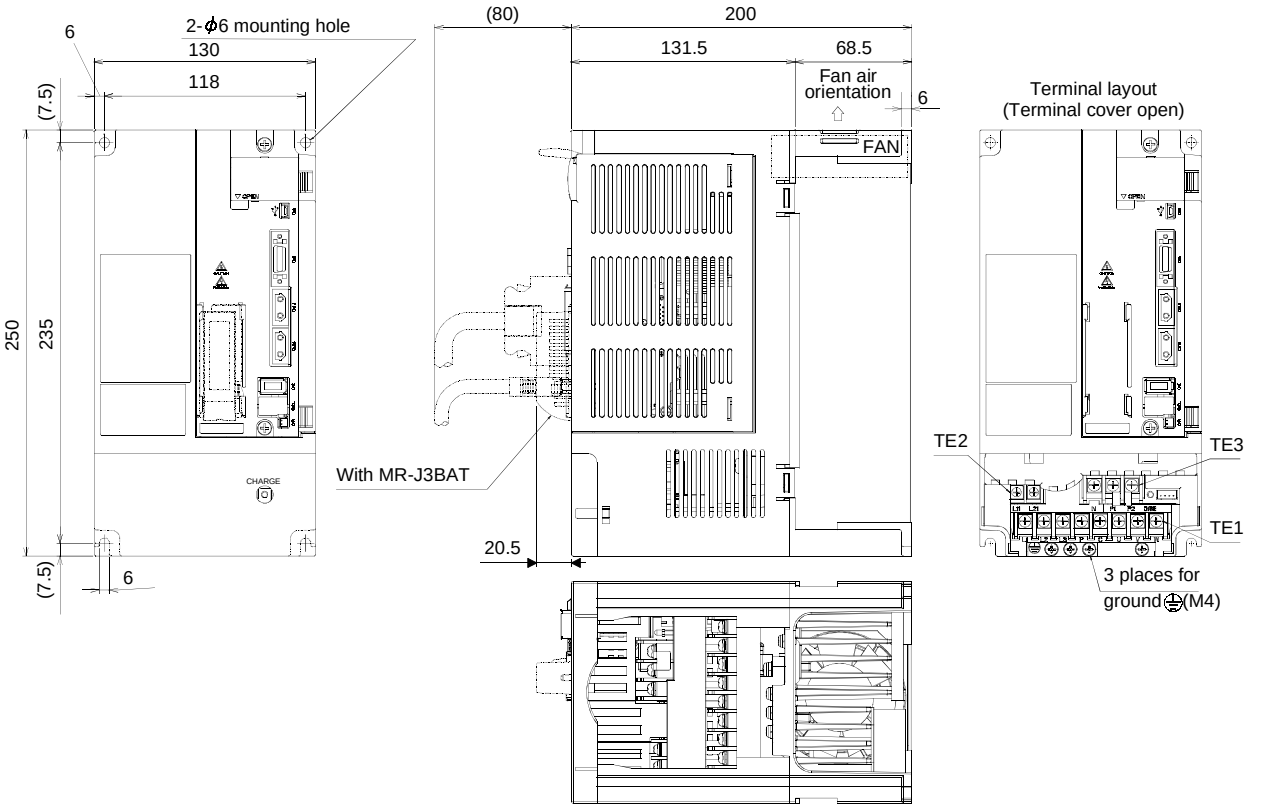


Screw size: M4
Tightening torque:
1.2 [N▪m] (10 [lb▪in])

Mounting screw
Screw size: M5
Tightening torque:
3.24 [N▪m] (28.7 [lb▪in])

(5) MR-J3-500B

[Unit: mm]



Mass: 4.6 [kg] (10.1 [lb])

Terminal signal layout

TE1

L_1	L_2	L_3	P	C	U	V	W

Terminal screw: M4
Tightening torque: 1.2[N・m]

TE2

L_{11}	L_{21}

Terminal screw: M3.5
Tightening torque: 0.8[N・m]

TE3

N	P_1	P_2

Terminal screw: M4
Tightening torque: 1.2[N・m]

PE terminal

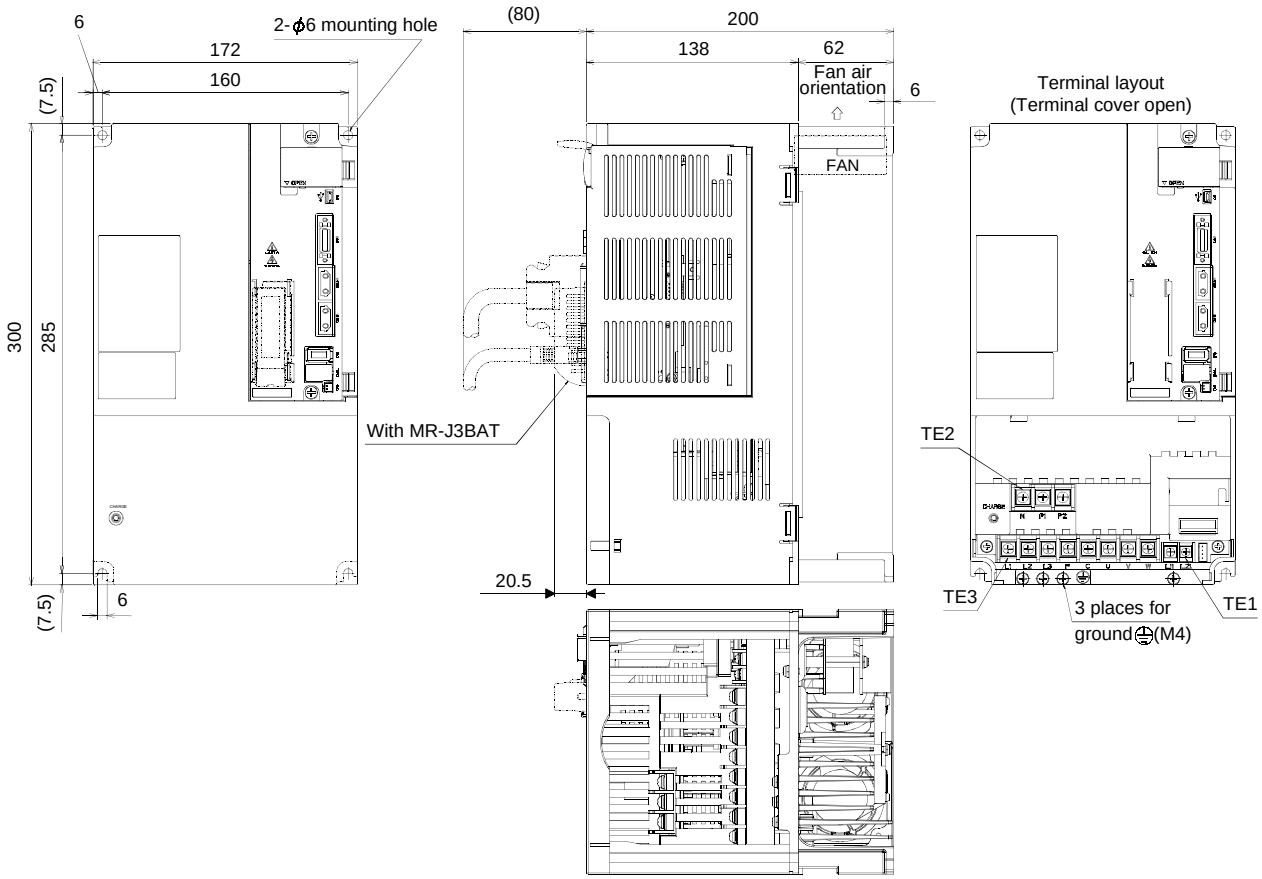
Terminal screw: M4
Tightening torque: 1.2[N・m]

Built-in regenerative brake resistor lead terminal fixing screw

Mounting screw
Screw size: M5
Tightening torque: 3.24[N・m] (28.7[ib・in])

(6) MR-J3-700B

[Unit: mm]



Mass: 6.2 [kg] (13.7[lb])

Terminal signal layout

TE1

L_1	L_2	L_3	P	C	U	V	W

Terminal screw: M4
Tightening torque: 1.2[N·m]

TE2

L_{11}	L_{21}

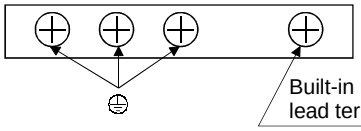
Terminal screw: M3.5
Tightening torque: 0.8[N·m]

TE3

N	P_1	P_2

Terminal screw: M4
Tightening torque: 1.2[N·m]

PE terminal



Terminal screw: M4
Tightening torque: 1.2[N·m]

Built-in regenerative brake resistor lead terminal fixing screw

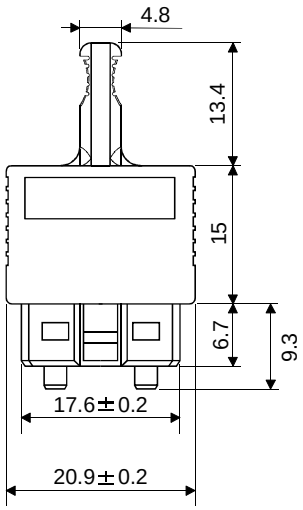
Mounting screw
Screw size: M5
Tightening torque: 3.24[N·m] (28.7[ib·in])

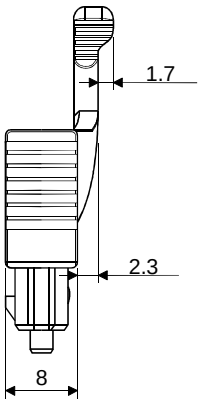
9.2 Connector

(1) For CN1A・CN1B connector

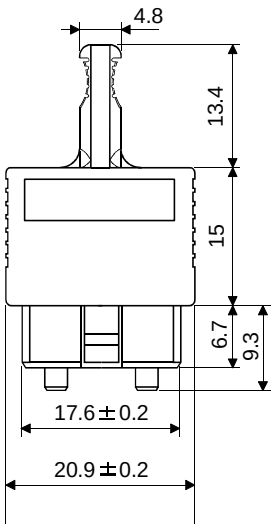
[Unit: mm]

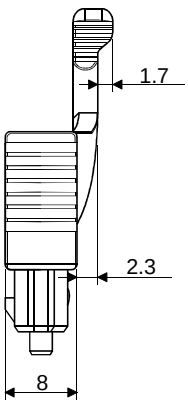
F0-PF2D103





F0-PF2D103-S

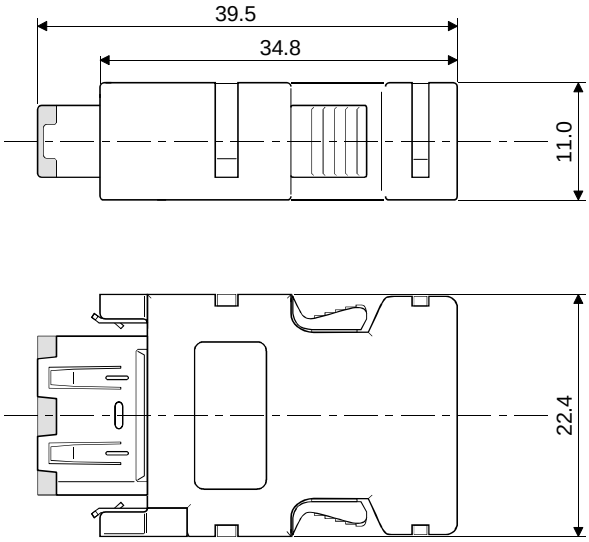




(2) For CN2 connector

Receptacle : 36210-0100JL
Shell kit : 36310-3200-008

[Unit: mm]



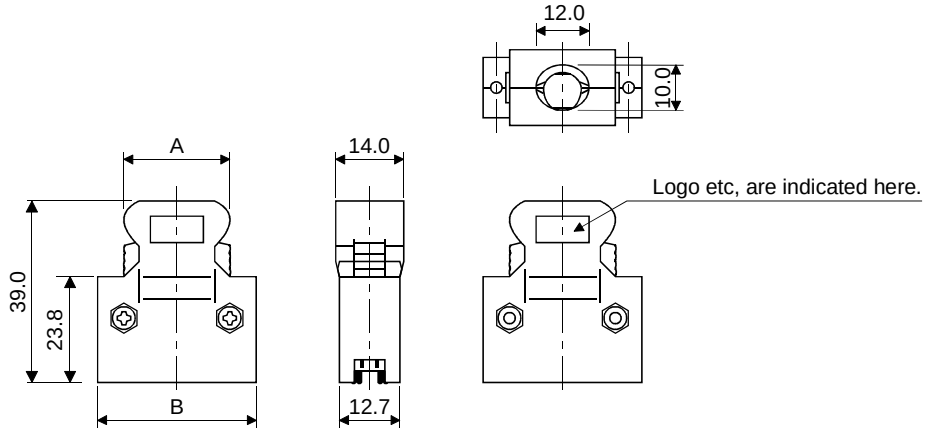
(3) For CN3 connector

(a) Soldered type

Model Connector : 10120-3000VE

Shell kit : 10320-52F0-008

[Unit: mm]



Connector	Shell kit	Each type of dimention	
		A	B
10120-3000VE	10320-52F0-008	22.0	33.3

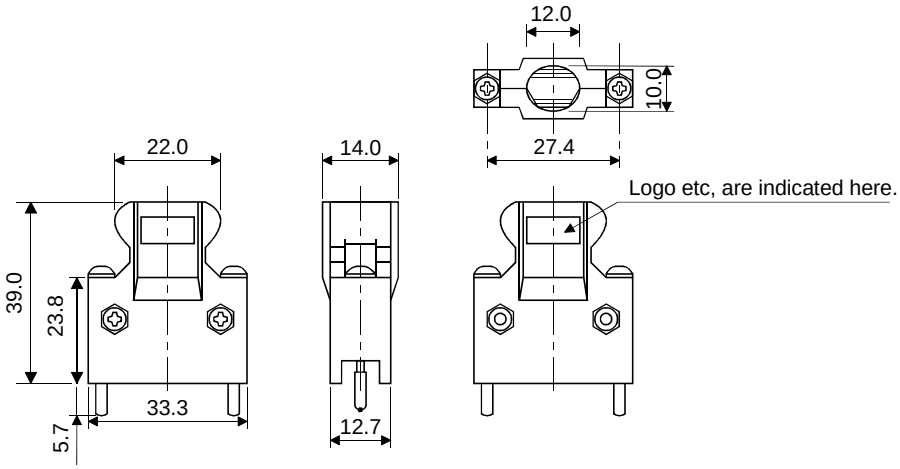
(b) Threaded type

Model Connector : 10120-3000VE

Shell kit : 10320-52A0-008

Note. This is not available as option and should be user prpared (0.472)

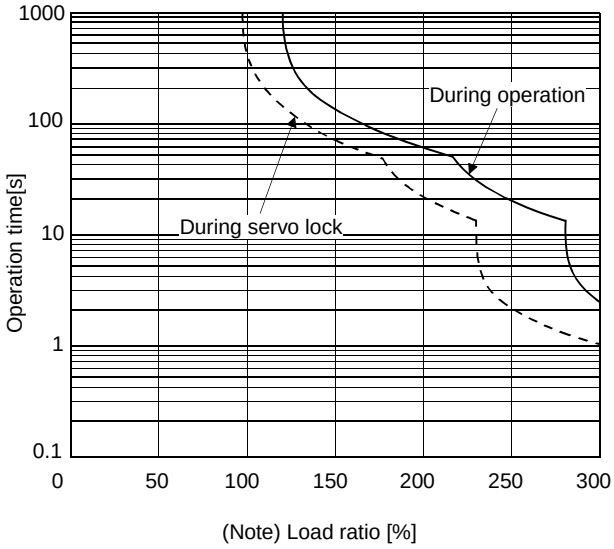
[Unit: mm]



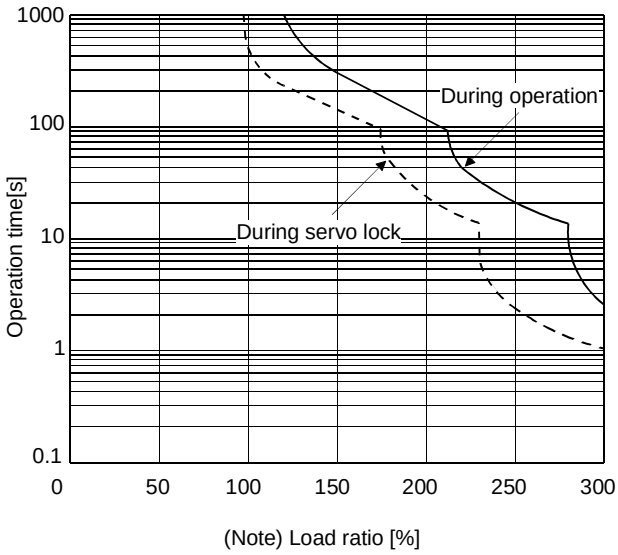
10. CHARACTERISTICS

10.1 Overload protection characteristics

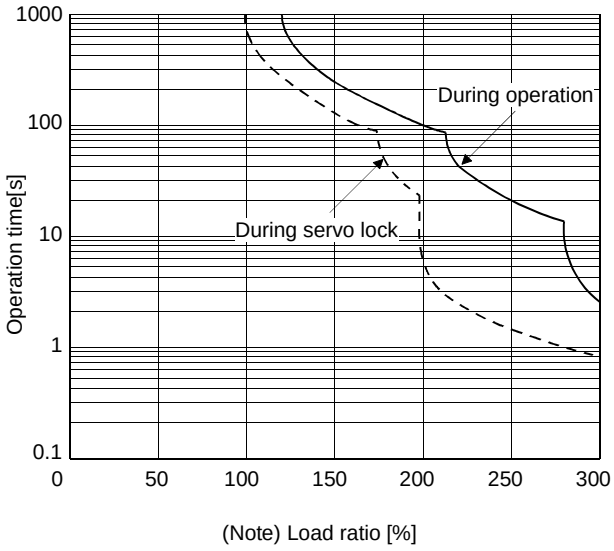
An electronic thermal relay is built in the servo amplifier to protect the servo motor and servo amplifier from overloads. Overload 1 alarm (50) occurs if overload operation performed is above the electronic thermal relay protection curve shown in any of Figs 10.1. Overload 2 alarm (51) occurs if the maximum current flew continuously for several seconds due to machine collision, etc. Use the equipment on the left-hand side area of the continuous or broken line in the graph.
In a machine like the one for vertical lift application where unbalanced torque will be produced, it is recommended to use the machine so that the unbalanced torque is 70% or less of the rated torque.
When you carry out adhesion mounting of the servo amplifier, make circumference temperature into 0 to 45℃, or use it at 75% or a smaller effective load ratio.



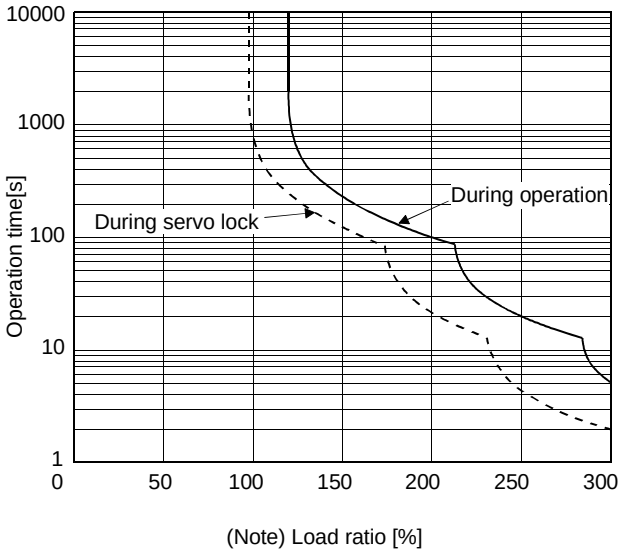
a. HF-MP053・13
HF-KP053・13



b. HF-MP23 to 73
HF-KP23 to 73
HF-SP51・52・81・102



c. HF-SP121・201・152 to 352



d. HF-SP502・702

Note. If operation that generates torque more than 100% of the rating is performed with an abnormally high frequency in a servo motor stop status (servo lock status) or in a 30r/min or less low-speed operation status, the servo amplifier may fail even when the electronic thermal relay protection is not activated.

Fig 10.1 Electronic thermal relay protection characteristics

10.2 Power supply equipment capacity and generated loss

(1) Amount of heat generated by the servo amplifier

Table 10.1 indicates servo amplifiers' power supply capacities and losses generated under rated load. For thermal design of an enclosure, use the values in Table 10.1 in consideration for the worst operating conditions. The actual amount of generated heat will be intermediate between values at rated torque and servo off according to the duty used during operation. When the servo motor is run at less than the maximum speed, the power supply capacity will be smaller than the value in the table, but the servo amplifier's generated heat will not change.

Table 10.1 Power supply capacity and generated heat per servo amplifier at rated output

Servo amplifier	Servo motor	(Note 1) Power supply capacity[kVA]	(Note 2) Servo amplifier-generated heat[W]		Area required for heat dissipation	
			At rated torque	With servo off	[m²]	[ft²]
MR-J3-10B (1)	HF-MP053	0.3	25	15	0.5	5.4
	HF-MP13	0.3	25	15	0.5	5.4
	HF-KP053・13	0.3	25	15	0.5	5.4
MR-J3-20B (1)	HF-MP23	0.5	25	15	0.5	5.4
	HF-KP23	0.5	25	15	0.5	5.4
MR-J3-40B (1)	HF-MP43	0.9	35	15	0.7	7.5
	HF-KP43	0.9	35	15	0.7	7.5
MR-J3-60B	HF-SP52	1.0	40	15	0.8	8.5
	HF-SP51	1.0	40	15	0.8	8.5
MR-J3-70B	HF-MP73	1.3	50	15	1.0	10.8
	HF-KP73	1.3	50	15	1.0	10.8
MR-J3-100B	HF-SP102	1.7	50	15	1.0	10.8
	HF-SP81	1.5	50	15	1.0	10.8
MR-J3-200B	HF-SP152	2.5	90	20	1.8	19.8
	HF-SP202	3.5	90	20	1.8	19.8
	HF-SP121	2.1	90	20	1.8	19.8
	HF-SP201	3.5	90	20	1.8	19.8
MR-J3-350B	HF-SP352	5.5	130	20	2.7	29.1
MR-J3-500B	HF-SP502	7.5	195	25	3.9	42
MR-J3-700B	HF-SP702	10.0	300	25	6.0	64.6

Note 1. Note that the power supply capacity will vary according to the power supply impedance. This value assumes that the power factor improving reactor is not used.

2. Heat generated during regeneration is not included in the servo amplifier-generated heat. To calculate heat generated by the regenerative brake option, in Section 11.2.

(2) Heat dissipation area for enclosed servo amplifier

The enclosed control box (hereafter called the control box) which will contain the servo amplifier should be designed to ensure that its temperature rise is within +10℃ at the ambient temperature of 40℃. (With a 5℃ (41°F) safety margin, the system should operate within a maximum 55℃ (131°F) limit.) The necessary enclosure heat dissipation area can be calculated by Equation 10.1:

$$A = \frac{P}{K \cdot \Delta T} \quad \text{..... (10.1)}$$

where, A : Heat dissipation area [m^2]
P : Loss generated in the control box [W]
ΔT : Difference between internal and ambient temperatures [℃]
K : Heat dissipation coefficient [5 to 6]

When calculating the heat dissipation area with Equation 10.1, assume that P is the sum of all losses generated in the enclosure. Refer to Table 10.1 for heat generated by the servo amplifier. "A" indicates the effective area for heat dissipation, but if the enclosure is directly installed on an insulated wall, that extra amount must be added to the enclosure's surface area.

The required heat dissipation area will vary wit the conditions in the enclosure. If convection in the enclosure is poor and heat builds up, effective heat dissipation will not be possible. Therefore, arrangement of the equipment in the enclosure and the use of a fan should be considered.

Table 10.1 lists the enclosure dissipation area for each servo amplifier when the servo amplifier is operated at the ambient temperature of 40℃ (104°F) under rated load.

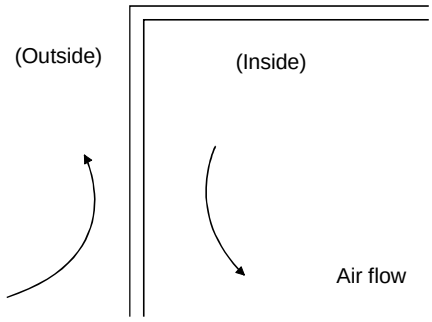


Fig. 10.2 Temperature distribution in enclosure

When air flows along the outer wall of the enclosure, effective heat exchange will be possible, because the temperature slope inside and outside the enclosure will be steeper.

10.3 Dynamic brake characteristics

Fig. 10.3 shows the pattern in which the servo motor comes to a stop when the dynamic brake is operated. Use Equation 10.2 to calculate an approximate coasting distance to a stop. The dynamic brake time constant τ varies with the servo motor and machine operation speeds. (Refer to Fig. 10.4)

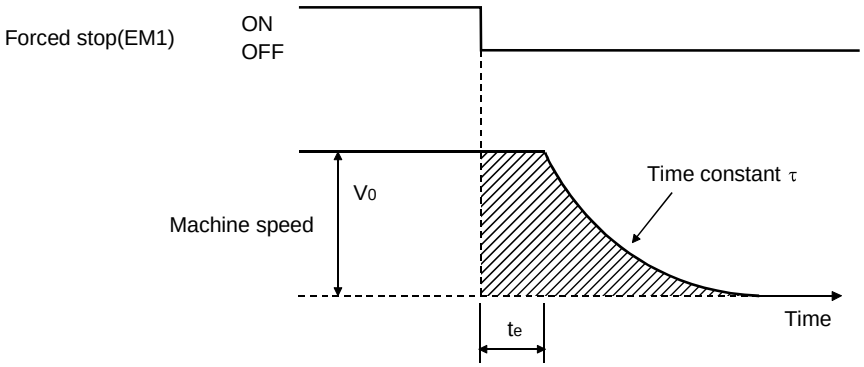
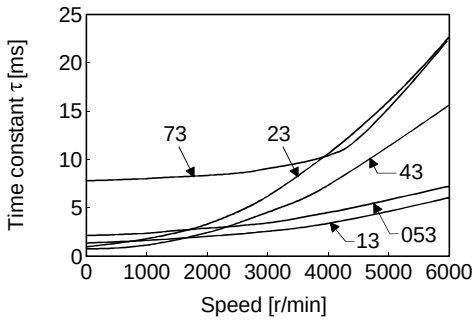


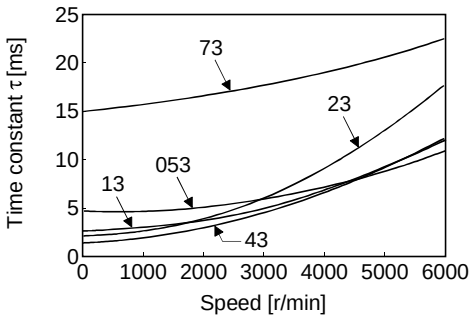
Fig. 10.3 Dynamic brake operation diagram

$$L_{max} = \frac{V_0}{60} \cdot \left\{ te + \tau \left(1 + \frac{J_L}{J_M} \right) \right\} \quad \text{(10.2)}$$

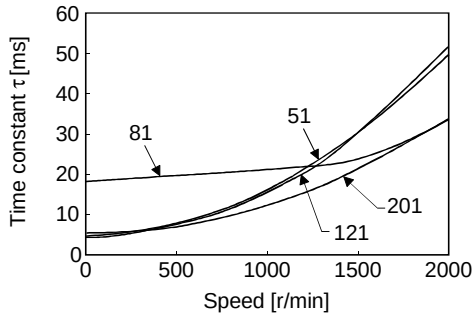
L_{max} : Maximum coasting distance ..... [mm][in]
Vo : Machine rapid feedrate .....[mm/min][in/min]
J_M : Servo motor inertial moment..... [kg・cm^2][oz・in^2]
J_L : Load inertia moment converted into equivalent value on servo motor shaft ..... [kg・cm^2][oz・in^2]
τ : Brake time constant ..... [s]
t_e : Delay time of control section..... [s]
For 7kW or less servo, there is internal relay delay time of about 30ms. For 11kW to 22kW servo, there is delay time of about 100ms caused by a delay of the external relay and a delay of the magnetic contactor built in the external dynamic brake.



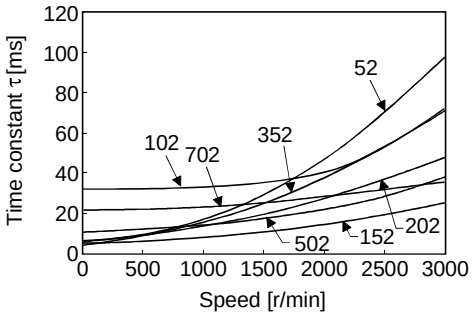
HF-MP series



HF-KP series



HF-SP1000r/min series



HF-SP2000r/min series

Fig. 10.4 Dynamic brake time constant

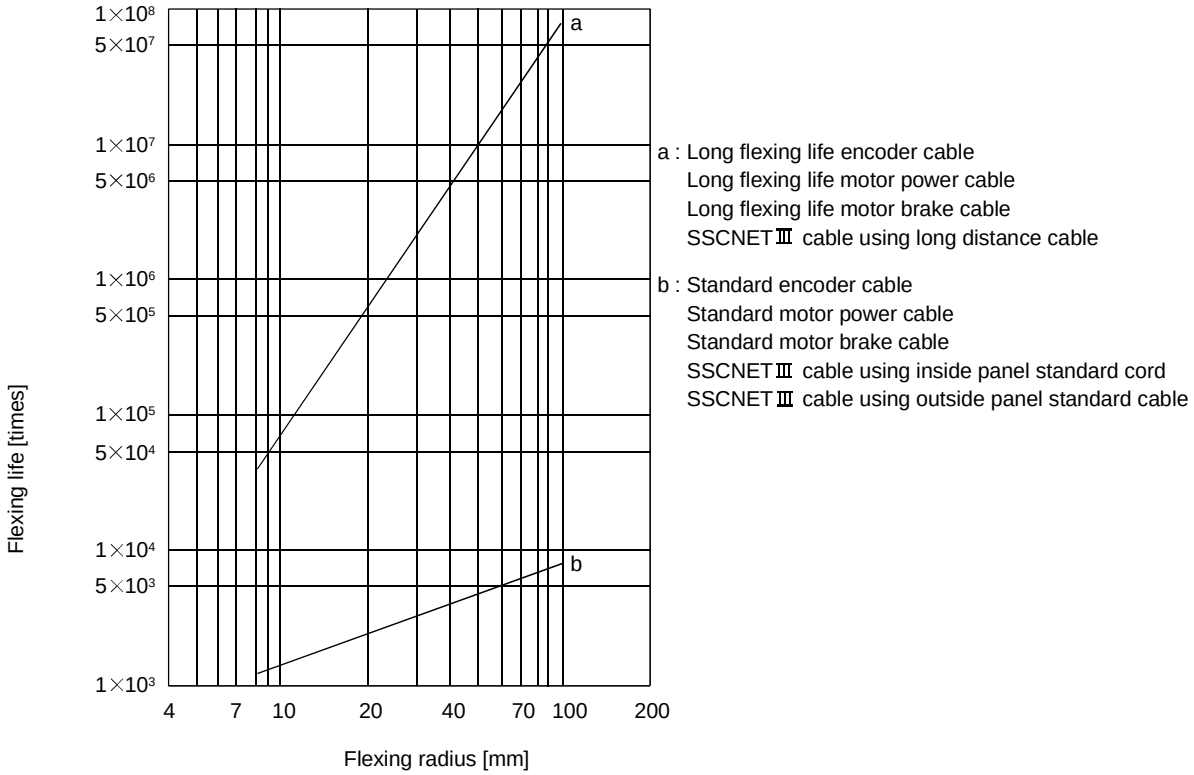
Use the dynamic brake at the load inertia moment indicated in the following table. If the load inertia moment is higher than this value, the built-in dynamic brake may burn. If there is a possibility that the load inertia moment may exceed the value, contact Mitsubishi.

Servo amplifier	Load inertia moment ratio [times]
MR-J3-10B (1)	30
MR-J3-20B (1)	
MR-J3-40B (1)	
MR-J3-60B	
MR-J3-70B	
MR-J3-100B	
MR-J3-200B	
MR-J3-350B	16
MR-J3-500B	15
MR-J3-700B	(Note) 15

Note. The value is 5 when used at motor speed over 2000r/min.

10.4 Cable flexing life

The flexing life of the cables is shown below. This graph calculated values. Since they are not guaranteed values, provide a little allowance for these values.



10.5 Inrush currents at power-on of main circuit and control circuit

The following table indicates the inrush currents (reference data) that will flow when the maximum permissible voltage (253VAC) is applied at the power supply capacity of 2500kVA and the wiring length of 1m (3.28ft).

Servo Amplifier	Inrush Currents (A_0-p)	
	Main circuit power supply (L_1, L_2, L_3)	Control circuit power supply (L_{11}, L_{21})
MR-J3-10B to 60B	30A (Attenuated to approx. 5A in 10ms)	20 to 30A (Attenuated to approx. 0A in 1 to 2ms)
MR-J3-70B・100B	54A (Attenuated to approx. 12A in 10ms)	
MR-J3-200B・350B	120A (Attenuated to approx. 12A in 20ms)	
MR-J3-10B1 to 40B1	38A (Attenuated to approx. 14A in 10ms)	
MR-J3-500B	44A (Attenuated to approx. 20A in 20ms)	30A (Attenuated to approx. 0A in 3ms)
MR-J3-700B	88A (Attenuated to approx. 20A in 20ms)	

Since large inrush currents flow in the power supplies, always use no-fuse breakers and magnetic contactors. (Refer to Section 11.9.)
When circuit protectors are used, it is recommended to use the inertia delay type that will not be tripped by an inrush current.

11. OPTIONS AND AUXILIARY EQUIPMENT

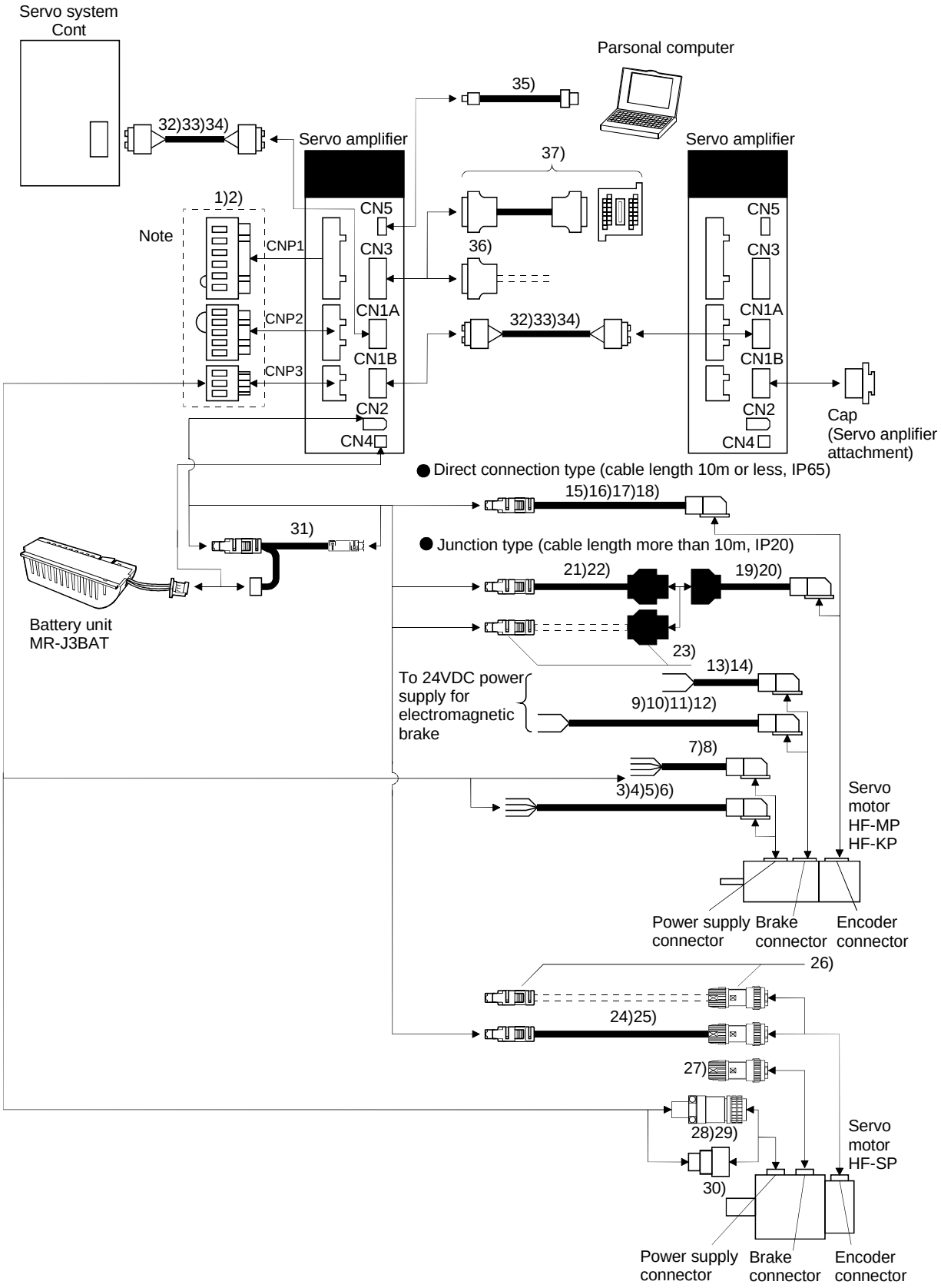
⚠ WARNING	▪ Before connecting any option or auxiliary equipment, make sure that the charge lamp is off more than 15 minutes after power-off, then confirm the voltage with a tester or the like. Otherwise, you may get an electric shock.

⚠ CAUTION	▪ Use the specified auxiliary equipment and options. Unspecified ones may lead to a fault or fire.

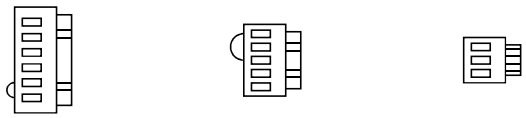
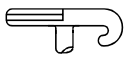
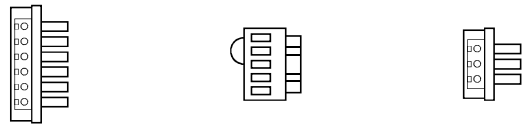
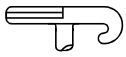
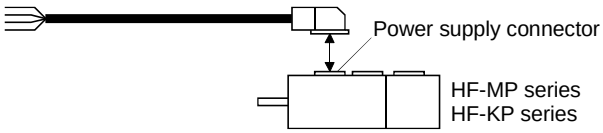
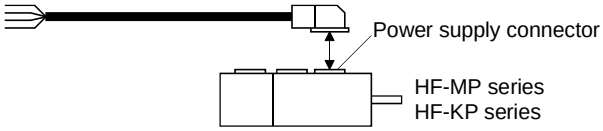
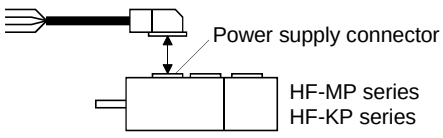
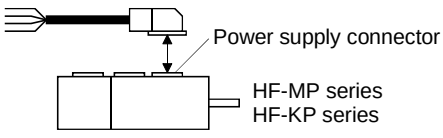
11.1 Cable/Connector Sets

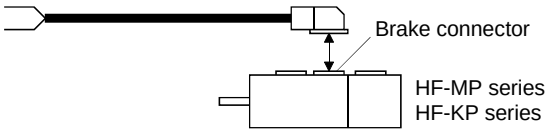
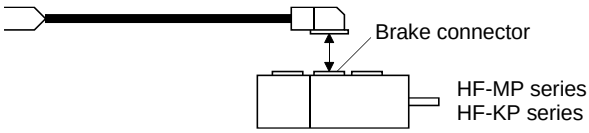
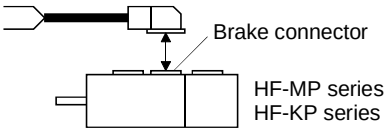
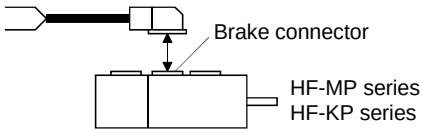
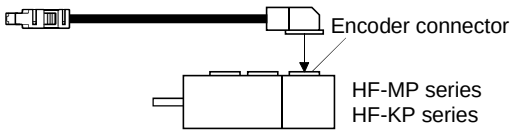
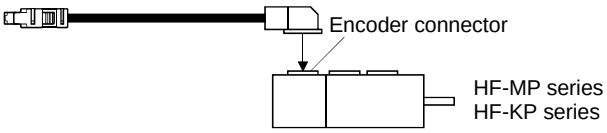
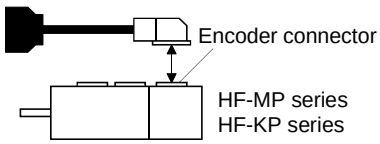
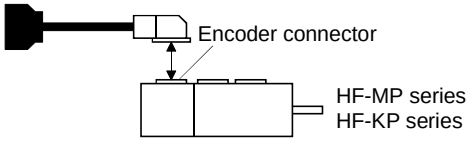
As the cables and connectors used with this servo, purchase the options indicated in this section.

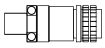
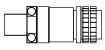
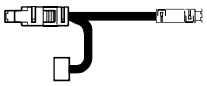
11.1.1 Combinations of cable/connector sets

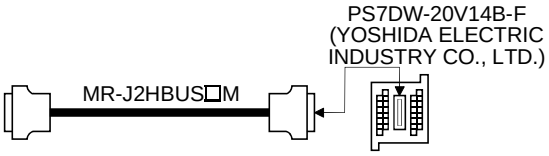


Note. Connectors for 3.5kw or less. For 5kw or more, terminal blocks.

No.	Product	Model	Description	Application
1)	Servo amplifier power supply connector		 CNP1 connector: 54928-0610 (Molex) CNP2 connector: 54927-0510 (Molex) CNP3 connector: 54928-0310 (Molex) <Applicable cable example> Wire size: 0.14mm^2(AWG26) to 2.5mm^2 (AWG14) Cable finish OD: to ϕ3.8mm  REC. Lever: 54932-0000 (Molex)	Supplied with servo amplifiers of 1kW or less
2)	Servo amplifier power supply connector		 CNP1 connector: PC4/6-STF-7.62-CRWH (Phoenix Contact) CNP2 connector: 54927-0510 (Molex) CNP3 connector: PC4/3-STF-7.62-CRWH (Phoenix Contact) <Applicable cable example> Wire size: 0.2mm^2 (AWG24) to 5.5mm^2 (AWG10) Cable finish OD: to ϕ5mm  REC. Lever: 54932-0000 (Molex)	Supplied with servo amplifiers of 2kW and 3.5kW
3)	Motor power supply cable	MR-PWS1CBL☐M-A1-L Cable length: 2・5・10m	 Refer to Section 11.1.3 for details.	IP65 Load side lead
4)	Motor power supply cable	MR-PWS1CBL☐M-A1-H Cable length: 2・5・10m		IP65 Load side lead Long flex life
5)	Motor power supply cable	MR-PWS1CBL☐M-A2-L Cable length: 2・5・10m	 Refer to Section 11.1.3 for details.	IP65 Opposite-to-load side lead
6)	Motor power supply cable	MR-PWS1CBL☐M-A2-H Cable length: 2・5・10m		IP65 Opposite-to-load side lead Long flex life
7)	Motor power supply cable	MR-PWS2CBL03M-A1-L Cable length: 0.3m	 Refer to Section 11.1.3 for details.	IP55 Load side lead
8)	Motor power supply cable	MR-PWS2CBL03M-A2-L Cable length: 0.3m	 Refer to Section 11.1.3 for details.	IP55 Opposite-to-load side lead

No.	Product	Model	Description	Application
9)	Motor brake cable	MR-BKS1CBL ☐ M-A1-L Cable length: 2・5・10m	 Refer to Section 11.1.4 for details.	IP65 Load side lead
10)	Motor brake cable	MR-BKS1CBL ☐ M-A1-H Cable length: 2・5・10m		IP65 Load side lead Long flex life
11)	Motor brake cable	MR-BKS1CBL ☐ M-A2-L Cable length: 2・5・10m	 Refer to Section 11.1.4 for details.	IP65 Opposite-to-load side lead
12)	Motor brake cable	MR-BKS1CBL ☐ M-A2-H Cable length: 2・5・10m		IP65 Opposite-to-load side lead Long flex life
13)	Motor brake cable	MR-BKS2CBL03M-A1-L Cable length: 0.3m	 Refer to Section 11.1.4 for details.	IP55 Load side lead
14)	Motor brake cable	MR-BKS2CBL03M-A2-L Cable length: 0.3m	 Refer to Section 11.1.4 for details.	IP55 Opposite-to-load side lead
15)	Encoder cable	MR-J3ENCBL ☐ M-A1-L Cable length: 2・5・10m	 Refer to Section 11.1.2 (1) for details.	IP65 Load side lead
16)	Encoder cable	MR-J3ENCBL ☐ M-A1-H Cable length: 2・5・10m		IP65 Opposite-to-load side lead Long flex life
17)	Encoder cable	MR-J3ENCBL ☐ M-A2-L Cable length: 2・5・10m	 Refer to Section 11.1.2 (1) for details.	IP65 Opposite-to-load side lead
18)	Encoder cable	MR-J3ENCBL ☐ M-A2-H Cable length: 2・5・10m		IP65 Opposite-to-load side lead Long flex life
19)	Encoder cable	MR-J3JCBL03M-A1-L Cable length: 0.3m	 Refer to Section 11.1.2 (3) for details.	IP20 Load side lead
20)	Encoder cable	MR-J3JCBL03M-A2-L Cable length: 0.3m	 Refer to Section 11.1.2 (3) for details.	IP20 Opposite-to-load side lead

No.	Product	Model	Description	Application
21)	Encoder cable	MR-EKCBL ☐ M-L Cable length: 20・30m		IP20
22)	Encoder cable	MR-EKCBL ☐ M-H Cable length: 20・30・40・50m	For HF-MP・HF-KP series Refer to Section 11.1.2 (2) for details.	IP20 Long flex life
23)	Encoder connector set	MR-ECNM	 For HF-MP・HF-KP series Refer to Section 11.1.2 (2) for details.	IP20
24)	Encoder cable	MR-J3ENSCBL ☐ M-L Cable length: 2・5・10・20・30m		IP67 Standerd flex life
25)	Encoder cable	MR-J3ENSCBL ☐ M-H Cable length: 2・5・10・20・30・40・50m	For HF-SP series Refer to Section 11.1.2 (4) for details.	IP67 Long flex linfe
26)	Encoder connector set	MR-J3SCNS	 For HF-SP series Refer to Section 11.1.2 (4) for details.	IP67
27)	Brake connector set	MR-BKCNS1	Straight plug: CM10-SP2S-L Socket contact: CM10-#22SC(S2)-100 (DDK)  For HF-SP series	IP67
28)	Power supply connector set	MR-PWCNS4	Plug: CE05-6A18-10SD-B-BSS Cable clamp: CE3057-10A-1 (D265) (DDK) Example of applicable cable Wire size: 2mm^2 (AWG14) to 3.5mm^2 (AWG12) Cable finish ϕD: ϕ10.5 to 14.1mm  For HF-SP51・81 For HF-SP52・152	IP67
29)	Power supply connector set	MR-PWCNS5	Plug: CE05-6A22-22D-B-BSS Cable clamp: CE3057-12A-1 (D265) (DDK) Example of applicable cable Wire size: 5.5mm^2 (AWG10) to 8mm^2 (AWG8) Cable finish ϕD: ϕ12.5 to 16mm  For HF-SP121・201 For HF-SP202 to 502	IP67
30)	Power supply connector set	MR-PWCNS3	Plug: CE05-6A32-17SD-B-BSS Cable clamp: CE3057-20A-1(D265) (DDK)  For HF-SP702	IP65 IP67 Be sure to use this when corresponding to EN Standard.
31)	Cable for connecting battery	MR-J3BTCBL03M	 Refer to Section 11.1.2 (5) for details.	For connection of battery

No.	Product	Model	Description	Application
32)	SSCNETⅢ cable	MR-J3BUS□M Cable length: 0.15 to 3m (Refer to Section 11.1.5.)	Connector: PF-2D103 (Japan Aviation Electronics Industry, Ltd.) — Connector: PF-2D103 (Japan Aviation Electronics Industry, Ltd.)	Inside panel standard cord
33)	SSCNETⅢ cable	MR-J3BUS□M-A Cable length: 5 to 20m (Refer to Section 11.1.5.)		Outside panel standard cable
34)	SSCNETⅢ cable	MR-J3BUS□M-B Cable length: 30 to 50m (Refer to Section 11.1.5.)	Connector: PF-2D103 (Japan Aviation Electronics Industry, Ltd.) — Connector: PF-2D103 (Japan Aviation Electronics Industry, Ltd.) 	Outside panel long distance cable
35)	USB cable	MR-J3USBCBL3M Cable length: 3m	For CN5 connector minB connector (5 pins) — For personal computer connector A connector 	For connection with PC-AT compatible personal computer
36)	Connector set	MR-CCN1	 Connector: 10120-3000VE Shell kit: 10320-52F0-008 (3M or similar product)	
37)	Junction terminal block (Recommended)		 Junction terminal block PS7DW-20V14B-F is not available from us as option. For using the junction terminal block, our option MR-J2HBUS□M is necessary. Refer to Section 11.5 for details.	

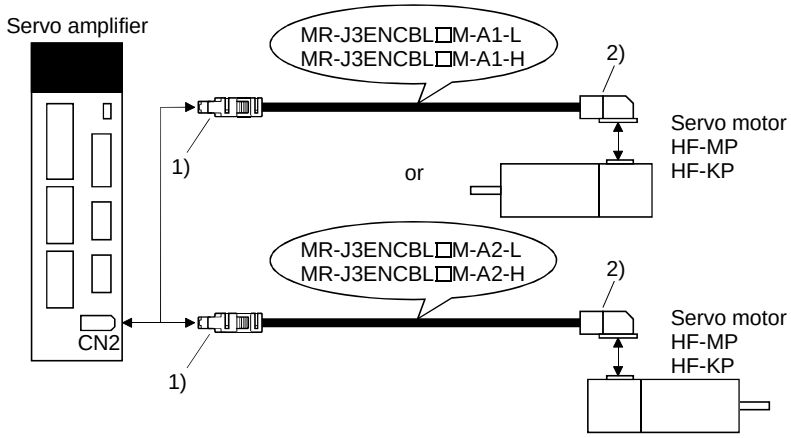
11.1.2 Encoder cable/connector sets

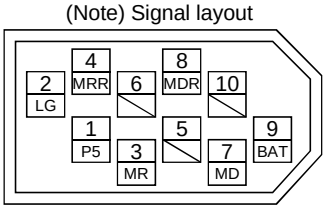
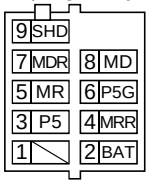
(1) MR-J3ENCBL ☐ M-A1-L/H ▪ MR-J3ENCBL ☐ M-A2-L/H

These cables are encoder cables for the HF-MP ▪ HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the ☐ part of the cable model. The cables of the lengths with the symbols are available.

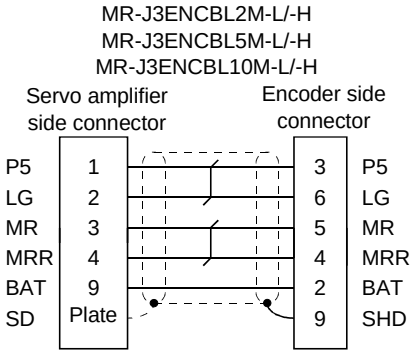
Cable Model	Cable Length								Protective Structure	Flex Life	Application
	0.3m	2m	5m	10m	20m	30m	40m	50m			
MR-J3ENCBL ☐ M-A1-L		2	5	10					IP65	Standard	For HF-MP ▪ HF-KP servo motor Load side lead
MR-J3ENCBL ☐ M-A1-H		2	5	10					IP65	Long flex	
MR-J3ENCBL ☐ M-A2-L		2	5	10					IP65	Standard	For HF-MP ▪ HF-KP servo motor Opposite-to-load side lead
MR-J3ENCBL ☐ M-A2-H		2	5	10					IP65	Long flex	

(a) Connection of servo amplifier and servo motor



Cable Model	1) For CN2 Connector	2) For Encoder Connector
MR-J3ENCBL ☐ M-A1-L	Receptacle: 36210-0100JL Shell kit: 536310-3200-008 (3M or equivalent) (Note) Signal layout  View seen from wiring side.	Connector: 1674320-1 Crimping tool for ground clip: 1596970-1 Crimping tool for receptacle contact: 1596847 (Tyco Electronics) (Note) Signal layout  View seen from wiring side.
MR-J3ENCBL ☐ M-A1-H		
MR-J3ENCBL ☐ M-A2-L	Note. Keep open the pins shown with ⊘. Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.	Note. Keep open the pin shown with an ⊘.
MR-J3ENCBL ☐ M-A2-H		

(b) Cable internal wiring diagram



(2) MR-EKCBL ☐ M-L/H

POINT

- The following encoder cables are of four-wire type. When using any of these encoder cables, set parameter No. PC04 to "1 ☐☐☐" to select the four-wire type.
  MR-EKCBL30M-L
  MR-EKCBL30M-H
  MR-EKCBL40M-H
  MR-EKCBL50M-H

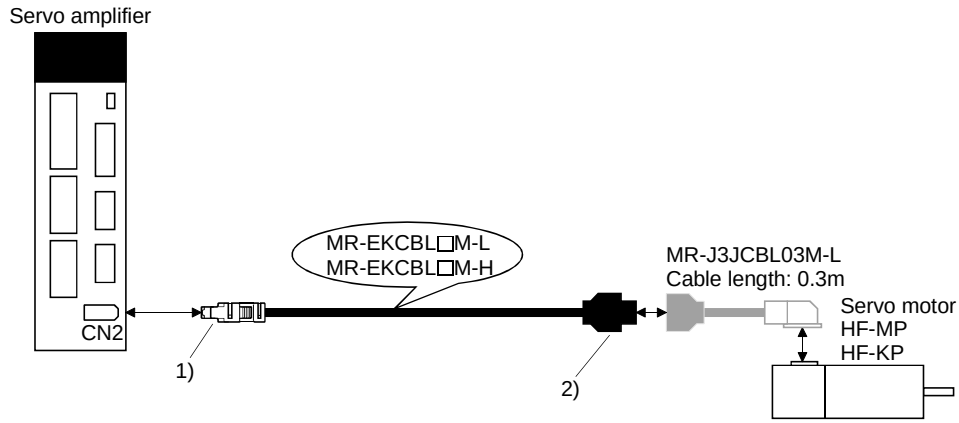
The servo amplifier and servo motor cannot be connected with these cables only. The servo motor side encoder cable (MR-J3JCBL03M-A1-L or MR-J3JCBL03M-A2-L) is required.

The numerals in the Cable Length field of the table are the symbols entered in the ☐ part of the cable model. The cables of the lengths with the symbols are available.

Cable Model	Cable Length								Protective Structure	Flex Life	Application
	0.3m	2m	5m	10m	20m	30m	40m	50m			
MR-EKCBL ☐ M-L					20	(Note) 30			IP20	Standard	For HF-MP・HF-KP servo motor Use in combination with MR-J3JCBL03M-A1-L or MR-J3JCBL03M-A2-L.
MR-EKCBL ☐ M-H					20	(Note) 30	(Note) 40	(Note) 50	IP20	Long flex	

Note. Four-wire type cable.

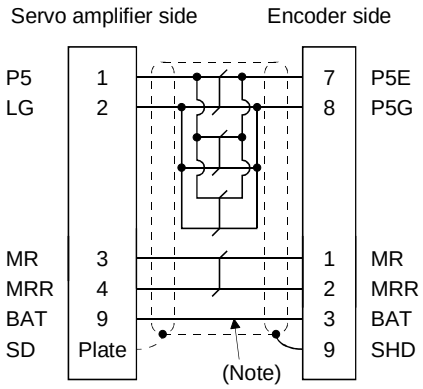
(a) Connection of servo amplifier and servo motor



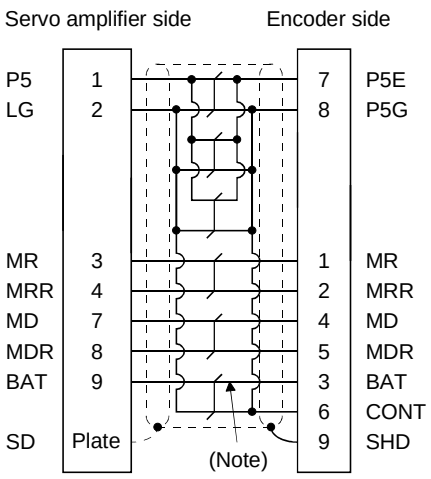
Cable Model	1) CN2 Connector	2) Junction Connector
MR-EKCBL ☐ M-L	(1) For soldering Connector housing: 54593-1011 Cover A: 54594-1015 Cover B: 54595-1005 Shell cover: 58935-1000 Shell body: 58934-1000 Cable clamp: 58937-0000 Screw: 58203-0010 (Molex or equivalent) (2) For crimping Connector housing: 51209-1001 Cover A: 54594-1015 Cover B: 54595-1005 Shell cover: 58935-1000 Shell body: 58934-1000 Terminal: 59351-8187 Cable clamp: 58937-0000 Screw: 58203-0010 (Molex or equivalent)	Housing: 1-172161-9 Connector pin: 170359-1 (Tyco Electronics or equivalent) Cable clamp: MTI-0002 (Toa Electric Industries) Signal layout 1 2 3 MR MRR BAT 4 5 6 MD MDR CONT 7 8 9 P5 LG SHD View seen from wiring side.
MR-EKCBL ☐ M-H	(Note) Signal layout 2 LG, 4 MRR, 6, 8 MDR, 10 1 P5, 3 MR, 5, 7 MD, 9 BAT View seen from wiring side. Note. Keep open the pins shown with ▨. Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.	

(b) Internal wiring diagram

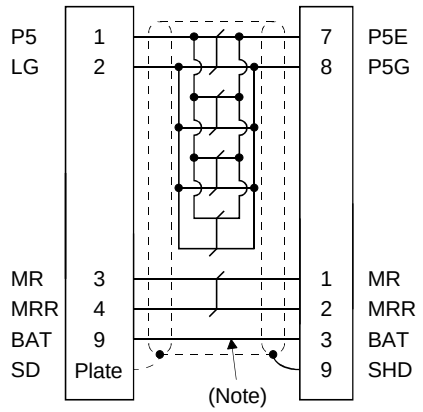
MR-EKCBL20M-L



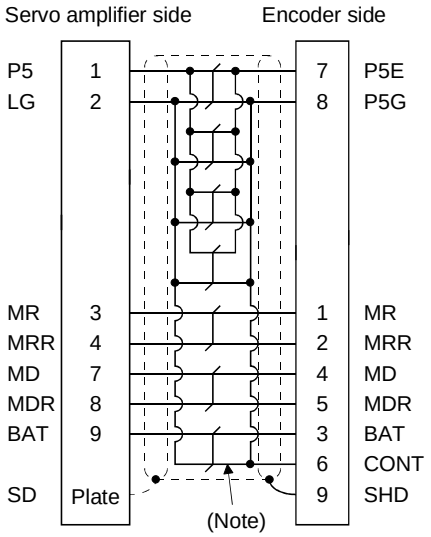
MR-EKCBL30M-L



MR-EKCBL20M-H



MR-EKCBL30M-H
MR-EKCBL40M-H
MR-EKCBL50M-H



Note. Always make connection for use in an absolute position detection system. Wiring is not necessary for use in an incremental system.

When fabricating the cable, use the wiring diagram corresponding to the length indicated below.

Cable Flex Life	Applicable Wiring Diagram	
	Less than 10m	30m to 50m
Standard	MR-EKCBL20M-L	
Long flex	MR-EKCBL20M-H	MR-EKCBL30M-H MR-EKCBL40M-H MR-EKCBL50M-H

(c) When fabricating the encoder cable

When fabricating the cable, prepare the following parts and tool, and fabricate it according to the wiring diagram in (b). Refer to Section 11.8 for the specifications of the used cable.

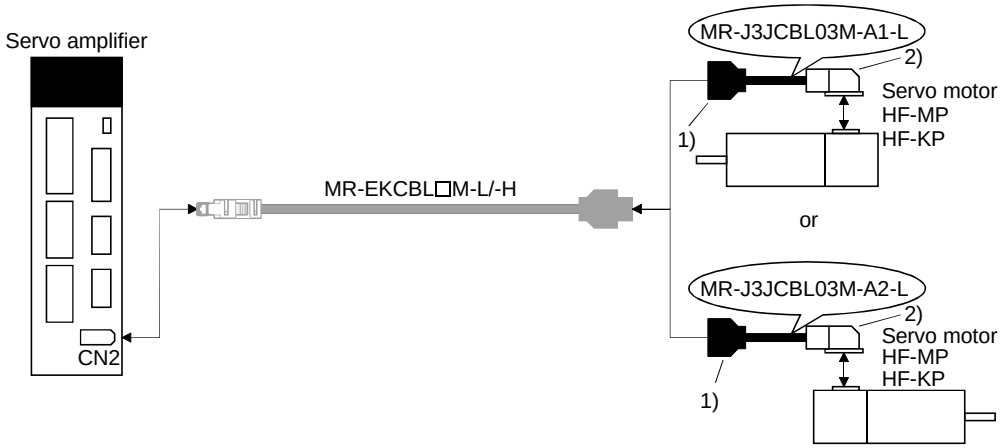
Parts/Tool	Description	
Connector set	MR-ECNM	
		
	For CN2 connector Connector housing: 54593-1011 Cover A: 54594-1015 Cover B: 54595-1005 Shell cover: 58935-1000 Shell body: 58934-1000 Cable clamp: 58937-0000 Screw: 58203-0010 (Molex)	Junction connector Housing: 1-172161-9 Connector pin: 170359-1 (Tyco Electronics or equivalent) Cable clamp: MTI-0002 (Toa Electric Industries)

(3) MR-J3JCBL03M-A1-L・MR-J3JCLB03M-A2-L

The servo amplifier and servo motor cannot be connected with these cables only. The servo motor side encoder cable (MR-EKCBL ☐ M-L/H) is required.

Cable Model	Cable Length	Protective Structure	Flex Life	Application
MR-J3JCBL03M-A1-L	0.3m	IP20	Standard	For HF-MP・HF-KP servo motor Load side lead Use in combination with MR-EKCBL ☐ M-L/H.
MR-J3JCBL03M-A2-L				For HF-MP・HF-KP servo motor Opposite-to-load side lead Use in combination with MR-EKCBL ☐ M-L/H.

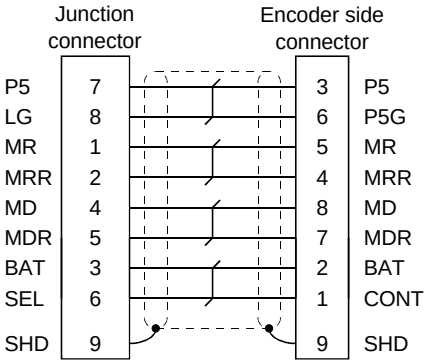
(a) Connection of servo amplifier and servo motor



Cable Model	1) Junction Connector	2) For Encoder Connector
MR-J3JCBL03M-A1-L MR-J3JCBL03M-A2-L	Housing: 1-172169-9 Contact: 1473226-1 Cable clamp: 316454-1 (Tyco Electronics) Signal layout 3 2 1 BAT MRR MR 6 5 4 CONT MDR MD 9 8 7 SHD LG P5 View seen from wiring side.	Connector: 1674320-1 Crimping tool for ground clip: 1596970-1 Crimping tool for receptacle contact: 1596847 (Tyco Electronics) Signal layout 9 SHD 7 MDR 8 MD 5 MR 6 P5G 3 P5 4 MRR 1 CONT 2 BAT View seen from wiring

(b) Internal wiring diagram

MR-J3JCBL03M-A1-L

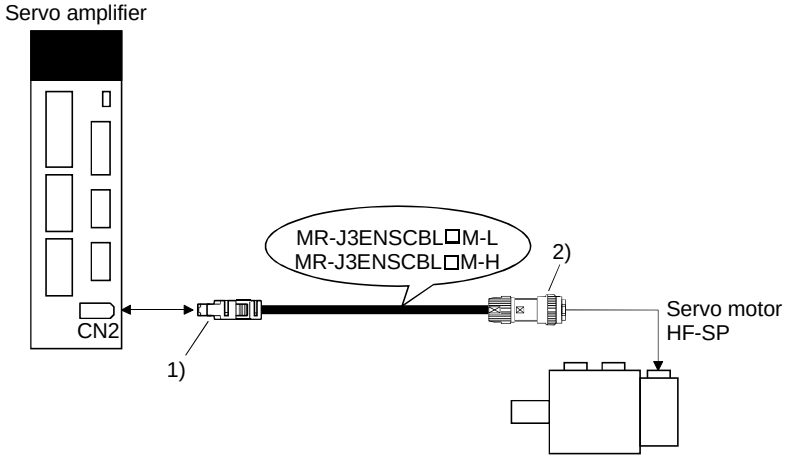


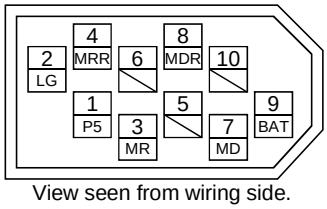
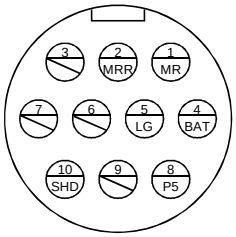
(4) MR-J3ENSCBL ☐ M-L · MR-J3ENSCBL ☐ M-H

These cables are detector cables for HF-SP Series servomotors. The number in the cable length column of the table indicates the symbol filling the square ☐ in the cable model. Cable lengths corresponding to the specified symbols are prepared.

Cable Model	Cable Length							Protective Structure	Flex Life	Application
	2m	5m	10m	20m	30m	40m	50m			
MR-J3ENSCBL ☐ M-L	2	5	10	20	30			IP67	Standard	For HF-SP servo motor
MR- J3ENSCBL ☐ M-H	2	5	10	20	30	40	50	IP67	Long flex	

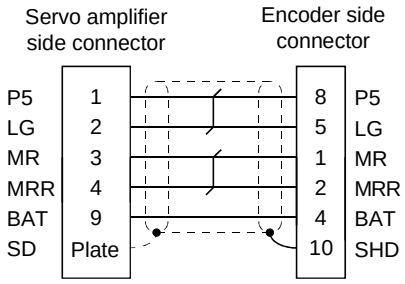
(a) Connection of servo amplifier and servo motor



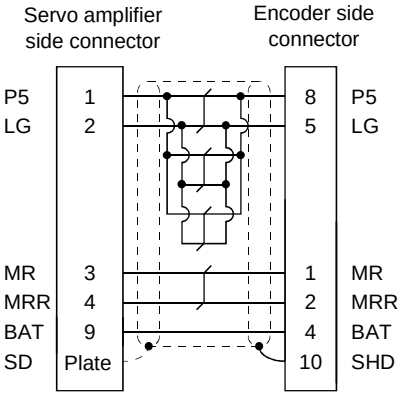
Cable Model	1) For CN2 Connector	2) For Encoder Connector
MR-J3ENSCBL ☐ M-L	Receptacle: 36210-0100JL Shell kit: 536310-3200-008 (3M or equivalent) (Note) Signal layout  View seen from wiring side.	In case of 10m or shorter cables Straight plug: CM10-SP10S-M Socket contact: CM10-#22SC(C1)-100 Crimping tool: 357J-50446 (DDK) Applicable cable AWG20 to 22 In case of 20m or longer cables Straight plug: CM10-SP10S-M Socket contact: CM10-#22SC(C2)-100 Crimping tool: 357J-50447 (DDK) Applicable cable AWG23 to 28
MR-J3ENSCBL ☐ M-H	Note. Keep open the pins shown with ⊘. Especially, pin 10 is provided for manufacturer adjustment. If it is connected with any other pin, the servo amplifier cannot operate normally.	(Note) Signal layout  View seen from wiring side Note. Keep open the pin shown with an ⊘.

(b) Internal wiring diagram

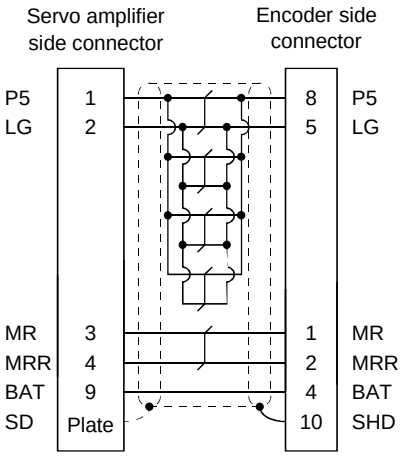
MR-J3ENSCBL2M-L/H
MR-J3ENSCBL5M-L/H
MR-J3ENSCBL10M-L/H



MR-J3ENSCBL20M-L
MR-J3ENSCBL30M-L



MR-J3ENSCBL20M-H
MR-J3ENSCBL30M-H
MR-J3ENSCBL40M-H
MR-J3ENSCBL50M-H



(c) When fabricating the encoder cable

When fabricating the cable, prepare the following parts and tool, and fabricate it according to the wiring diagram in (b). Refer to Section 11.8 for the specifications of the used cable.

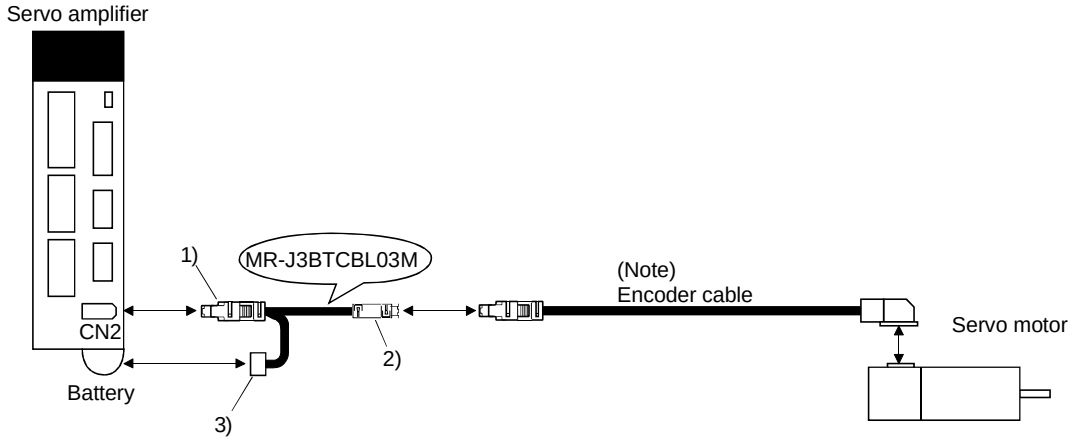
Parts/Tool	Description	
Connector set	MR- J3SCNS (Option) Receptacle: 36210-0100JL Shell kit: 36310-3200-008 (3M)	Straight plug: CM10-SP10S-M Socket contact: CM10-#22SC(S1)-100 Applicable wire size: AWG20 or less Recommended tightening jig: 357J-51456T (DDK)

(5) MR-J3BTCBL03M

This cable is a battery connection cable. Use this cable to retain the current position even if the detector cable is disconnected from the servo amplifier.

Cable Model	Cable Length	Application
MR-J3BTCBL03M	0.3m	For HF-MP ▪ HF-KP ▪ HF-SP servo motor

(a) Connection of servo amplifier and servo motor



Note. For the detector cable, refer to (1), (2), (3) and (4) in this section.

Cable Model	1) For CN2 Connector	1) Junction Connector	2) For Battery Connector
MR-J3BTCBL03M	Receptacle: 36210-0100JL Shell kit: 36310-3200-008 (3M or equivalent)	Plug: 36110-3000FD Shell kit: 36310-F200-008 (3M)	Connector: DF3-2EP-2C Contact: DF3-EP2428PCFA (Hirose Denki)

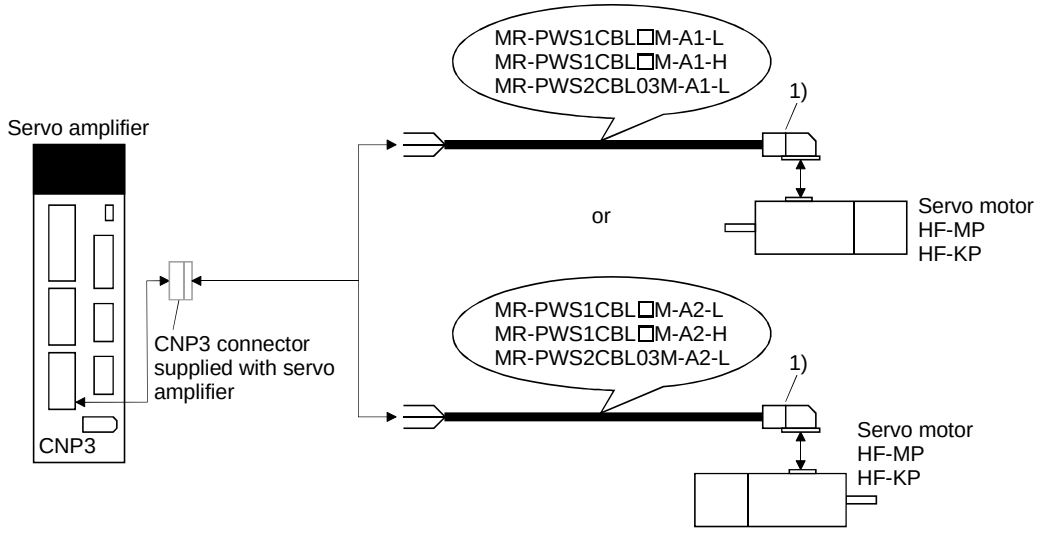
11.1.3 Motor power supply cables

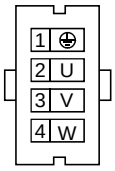
These cables are motor power supply cables for the HF-MP・HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.

Refer to Section 3.10 when wiring.

Cable Model	Cable Length								Protective Structure	Flex Life	Application
	0.3m	2m	5m	10m	20m	30m	40m	50m			
MR-PWS1CBL□M-A1-L		2	5	10					IP65	Standard	For HF-MP・HF-KP servo motor Load side lead
MR-PWS1CBL□M-A2-L		2	5	10					IP65	Standard	For HF-MP・HF-KP servo motor Opposite-to-load side lead
MR-PWS1CBL□M-A1-H		2	5	10					IP65	Long flex	For HF-MP・HF-KP servo motor Load side lead
MR-PWS1CBL□M-A2-H		2	5	10					IP65	Long flex	For HF-MP・HF-KP servo motor Opposite-to-load side lead
MR-PWS2CBL□M-A1-L	03								IP55	Standard	For HF-MP・HF-KP servo motor Load side lead
MR-PWS2CBL□M-A2-L	03								IP55	Standard	For HF-MP・HF-KP servo motor Opposite-to-load side lead

(1) Connection of servo amplifier and servo motor



Cable Model	1) For Motor Power Supply Connector
MR-PWS1CBL□M-A1-L MR-PWS1CBL□M-A2-L MR-PWS1CBL□M-A1-H MR-PWS1CBL□M-A2-H MR-PWS2CBL03M-A1-L MR-PWS2CBL03M-A2-L	Connector: JN4FT04SJ1 Hod, socket insulator Bushing, ground nut Contact: ST-TMH-S-C1B-100(A534G) Crimping tool: CT160-3TM5B (Japan Aviation Electronics Industry) Signal layout  View seen from wiring side.

(2) Internal wiring diagram

MR-PWS1CBL□M-A1-H MR-PWS1CBL□M-A2-H
MR-PWS2CBL03M-A1-L MR-PWS1CBL03M-A2-L

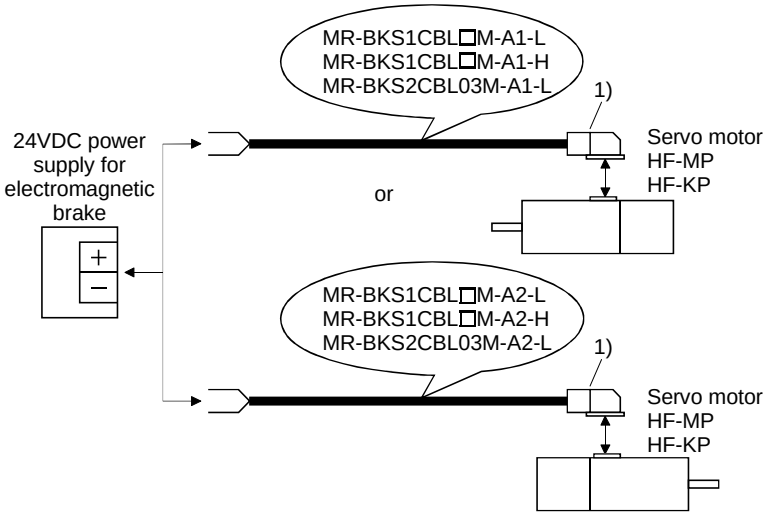
11.1.4 Motor brake cables

These cables are motor brake cables for the HF-MP · HF-KP series servo motors. The numerals in the Cable Length field of the table are the symbols entered in the □ part of the cable model. The cables of the lengths with the symbols are available.

Refer to Section 3.11 when wiring.

Cable Model	Cable Length								Protective Structure	Flex Life	Application
	0.3m	2m	5m	10m	20m	30m	40m	50m			
MR-PWS1CBL□M-A1-L		2	5	10					IP65	Standard	For HF-MP · HF-KP servo motor Load side lead
MR-PWS1CBL□M-A2-L		2	5	10					IP65	Standard	For HF-MP · HF-KP servo motor Opposite-to-load side lead
MR-PWS1CBL□M-A1-H		2	5	10					IP65	Long flex	For HF-MP · HF-KP servo motor Load side lead
MR-PWS1CBL□M-A2-H		2	5	10					IP65	Long flex	For HF-MP · HF-KP servo motor Opposite-to-load side lead
MR-PWS2CBL□M-A1-L	03								IP55	Standard	For HF-MP · HF-KP servo motor Load side lead
MR-PWS2CBL□M-A2-L	03								IP55	Standard	For HF-MP · HF-KP servo motor Opposite-to-load side lead

(1) Connection of servo amplifier and servo motor

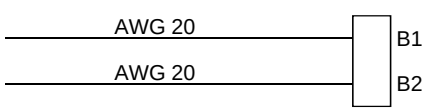


Cable Model	1) For Motor Brake Connector
MR-BKS1CBL□M-A1-L MR-BKS1CBL□M-A2-L MR-BKS1CBL□M-A1-H MR-BKS1CBL□M-A2-H MR-BKS2CBL03M-A1-L MR-BKS2CBL03M-A2-L	Connector: JN4FT02SJ1 Hod, socket insulator Bushing, ground nut Contact: ST-TMH-S-C1B-100(A534G) Crimping tool: CT160-3TMH5B (Japan Aviation Electronics Industry) Signal layout 1 B1 2 B2 View seen from wiring side.

(2) Internal wiring diagram

MR-BKS1CBL□M-A1-H
MR-BKS2CBL03M-A1-L

MR-BKS1CBL□M-A2-H
MR-BKS1CBL03M-A2-L



11.1.5 SSCNETⅢ cable

> **POINT**
>
> ・Do not see directly the light generated from CN1A・CN1B connector of servo amplifier or the end of SSCNETⅢ cable. When the light gets into eye, you may feel something is wrong for eye. (The light source of SSCNETⅢ corresponds to class1 defined in JISC6802 or IEC60825-1.)

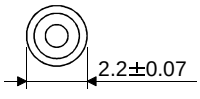
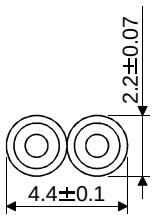
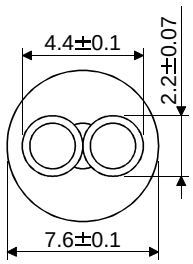
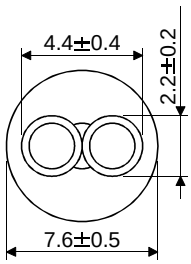
(1) Model explanations

Numeral in the column of cable length on the table is a symbol put in the □ part of cable model. Cables of which symbol exists are available.

Cable Model	Cable Length											Flex Life	Application・Remark
	0.15m	0.3m	0.5m	1m	3m	5m	10m	20m	30m	40m	50m		
MR-J3BUS□M	015	03	05	1	3							Standard	Using inside panel standard cord
MR-J3BUS□M-A						5	10	20				Standard	Using outside panel standard cable
(Note) MR-J3BUS□M-B									30	40	50	Long flex	Using long distance cable

Note. For cable of 30m or less, contact our company.

(2) Specifications

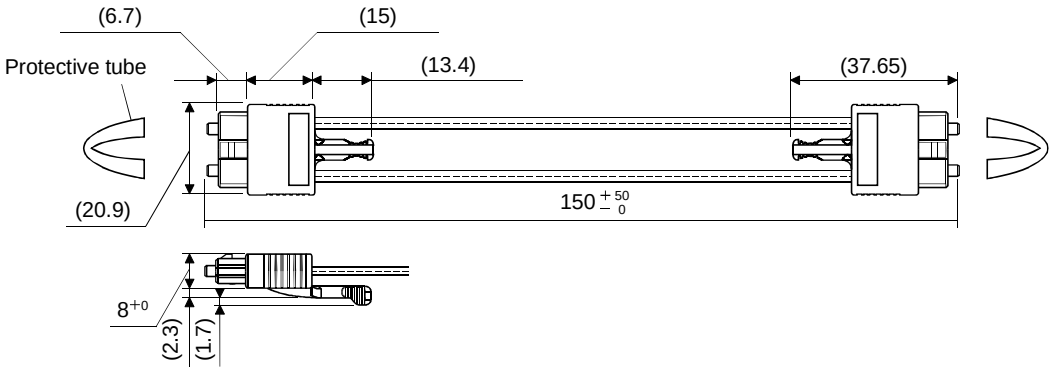
		Description			
SSCNETⅢ cable model		MR-J3BUS□M		MR-J3BUS□M-A	MR-J3BUS□M-B
SSCNETⅢ cable length		0.15m	0.3 to 3m	5 to 20m	30 to 50m
Optical cable (cord)	Minimum bend radius	25mm		Enforced covering cord: 50mm Cord: 25mm	Enforced covering cord: 50mm Cord: 30mm
	Tension strength	70N	140N	420N (Enforced covering cord)	980N (Enforced covering cord)
	Temperature range for use (Note)	-40 to 85℃			-20 to 70℃
	Ambient	Indoors (no direct sunlight) No solvent or oil			
	External appearance [mm]				

Note. This temperature range for use is the value for optical cable (cord) only. Temperature condition for the connector is the same as that for servo amplifier.

(3) Outline drawings

(a) MR-J3BUS015M

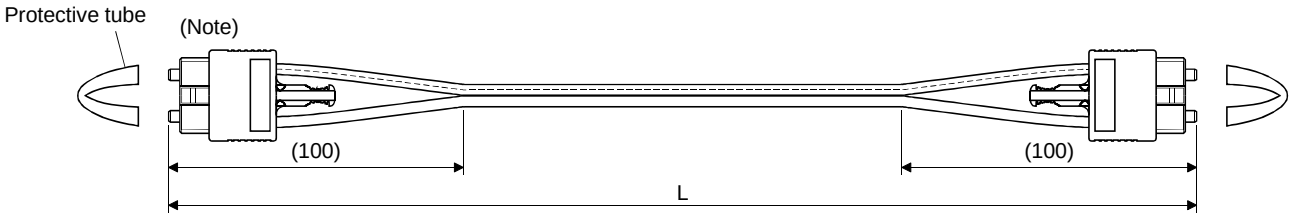
[Unit: mm]



(b) MR-J3BUS03M to MR-J3BUS3M

Refer to the table of this section (1) for cable length (L).

[Unit: mm]



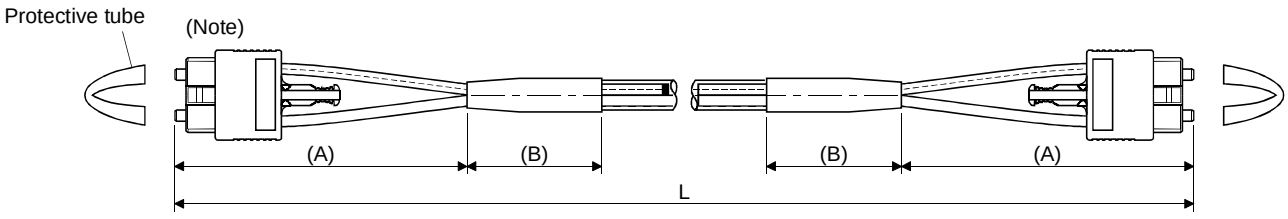
Note. Dimension of connector part is the same as that of MR-J3BUS015M.

(c) MR-J3BUS5M-A to MR-J3BUS20M-A・MR-J3BUS30M-B to MR-J3BUS50M-B

Refer to the table of this section (1) for cable length (L).

SSCNETⅢ cable	Distortion dimension [mm]	
	A	B
MR-J3BUS5M-A to MR-J3BUS20M-A	100	30
MR-J3BUS30M-B to MR-J3BUS50M-B	150	50

[Unit: mm]



Note. Dimension of connector part is the same as that of MR-J3BUS015M.

11.2 Regenerative brake options

> **CAUTION** ・The specified combinations of regenerative brake options and servo amplifiers may only be used. Otherwise, a fire may occur.

(1) Combination and regenerative power

The power values in the table are resistor-generated powers and not rated powers.

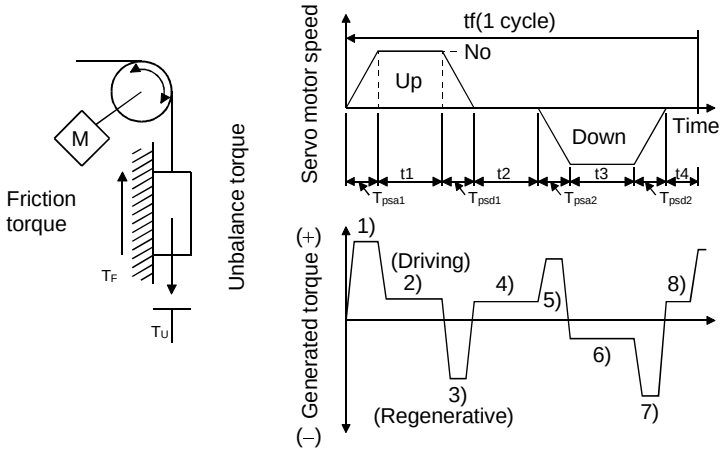
Servo amplifier	Regenerative power[W]							
	Built-in regenerative brake resistor	MR-RB032 [40Ω]	MR-RB12 [40Ω]	MR-RB30 [13Ω]	MR-RB31 [6.7Ω]	MR-RB32 [40Ω]	MR-RB50 [13Ω]	MR-MB51 [6.7Ω]
MR-J3-10B (1)		30						
MR-J3-20B (1)	10	30	100					
MR-J3-40B (1)	10	30	100					
MR-J3-60B	10	30	100					
MR-J3-70B	20	30	100			300		
MR-J3-100B	20	30	100			300		
MR-J3-200B	100			300			500	
MR-J3-350B	100			300			500	
MR-J3-500B	130				300			500
MR-J3-700B	170				300			500

(2) Selection of the regenerative brake option

Use the following method when regeneration occurs continuously in vertical motion applications or when it is desired to make an in-depth selection of the regenerative brake option:

(a) Regenerative energy calculation

Use the following table to calculate the regenerative energy.



Formulas for calculating torque and energy in operation

Regenerative power	Torque applied to servo motor [N・m]	Energy [J]
1)	$T_1 = \frac{(J_L+J_M)\cdot N_0}{9.55\times10^4}\cdot\frac{1}{T_{psa1}} + T_U + T_F$	$E_1 = \frac{0.1047}{2}\cdot N_0\cdot T_1\cdot T_{psa1}$
2)	$T_2 = T_U + T_F$	$E_2 = 0.1047\cdot N_0\cdot T_2\cdot t_1$
3)	$T_3 = \frac{(J_L+J_M)\cdot N_0}{9.55\times10^4}\cdot\frac{1}{T_{psd1}} + T_U + T_F$	$E_3 = \frac{0.1047}{2}\cdot N_0\cdot T_3\cdot T_{psd1}$
4), 8)	$T_4 = T_U$	$E_4 \geq 0$ (No regeneration)
5)	$T_5 = \frac{(J_L+J_M)\cdot N_0}{9.55\times10^4}\cdot\frac{1}{T_{psa2}} - T_U + T_F$	$E_5 = \frac{0.1047}{2}\cdot N_0\cdot T_5\cdot T_{psa2}$
6)	$T_6 = T_U + T_F$	$E_6 = 0.1047\cdot N_0\cdot T_6\cdot t_3$
7)	$T_7 = \frac{(J_L+J_M)\cdot N_0}{9.55\times10^4}\cdot\frac{1}{T_{psd2}} - T_U + T_F$	$E_7 = \frac{0.1047}{2}\cdot N_0\cdot T_7\cdot T_{psd2}$

From the calculation results in 1) to 8), find the absolute value (Es) of the sum total of negative energies.

(b) Losses of servo motor and servo amplifier in regenerative mode

The following table lists the efficiencies and other data of the servo motor and servo amplifier in the regenerative mode.

Servo amplifier	Inverse efficiency[%]	Capacitor charging[J]
MR-J3-10B	55	9
MR-J3-10B1	55	4
MR-J3-20B	70	9
MR-J3-20B1	70	4
MR-J3-40B	85	11
MR-J3-40B1	85	10
MR-J3-60B	85	11
MR-J3-70B	80	18
MR-J3-100B	80	18
MR-J3-200B	85	40
MR-J3-350B	85	40
MR-J3-500B	90	45
MR-J3-700B	90	70

Inverse efficiency (η) :Efficiency including some efficiencies of the servo motor and servo amplifier when rated (regenerative) torque is generated at rated speed. Since the efficiency varies with the speed and generated torque, allow for about 10%.

Capacitor charging (Ec) :Energy charged into the electrolytic capacitor in the servo amplifier.

Subtract the capacitor charging from the result of multiplying the sum total of regenerative energies by the inverse efficiency to calculate the energy consumed by the regenerative brake option.

$$ER\ [J] = \eta \cdot Es - Ec$$

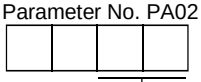
Calculate the power consumption of the regenerative brake option on the basis of single-cycle operation period tf [s] to select the necessary regenerative brake option.

$$PR\ [W] = ER/tf \quad \text{.....(11.1)}$$

(3) Connection of the regenerative brake option

Set parameter No. PA02 according to the open to be used.

Parameter No. PA02



Selection of regenerative
00: Regenerative brake option is not used
- For MR-J3-10B, regenerative brake resistor is not used.
- For MR-J3-20B, built-in regenerative brake resistor is used.

01: MR-BU・MR-RC
02: MR-RB032
03: MR-RB12
04: MR-RB32
05: MR-RB30
06: MR-RB50
08: MR-RB31
09: MR-RB51

(4) Connection of the regenerative brake option

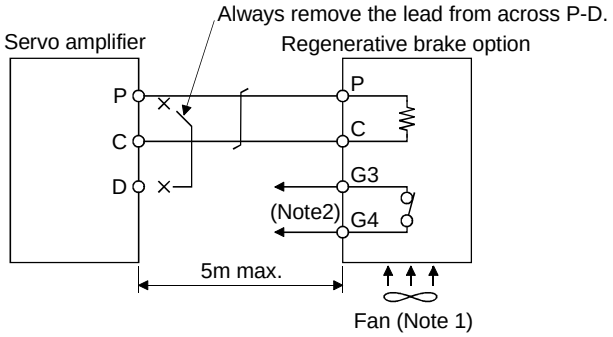
POINT
・When the MR-RB50・MR-RB51 is used, a fan is required to cool it. The cooling fan should be prepared by the customer.
・For the sizes of wires used for wiring, refer to Section 11.8.

The regenerative brake option will generate heat of about 100℃. Fully examine heat dissipation, installation position, used cables, etc. before installing the option. For wiring, use flame-resistant cables and keep them clear of the regenerative brake option body. Always use twisted cables of max. 5m length for connection with the servo amplifier.

(a) MR-J3-350B or less

Always remove the wiring from across P-D and fit the regenerative brake option across P-C.

The G3 and G4 terminals act as a thermal sensor. G3-G4 are disconnected when the regenerative brake option overheats abnormally.

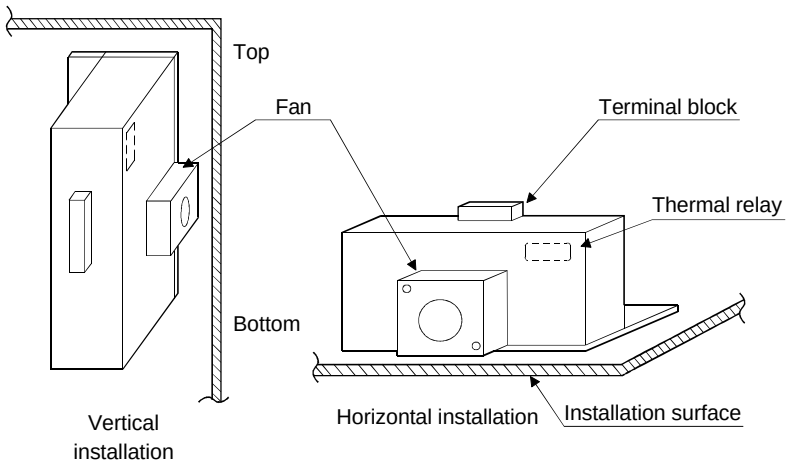


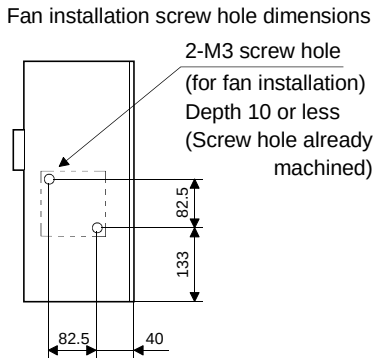
Note 1. When using the MR-RB50, forcibly cool it with a cooling fan (1.0m3/min, □92 or so).

2. Make up a sequence which will switch off the magnetic contactor (MC) when abnormal heating occurs.
   G3-G4 contact specifications
   Maximum voltage: 120V AC/DC
   Maximum current: 0.5A/4.8VDC
   Maximum capacity: 2.4VA

For the MR-RB50 install the cooling fan as shown.

[Unit : mm]



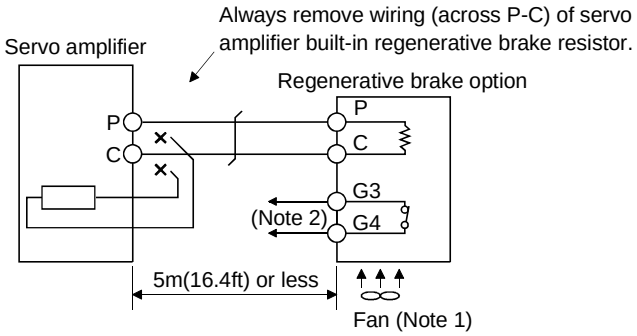


Recommended fan:
Toyo Denki's TL396A or equivalent

(b) MR-J3-500B・MR-J3-700B

Always remove the wiring (across P-C) of the servo amplifier built-in regenerative brake resistor and fit the regenerative brake option across P-C.

The G3 and G4 terminals act as a thermal protector. G3-G4 are opened when the regenerative brake option overheats abnormally.

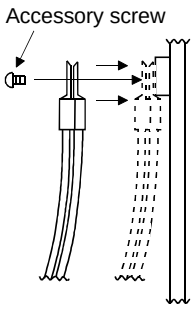


Note 1. When using the MR-RB51, forcibly cool it with a cooling fan (1.0m³/min,□92 or so).

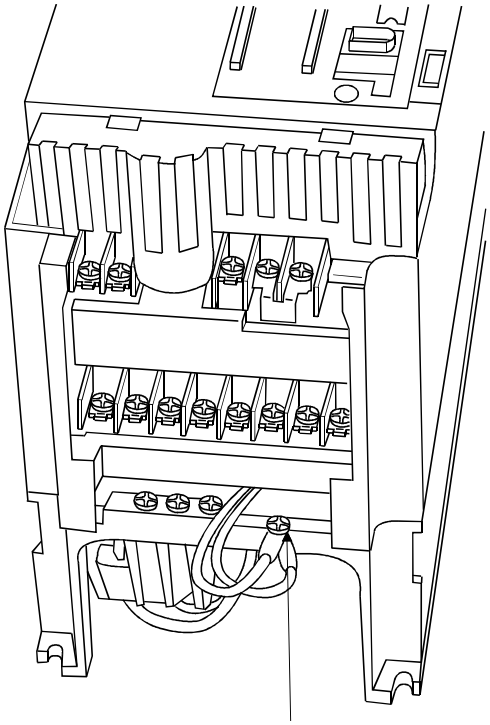
2. Make up a sequence which will switch off the magnetic contactor (MC) when abnormal heating occurs.
   G3-G4 contact specifications
   Maximum voltage: 120V AC/DC
   Maximum current: 0.5A/4.8VDC
   Maximum capacity: 2.4VA

When using the regenerative brake resistor option, remove the servo amplifier's built-in regenerative brake resistor terminals (across P-C), fit them back to back, and secure them to the frame with the accessory screw as shown below.

Mounting method

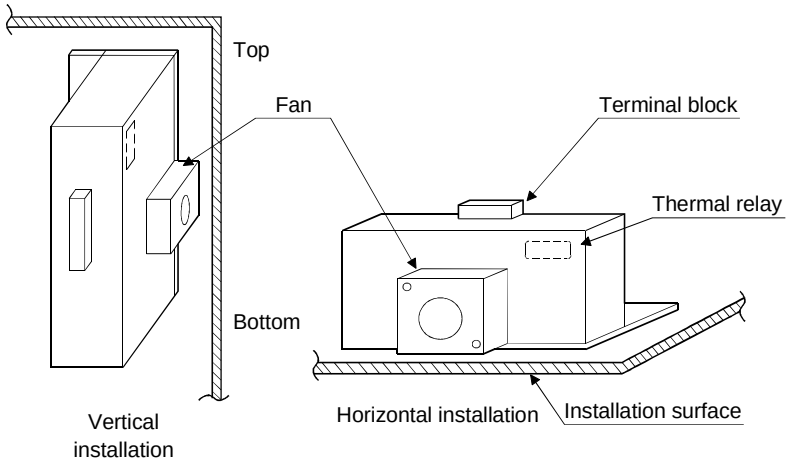


The drawing below shows the MR-J3-500B. For built-in regenerative brake resistor lead terminal fixing screw, refer to Chapter 9.

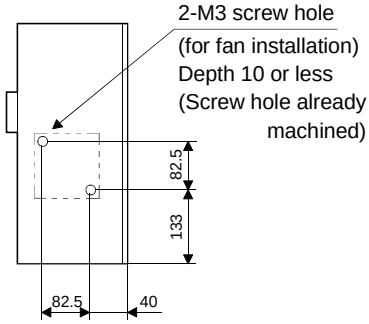


For the MR-RB51 install the cooling fan as shown.

[Unit : mm]



Fan installation screw hole dimensions

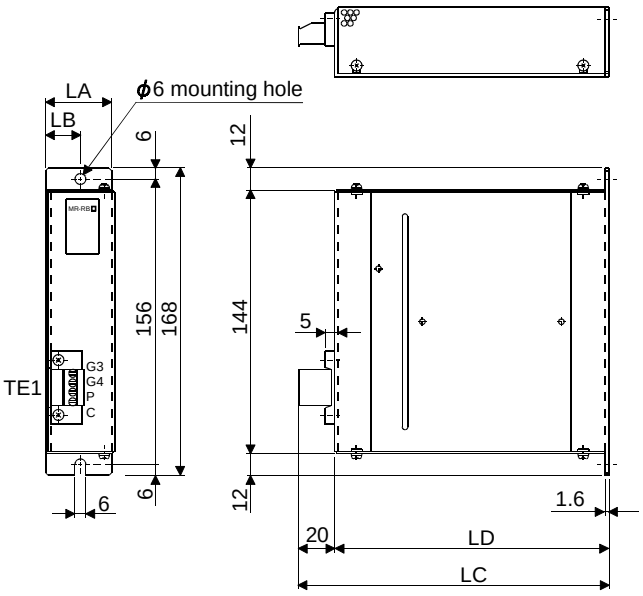


Recommended fan:
Toyo Denki's TL396A or equivalent

(5) Outline dimension drawings

(a) MR-RB032・MR-RB12

[Unit: mm]



・TE1 terminal block

G3
G4
P
C

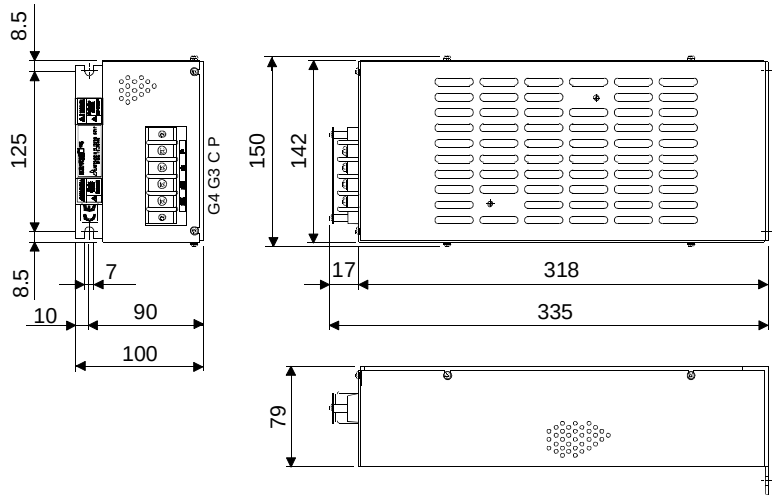
Terminal screw: M3
Tightening torque: 0.5 to 0.6 [N・m] (4 to 5 [lb・in])

・Mounting screw
Screw: M5
Tightening torque: 3.2 [N・m] (28.3 [lb・in])

Regenerative brake option	Variable dimensions				Mass	
	LA	LB	LC	LD	[kg]	[lb]
MR-RB032	30	15	119	99	0.5	1.1
MR-RB12	40	15	169	149	1.1	2.4

(b) MR-RB30・MR-RB31・MR-RB32

[Unit: mm]



・Terminal block

P
C
G3
G4

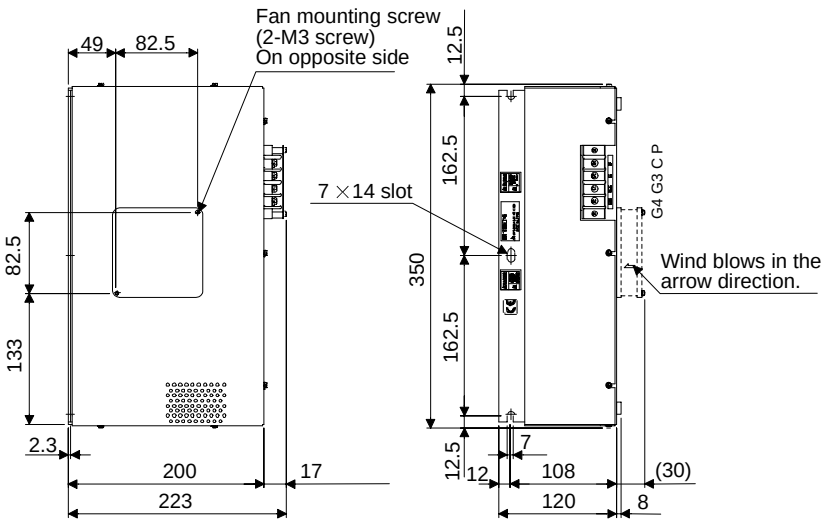
Terminal screw: M4
Tightening torque: 1.2 [N・m] (10 [lb・in])

・Mounting screw
Screw: M6
Tightening torque: 5.4 [N・m]
(47.8 [lb・in])

Regenerative brake option	Mass	
	[kg]	[lb]
MR-RB30	2.9	6.4
MR-RB31		
MR-RB32		

(c) MR-RB50 · MR-RB51

[Unit: mm]



· Terminal block

P
C
G3
G4

Terminal screw: M4
Tightening torque: 1.2 [N·m](10 [lb·in])

· Mounting screw
Screw : M6
Tightening torque: 5.4 [N·m](47.79 [lb·in])

Regenerative brake option	Mass	
	[kg]	[lb]
MR-RB50	5.6	12.3
MR-RB51		

11.3 Brake unit

POINT

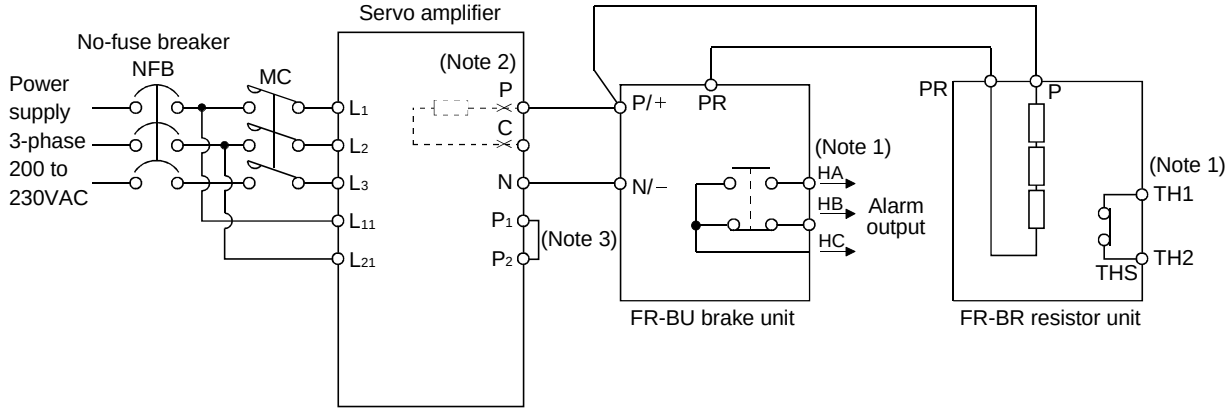
- The brake unit and resistor unit of other than 200V class are not applicable to the servo amplifier.
- The brake unit and resistor unit of the same capacity must be combined. The units of different capacities may result in damage.
- The brake unit and resistor unit must be installed on a vertical surface in the vertical direction. If they are installed in the horizontal direction or on a horizontal surface, a heat dissipation effect reduces.
- The temperature of the resistor unit casing rises to higher than 100°C. Do not cause cables and combustibles to make contact with the casing.

The brake unit is the integration of the regenerative control and resistor and is connected to the bus (across P-N) of the servo amplifier. As compared to the MR-RB regenerative brake option, the brake unit can return larger power. Hence, use the this brake unit when the MR-RB cannot provide sufficient regenerative brake capability.
When using the brake unit, set "☐☐01" in parameter No.PA02.

(1) Selection

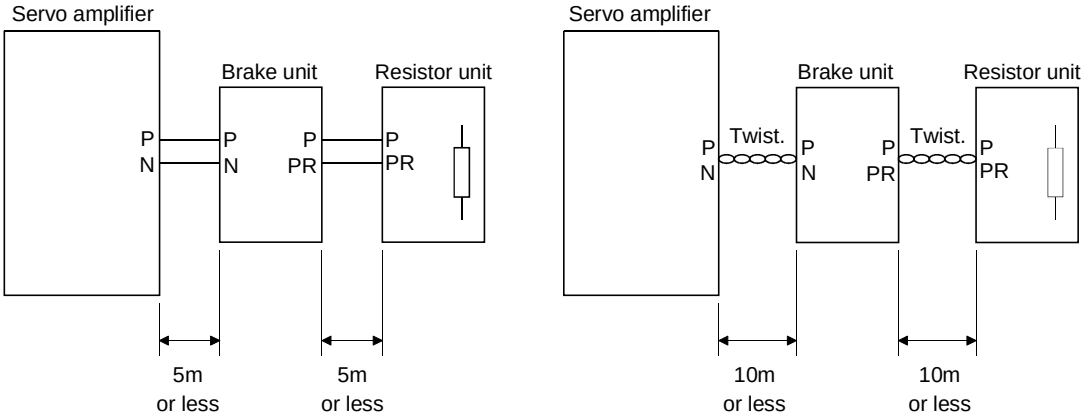
Brake unit	Resistor unit	Permissible Continuous Power [kw]	Max. Instantaneous Power [kw]	Applicable Servo Amplifier
FR-BU-15K	FR-BR-15K	0.99	16.5	MR-J3-500B MR-J3-700B
FR-BU-30K	FR-BR-30K	1.99	33.4	

(2) Connection example



Note 1. Make up the external sequence to switch the power off when an alarm occurs or when the thermal relay is actuated.
2. For sink input-output interface. Refer to Section 3.8.3 for source input-output interface.
3. Always connect P_1-P_2. (Factory-wired.) When using the power factor improving DC reactor, refer to Section 12.10.

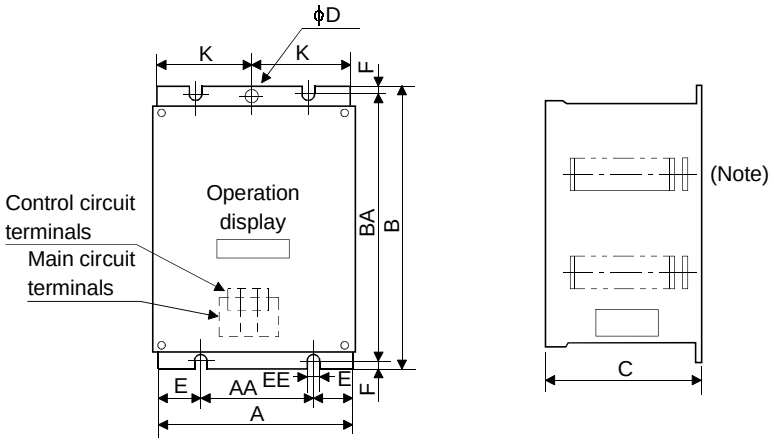
The cables between the servo amplifier and brake unit and between the resistor unit and brake unit should be as short as possible. The cables longer than 5m should be twisted. If twisted, the cables must not be longer than 10m.
The cable size should be equal to or larger than the recommended size. See the brake unit instruction manual. You cannot connect one set of brake unit to two servo amplifiers or two sets of brake units to one servo amplifier.



(3) Outside dimensions

(a) Brake unit (FR-BU)

[Unit : mm]

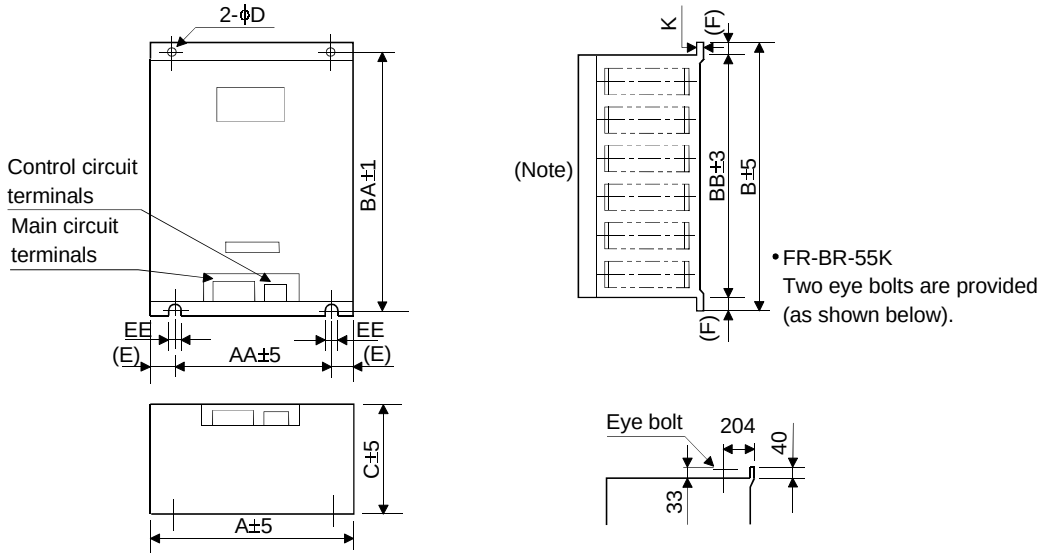


Note: Ventilation ports are provided in both side faces and top face. The bottom face is open.

Brake Unit	A	AA	B	BA	C	D	E	EE	K	F	Approx. Mass [kg(lb)]
FR-BU-15K	100	60	240	225	128	6	18.5	6	48.5	7.5	2.4 (5.291)
FR-BU-30K	160	90	240	225	128	6	33.5	6	78.5	7.5	3.2 (7.055)

(b) Resistor unit (FR-BR)

[Unit : mm]



Note: Ventilation ports are provided in both side faces and top face. The bottom face is open.

Resistor Unit Model	A	AA	B	BA	BB	C	D	E	EE	K	F	Approx. Mass [kg(lb)]
FR-BR-15K	170	100	450	432	410	220	6	35	6	1.6	20	15 (66.139)
FR-BR-30K	340	270	600	582	560	220	10	35	10	2	20	30 (33.069)

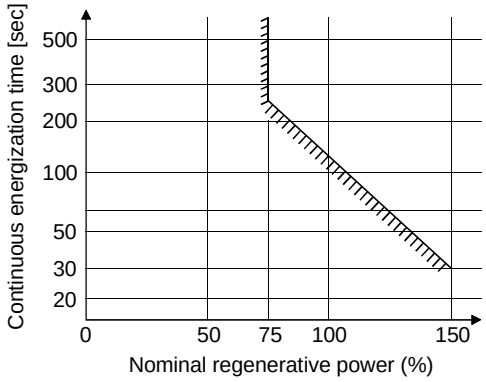
11.4 Power regeneration converter

When using the power regeneration converter, set "□□01" in parameter No.PA02.

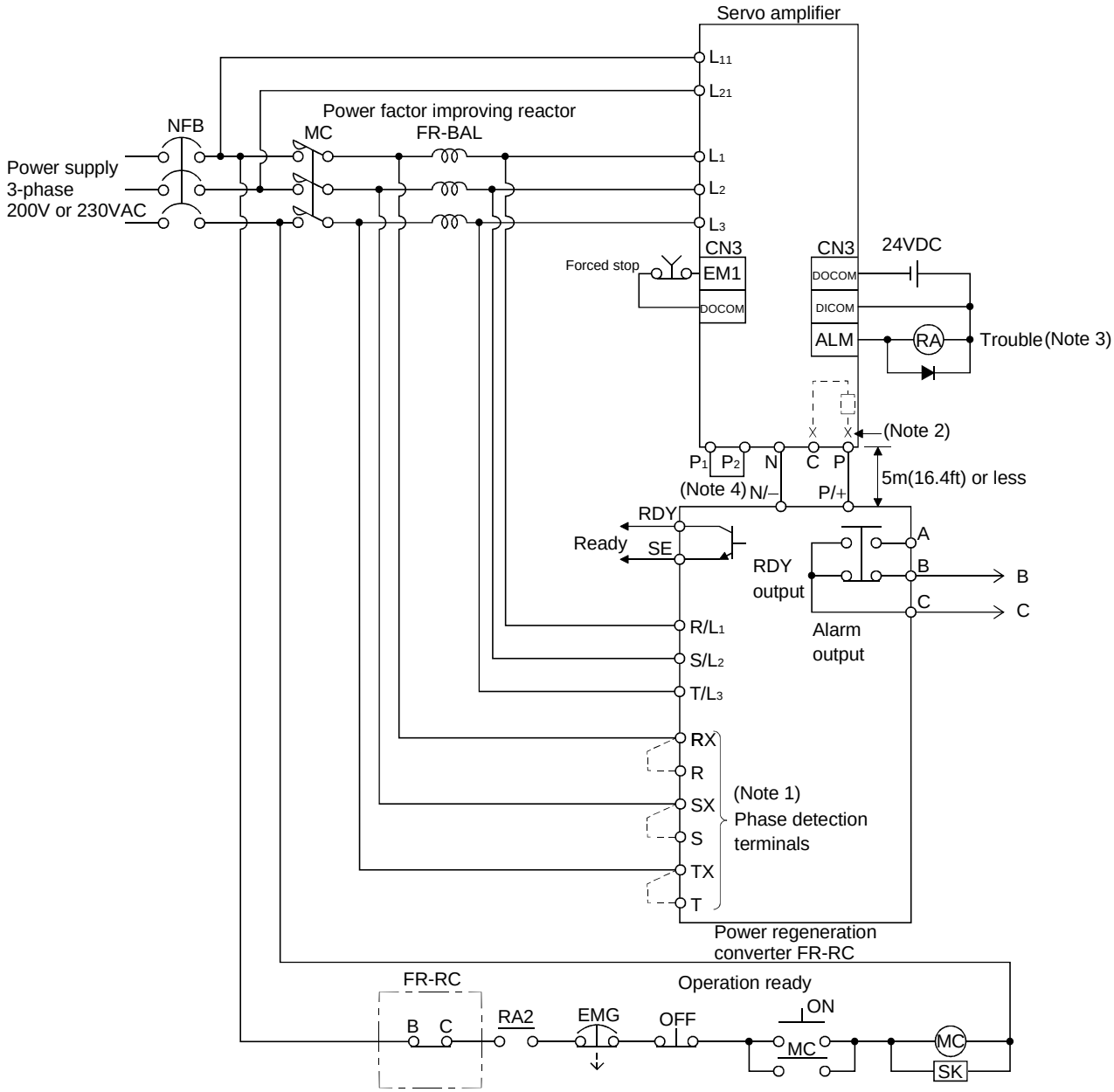
(1) Selection

The converters can continuously return 75% of the nominal regenerative power. They are applied to the servo amplifiers of the MR-J3-500B to MR-J3-700B.

Power regeneration converter	Nominal Regenerative Power (kW)	Servo Amplifier
FR-RC-15	15	MR-J3-500B MR-J3-700B
FR-RC-30	30	



(2) Connection example

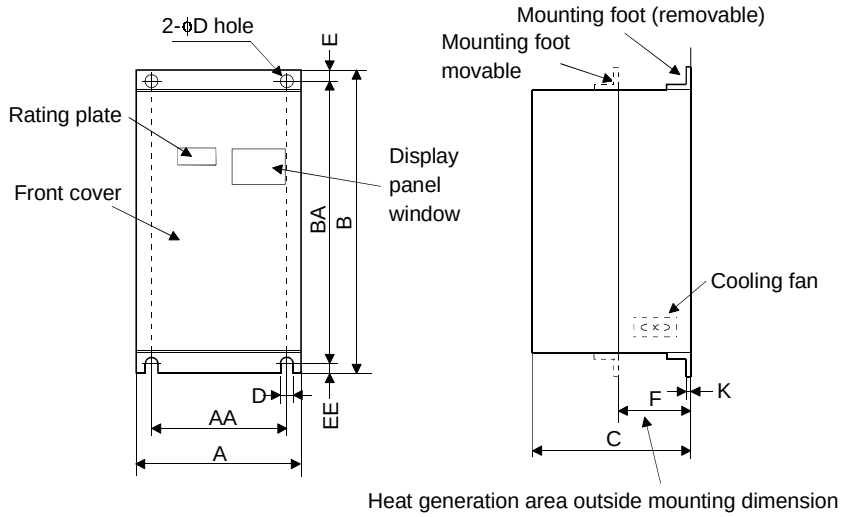


Note 1. When not using the phase detection terminals, fit the jumpers across RX-R, SX-S and TX-T. If the jumpers remain removed, the FR-RC will not operate.

2. When using servo amplifiers of 5kW and 7kW, always remove the lead of built-in regenerative brake resistor connected to P terminal and C terminal.
3. When setting not to output Trouble (ALM) with parameter change, configure power supply circuit for turning magnet contactor off after detecting an occurrence of alarm on the controller side.
4. Always connect P1-P2. (Factory-wired.) When using the power factor improving DC reactor, refer to Section 11.10.

(3) Outside dimensions of the power regeneration converters

[Unit : mm]

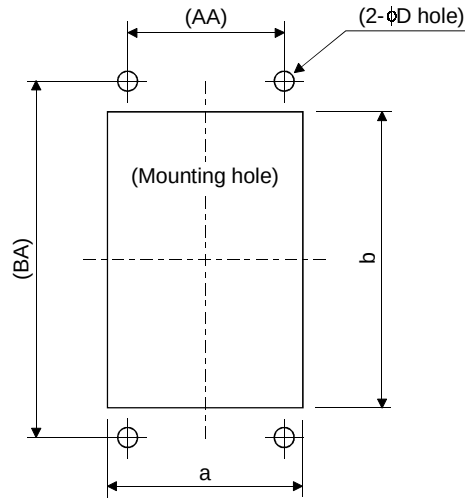


Power regeneration converter	A	AA	B	BA	C	D	E	EE	K	F	Approx. Mass [kg(lb)]
FR-RC-15K	270	200	450	432	195	10	10	8	3.2	87	19 (41.888)
FR-RC-30K	340	270	600	582	195	10	10	8	3.2	90	31 (68.343)

(4) Mounting hole machining dimensions

When the power regeneration converter is fitted to a totally enclosed type box, mount the heat generating area of the converter outside the box to provide heat generation measures. At this time, the mounting hole having the following dimensions is machined in the box.

[Unit : mm]

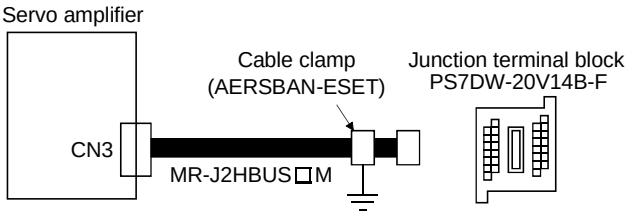


Model	A	B	D	AA	BA
FR-RC-15K	260	412	10	200	432
FR-RC-30K	330	562	10	270	582

11.5 Junction terminal block PS7DW-20V14B-F (Recommended)

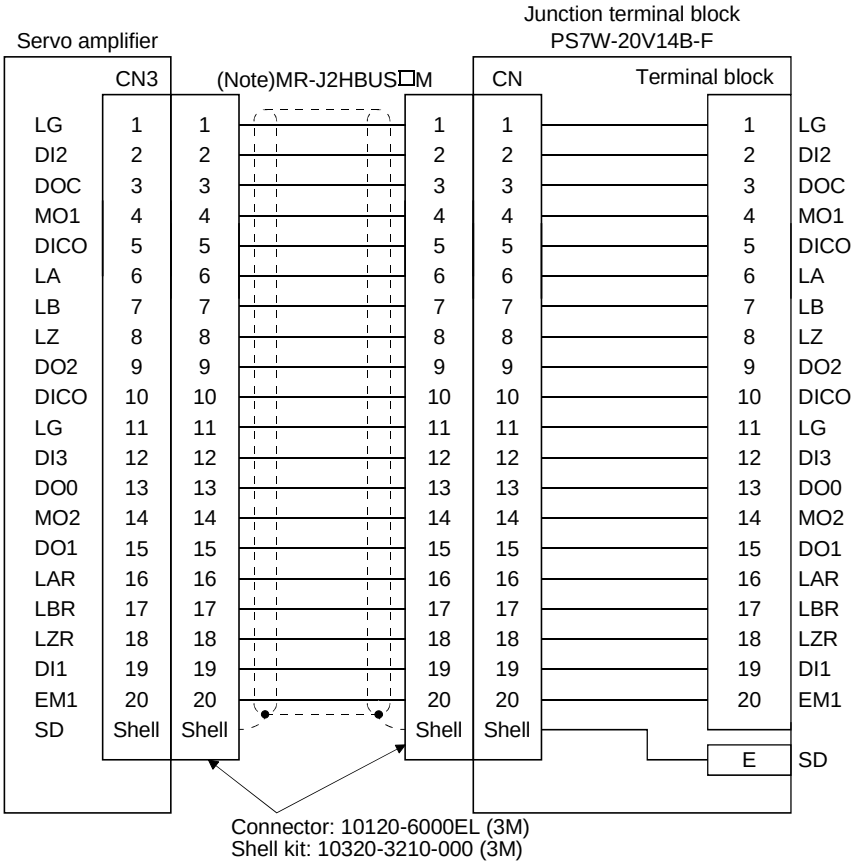
(1) How to use the junction terminal block

Always use the junction terminal block (PS7W-20V14B-F(YOSHIDA ELECTRIC INDUSTRY)) with the option cable (MR-J2HBUS□M) as a set. A connection example is shown below:



Ground the option cable on the junction terminal block side with the cable clamp fitting (AERSBAN-ESET). For the use of the cable clamp fitting, refer to Section 11.14, (2)(c).

(2) Connection of MR-J2HBUS□M cable and junction terminal block



Note. Symbol indicating cable length is put in □.

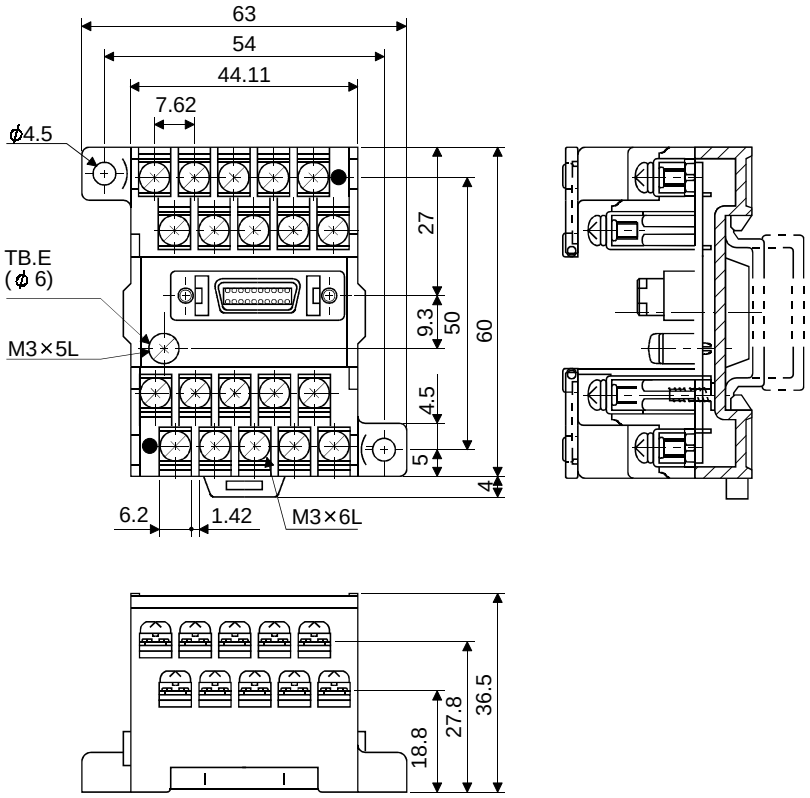
05: 0.5m

1: 1m

5: 5m

(3) Outline drawings of junction terminal block

[Unit : mm]



11.6 MR Configurator

The MR configurator (MRZJW3-SETUP221E) uses the communication function of the servo amplifier to perform parameter setting changes, graph display, test operation, etc. on a personal computer.

(1) Specifications

Item	Description
Monitor	Display, high speed monitor, trend graph Minimum resolution changes with the processing speed of the personal computer.
Alarm	Display, history, amplifier data
Diagnostic	Digital I/O, no motor rotation, total power-on time, amplifier version info, motor information, tuning data, absolute encoder data, Axis name setting.
Parameters	Parameter list, turning, change list, detailed information
Test operation	Jog operation, positioning operation, Do forced output, program operation.
Advanced function	Machine analyzer, gain search, machine simulation.
File operation	Data read, save, print
Others	Automatic demo, help display

(2) System configuration

(a) Components

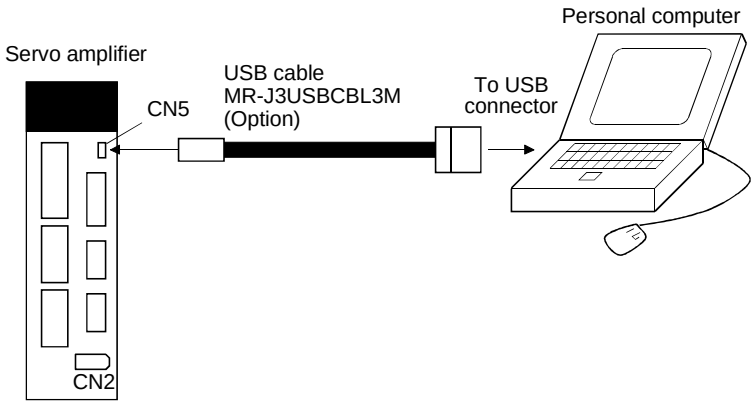
To use this software, the following components are required in addition to the servo amplifier and servo motor:

Model	Description
(Note 2) Personal computer	IBM PC-AT compatible where the English version of Windows® 98, Windows® Me, Windows® 2000 Professional, Windows® XP Professional and Windows® XP Home Edition operates Processor: Pentium® 133MHz or more (Windows® 98, Windows® 2000 Professional) Pentium® 150MHz or more (Windows® Me) Pentium® 300MHz or more (Windows® XP Professional, Windows® XP Home Edition) Memory: 24MB or more (Windows® 98) 32MB or more (Windows® Me, Windows® 2000 Professional) 128MB or more (Windows® XP Professional, Windows® XP Home Edition) Free hard disk space: 130MB or more
OS	Windows® 98, Windows® Me, Windows® 2000 Professional, Windows® XP Professional, Windows® XP Home Edition (English version)
Display	One whose resolution is 800×600 or more and that can provide a high color (16 bit) display. Connectable with the above personal computer.
Keyboard	Connectable with the above personal computer.
Mouse	Connectable with the above personal computer.
Printer	Connectable with the above personal computer.
USB cable	MR-J3USBCBL3M

Note 1. Windows is the registered trademarks of Microsoft Corporation in the United State and other countries.
Pentium is the registered trademarks of Intel Corporation.
2. On some personal computers, this software may not run properly.

(b) Connection with servo amplifier

1) For use of USB



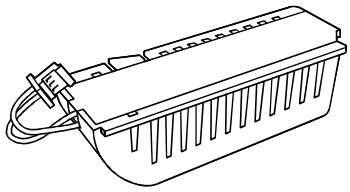
11.7 Battery Unit MR-J3BAT

POINT

- The revision (Edition 44) of the Dangerous Goods Rule of the International Air Transport Association (IATA) went into effect on January 1, 2003 and was enforced immediately. In this rule, "provisions of the lithium and lithium ion batteries" were revised to tighten the restrictions on the air transportation of batteries. However, since this battery is non-dangerous goods (non-Class 9), air transportation of 24 or less batteries is outside the range of the restrictions. Air transportation of more than 24 batteries requires packing compliant with the Packing Standard 903. When a self-certificate is necessary for battery safety tests, contact our branch or representative. For more information, consult our branch or representative. (As of May, 2005).

(1) Purpose of use for MR-J3BAT

This battery is used to construct an absolute position detection system. Refer to Section 12.3 for the fitting method, etc.

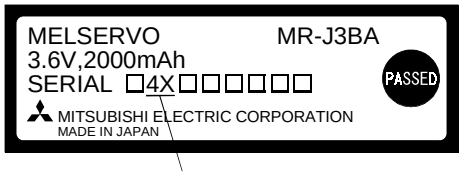


(2) Year and month when MR-J3BAT is manufactured

The year and month when MR-J3BAT is manufactured are written down in Serial No. on the name plate of the battery back face.

The year and month of manufacture are indicated by the last one digit of the year and 1 to 9, X(10), Y(11), Z(12).

For October 2004, the Serial No. is like, "SERIAL □4X□□□□□□".



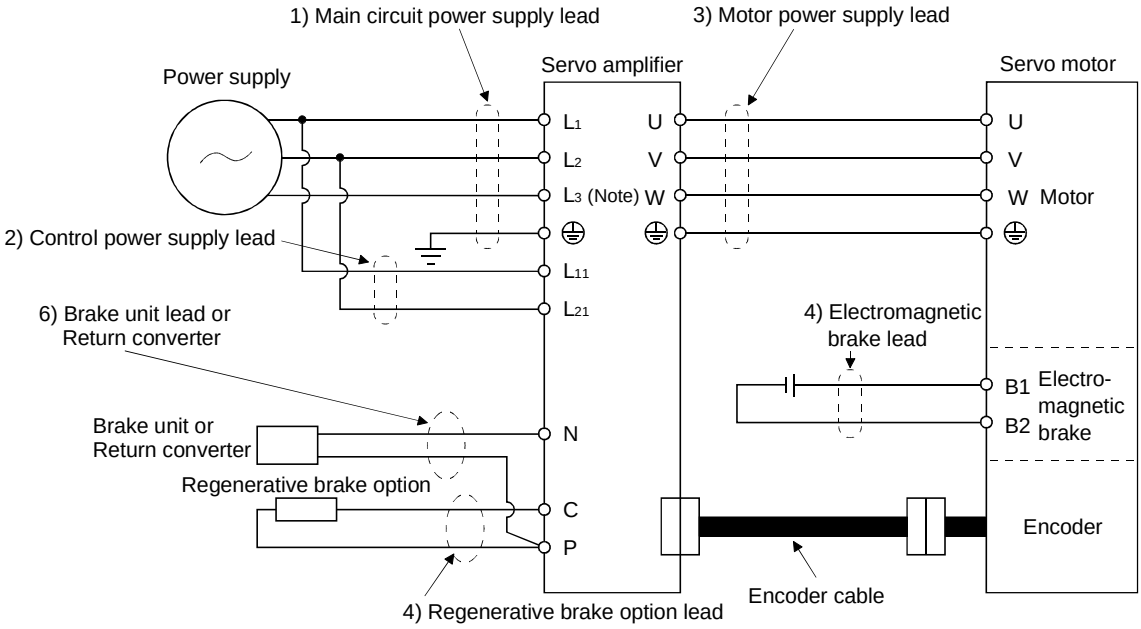
The year and month of manufacture

11.8 Recommended wires

POINT
・Refer to Section 11.1.5 for SSCNETⅢ cable.

(1) Wires for power supply wiring

The following diagram shows the wires used for wiring. Use the wires given in this section or equivalent.



Note. There is no L_3 for 1-phase 100 to 120VAC power supply.

The following table lists wire sizes. The wires used assume that they are 600V vinyl wires and the wiring distance is 30m(98.4ft) max. If the wiring distance is over 30m(98.4ft), choose the wire size in consideration of voltage drop.

To comply with the UL/C-UL (CSA) Standard, use UL-recognized copper wires rated at 60°C (140°F) or more for wiring.

Table 11.1 Recommended wires

Servo amplifier	Wires [mm^2]				
	1) L1・L2・L3・⏚	2) L11・L21	3) U・V・W・⏚	4) P・C	5) B1・B2
MR-J3-10B (1)	2 (AWG14)	1.25 (AWG16)	1.25 (AWG16)	2(AWG14)	1.25 (AWG16)
MR-J3-20B (1)					
MR-J3-40B (1)					
MR-J3-60B					
MR-J3-70B					
MR-J3-100B			2 (AWG14)		
MR-J3-200B	3.5 (AWG12)		3.5 (AWG12)		
MR-J3-350B	5.5 (AWG10)		5.5 (AWG10)		
MR-J3-500B	5.5(AWG10): b(note)		5.5(AWG10): b(note)		
MR-J3-700B	8(AWG8): c(note)		8(AWG8): c(note)	3.5(AWG12): b	

Note. For crimping terminals and applicable tools, refer to Table 11.2.

Use wires 6) of the following sizes with the brake unit (FR-BU) and power regeneration converter (FR-RC).

Model	Wires[mm^2]
FR-BU-15K	3.5(AWG12)
FR-BU-30K	5.5(AWG10)
FR-BU-55K	14(AWG6)
FR-RC-15K	14(AWG6)

Table 11.2 Recommended crimping terminals

Symbol	Servo amplifier side crimping terminals		
	Crimping terminal	Applicable tool	Maker name
a	32959	47387	Tyco Electronics
b	32968	59239	
c	FVD8-5	Body YF-1 E-4 Head YNE-38 Dice DH-111 DH-121	Japan Solderless Terminal

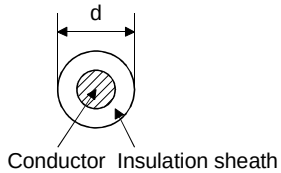
(2) Wires for cables

When fabricating a cable, use the wire models given in the following table or equivalent:

Table 11.3 Wires for option cables

Type	Model	Length [m]	Core size [mm^2]	Number of Cores	Characteristics of one core			(Note 3) Finishing OD [mm]	Wire model
					Structure [Wires/mm]	Conductor resistance [Ω/mm]	Insulation coating ODd [mm] (Note 1)		
Encoder cable	MR-J3ENCBL☐M-A1-L	2 to 10	AWG22	6 (3 pairs)	7/0.26	53 or less	1.2	7.1±0.3	(Note 4) VSVP 7/0.26 (AWG#22 or equivalent)-3P Specification-16823
	MR-J3ENCBL☐M-A2-L								
	MR-J3ENCBL☐M-A1-H	2 to 10	AWG22	6 (3 pairs)	70/0.08	56 or less	1.2	7.1±0.3	(Note 4) ETEF SVP 70/0.08 (AWG#22 or equivalent)-3P Specification-16824
	MR-J3ENCBL☐M-A2-H								
	MR-J3JCBL03M-A1-L	0.3	AWG26	8 (4 pairs)	30/0.08	233 or less	1.2	7.1±0.3	(Note 6) T/2464-1061/II A-SB 4P×26AWG
	MR-J3JCBL03M-A2-L								
	MR-EKCBL☐M-L	2 to 10	0.3mm^2	4 (2 pairs)	12/0.18	65.7 or less	1.3	7.3	(Note 4) 20276 composite 4-pair shielded cable (A-TYPE)
			0.08mm^2	4 (2 pairs)	7/0.127	234 or less	0.67		
		20・30	0.3mm^2	12 (6 pairs)	12/0.18	63.6 or less	1.2	8.2	UL20276 AWG#23 6pair(BLACK)
	MR-EKCBL☐M-H	20	0.2mm^2	12 (6 pairs)	40/0.08	105 or less	0.88	7.2	(Note 3) A14B2343 6P
		30 to 50	0.2mm^2	14 (7 pairs)	40/0.08	105 or less	0.88	8.0	(Note 3) J14B0238(0.2*7P)
	MR-J3ENSCBL☐M-L	2 to 10	AWG22	6 (3 pairs)	7/0.26	53 or less	1.2	7.1±0.3	(Note 4) VSVP 7/0.26 (Equivalent to AWG#22)-3P Ban-gi-shi-16823
		20・30	AWG23	12 (6 pairs)	12/0.18	63.3 or less	1.2	8.2±0.3	(Note 4) 20276 VSVCAWG#23×6P KB-0122
	MR-J3ENSCBL☐M-H	2 to 10	AWG22	6 (3 pairs)	70/0.08	56 or less	1.2	7.1±0.3	(Note 4) ETEF SVP 70/0.08 (Equivalent to AWG#22)-3P Ban-gi-shi-16824
		20 to 50	AWG24	12 (6 pairs)	40/0.08	105 or less	0.88	7.2	(Note 4) ETFE・SVP 40/0.08mm×6P KB-0308
Motor power supply cable	MR-PWS1CBL☐M-A1-L	2 to 10	(Note 7) AWG19	4	50/0.08	25.40 or less	1.8	5.7±0.3	(Note 5) UL Style 2103 AWG19 4 cores
	MR-PWS1CBL☐M-A2-L	2 to 10							
	MR-PWS1CBL☐M-A1-H	2 to 10							
	MR-PWS1CBL☐M-A2-H	2 to 10							
	MR-PWS2CBL03M-A1-L	0.3							
	MR-PWS2CBL03M-A2-L	0.3							
Motor brake cable	MR-BKS1CBL☐M-A1-L	2 to 10	(Note 7) AWG20	2	100/0.08	38.14 or less	1.3	4.0±0.3	(Note 5) UL Style 2103 AWG20 2 cores
	MR-BKS1CBL☐M-A2-L	2 to 10							
	MR-BKS1CBL☐M-A1-H	2 to 10							
	MR-BKS1CBL☐M-A2-H	2 to 10							
	MR-BKS2CBL03M-A1-L	0.3							
	MR-BKS2CBL03M-A2-L	0.3							

Note 1. d is as shown below:



2. Purchased from Toa Electric Industry
3. Standard OD. Max. OD is about 10% greater.
4. Bando Electric Wire
5. Kurabe
6. Taiyo Electric Wire and Cable
7. These wire sizes assume that the UL-compliant wires are used at the wiring length of 10m.

11.9 No-fuse breakers, fuses, magnetic contactors

Always use one no-fuse breaker and one magnetic contactor with one servo amplifier. When using a fuse instead of the no-fuse breaker, use the one having the specifications given in this section.

Servo amplifier	No-fuse breaker	Fuse			Magnetic contactor
		(Note) Class	Current [A]	Voltage [V]	
MR-J3-10B (1)	30A frame 5A	K5	10	AC250	S-N10
MR-J3-20B	30A frame 5A	K5	10		
MR-J3-40B・20B1	30A frame 10A	K5	15		
MR-J3-60B・70B・100B・40B1	30A frame 15A	K5	20		
MR-J3-200B	30A frame 20A	K5	40		S-N18
MR-J3-350B	30A frame 30A	K5	70		S-N20
MR-J3-500B	50A frame 50A	K5	125		S-N35
MR-J3-700B	100A frame 75A	K5	150		S-N50

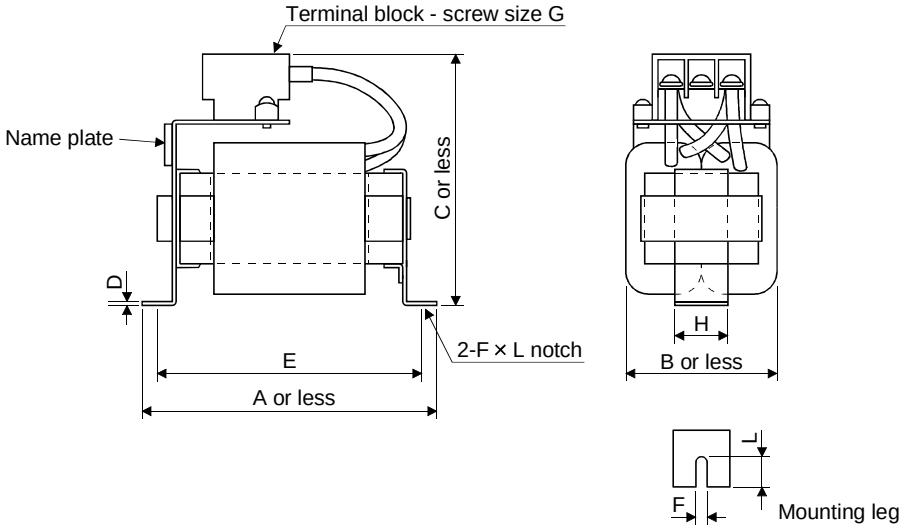
Note. This servo amplifier is UL/C-UL-listed when using a Class T fuse. Therefore, when using the servo amplifier as a UL/C-UL Standard compliant product, be sure to use the Class T fuse.

11.10 Power Factor Improving DC Reactor

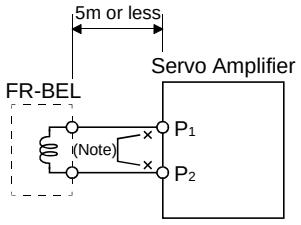
> POINT
> ▪ For the 100VAC power supply type (MR-J3-□B1), the power factor improving DC reactor cannot be used.

The power factor improving DC reactor increases the form factor of the servo amplifier's input current to improve the power factor. It can decrease the power supply capacity. As compared to the power factor improving AC reactor (FR-BAL), it can decrease the loss. The input power factor is improved to about 95%.
It is also effective to reduce the input side harmonics.
When connecting the power factor improving DC reactor to the servo amplifier, always disconnect the wiring across P1-P2. If it remains connected, the effect of the power factor improving DC reactor is not produced.
When used, the power factor improving DC reactor generates heat. To release heat, therefore, leave a 10cm or more clearance at each of the top and bottom, and a 5cm or more clearance on each side.

[Unit: mm]



Servo Amplifier	Power Factor Improving DC Reactor	Dimensions [mm]									Mounting Screw Size	Mass [kg(lb)]	Used Power Supply [mm²]
		A	B	C	D	E	F	L	G	H			
MR-J3-10B ▪ 20B	FR-BEL-0.4K	110	50	94	1.6	95	6	12	M3.5	25	M5	0.5 (1.10)	2 (AWG14)
MR-J3-40B	FR-BEL-0.75K	120	53	102	1.6	105	6	12	M4	25	M5	0.7 (1.54)	
MR-J3-60B ▪ 70B	FR-BEL-1.5K	130	65	110	1.6	115	6	12	M4	30	M5	1.1 (2.43)	
MR-J3-100B	FR-BEL-2.2K	130	65	110	1.6	115	6	12	M4	30	M5	1.2 (2.43)	
MR-J3-200B	FR-BEL-3.7K	150	75	102	2.0	135	6	12	M4	40	M5	1.7 (3.75)	3.5 (AWG12)
MR-J3-350B	FR-BEL-7.5K	150	75	126	2.0	135	6	12	M5	40	M5	2.3 (5.07)	5.5 (AWG10)
MR-J3-500B	FR-BEL-11K	170	93	132	2.3	155	6	14	M5	50	M5	3.1 (6.84)	5.5(AWG10)
MR-J3-700B	FR-BEL-15K	170	93	170	2.3	155	6	14	M8	56	M5	3.8 (8.38)	8(AWG8)

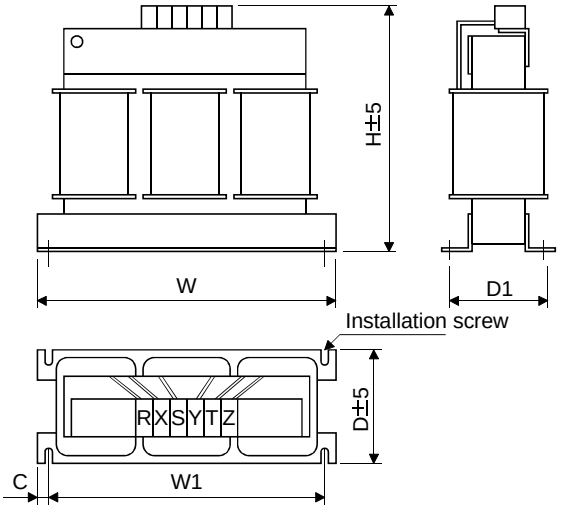


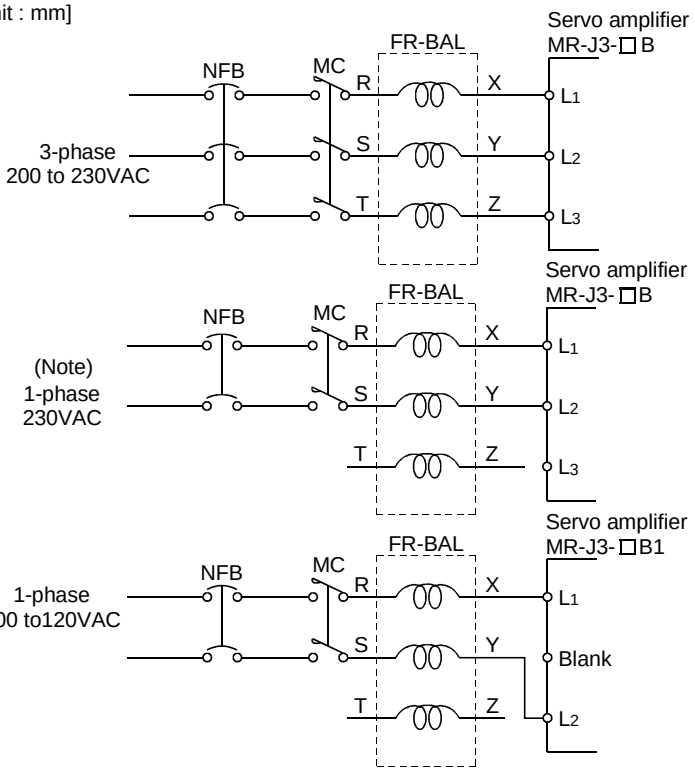
Note. When using the power factor improving DC reactor, disconnect the wiring across P_1-P_2.

11.11 Power factor improving reactors

The power factor improving reactors improve the phase factor by increasing the form factor of servo amplifier's input current.
It can reduce the power capacity.
The input power factor is improved to be about 90%. For use with a 1-phase power supply, it may be slightly lower than 90%.
In addition, it reduces the higher harmonic of input side.
When using power factor improving reactors for two servo amplifiers or more, be sure to connect a power factor improving reactor to each servo amplifier.
If using only one power factor improving reactor, enough improvement effect of phase factor cannot be obtained unless all servo amplifiers are operated.

[Unit : mm]





Note. For the 1-phase 230V power supply, Connect the power supply to L1, L2 and leave L3 open.

Servo amplifier	Model	Dimensions [mm]						Mounting screw size	Terminal screw size	Mass [kg (lb)]
		W	W1	H	D	D1	C			
MR-J3-10B/20B/10B1	FR-BAL-0.4K	135	120	115	59	$45^{0}_{-2.5}$	7.5	M4	M3.5	2.0 (4.4)
MR-J3-40B/20B1	FR-BAL-0.75K	135	120	115	69	$57^{0}_{-2.5}$	7.5	M4	M3.5	2.8 (6.17)
MR-J3-60B/70B/40B1	FR-BAL-1.5K	160	145	140	71	$55^{0}_{-2.5}$	7.5	M4	M3.5	3.7 (8.16)
MR-J3-100B	FR-BAL-2.2K	160	145	140	91	$75^{0}_{-2.5}$	7.5	M4	M3.5	5.6 (12.35)
MR-J3-200B	FR-BAL-3.7K	220	200	192	90	70±5	10	M5	M4	8.5 (18.74)
MR-J3-350B	FR-BAL-7.5K	220	200	194	120	100±5	10	M5	M5	14.5 (32.0)
MR-J3-500B	FR-BAL-11K	280	255	220	135	100	12.5	M6	M6	19 (41.9)
MR-J3-700B	FR-BAL-15K	295	270	275	133	110	12.5	M6	M6	27 (59.5)

11.12 Relays (Recommended)

The following relays should be used with the interfaces:

Interface	Selection example
Relay used for digital input command signals (interface DI-1)	To prevent defective contacts , use a relay for small signal (twin contacts). (Ex.) Omron : type G2A , MY
Relay used for digital output signals (interface DO-1)	Small relay with 12VDC or 24VDC of 40mA or less (Ex.) Omron : type MY

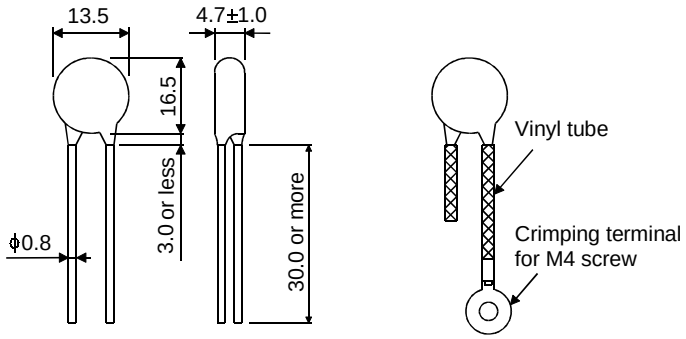
11.13 Surge absorbers (Recommended)

A surge absorber is required for the electromagnetic brake. Use the following surge absorber or equivalent. Insulate the wiring as shown in the diagram.

Maximum rating					Maximum limit voltage		Static capacity (reference value)	Varistor voltage rating (range) V1mA
Permissible circuit voltage		Surge immunity	Energy immunity	Rated power				
AC[Vma]	DC[V]	[A]	[J]	[W]	[A]	[V]	[pF]	[V]
140	180	(Note) 500/time	5	0.4	25	360	300	220 (198 to 242)

Note. 1 time = 8 × 20μs

(Example) ERZV10D221 (Matsushita Electric Industry)
TNR-10V221K (Nippon chemi-con)
Outline drawing [mm] (ERZ-C10DK221)



11.14 Noise reduction techniques

Noises are classified into external noises which enter the servo amplifier to cause it to malfunction and those radiated by the servo amplifier to cause peripheral devices to malfunction. Since the servo amplifier is an electronic device which handles small signals, the following general noise reduction techniques are required. Also, the servo amplifier can be a source of noise as its outputs are chopped by high carrier frequencies. If peripheral devices malfunction due to noises produced by the servo amplifier, noise suppression measures must be taken. The measures will vary slightly with the routes of noise transmission.

(1) Noise reduction techniques

(a) General reduction techniques

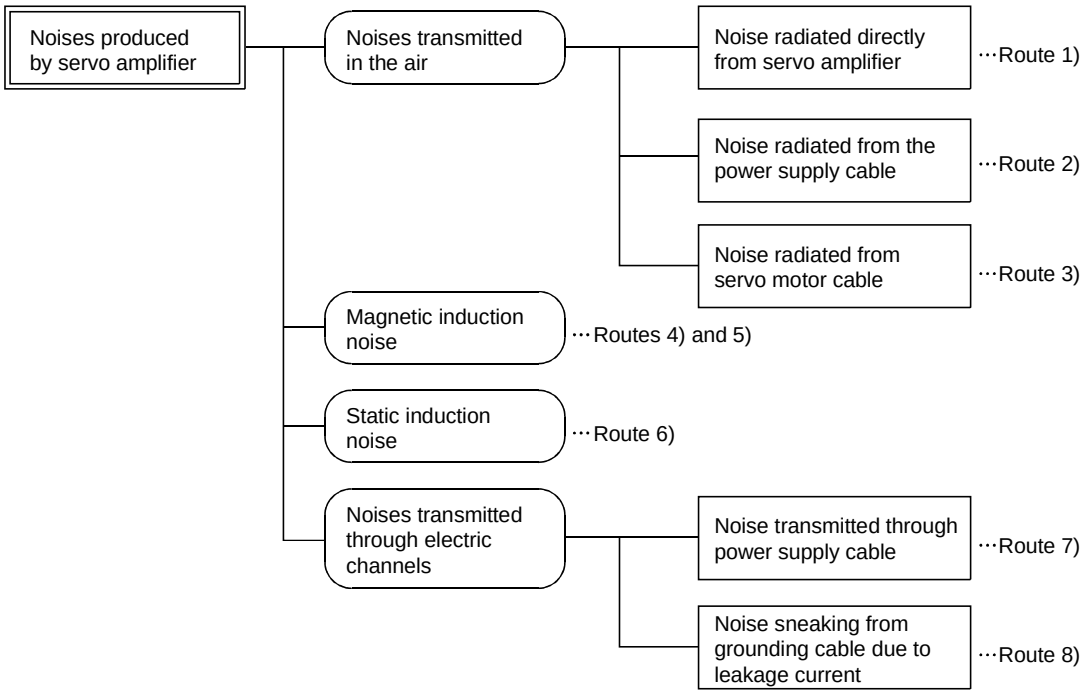
- Avoid laying power lines (input and output cables) and signal cables side by side or do not bundle them together. Separate power lines from signal cables.
- Use shielded, twisted pair cables for connection with the encoder and for control signal transmission, and connect the shield to the SD terminal.
- Ground the servo amplifier, servo motor, etc. together at one point (refer to Section 3.12).

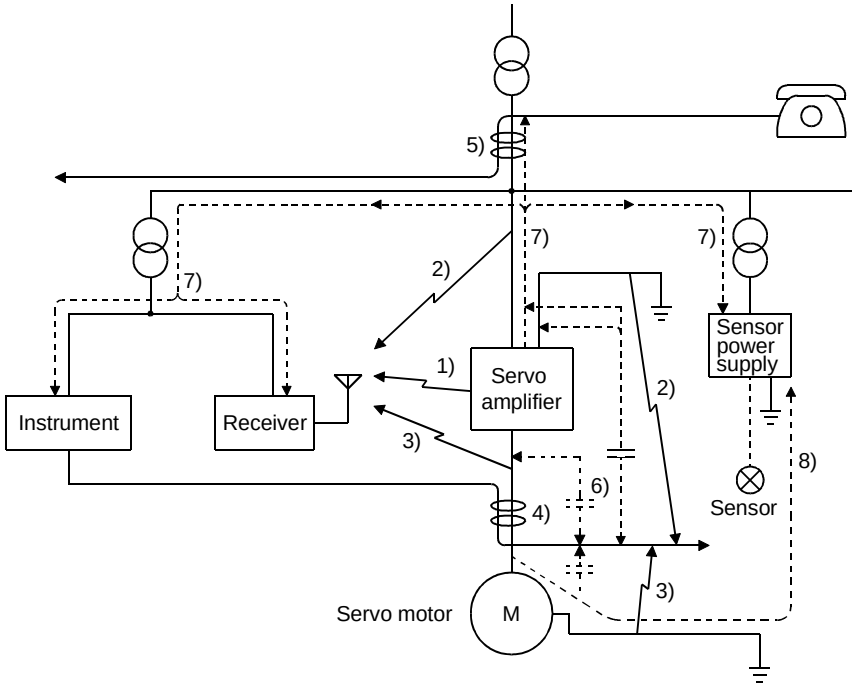
(b) Reduction techniques for external noises that cause the servo amplifier to malfunction

If there are noise sources (such as a magnetic contactor, an electromagnetic brake, and many relays which make a large amount of noise) near the servo amplifier and the servo amplifier may malfunction, the following countermeasures are required.

- Provide surge absorbers on the noise sources to suppress noises.
- Attach data line filters to the signal cables.
- Ground the shields of the encoder connecting cable and the control signal cables with cable clamp fittings.

(c) Techniques for noises radiated by the servo amplifier that cause peripheral devices to malfunction
Noises produced by the servo amplifier are classified into those radiated from the cables connected to the servo amplifier and its main circuits (input and output circuits), those induced electromagnetically or statically by the signal cables of the peripheral devices located near the main circuit cables, and those transmitted through the power supply cables.





Noise transmission route	Suppression techniques
1) 2) 3)	When measuring instruments, receivers, sensors, etc. which handle weak signals and may malfunction due to noise and/or their signal cables are contained in a control box together with the servo amplifier or run near the servo amplifier, such devices may malfunction due to noises transmitted through the air. The following techniques are required. 1. Provide maximum clearance between easily affected devices and the servo amplifier. 2. Provide maximum clearance between easily affected signal cables and the I/O cables of the servo amplifier. 3. Avoid laying the power lines (Input cables of the servo amplifier) and signal cables side by side or bundling them together. 4. Insert a line noise filter to the I/O cables or a radio noise filter on the input line. 5. Use shielded wires for signal and power cables or put cables in separate metal conduits.
4) 5) 6)	When the power lines and the signal cables are laid side by side or bundled together, magnetic induction noise and static induction noise will be transmitted through the signal cables and malfunction may occur. The following techniques are required. 1. Provide maximum clearance between easily affected devices and the servo amplifier. 2. Provide maximum clearance between easily affected signal cables and the I/O cables of the servo amplifier. 3. Avoid laying the power lines (I/O cables of the servo amplifier) and signal cables side by side or bundling them together. 4. Use shielded wires for signal and power cables or put the cables in separate metal conduits.
7)	When the power supply of peripheral devices is connected to the power supply of the servo amplifier system, noises produced by the servo amplifier may be transmitted back through the power supply cable and the devices may malfunction. The following techniques are required. 1. Insert the radio noise filter (FR-BIF) on the power cables (Input cables) of the servo amplifier. 2. Insert the line noise filter (FR-BSF01・FR-BLF) on the power cables of the servo amplifier.
8)	When the cables of peripheral devices are connected to the servo amplifier to make a closed loop circuit, leakage current may flow to malfunction the peripheral devices. If so, malfunction may be prevented by disconnecting the grounding cable of the peripheral device.

(2) Noise reduction products

(a) Data line filter (Recommended)

Noise can be prevented by installing a data line filter onto the encoder cable, etc.

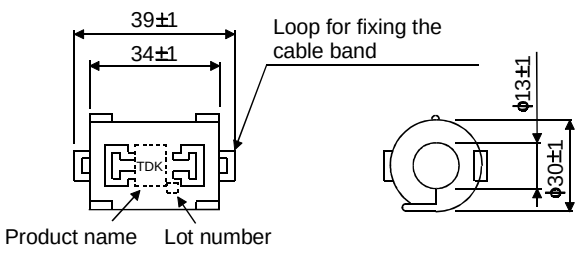
For example, the ZCAT3035-1330 of TDK and the ESD-SR-25 of NEC TOKIN make are available as data line filters.

As a reference example, the impedance specifications of the ZCAT3035-1330 (TDK) are indicated below.

This impedances are reference values and not guaranteed values.

Impedance[Ω]	
10 to 100MHz	100 to 500MHz
80	150

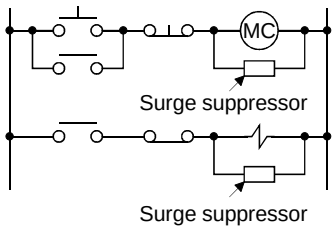
[Unit: mm]

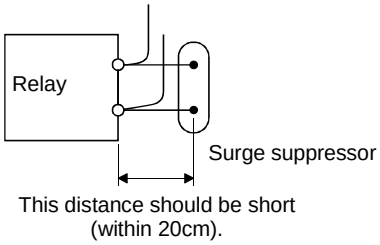


Outline drawing (ZCAT3035-1330)

(b) Surge suppressor

The recommended surge suppressor for installation to an AC relay, AC valve, AC electromagnetic brake or the like near the servo amplifier is shown below. Use this product or equivalent.

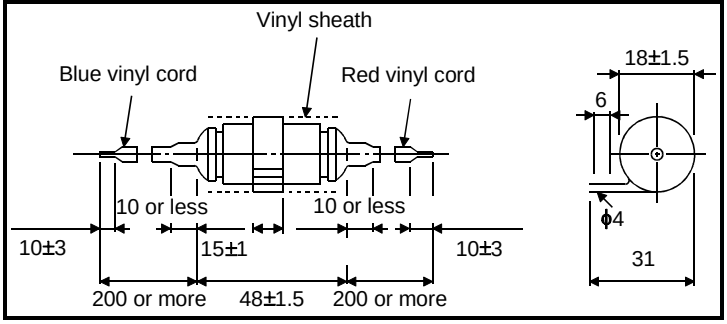




(Ex.) 972A.2003 50411
(Matsuo Electric Co.,Ltd.−200VAC rating)

Rated voltage AC[V]	C [μF]	R [Ω]	Test voltage AC[V]
200	0.5	50 (1W)	Across T-C 1000(1 to 5s)

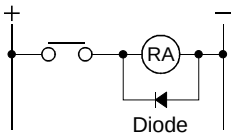
Outline drawing [Unit: mm]



Note that a diode should be installed to a DC relay, DC valve or the like.

Maximum voltage: Not less than 4 times the drive voltage of the relay or the like

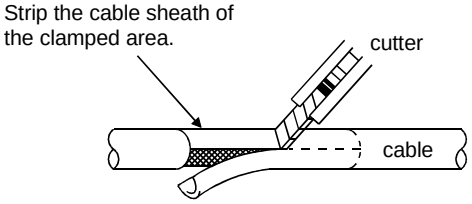
Maximum current: Not less than twice the drive current of the relay or the like

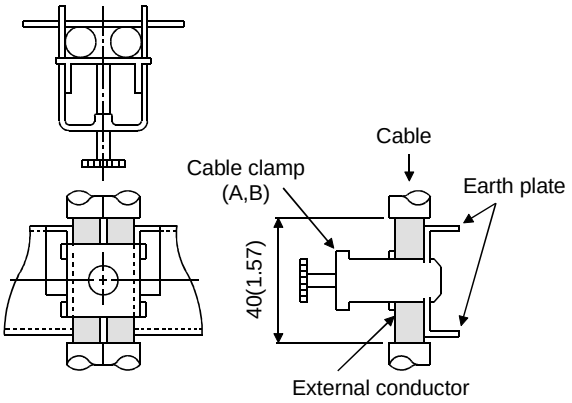


(c) Cable clamp fitting AERSBAN□-SET

Generally, the earth of the shielded cable may only be connected to the connector's SD terminal. However, the effect can be increased by directly connecting the cable to an earth plate as shown below. Install the earth plate near the servo amplifier for the encoder cable. Peel part of the cable sheath to expose the external conductor, and press that part against the earth plate with the cable clamp. If the cable is thin, clamp several cables in a bunch.

The clamp comes as a set with the earth plate.



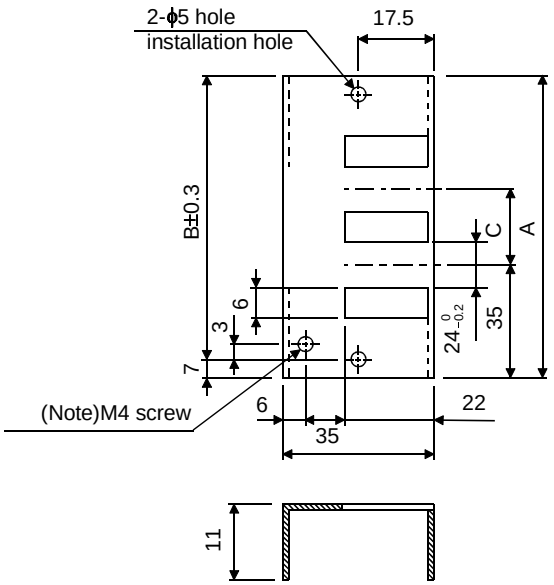


Clamp section diagram

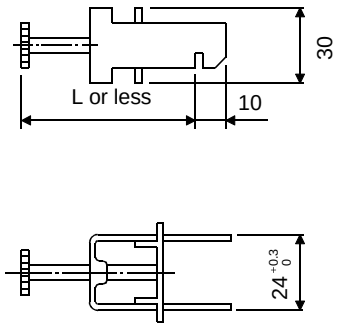
- Outline drawing

[Unit: mm]

Earth plate



Clamp section diagram



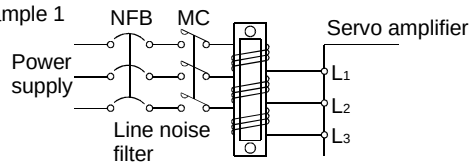
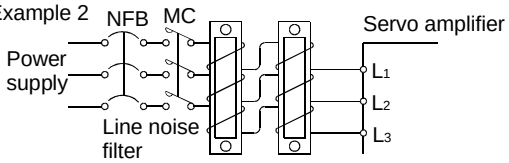
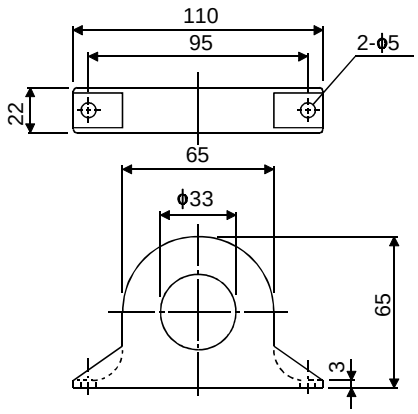
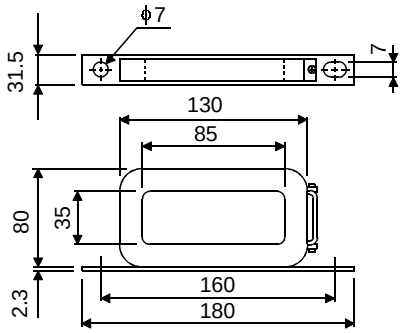
Note. Screw hole for grounding. Connect it to the earth plate of the control box.

Type	A	B	C	Accessory fittings
AERSBAN-DSET	100	86	30	clamp A: 2pcs.
AERSBAN-ESET	70	56		clamp B: 1pc.

Clamp fitting	L
A	70
B	45

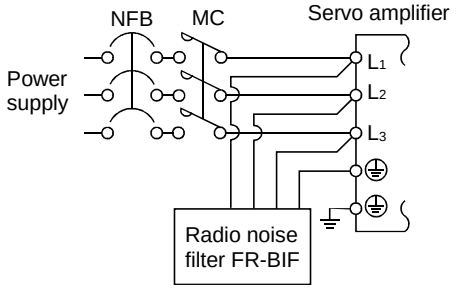
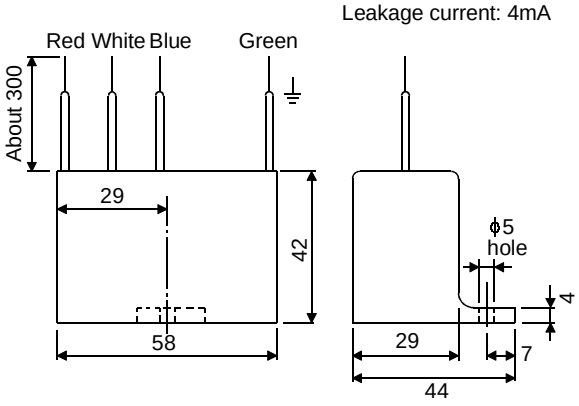
(d) Line noise filter (FR-BSF01, FR-BLF)

This filter is effective in suppressing noises radiated from the power supply side and output side of the servo amplifier and also in suppressing high-frequency leakage current (zero-phase current) especially within 0.5MHz to 5MHz band.

Connection diagram	Outline drawing [Unit: mm]
Wind the 3-phase wires by the equal number of times in the same direction, and connect the filter to the power supply side and output side of the servo amplifier. The effect of the filter on the power supply side is higher as the number of winds is larger. The number of turns is generally four. If the wires are too thick to be wound, use two or more filters and make the total number of turns as mentioned above. On the output side, the number of turns must be four or less. Do not wind the grounding wire together with the 3-phase wires. The filter effect will decrease. Use a separate wire for grounding. Example 1  (Number of turns: 4) Example 2  Two filters are used (Total number of turns: 4)	FR-BSF01 (for MR-J3-200B or less)  FR-BLF(MR-J3-350B or more) 

(e) Radio noise filter FR-BIF

This filter is effective in suppressing noises radiated from the power supply side of the servo amplifier especially in 10MHz and lower radio frequency bands. The FR-BIF is designed for the input only.

Connection diagram	Outline drawing (Unit: mm)
Make the connection cables as short as possible. Grounding is always required. When using the FR-BIF with a single-phase wire, always insulate the wires that are not used for wiring.  	Leakage current: 4mA 

11.15 Leakage current breaker

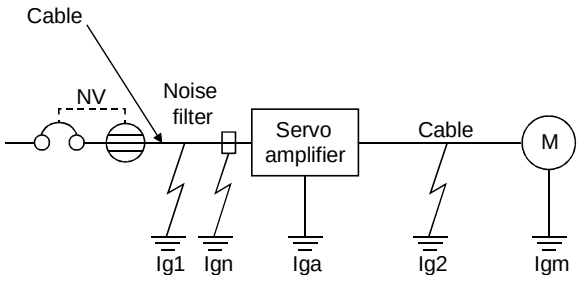
(1) Selection method

High-frequency chopper currents controlled by pulse width modulation flow in the AC servo circuits. Leakage currents containing harmonic contents are larger than those of the motor which is run with a commercial power supply.

Select a leakage current breaker according to the following formula, and ground the servo amplifier, servo motor, etc. securely.

Make the input and output cables as short as possible, and also make the grounding cable as long as possible (about 30cm (11.8 in)) to minimize leakage currents.

Rated sensitivity current ≥ 10 · {Ig1+Ign+Iga+K · (Ig2+Igm)} [mA].....(11.2)



K: Constant considering the harmonic contents

Leakage current breaker		K
Type	Mitsubishi products	
Models provided with harmonic and surge reduction techniques	NV-SP NV-SW NV-CP NV-CW NV-L	1
General models	BV-C1 NFB NV-L	3

Ig1: Leakage current on the electric channel from the leakage current breaker to the input terminals of the servo amplifier (Found from Fig. 11.1.)

Ig2: Leakage current on the electric channel from the output terminals of the servo amplifier to the servo motor (Found from Fig. 11.1.)

Ign: Leakage current when a filter is connected to the input side (4.4mA per one FR-BIF)

Iga: Leakage current of the servo amplifier (Found from Table 11.5.)

Igm: Leakage current of the servo motor (Found from Table 11.4.)

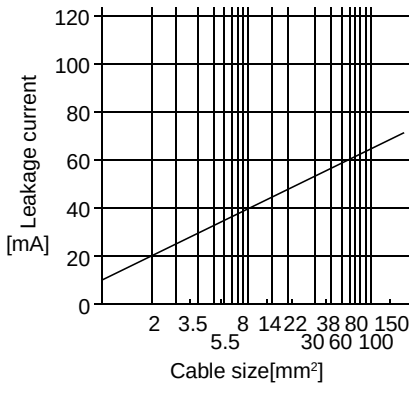


Fig. 11.1 Leakage current example (Ig1, Ig2) for CV cable run in metal conduit

Table 11.4 Servo motor's leakage current example (Igm)

Servo motor output [kW]	Leakage current [mA]
0.05 to 1	0.1
2	0.2
3.5	0.3
5	0.5
7	0.7

Table 11.5 Servo amplifier's leakage current example (Iga)

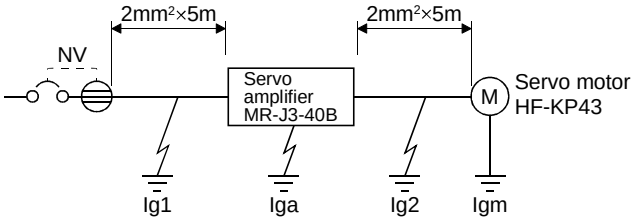
Servo amplifier capacity [kW]	Leakage current [mA]
0.1 to 0.6	0.1
0.75 to 3.5	0.15
5 · 7	2

Table 11.6 Leakage circuit breaker selection example

Servo amplifier	Rated sensitivity current of leakage circuit breaker [mA]
MR-J3-10B to MR-J3-350B MR-J3-10B1 to MR-J3-40B1	15
MR-J3-500B	30
MR-J3-700B	50

(2) Selection example

Indicated below is an example of selecting a leakage current breaker under the following conditions:



Use a leakage current breaker generally available.

Find the terms of Equation (11.2) from the diagram:

$$Ig1 = 20 \cdot \frac{5}{1000} = 0.1 \text{ [mA]}$$

$$Ig2 = 20 \cdot \frac{5}{1000} = 0.1 \text{ [mA]}$$

$Ign = 0$ (not used)

$Iga = 0.1$ [mA]

$Igm = 0.1$ [mA]

Insert these values in Equation (11.2):

$$Ig \geq 10 \cdot \{0.1+0+0.1+1 \cdot (0.1+0.1)\}$$

$$\geq 4.0 \text{ [mA]}$$

According to the result of calculation, use a leakage current breaker having the rated sensitivity current (Ig) of 4.0[mA] or more. A leakage current breaker having Ig of 15[mA] is used with the NV-SP/SW/CP/CW/HW series.

11.16 EMC filter (Recommended)

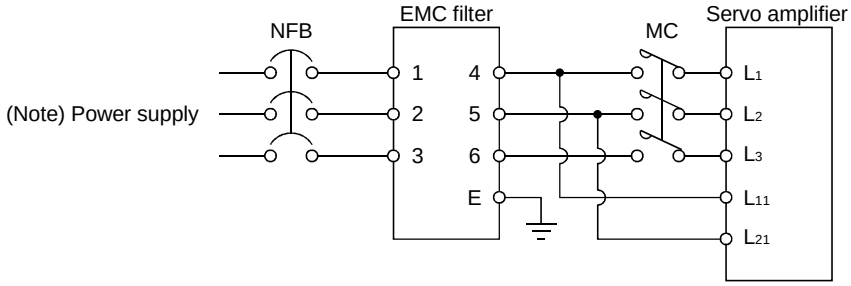
For compliance with the EMC directive of the EN Standard, it is recommended to use the following filter: Some EMC filters are large in leakage current.

(1) Combination with the servo amplifier

Servo amplifier	Recommended filter		Mass [kg]([lb])
	Model	Leakage current [mA]	
MR-J3-10B to MR-J3-100B MR-J3-10B1 to MR-J3-40B1	(Note) HF3010A-UN	5	3 (6.61)
MR-J3-250B ▪ MR-J3-350B	(Note) HF3030A-UN	5	5.5 (12.13)
MR-J3-500B ▪ MR-J3-700B	(Note) HF3040A-UN	1.5	6.0 (13.23)

Note. Soshin Electric A surge protector is separately required to use any of these EMC filters. (Refer to the EMC Installation Guidelines.)

(2) Connection example

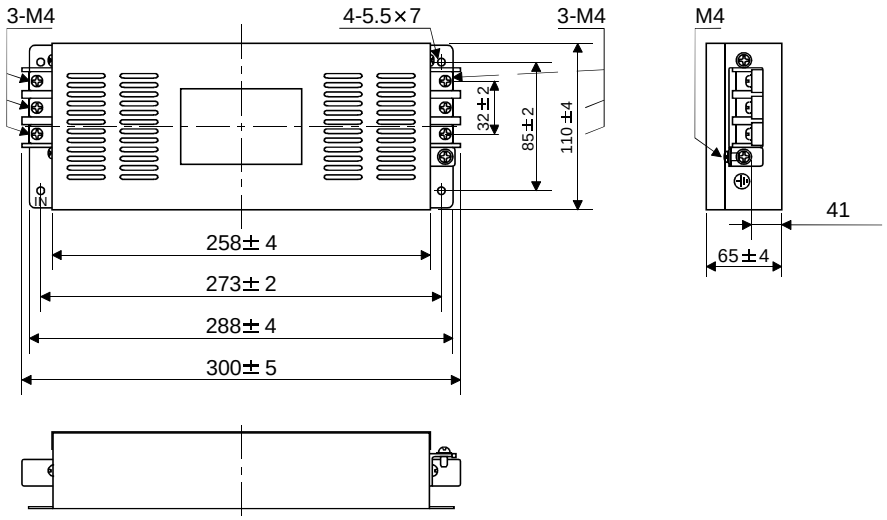


Note. For 1-phase 230VAC power supply, connect the power supply to L_1,L_2 and leave L_3 open.
There is no L_3 for 1-phase 100 to 120VAC power supply.

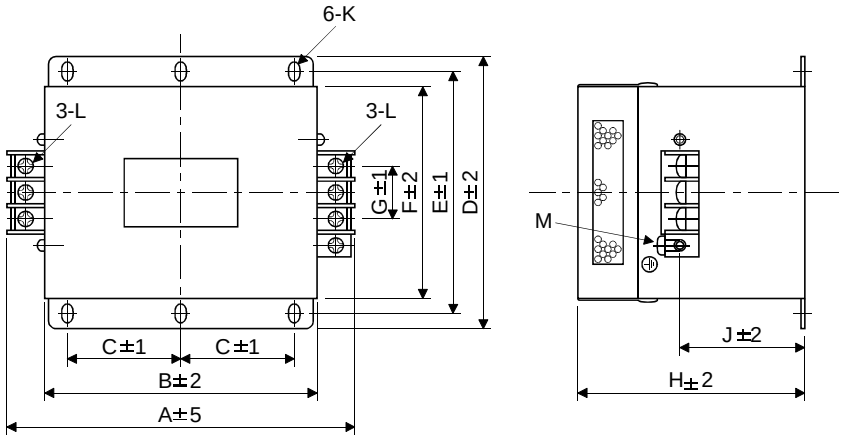
(3) Outline drawing

HF3010A-UN

[Unit: mm]



HF3030A-UN · HF-3040A-UN



Model	Dimensions [mm]											
	A	B	C	D	E	F	G	H	J	K	L	M
HF3030A-UN	260	210	85	155	140	125	44	140	70	R3.25, length 8	M5	M4
HF3040A-UN	260	210	85	155	140	125	44	140	70		M5	M4

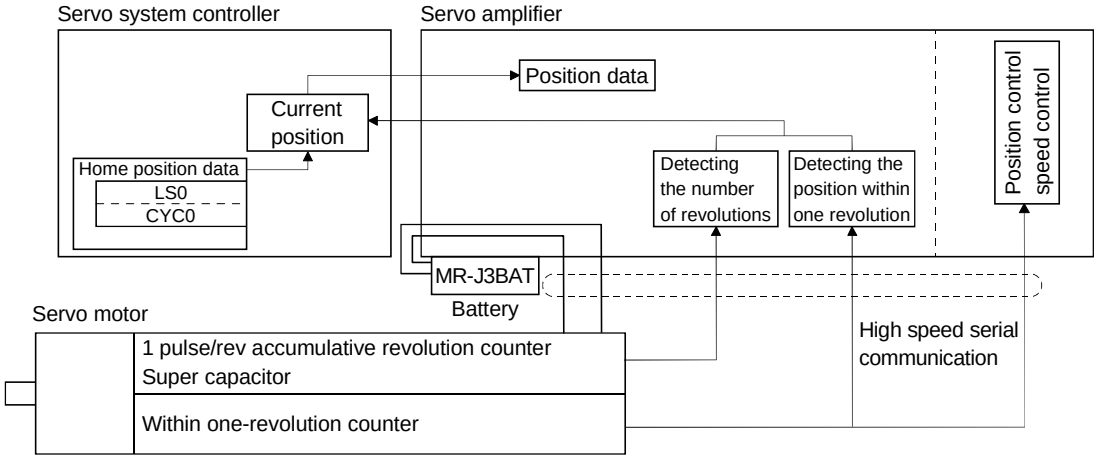
MEMO

12. ABSOLUTE POSITION DETECTION SYSTEM

⚠ CAUTION	▪ If an absolute position erase alarm (25) or absoluto position counter warning (E3) has occurred, always perform home position setting again. Not doing so can cause runaway.

12.1 Features

For normal operation, as shown below, the encoder consists of a detector designed to detect a position within one revolution and a cumulative revolution counter designed to detect the number of revolutions.
The absolute position detection system always detects the absolute position of the machine and keeps it battery-backed, independently of whether the servo system controller power is on or off.
Therefore, once home position return is made at the time of machine installation, home position return is not needed when power is switched on thereafter.
If a power failure or a fault occurs, restoration is easy.



12.2 Specifications

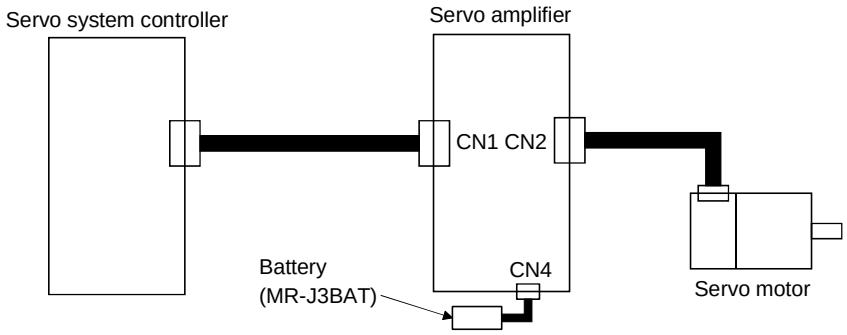
POINT
▪ Replace the battery with only the control circuit power ON. Removal of the battery with the control circuit power OFF will erase the absolute position data.

(1) Specification list

Item	Description
System	Electronic battery backup system
Battery	1 piece of lithium battery (primary battery, nominal + 3.6V) Type: MR-J3BAT
Maximum revolution range	Home position ± 32767 rev.
(Note 1) Maximum speed at power failure	3000r/min
(Note 2) Battery backup time	Approx. 10,000 hours (battery life with power off)
Battery storage period	5 years from date of manufacture

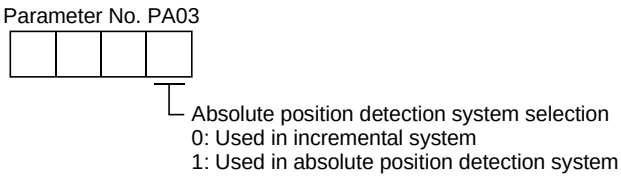
Note 1. Maximum speed available when the shaft is rotated by external force at the time of power failure or the like.
2. Time to hold data by a battery with power off. It is recommended to replace the battery in three years independently of whether power is kept on or off.

(2) Configuration



(3) Parameter setting

Set "☐☐☐1" in parameter No.PA03 to make the absolute position detection system valid.



12.3 Battery installation procedure

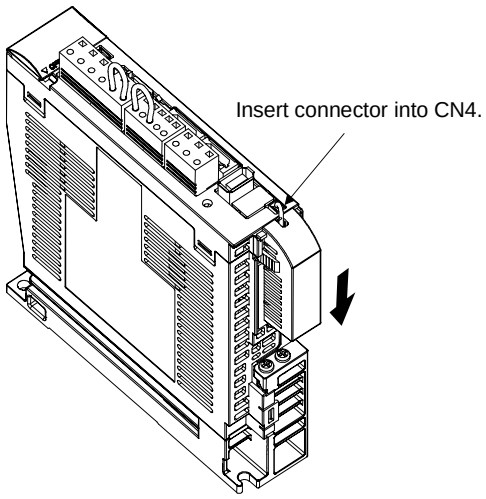
⚠ WARNING	・Before starting battery installation procedure, make sure that the charge lamp is off more than 15 minutes after main circuit power is switched OFF. Then, confirm that the voltage between P-N terminals is safe in the tester or the like with control circuit power ON. Otherwise, you may get an electrical shock.

POINT

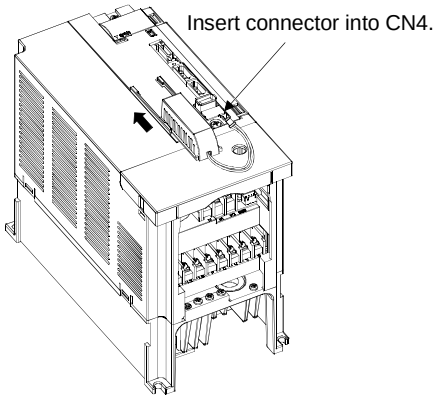
The internal circuits of the servo amplifier may be damaged by static electricity. Always take the following precautions:

- Ground human body and work bench.
- Do not touch the conductive areas, such as connector pins and electrical parts, directly by hand.
- Before starting battery changing procedure, make sure that the main circuit power is switched OFF with the control circuit power ON. When battery is changed with the control power OFF, the absolute position data is lost.

(1) For MR-J3-350B or less

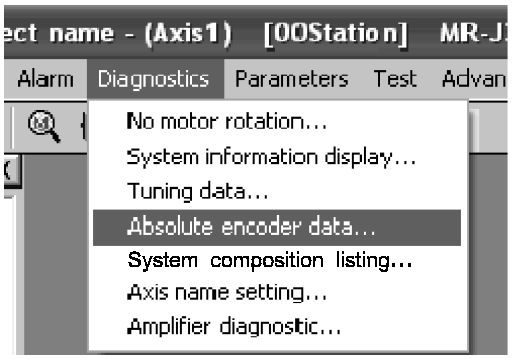


(2) For MR-J3-500B or more

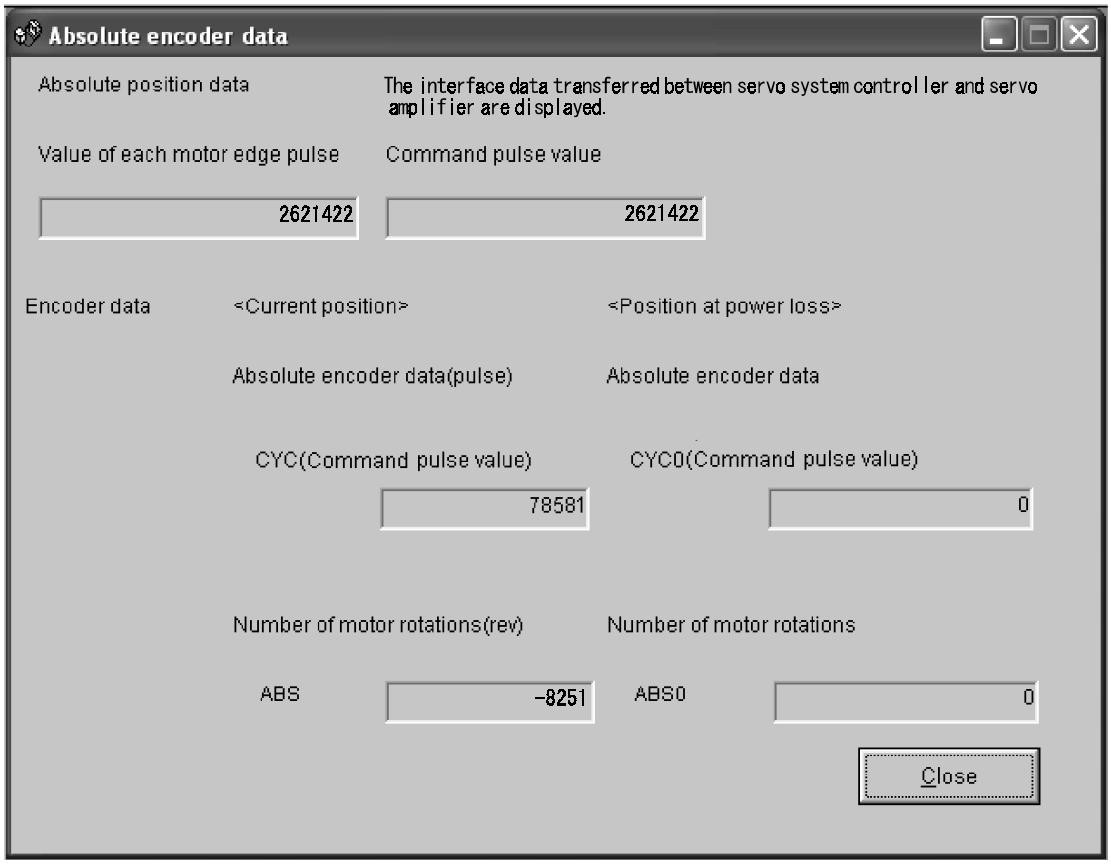


12.4 Confirmation of absolute position detection data

You can confirm the absolute position data with MR Configurator (servo configuration software).
Choose "Diagnostics" and "Absolute Encoder Data" to open the absolute position data display screen.
(1) Choosing "Diagnostics" in the menu opens the sub-menu as shown below:



(2) By choosing "Absolute Encoder Data" in the sub-menu, the absolute encoder data display window appears.



(3) Press the "Close" button to close the absolute encoder data display window.

App 1. Parameter list

POINT

- Parameter whose symbol is preceded by * is made valid with the following conditions.
  * : Set the parameter value, switch power off once after setting, and then switch it on again, or perform the controller reset.
  **: Set the parameter value, switch power off once, and then switch it on again.

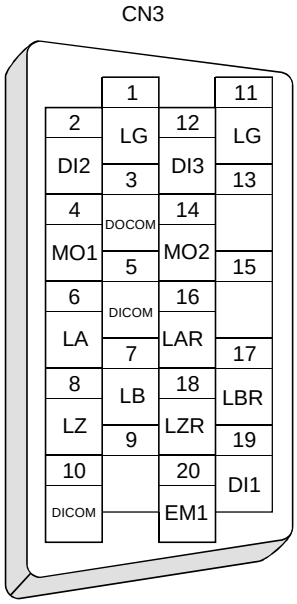
Basic setting parameters (PA ☐☐)		
No.	Symbol	Name
PA01		For manufacturer setting
PA02	**REG	Regenerative brake option
PA03	*ABS	Absolute position detection system
PA04	*AOP1	Function selection A-1
PA05 to PA07		For manufacturer setting
PA08	ATU	Auto tuning
PA09	RSP	Auto tuning response
PA10	INP	Control mode,regenerative brake option selection
PA11 to PA13		For manufacturer setting
PA14	*POL	Rotation direction selection
PA15	*ENR	Encoder output pulses
PA16 to PA18		For manufacturer setting
PA19	*BLK	Parameter write inhibit

Gain/filter parameters (PB ☐☐)		
No.	Symbol	Name
PB01	FILT	Adaptive tuning mode (Adaptive filter Ⅱ)
PB02	VRFT	Vibration suppression control filter tuning mode (Advanced vibration suppression control)
PB03		For manufacturer setting
PB04	FFC	Feed forward gain
PB05		For manufacturer setting
PB06	GD2	For manufacturer setting Ratio of load inertia moment to servo motor inertia moment
PB07	PG1	Model loop gain
PB08	PG2	Position loop gain
PB09	VG2	Speed loop gain
PB10	VIC	Speed integral compensation
PB11	VDC	Speed differential compensation
PB12		For manufacturer setting
PB13	NH1	Machine resonance suppression filter 1
PB14	NHQ1	Notch form selection 1
PB15	NH2	Machine resonance suppression filter 2
PB16	NHQ2	Notch form selection 2
PB17		For manufacturer setting
PB18	LPF	Low-pass filter
PB19	VRF1	Vibration suppression control vibration frequency setting
PB20	VRF2	Vibration suppression control resonance frequency setting
PB21 PB22		For manufacturer setting
PB23	VFBF	Low-pass filter selection
PB24	*MVS	Slight vibration suppression control selection
PB25		For manufacturer setting
PB26	*CDP	Gain changing selection
PB27	CDL	Gain changing condition
PB28	CDT	Gain changing time constant
PB29	GD2B	Gain changing ratio of load inertia moment to servo motor inertia moment
PB30	PG2B	Gain changing position loop gain
PB31	VG2B	Gain changing speed loop gain
PB32	VICB	Gain changing speed integral compensation
PB33	VRF1B	Gain changing vibration suppression control vibration frequency setting
PB34	VRF2B	Gain changing vibration suppression control resonance frequency setting
PB35 to PB45		For manufacturer setting

Extension setting parameters (PC ☐☐)		
No.	Symbol	Name
PC01	*ERZ	Error excessive alarm level
PC02	MBR	Electromagnetic brake sequence output
PC03	*ENRS	Encoder output pulses selection
PC04	**COP1	Function selection C-1
PC05	** COP2	Function selection C-2
PC06		For manufacturer setting
PC07	ZSP	Zero speed
PC08		For manufacturer setting
PC09	MOD1	Analog monitor output 1
PC10	MOD2	Analog monitor output 2
PC11	MO1	Analog monitor 1 offset
PC12	MO2	Analog monitor 2 offset
PC13 to PC16		For manufacturer setting
PC17	** COP4	Function selection C-4
PC18 to PC20		For manufacturer setting
PC21	*BPS	Alarm history clear
PC22 to PC32		For manufacturer setting

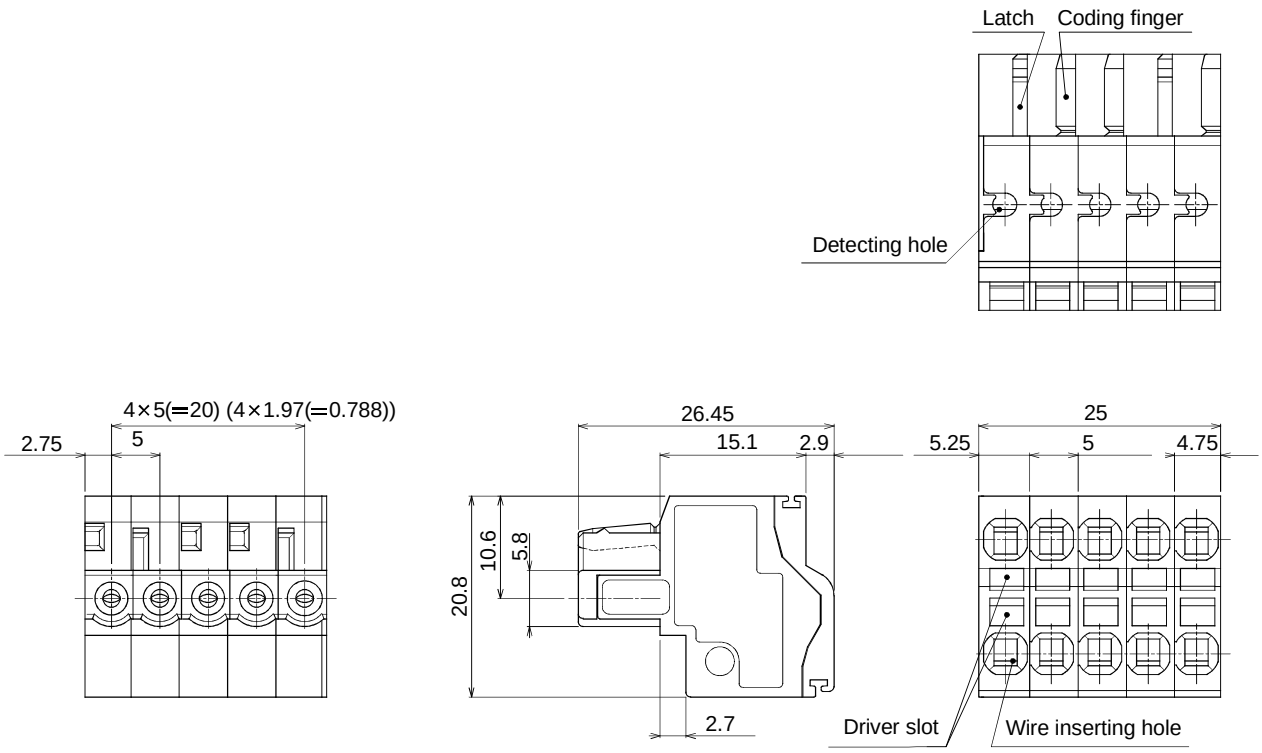
I/O setting parameters (PD ☐☐)		
No.	Symbol	Name
PD01 to PD06		For manufacturer setting
PD07	*D01	Output signal device selection 1 (CN3-pin 13)
PD08	*D02	Output signal device selection 2 (CN3-pin 9)
PD09	*D03	Output signal device selection 3 (CN3-pin 15)
PD010 to PD13		For manufacturer setting
PD14	*D0P3	Function selection D-3
PD15 to PD32		For manufacturer setting

App 2. Signal Layout Recording Paper



App 3. Twin type connector : Outline drawing for 721-2105/026-000(WAGO)

[Unit: mm]



App 4. Combination of servo amplifier and servo motor

The servo amplifier software versions compatible with the servo motors are indicated in the parentheses.
The servo amplifiers whose software versions are not indicated can be used regardless of the versions.

Servo motor	Servo amplifier (Software version)
HF-KP053	MR-J3-10B MR-J3-10B1
HF-KP13	MR-J3-10B MR-J3-10B1
HF-KP23	MR-J3-20B MR-J3-20B1
HF-KP43	MR-J3-40B MR-J3-40B1
HF-KP73	MR-J3-70B
HF-SP52	MR-J3-60B
HF-SP102	MR-J3-100B
HF-SP152	MR-J3-200B
HF-SP202	MR-J3-200B
HF-SP352	MR-J3-350B
HF-SP502	MR-J3-500B
HF-SP702	MR-J3-700B
HF-SP51	MR-J3-60B
HF-SP81	MR-J3-100B
HF-SP121	MR-J3-200B
HF-SP201	MR-J3-200B
HF-MP053	MR-J3-10B MR-J3-10B1
HF-MP13	MR-J3-10B MR-J3-10B1
HF-MP23	MR-J3-20B MR-J3-20B1
HF-MP43	MR-J3-40B MR-J3-40B1
HF-MP73	MR-J3- 70B

REVISIONS

*The manual number is given on the bottom left of the back cover.

Print Data	*Manual Number	Revision
May, 2005	SH(NA)030051-A	First edition

MODEL	
MODEL CODE	

MITSUBISHI ELECTRIC CORPORATION
HEAD OFFICE:MITSUBISHI DENKI BLDG MARUNOUCHI TOKYO 100-8310

This Instruction Manual uses recycled paper.
SH (NA) 030051-A (0505) MEE Printed in Japan Specifications subject to change without notice.