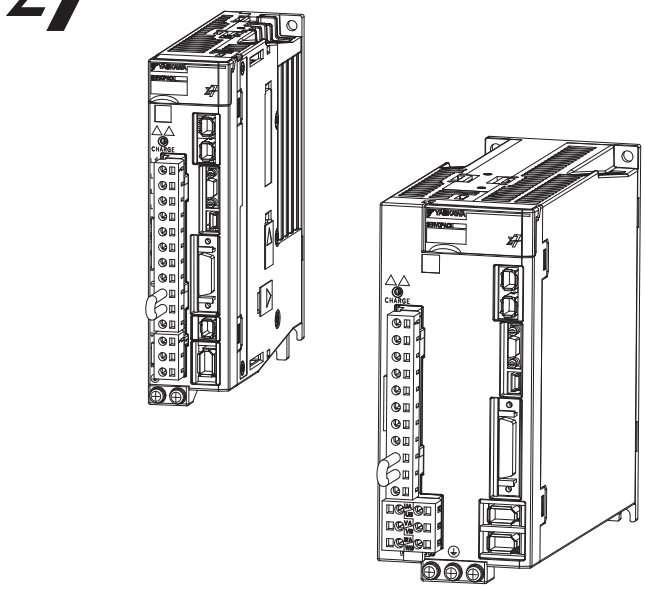
YASKAWA

Σ-7-Series AC Servo Drive

MECHATROLINK-III Communications Standard Servo Profile Command Manual



MANUAL NO. SIEP S800001 31B

About this Manual

This manual describes the specifications of standard servo profile commands used in MECHATROLINK-III communications for the following MECHATROLINK-III communications reference input type SERVOPACKs, the basic operations using these commands, and the parameters for these commands.

- Σ-7-Series Σ-7S SERVOPACKs (Models: SGD7S-□□□□20□)
- Σ-7-Series Σ-7W SERVOPACKs (Models: SGD7W-□□□□20□)

Read and understand this manual to ensure correct usage of the Σ-7-Series AC Servo Drives.

Keep this manual in a safe place so that it can be referred to whenever necessary.

- Supported Profile Version: Ver. 1.0

- Targeted Readers

Users who incorporate the standard servo profile commands in controllers
Users who design applications for host controllers that use standard servo profile commands directly

Outline of Manual

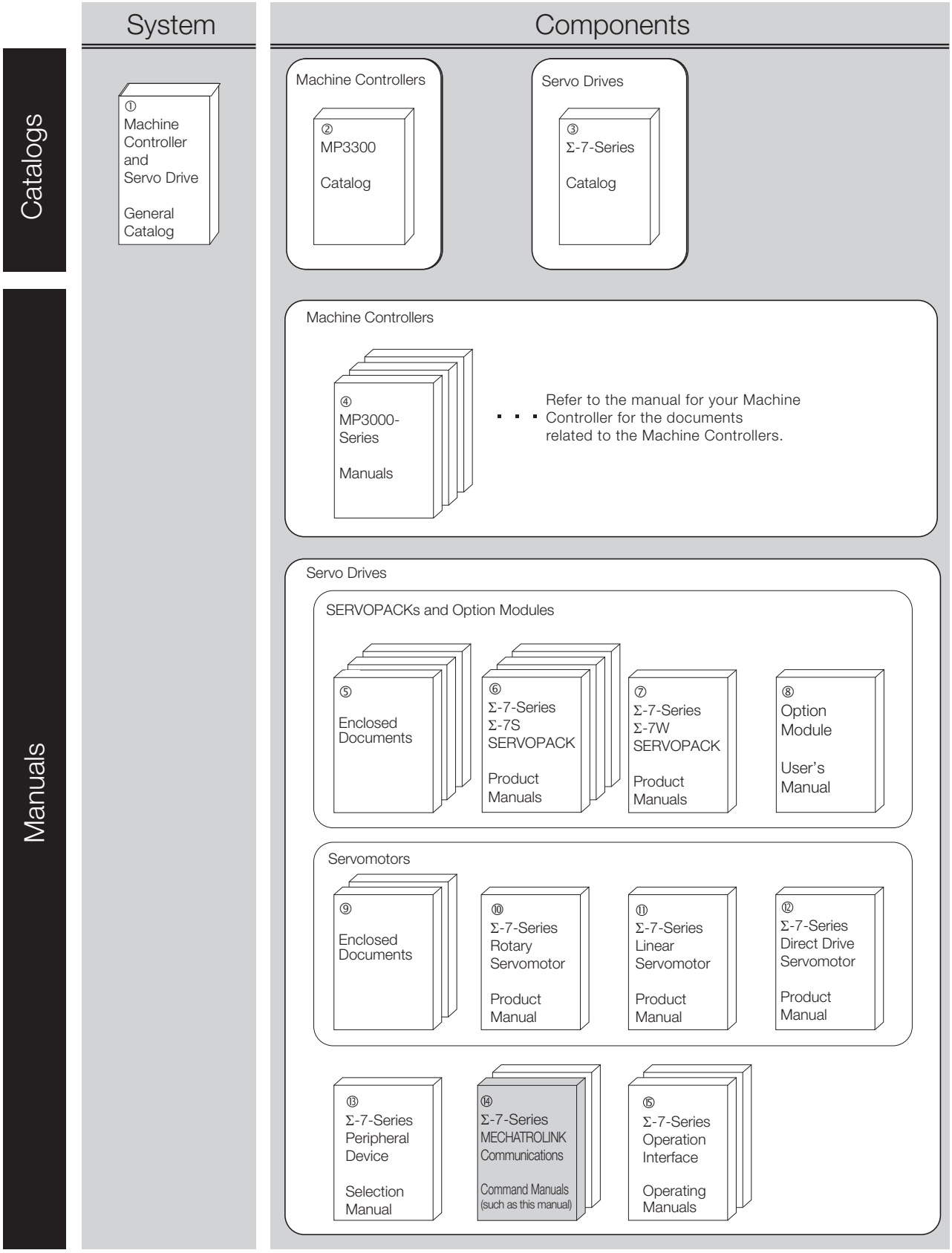
The contents of the chapters of this manual are described in the following table.

Refer to these chapters as required.

Chapter	Chapter Title	Contents
1	MECHATROLINK-III Communication Settings	Provides detailed information on MECHATROLINK-III communications.
2	Command Format	Describes the common specifications for all commands and the command format.
3	Main Commands	Provides detailed information on the main commands.
4	Subcommands	Provides detailed information on the subcommands.
5	Operation Sequence	Describes basic operation sequences using MECHATROLINK-III communications.
6	Function/Command Related Parameters	Describes the parameter settings required for executing commands and functions.
7	Detecting Alarms/Warnings Related to Communications or Commands	Describes the alarms and warnings that may occur in MECHATROLINK-III communications.
8	Common Parameters	Provides detailed information on the common parameters.
9	Virtual Memory Space	Provides detailed information on the virtual memory space.

Related Documents

The relationships between the documents that are related to the Servo Drives are shown in the following figure. The numbers in the figure correspond to the numbers in the table on the following pages. Refer to these documents as required.



Classification	Document Name	Document No.	Description
① Machine Controller and Servo Drive General Catalog	Machine Controller and AC Servo Drive Solutions Catalog	KAEP S800001 22	Describes the features and application examples for combinations of MP3000-Series Machine Controllers and Σ-7-Series AC Servo Drives.
② MP3300 Catalog	Machine Controller MP3300	KAEP C880725 03	Provides detailed information on MP3300 Machine Controllers, including features and specifications.
③ Σ-7-Series Catalog	AC Servo Drives Σ-7 Series	KAEP S800001 23	Provides detailed information on Σ-7-Series AC Servo Drives, including features and specifications.
④ MP3000-Series Manuals	Machine Controller MP3000 Series MP3300 Product Manual	SIEP C880725 21	Describes the functions, specifications, operating methods, maintenance, inspections, and troubleshooting of the MP3000-series MP3300 Machine Controllers.
⑤ Enclosed Documents	Σ-7-Series AC Servo Drive Σ-7S and Σ-7W SERVOPACK Safety Precautions	TOMP C710828 00	Provides detailed information for the safe usage of Σ-7-Series SERVOPACKs.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Safety Precautions Option Module	TOBP C720829 00	Provides detailed information for the safe usage of Option Modules.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide Command Option Module	TOBP C720829 01	Provides detailed procedures for installing a Command Option Module in a SERVOPACK.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide Fully-closed Module	TOBP C720829 03	Provides detailed procedures for installing the Fully-closed Module in a SERVOPACK.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide Safety Module	TOBP C720829 06	Provides detailed procedures for installing the Safety Module in a SERVOPACK.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide Indexer Module	TOBP C720829 02	Provides detailed procedures for installing the Indexer Module in a SERVOPACK.
	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series Installation Guide DeviceNet Module	TOBP C720829 07	Provides detailed procedures for installing the DeviceNet Module in a SERVOPACK.

Continued on next page.

Continued from previous page.

Classification	Document Name	Document No.	Description
⑥ Σ-7-Series Σ-7S SERVOPACK Product Manuals	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with MECHATROLINK-III Communications References Product Manual	SIEP S800001 28	Provide detailed information on selecting Σ-7-Series SERVOPACKs and information on installing, connecting, setting, performing trial operation for, tuning, and monitoring the Servo Drives.
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with MECHATROLINK-II Communications References Product Manual	SIEP S800001 27	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK with Analog Voltage/Pulse Train References Product Manual	SIEP S800001 26	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK Command Option Attachable Type with Indexer Module Product Manual	SIEP S800001 64	
	Σ-7-Series AC Servo Drive Σ-7S SERVOPACK Command Option Attachable Type with DeviceNet Module Product Manual	SIEP S800001 70	
⑦ Σ-7-Series Σ-7W SERVOPACK Product Manual	Σ-7-Series AC Servo Drive Σ-7W SERVOPACK with MECHATROLINK-III Communications References Product Manual	SIEP S800001 29	
⑧ Option Module User's Manual	Σ-V-Series/Σ-V-Series for Large-Capacity Models/ Σ-7-Series User's Manual Safety Module	SIEP C720829 06	Provides details information required for the design and maintenance of a Safety Module.
⑨ Enclosed Documents	AC Servo Drive Rotary Servomotor Safety Precautions	TOBP C230260 00	Provides detailed information for the safe usage of Rotary Servomotors and Direct Drive Servomotors.
	AC Servomotor Linear Σ Series Safety Precautions	TOBP C230800 00	Provides detailed information for the safe usage of Linear Servomotors.

Continued on next page.

Continued from previous page.

Classification	Document Name	Document No.	Description
⑩ Σ-7-Series Rotary Servomotor Product Manual	Σ-7-Series AC Servo Drive Rotary Servomotor Product Manual	SIEP S800001 36	Provide detailed information on selecting, installing, and connecting the Σ-7-Series Servomotors.
⑪ Σ-7-Series Linear Servomotor Product Manual	Σ-7-Series AC Servo Drive Linear Servomotor Product Manual	SIEP S800001 37	
⑫ Σ-7-Series Direct Drive Servomotor Product Manual	Σ-7-Series AC Servo Drive Direct Drive Servomotor Product Manual	SIEP S800001 38	
⑬ Σ-7-Series Peripheral Device Selection Manual	Σ-7-Series AC Servo Drive Peripheral Device Selection Manual	SIEP S800001 32	Describes the peripheral devices for a Σ-7-Series Servo System.
⑭ Σ-7-Series MECHATROLINK Communications Command Manuals	Σ-7-Series AC Servo Drive MECHATROLINK-II Communications Command Manual	SIEP S800001 30	Provides detailed information on the MECHATROLINK-II communications commands that are used for a Σ-7-Series Servo System.
	Σ-7-Series AC Servo Drive MECHATROLINK-III Communications Standard Servo Profile Command Manual	This manual (SIEP S800001 31)	Provides detailed information on the MECHATROLINK-III communications standard servo profile commands that are used for a Σ-7-Series Servo System.
⑮ Σ-7-Series Operation Interface Operating Manuals	Σ-7-Series AC Servo Drive Digital Operator Operating Manual	SIEP S800001 33	Describes the operating procedures for a Digital Operator for a Σ-7-Series Servo System.
	AC Servo Drives Engineering Tool SigmaWin+ Online Manual Σ-7 Component	SIEP S800001 48	Provides detailed operating procedures for the SigmaWin+ Engineering Tool for a Σ-7-Series Servo System.

<Issued by the MECHATROLINK Members Association>

Document Name	Document Number
MECHATROLINK-III Protocol Specifications	MMA TDEP 020A
MECHATROLINK-III Command Specifications for Standard Servo Profile	MMA TDEP 021A

Using This Manual

◆ Technical Terms Used in This Manual

The following terms are used in this manual.

Basic Term	Meaning
Transmission Cycle	The transmission cycle is the cycle in the MAC (Media Access Control) layer. It is the communication cycle for physically sending data to the transmission path. The transmission cycle is unaffected by the services provided by the application layer.
Communication Cycle	The communication cycle is the cycle for application layer. The communication cycle is set to an integral multiple of the transmission cycle.
Synchronous Commands (Classification S)	For commands of this type, commands are sent and response are received every communication cycle. The WDT (Watchdog Timer) in the frames are refreshed and checked every communication cycle. Synchronous commands can be used only during synchronous communications (Phase 3).
Asynchronous Commands (Classification A)	For commands of this type, commands are sent and response are received asynchronously to the communication cycle. Subsequent commands can be sent after confirming the completion of processing of the slave station that received the command. The WDT (Watchdog Timer) in the frames are not checked.
Common Commands	Commands that are common for MECHATROLINK-III communications, independent of profiles
Servo Commands	Commands that are defined in the standard servo profile and specific to SERVOPACKs
Motion Commands	Among servo commands, the following commands are called motion commands. INTERPOLATE, POSING, FEED, EX_FEED, EX_POSING, ZRET, VELCTRL, and TRQCTRL

Be sure that you fully understand each command and use the commands in the order appropriate for your application.
Incorrect usage of the commands can result not only unexpected motions, but in a serious accident.
Special care and verification must be taken for usage of the commands in order to avoid accidents.
Be sure to also establish safety measures for the system.
This manual does not apply to users who use MP-series motion controllers for controlling Σ-7-Series SERVOPACKs.

◆ Differences in Terms for Rotary Servomotors and Linear Servomotors

There are differences in the terms that are used for Rotary Servomotors and Linear Servomotors. This manual primarily describes Rotary Servomotors. If you are using a Linear Servomotor, you need to interpret the terms as given in the following table.

Rotary Servomotors	Linear Servomotors
torque	force
moment of inertia	mass
rotation	movement
forward rotation and reverse rotation	forward movement and reverse movement
CW and CCW pulse trains	forward and reverse pulse trains
rotary encoder	linear encoder
absolute rotary encoder	absolute linear encoder
incremental rotary encoder	incremental linear encoder
unit: min^{-1}	unit: mm/s
unit: N·m	unit: N

◆ Notation Used in this Manual

■ Notation for Reverse Signals

The names of reverse signals (i.e., ones that are valid when low) are written with a forward slash (/) before the signal abbreviation.

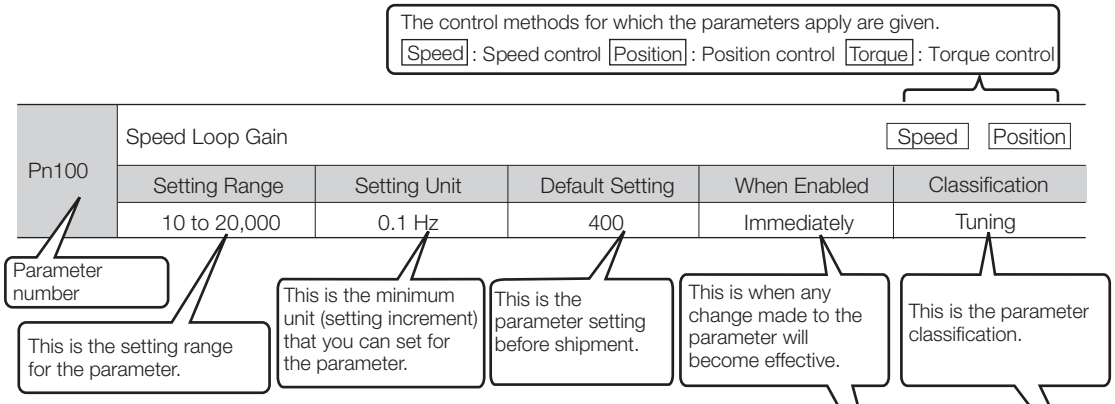
Notation Example

BK is written as /BK.

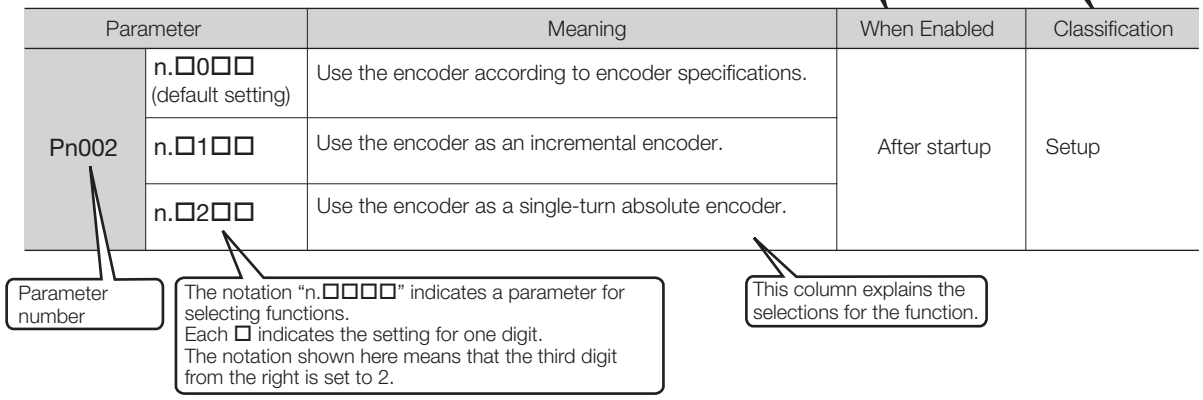
■ Notation for Parameters

The notation depends on whether the parameter requires a numeric setting (parameter for numeric setting) or requires the selection of a function (parameter for selecting functions).

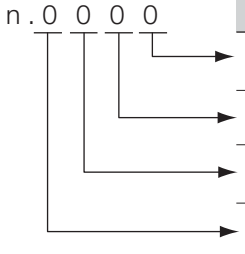
- Parameters for Numeric Settings



- Parameters for Selecting Functions



Notation Example



Notation Examples for Pn002

Digit Notation		Numeric Value Notation	
Notation	Meaning	Notation	Meaning
Pn002 = n.□□□X	Indicates the first digit from the right in Pn002.	Pn002 = n.□□□1	Indicates that the first digit from the right in Pn002 is set to 1.
Pn002 = n.□□X□	Indicates the second digit from the right in Pn002.	Pn002 = n.□□1□	Indicates that the second digit from the right in Pn002 is set to 1.
Pn002 = n.□X□□	Indicates the third digit from the right in Pn002.	Pn002 = n.□1□□	Indicates that the third digit from the right in Pn002 is set to 1.
Pn002 = n.X□□□	Indicates the fourth digit from the right in Pn002.	Pn002 = n.1□□□	Indicates that the fourth digit from the right in Pn002 is set to 1.

◆ Trademarks

- MECHATROLINK is a trademark of the MECHATROLINK Members Association.
- Other product names and company names are the trademarks or registered trademarks of the respective company. “TM” and the ® mark do not appear with product or company names in this manual.

◆ Visual Aids

The following aids are used to indicate certain types of information for easier reference.


Important

Indicates precautions or restrictions that must be observed.
Also indicates alarm displays and other precautions that will not result in machine damage.


Term

Indicates definitions of difficult terms or terms that have not been previously explained in this manual.

Example Indicates operating or setting examples.

Information Indicates supplemental information to deepen understanding or useful information.

Safety Precautions

◆ Safety Information

To prevent personal injury and equipment damage in advance, the following signal words are used to indicate safety precautions in this document. The signal words are used to classify the hazards and the degree of damage or injury that may occur if a product is used incorrectly. Information marked as shown below is important for safety. Always read this information and heed the precautions that are provided.

⚠ DANGER

- Indicates precautions that, if not heeded, are likely to result in loss of life, serious injury, or fire.

⚠ WARNING

- Indicates precautions that, if not heeded, could result in loss of life, serious injury, or fire.

⚠ CAUTION

- Indicates precautions that, if not heeded, could result in relatively serious or minor injury, or in fire.

NOTICE

- Indicates precautions that, if not heeded, could result in property damage.

◆ Safety Precautions That Must Always Be Observed

■ General Precautions

⚠ DANGER

- Read and understand this manual to ensure the safe usage of the product.
- Keep this manual in a safe, convenient place so that it can be referred to whenever necessary. Make sure that it is delivered to the final user of the product.
- Do not remove covers, cables, connectors, or optional devices while power is being supplied to the SERVOPACK.
  There is a risk of electric shock, operational failure of the product, or burning.

⚠ WARNING

- Use a power supply with specifications (number of phases, voltage, frequency, and AC/DC type) that are appropriate for the product.
  There is a risk of burning, electric shock, or fire.
- Connect the ground terminals on the SERVOPACK and Servomotor to ground poles according to local electrical codes (100 Ω or less for a SERVOPACK with a 100-VAC or 200-VAC power supply, and 10 Ω or less for a SERVOPACK with a 400-VAC power supply).
  There is a risk of electric shock or fire.
- Do not attempt to disassemble, repair, or modify the product.
  There is a risk of fire or failure.
  The warranty is void for the product if you disassemble, repair, or modify it.

⚠ CAUTION

- The SERVOPACK heat sinks, regenerative resistors, Servomotors, and other components can be very hot while power is ON or soon after the power is turned OFF. Implement safety measures, such as installing covers, so that hands and parts such as cables do not come into contact with hot components.
  There is a risk of burn injury.
- For a 24-VDC power supply, use a power supply device with double insulation or reinforced insulation.
  There is a risk of electric shock.
- Do not damage, pull on, apply excessive force to, place heavy objects on, or pinch cables.
  There is a risk of failure, damage, or electric shock.
- The person who designs the system that uses the hard wire base block safety function must have a complete knowledge of the related safety standards and a complete understanding of the instructions in this document.
  There is a risk of injury, product damage, or machine damage.
- Do not use the product in an environment that is subject to water, corrosive gases, or flammable gases, or near flammable materials.
  There is a risk of electric shock or fire.

NOTICE

- Do not attempt to use a SERVOPACK or Servomotor that is damaged or that has missing parts.
- Install external emergency stop circuits that shut OFF the power supply and stops operation immediately when an error occurs.
- In locations with poor power supply conditions, install the necessary protective devices (such as AC reactors) to ensure that the input power is supplied within the specified voltage range.
  There is a risk of damage to the SERVOPACK.
- Use a Noise Filter to minimize the effects of electromagnetic interference.
  Electronic devices used near the SERVOPACK may be affected by electromagnetic interference.
- Always use a Servomotor and SERVOPACK in one of the specified combinations.
- Do not touch a SERVOPACK or Servomotor with wet hands.
  There is a risk of product failure.

■ Storage Precautions

⚠ CAUTION

- Do not place an excessive load on the product during storage. (Follow all instructions on the packages.)
  There is a risk of injury or damage.

NOTICE

- Do not install or store the product in any of the following locations.
  - Locations that are subject to direct sunlight
  - Locations that are subject to ambient temperatures that exceed product specifications
  - Locations that are subject to relative humidities that exceed product specifications
  - Locations that are subject to condensation as the result of extreme changes in temperature
  - Locations that are subject to corrosive or flammable gases
  - Locations that are near flammable materials
  - Locations that are subject to dust, salts, or iron powder
  - Locations that are subject to water, oil, or chemicals
  - Locations that are subject to vibration or shock that exceeds product specifications
  - Locations that are subject to radiation

  If you store or install the product in any of the above locations, the product may fail or be damaged.

■ Transportation Precautions

⚠ CAUTION

- Transport the product in a way that is suitable to the mass of the product.
- Do not use the eyebolts on a SERVOPACK or Servomotor to move the machine.
  There is a risk of damage or injury.
- When you handle a SERVOPACK or Servomotor, be careful of sharp parts, such as the corners.
  There is a risk of injury.
- Do not place an excessive load on the product during transportation. (Follow all instructions on the packages.)
  There is a risk of injury or damage.

NOTICE

- Do not hold onto the front cover or connectors when you move a SERVOPACK.
  There is a risk of the SERVOPACK falling.
- A SERVOPACK or Servomotor is a precision device. Do not drop it or subject it to strong shock.
  There is a risk of failure or damage.
- Do not subject connectors to shock.
  There is a risk of faulty connections or damage.
- If disinfectants or insecticides must be used to treat packing materials such as wooden frames, plywood, or pallets, the packing materials must be treated before the product is packaged, and methods other than fumigation must be used.
  Example: Heat treatment, where materials are kiln-dried to a core temperature of 56°C for 30 minutes or more.
  If the electronic products, which include stand-alone products and products installed in machines, are packed with fumigated wooden materials, the electrical components may be greatly damaged by the gases or fumes resulting from the fumigation process. In particular, disinfectants containing halogen, which includes chlorine, fluorine, bromine, or iodine can contribute to the erosion of the capacitors.
- Do not overtighten the eyebolts on a SERVOPACK or Servomotor.
  If you use a tool to overtighten the eyebolts, the tapped holes may be damaged.

■ Installation Precautions

⚠ CAUTION

- Install the Servomotor or SERVOPACK in a way that will support the mass given in technical documents.
- Install SERVOPACKs, Servomotors, and regenerative resistors on nonflammable materials.
  Installation directly onto or near flammable materials may result in fire.
- Provide the specified clearances between the SERVOPACK and the control panel as well as with other devices.
  There is a risk of fire or failure.
- Install the SERVOPACK in the specified orientation.
  There is a risk of fire or failure.
- Do not step on or place a heavy object on the product.
  There is a risk of failure, damage, or injury.
- Do not allow any foreign matter to enter the SERVOPACK or Servomotor.
  There is a risk of failure or fire.

NOTICE

- Do not install or store the product in any of the following locations.
  - Locations that are subject to direct sunlight
  - Locations that are subject to ambient temperatures that exceed product specifications
  - Locations that are subject to relative humidities that exceed product specifications
  - Locations that are subject to condensation as the result of extreme changes in temperature
  - Locations that are subject to corrosive or flammable gases
  - Locations that are near flammable materials
  - Locations that are subject to dust, salts, or iron powder
  - Locations that are subject to water, oil, or chemicals
  - Locations that are subject to vibration or shock that exceeds product specifications
  - Locations that are subject to radiation

  If you store or install the product in any of the above locations, the product may fail or be damaged.
- Use the product in an environment that is appropriate for the product specifications.
  If you use the product in an environment that exceeds product specifications, the product may fail or be damaged.
- A SERVOPACK or Servomotor is a precision device. Do not drop it or subject it to strong shock.
  There is a risk of failure or damage.
- Always install a SERVOPACK in a control panel.
- Do not allow any foreign matter to enter a SERVOPACK or a Servomotor with a Cooling Fan and do not cover the outlet from the Servomotor's cooling fan.
  There is a risk of failure.

■ Wiring Precautions

⚠ DANGER

- Do not change any wiring while power is being supplied.
  There is a risk of electric shock or injury.

⚠ WARNING

- Wiring and inspections must be performed only by qualified engineers.
  There is a risk of electric shock or product failure.
- Check all wiring and power supplies carefully.
  Incorrect wiring or incorrect voltage application to the output circuits may cause short-circuit failures. If a short-circuit failure occurs as a result of any of these causes, the holding brake will not work. This could damage the machine or cause an accident that may result in death or injury.
- Connect the AC and DC power supplies to the specified SERVOPACK terminals.
  - Connect an AC power supply to the L1, L2, and L3 terminals and the L1C and L2C terminals on the SERVOPACK.
  - Connect a DC power supply to the B1/⊕ and ⊖2 terminals and the L1C and L2C terminals on the SERVOPACK.

  There is a risk of failure or fire.

⚠ CAUTION

- Wait for six minutes after turning OFF the power supply and then make sure that the CHARGE indicator is not lit before starting wiring or inspection work. Do not touch the power supply terminals while the CHARGE lamp is lit after turning OFF the power supply because high voltage may still remain in the SERVOPACK.
  There is a risk of electric shock.
- Observe the precautions and instructions for wiring and trial operation precisely as described in this document.
  Failures caused by incorrect wiring or incorrect voltage application in the brake circuit may cause the SERVOPACK to fail, damage the equipment, or cause an accident resulting in death or injury.
- Check the wiring to be sure it has been performed correctly.
  Connectors and pin layouts are sometimes different for different models. Always confirm the pin layouts in technical documents for your model before operation.
  There is a risk of failure or malfunction.
- Connect wires to power supply terminals and motor connection terminals securely with the specified methods and tightening torque.
  Insufficient tightening may cause wires and terminal blocks to generate heat due to faulty contact, possibly resulting in fire.
- Use shielded twisted-pair cables or screened unshielded multi-twisted-pair cables for I/O Signal Cables and Encoder Cables.
- Observe the following precautions when wiring the SERVOPACK's main circuit terminals.
  - Turn ON the power supply to the SERVOPACK only after all wiring, including the main circuit terminals, has been completed.
  - If a connector is used for the main circuit terminals, remove the main circuit connector from the SERVOPACK before you wire it.
  - Insert only one wire per insertion hole in the main circuit terminals.
  - When you insert a wire, make sure that the conductor wire (e.g., whiskers) does not come into contact with adjacent wires.
- Install molded-case circuit breakers and other safety measures to provide protection against short circuits in external wiring.
  There is a risk of fire or failure.

NOTICE

- Whenever possible, use the Cables specified by Yaskawa.
  If you use any other cables, confirm the rated current and application environment of your model and use the wiring materials specified by Yaskawa or equivalent materials.
- Securely tighten cable connector screws and lock mechanisms.
  Insufficient tightening may result in cable connectors falling off during operation.
- Do not bundle power lines (e.g., the Main Circuit Cable) and low-current lines (e.g., the I/O Signal Cables or Encoder Cables) together or run them through the same duct. If you do not place power lines and low-current lines in separate ducts, separate them by at least 30 cm.
  If the cables are too close to each other, malfunctions may occur due to noise affecting the low-current lines.
- Install a battery at either the host controller or on the Encoder Cable.
  If you install batteries both at the host controller and on the Encoder Cable at the same time, you will create a loop circuit between the batteries, resulting in a risk of damage or burning.
- When connecting a battery, connect the polarity correctly.
  There is a risk of battery rupture or encoder failure.

■ Operation Precautions

⚠ WARNING

- Before starting operation with a machine connected, change the settings of the switches and parameters to match the machine.
  Unexpected machine operation, failure, or personal injury may occur if operation is started before appropriate settings are made.
- Do not radically change the settings of the parameters.
  There is a risk of unstable operation, machine damage, or injury.
- Install limit switches or stoppers at the ends of the moving parts of the machine to prevent unexpected accidents.
  There is a risk of machine damage or injury.
- For trial operation, securely mount the Servomotor and disconnect it from the machine.
  There is a risk of injury.
- Forcing the motor to stop for overtravel is disabled when the Jog (Fn002), Origin Search (Fn003), or Easy FFT (Fn206) utility function is executed. Take necessary precautions.
  There is a risk of machine damage or injury.
- When an alarm occurs, the motor will coast to a stop or stop with the dynamic brake according to a setting in the SERVOPACK. The coasting distance will change with the moment of inertia of the load. Check the coasting distance during trial operation and implement suitable safety measures on the machine.
- Do not enter the machine's range of motion during operation.
  There is a risk of injury.
- Do not touch the moving parts of the Servomotor or machine during operation.
  There is a risk of injury.

⚠ CAUTION

- Design the system to ensure safety even when problems, such as broken signal lines, occur. For example, the P-OT and N-OT signals are set in the default settings to operate on the safe side if a signal line breaks. Do not change the polarity of this type of signal.
- When overtravel occurs, the power supply to the motor is turned OFF and the brake is released. If you use the Servomotor to drive a vertical load, set the Servomotor to enter a zero-clamped state after the Servomotor stops. Also, install safety devices (such as an external brake or counterweight) to prevent the moving parts of the machine from falling.
- Always turn OFF the servo before you turn OFF the power supply. If you turn OFF the main circuit power supply or control power supply during operation before you turn OFF the servo, the Servomotor will stop as follows:
  - If you turn OFF the main circuit power supply during operation without turning OFF the servo, the Servomotor will stop abruptly with the dynamic brake.
  - If you turn OFF the control power supply without turning OFF the servo, the stopping method that is used by the Servomotor depends on the model of the SERVOPACK. For details, refer to the manual for the SERVOPACK.

NOTICE

- When you adjust the gain during system commissioning, use a measuring instrument to monitor the torque waveform and speed waveform and confirm that there is no vibration.
  If a high gain causes vibration, the Servomotor will be damaged quickly.
- Do not frequently turn the power supply ON and OFF. After you have started actual operation, allow at least one hour between turning the power supply ON and OFF (as a guideline).
  Do not use the product in applications that require the power supply to be turned ON and OFF frequently.
  The elements in the SERVOPACK will deteriorate quickly.
- An alarm or warning may occur if communications are performed with the host controller while the SigmaWin+ or Digital Operator is operating.
  If an alarm or warning occurs, it may interrupt the current process and stop the system.
- After you complete trial operation of the machine and facilities, use the SigmaWin+ to back up the settings of the SERVOPACK parameters. You can use them to reset the parameters after SERVOPACK replacement.
  If you do not copy backed up parameter settings, normal operation may not be possible after a faulty SERVOPACK is replaced, possibly resulting in machine or equipment damage.

■ Maintenance and Inspection Precautions

⚠ DANGER

- Do not change any wiring while power is being supplied.
  There is a risk of electric shock or injury.

⚠ WARNING

- Wiring and inspections must be performed only by qualified engineers.
  There is a risk of electric shock or product failure.

⚠ CAUTION

- Wait for six minutes after turning OFF the power supply and then make sure that the CHARGE indicator is not lit before starting wiring or inspection work. Do not touch the power supply terminals while the CHARGE lamp is lit after turning OFF the power supply because high voltage may still remain in the SERVOPACK.
  There is a risk of electric shock.
- Before you replace a SERVOPACK, back up the settings of the SERVOPACK parameters. Copy the backed up parameter settings to the new SERVOPACK and confirm that they were copied correctly.
  If you do not copy backed up parameter settings or if the copy operation is not completed normally, normal operation may not be possible, possibly resulting in machine or equipment damage.

NOTICE

- Discharge all static electricity from your body before you operate any of the buttons or switches inside the front cover of the SERVOPACK.
  There is a risk of equipment damage.

■ Troubleshooting Precautions

⚠ WARNING

- The product may suddenly start to operate when the power supply is recovered after a momentary power interruption. Design the machine to ensure human safety when operation restarts.
  There is a risk of injury.

⚠ CAUTION

- When an alarm occurs, remove the cause of the alarm and ensure safety. Then reset the alarm or turn the power supply OFF and ON again to restart operation.
  There is a risk of injury or machine damage.
- If the Servo ON signal is input to the SERVOPACK and an alarm is reset, the Servomotor may suddenly restart operation. Confirm that the servo is OFF and ensure safety before you reset an alarm.
  There is a risk of injury or machine damage.
- Always insert a magnetic contactor in the line between the main circuit power supply and the main circuit power supply terminals on the SERVOPACK so that the power supply can be shut OFF at the main circuit power supply.
  If a magnetic contactor is not connected when the SERVOPACK fails, a large current may flow, possibly resulting in fire.
- If an alarm occurs, shut OFF the main circuit power supply.
  There is a risk of fire due to a regenerative resistor overheating as the result of regenerative transistor failure.
- Install a ground fault detector against overloads and short-circuiting or install a molded-case circuit breaker combined with a ground fault detector.
  There is a risk of SERVOPACK failure or fire if a ground fault occurs.
- The holding brake on a Servomotor will not ensure safety if there is the possibility that an external force (including gravity) may move the current position and create a hazardous situation when power is interrupted or an error occurs. If an external force may cause movement, install an external braking mechanism that ensures safety.

■ General Precautions

- Figures provided in this document are typical examples or conceptual representations. There may be differences between them and actual wiring, circuits, and products.
- The products shown in illustrations in this document are sometimes shown without covers or protective guards. Always replace all covers and protective guards before you use the product.
- If you need a new copy of this document because it has been lost or damaged, contact your nearest Yaskawa representative or one of the offices listed on the back of this document.
- This document is subject to change without notice for product improvements, specifications changes, and improvements to the manual itself.
  We will update the document number of the document and issue revisions when changes are made.
- Any and all quality guarantees provided by Yaskawa are null and void if the customer modifies the product in any way. Yaskawa disavows any responsibility for damages or losses that are caused by modified products.

Warranty

◆ Details of Warranty

■ Warranty Period

The warranty period for a product that was purchased (hereinafter called the “delivered product”) is one year from the time of delivery to the location specified by the customer or 18 months from the time of shipment from the Yaskawa factory, whichever is sooner.

■ Warranty Scope

Yaskawa shall replace or repair a defective product free of charge if a defect attributable to Yaskawa occurs during the above warranty period.
This warranty does not cover defects caused by the delivered product reaching the end of its service life and replacement of parts that require replacement or that have a limited service life.

This warranty does not cover failures that result from any of the following causes.

- Improper handling, abuse, or use in unsuitable conditions or in environments not described in product catalogs or manuals, or in any separately agreed-upon specifications
- Causes not attributable to the delivered product itself
- Modifications or repairs not performed by Yaskawa
- Use of the delivered product in a manner in which it was not originally intended
- Causes that were not foreseeable with the scientific and technological understanding at the time of shipment from Yaskawa
- Events for which Yaskawa is not responsible, such as natural or human-made disasters

◆ Limitations of Liability

- Yaskawa shall in no event be responsible for any damage or loss of opportunity to the customer that arises due to failure of the delivered product.
- Yaskawa shall not be responsible for any programs (including parameter settings) or the results of program execution of the programs provided by the user or by a third party for use with programmable Yaskawa products.
- The information described in product catalogs or manuals is provided for the purpose of the customer purchasing the appropriate product for the intended application. The use thereof does not guarantee that there are no infringements of intellectual property rights or other proprietary rights of Yaskawa or third parties, nor does it construe a license.
- Yaskawa shall not be responsible for any damage arising from infringements of intellectual property rights or other proprietary rights of third parties as a result of using the information described in catalogs or manuals.

◆ Suitability for Use

- It is the customer's responsibility to confirm conformity with any standards, codes, or regulations that apply if the Yaskawa product is used in combination with any other products.
- The customer must confirm that the Yaskawa product is suitable for the systems, machines, and equipment used by the customer.
- Consult with Yaskawa to determine whether use in the following applications is acceptable. If use in the application is acceptable, use the product with extra allowance in ratings and specifications, and provide safety measures to minimize hazards in the event of failure.
- Outdoor use, use involving potential chemical contamination or electrical interference, or use in conditions or environments not described in product catalogs or manuals
- Nuclear energy control systems, combustion systems, railroad systems, aviation systems, vehicle systems, medical equipment, amusement machines, and installations subject to separate industry or government regulations
- Systems, machines, and equipment that may present a risk to life or property
- Systems that require a high degree of reliability, such as systems that supply gas, water, or electricity, or systems that operate continuously 24 hours a day
- Other systems that require a similar high degree of safety
- Never use the product for an application involving serious risk to life or property without first ensuring that the system is designed to secure the required level of safety with risk warnings and redundancy, and that the Yaskawa product is properly rated and installed.
- The circuit examples and other application examples described in product catalogs and manuals are for reference. Check the functionality and safety of the actual devices and equipment to be used before using the product.
- Read and understand all use prohibitions and precautions, and operate the Yaskawa product correctly to prevent accidental harm to third parties.

◆ Specifications Change

The names, specifications, appearance, and accessories of products in product catalogs and manuals may be changed at any time based on improvements and other reasons. The next editions of the revised catalogs or manuals will be published with updated code numbers. Consult with your Yaskawa representative to confirm the actual specifications before purchasing a product.

Contents

MECHATROLINK-III Communication Settings

1

1.1 Layers

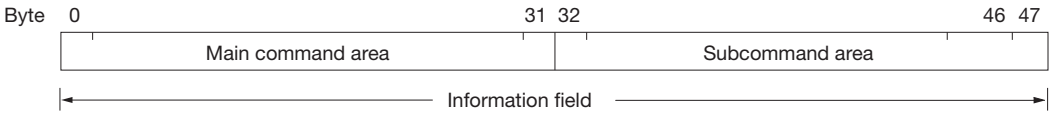
The MECHATROLINK-III communications layers have functions equivalent to layers 1, 2, and 7 in the OSI (Open System Interconnection) reference model.

OSI	MECHATROLINK-III Protocol
Layer 7: Application layer	MECHATROLINK-III application layer
Layers 3 to 6	None
Layer 2: Data link layer	ASIC dedicated to MECHATROLINK-III
Layer 1: Physical layer	Standard Ethernet PHY IEEE 802.3u

This manual describes standard servo profile commands for the application layer.

1.2 Frame Structure

A standard servo profile command is composed of the combination of a main command and a subcommand as shown below. It is also possible to use a main command alone.

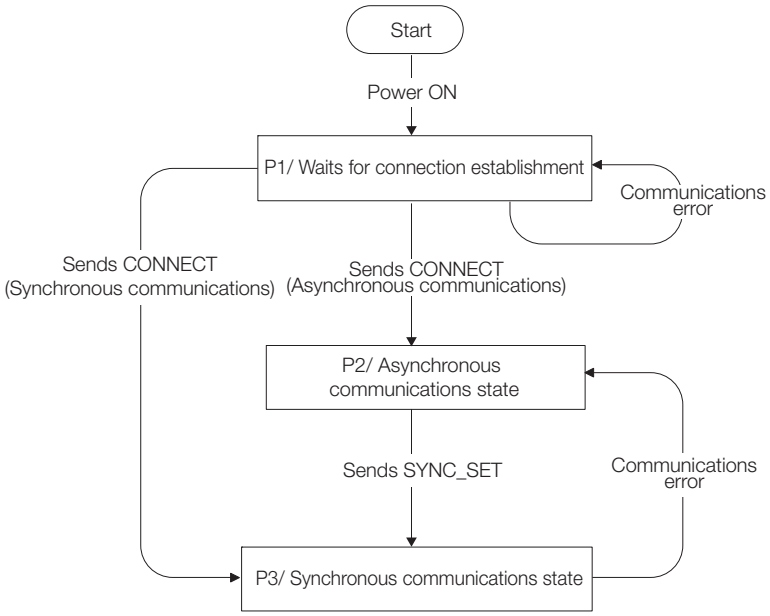


Classification	Byte	Command	Response
Information Field	0 to 31	Used by main commands.	
	32 to 47	Used by subcommands. The subcommands for servo commands use byte 33 to byte 48. Note: In some main commands, subcommand cannot be used.	

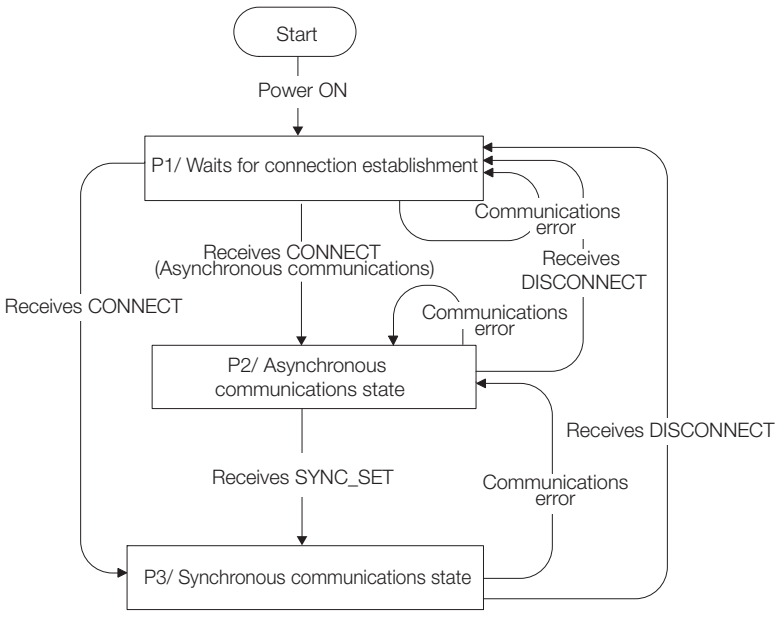
The application layer interfaces with only the information field.

1.3 State Transition Diagram

The master and slave station state transitions are shown in the following diagrams.



Master Station State Transition



Slave Station State Transition

Phase	Abbreviation	Description
1	P1	Waiting for establishment of connection.
2	P2	Asynchronous communications enabled. Only asynchronous commands can be used.
3	P3	Synchronous communications enabled. Both synchronous and asynchronous commands can be used.

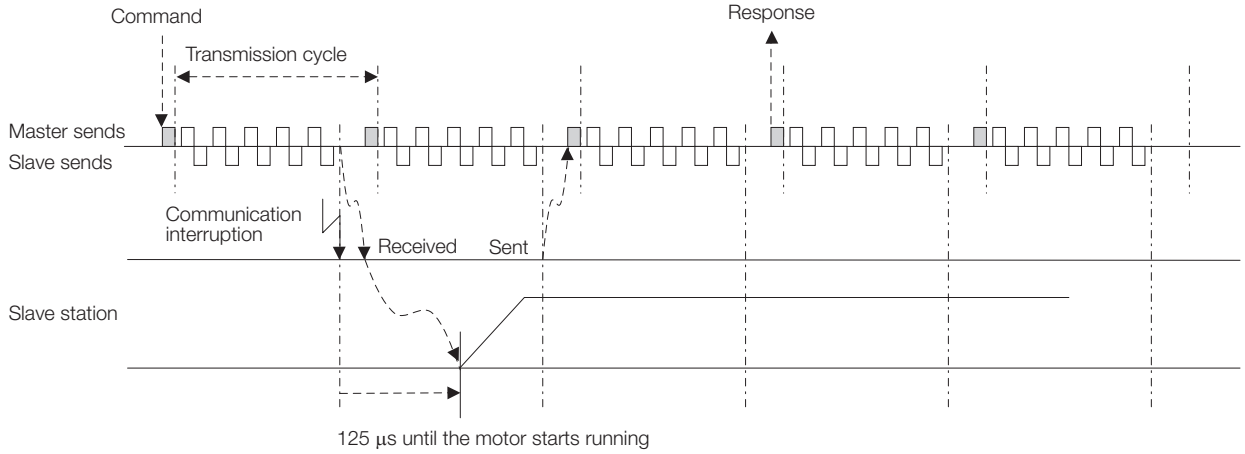
1.4 Command and Response Timing

This section describes command execution timing at the SERVOPACK and monitored data input timing at the master station.

These timings are constant, regardless of the transmission cycle and communication cycle.

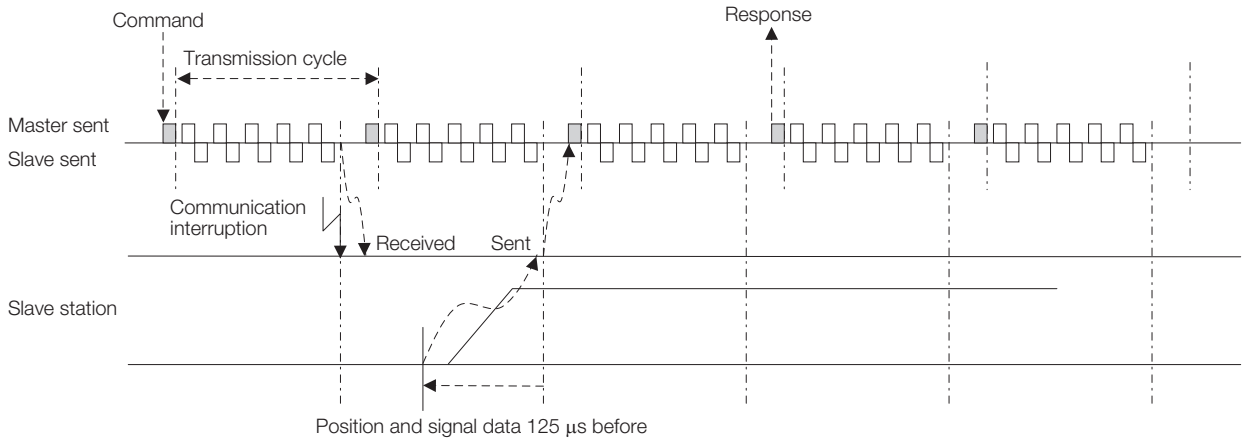
1.4.1 Command Data Execution Timing

Motion commands (such as POSING and INTERPOLATE), and the servo command control and servo command I/O signals (SVCMD_CTRL and SVCMD_IO) are executed 125 μs after their reception.



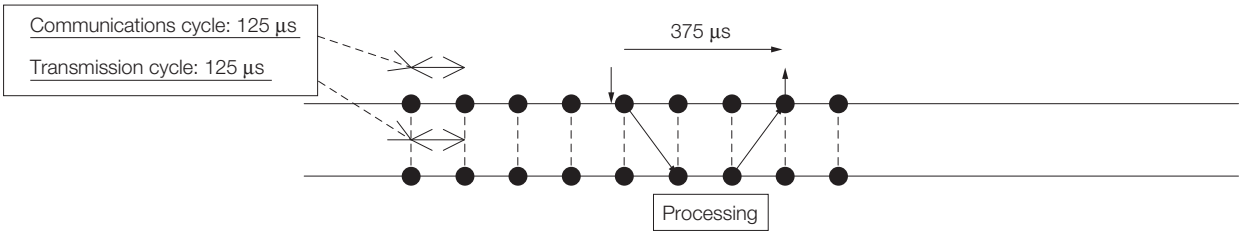
1.4.2 Monitored Data Input Timing

The monitor, I/O, and status data are the data of 125 μs before the response is sent.



1.4.3 Transmission Cycle and Communications Cycle (Support for 125 μs)

By adopting a shorter transmission cycle, the command throughput of the host controller is improved by eliminating transmission delays.



1.5 List of Commands

1.5.1 Command Types

Standard servo profile commands are classified into common commands and servo commands.

Common commands:Commands that are common for MECHATROLINK-III communications, independent of profiles

Servo commands:Commands that are defined in the standard servo profile and specific to SERVOPACKs

1.5.2 Main Commands

The standard servo profile main commands used for Σ-7-Series SERVOPACKs are listed below.

Category	Command Code	Command	Command Name	Function	Reference
Common Commands	00 hex	NOP	No operation command	Nothing is performed.	3.1.1
	03 hex	ID_RD	Read ID command	Reads the device ID.	3.1.2
	04 hex	CONFIG	Device setup request command	Enables the current parameter settings.	3.1.3
	05 hex	ALM_RD	Read alarm/ warning command	Reads the current alarm or warning status, and the alarm history.	3.1.4
	06 hex	ALM_CLR	Clear alarm/ warning state command	Clears the current alarm or warning status, and the alarm history.	3.1.5
	0D hex	SYNC_SET	Request for establishing synchronization command	Starts synchronous communications.	3.1.6
	0E hex	CONNECT	Request for establishing connection command	Requests the establishment of a connection and setting of the communication mode.	3.1.7
	0F hex	DISCONNECT	Request for releasing connection command	Requests disconnection.	3.1.8
	1D hex	MEM_RD	Read memory command	Reads data from virtual memory.	3.1.9
	1E hex	MEM_WR	Write memory command	Writes data to virtual memory.	3.1.10

Continued on next page.

Continued from previous page.

Category	Command Code	Command	Command Name	Function	Reference
Servo Commands	20 hex	POS_SET	Set coordinates command	Sets the coordinate system.	3.2.1
	21 hex	BRK_ON	Request for applying brake command	Turns the brake signal OFF and applies the holding brake.	3.2.2
	22 hex	BRK_OFF	Release brake command	Turns the brake signal ON and releases the holding brake.	3.2.3
	23 hex	SENS_ON	Request for turning sensor ON command	Turns the encoder power supply ON, and gets the position data.	3.2.4
	24 hex	SENS_OFF	Request for turning sensor OFF command	Turns the encoder power supply OFF.	3.2.5
	30 hex	SMON	Monitor servo status command	Monitors the SERVOPACK status.	3.2.6
	31 hex	SV_ON	Servo ON command	Turns the servo of the motor ON.	3.2.7
	32 hex	SV_OFF	Servo OFF command	Turns the servo of the motor OFF.	3.2.8
	34 hex	INTERPOLATE	Interpolation command	Starts interpolation feeding.	3.2.9
	35 hex	POSING	Positioning command	Starts positioning to the target position (TPOS) at the target speed (TSPD).	3.2.10
	36 hex	FEED	Constant speed feed command	Starts constant speed feeding at the target speed (TSPD).	3.2.11
	37 hex	EX_FEED	Positioning at constant speed by external input command	Starts constant speed feeding at the target speed (TSPD). When an external signal is input part way through, positioning to the specified position is performed from the external signal input position.	3.2.12
	39 hex	EX_POSING	Positioning by external input command	Starts positioning to the target position (TPOS) at the target speed (TSPD). When an external signal is input part way through, positioning to the specified position is performed from the external signal input position.	3.2.13
	3A hex	ZRET	Zero point return command	Performs zero point return.	3.2.14
	3C hex	VELCTRL	Velocity control command	Controls speed.	3.2.15
	3D hex	TRQCTRL	Torque control command	Controls torque.	3.2.16
	40 hex	SVPRM_RD	Read servo parameter command	Reads the specified servo parameter.	3.2.17
	41 hex	SVPRM_WR	Write servo parameter command	Writes the specified servo parameter.	3.2.18

1.5.3 Subcommands

The standard servo profile subcommands used for Σ-7-Series SERVOPACKs are listed below.

Category	Command Code	Command	Command Name	Function	Reference
Servo Commands	00 hex	NOP	No operation command	Nothing is performed.	4.2
	05 hex	ALM_RD	Read alarm/ warning command	Reads the current alarm or warning status, and the alarm history.	4.3
	06 hex	ALM_CLR	Clear alarm/ warning state command	Clears the current alarm or warning status, and the alarm history.	4.4
	1D hex	MEM_RD	Read memory command	Reads data from virtual memory.	4.5
	1E hex	MEM_WR	Write memory command	Writes data to virtual memory.	4.6
	30 hex	SMON	Monitor servo status command	Monitors the SERVOPACK status.	4.7
	40 hex	SVPRM_RD	Read servo parameter command	Reads the specified servo parameter.	4.8
	41 hex	SVPRM_WR	Write servo parameter command	Writes the specified servo parameter.	4.9

1.5.4 Combinations of Main Commands and Subcommands

The combinations of main commands and subcommands are listed below. When an invalid combination is specified, an alarm (SUBCMD_ALM = BH (A.95E)) occurs.

Main Command		Subcommands							
		NOP (00 hex)	ALM_RD (05 hex)	ALM_ CLR (06 hex)	MEM_ RD (1D hex)	MEM_ WR (1E hex)	SMON (30 hex)	SVPRM _RD (40 hex)	SVPRM _WR (41 hex)
Common Commands	NOP (00 hex)	○	○	○	○	○	○	○	○
	ID_RD (03 hex)	○	○	○	○	○	○	○	○
	CONFIG (04 hex)	○	×	×	×	×	○	×	×
	ALM_RD (05 hex)	○	×	×	×	×	○	×	×
	ALM_CLR (06 hex)	○	×	×	×	×	○	×	×
	SYNC_SET (0D hex)	○	×	×	×	×	○	×	×
	CONNECT (0E hex)	○	×	×	×	×	×	×	×
	DISCONNECT (0F hex)	○	×	×	×	×	×	×	×
	MEM_RD (1D hex)	○	×	×	×	×	○	×	×
	MEM_WR (1E hex)	○	×	×	×	×	○	×	×

Continued on next page.

Continued from previous page.

Main Command		Subcommands							
		NOP (00 hex)	ALM_RD (05 hex)	ALM_ CLR (06 hex)	MEM_ RD (1D hex)	MEM_ WR (1E hex)	SMON (30 hex)	SVPRM _RD (40 hex)	SVPRM _WR (41 hex)
Servo Commands	POS_SET (20 hex)	○	×	×	×	×	○	×	×
	BRK_ON (21 hex)	○	×	×	×	×	○	×	×
	BRK_OFF (22 hex)	○	×	×	×	×	○	×	×
	SENS_ON (23 hex)	○	×	×	×	×	○	×	×
	SENS_OFF (24 hex)	○	×	×	×	×	○	×	×
	SMON (30 hex)	○	○	○	○	○	○	○	○
	SV_ON (31 hex)	○	○	○	○	○	○	○	○
	SV_OFF (32 hex)	○	○	○	○	○	○	○	○
	INTERPOLATE (34 hex)	○	○	○	○	○	○	○	○
	POSING (35 hex)	○	○	○	○	○	○	○	○
	FEED (36 hex)	○	○	○	○	○	○	○	○
	EX_FEED (37 hex)	○	○	○	○	○	○	○	○
	EX_POSING (39 hex)	○	○	○	○	○	○	○	○
	ZRET (3A hex)	○	○	○	○	○	○	○	○
	VELCTRL (3C hex)	○	○	○	○	○	○	○	○
	TRQCTRL (3D hex)	○	○	○	○	○	○	○	○
	SVPRM_RD (40 hex)	○	×	×	×	×	○	×	×
	SVPRM_WR (41 hex)	○	×	×	×	×	○	×	×

○: Can be combined

×: Cannot be combined

Information Even for a valid combination, a command error (A.95A) occurs if the execution conditions of the commands are not satisfied.

Example If initialization of a parameter is attempted by the MEM_WR command while sending the SV_ON command (during the servo ON state), a command error (A.95A) occurs instead of a command interference error (A.95E).

Command Format

2

2.1 Common Command Format

This section describes the specifications that are common for all commands.

The format that is common for the commands sent from the master station and the responses returned from slave stations is shown below.

The format of a command can be divided into the main command area (32 bytes) and the subcommand area (16 bytes). The subcommand area is used to supplement the main command with another command. Whether the subcommand area is used or not is determined by the setting of the number of transmission bytes. When the number of transmission bytes is 32, the subcommand area is not used.

Both the main command area and subcommand area are divided into the command header section and the command data section.

Fields in the command header section of the main command area

Command: CMD, WDT, CMD_CTRL

Response: RCMD, RWDT, CMD_STAT

Fields in the command header section of the subcommand area

Command: SUBCMD, SUB_CTRL

Response: RSUBCMD, SUB_STAT

	Byte	Command	Response	Description
Main Command Area	0	CMD	RCMD	• CMD/RCMD: Command code specified for individual commands. Refer to the following section. ☞ *2.2.1 Command Code (CMD/RCMD)* on page 2-5.
	1	WDT	RWDT	
	2	CMD_CTRL	CMD_STAT	
	3			
	4	CMD_DATA	RSP_DATA	• WDT/RWDT: Refer to the following section. ☞ *2.2.2 Watchdog Data (WDT/RWDT)* on page 2-6. • CMD_CTRL: Refer to the following section. ☞ *2.2.3 Command Control (CMD_CTRL)* on page 2-6. • CMD_STAT: Refer to the following section. ☞ *2.2.4 Command Status (CMD_STAT)* on page 2-7. • CMD_DATA/RSP_DATA: Specified for individual commands.
	5			
	6			
	7			
	8			
	9			
	10			
	11			
	12			
	13			
	14			
	15			
	16			
	17			
	18			
	19			
	20			
	21			
	22			
	23			
	24			
	25			
	26			
	27			
	28			
	29			
	30			
	31			

Continued on next page.

Continued from previous page.

	Byte	Command	Response	Description
Sub-command Area	32	SUBCMD	RSUBCMD	• SUBCMD/RSUBCMD: Command code specified for individual commands. Refer to the following section. ☞ *4.1 Subcommands* on page 4-2. • SUB_CTRL: Refer to the following section. ☞ *2.3.2 Subcommand Control (SUB_CTRL)* on page 2-11. • SUB_STAT: Refer to the following section. ☞ *2.3.3 Subcommand Status (SUB_STAT)* on page 2-12. • SUB_CMD_DATA/SUB_RSP_DATA: Specified for individual commands. Refer to the following chapter. ☞ *Chapter 4 Subcommands*.
	33	SUB_CTRL	SUB_STAT	
	34			
	35			
	36	SUB_CMD_DATA	SUB_RSP_DATA	
	37			
	38			
	: :			
	45			
	46			
	47			

2.2 Command Header Section of Main Command Area

This section describes the command header section of the main command area.

2.2.1 Command Code (CMD/RCMD)

This is the command code that defines the meaning of the messaging. Byte 0 of the command format is defined as the CMD/RCMD field. The data set in this field of the response data is a copy of that of the command data.

The following table shows the command codes.

Profile	Command Code	Command	Operation	Applicability*1	Communication Phases*3		
					1	2	3
Common Commands	00 hex	NOP	No operation	○	–	○	○
	01 hex	PRM_RD	Read parameter	×*2	–	×	×
	02 hex	PRM_WR	Write parameter	×*2	–	×	×
	03 hex	ID_RD	Read ID	○	–	○	○
	04 hex	CONFIG	Device setup request	Δ	–	○	○
	05 hex	ALM_RD	Read alarm/warning	Δ	–	○	○
	06 hex	ALM_CLR	Clear alarm/warning state	○	–	○	○
	0D hex	SYNC_SET	Request for establishing synchronization	○	–	○	Δ
	0E hex	CONNECT	Request for establishing connection	○	○	Δ	Δ
	0F hex	DISCONNECT	Request for releasing connection	○	○	○	○
	1B hex	PPRM_RD	Read stored parameter	×*2	–	×	×
	1C hex	PPRM_WR	Write stored parameter	×*2	–	×	×
	1D hex	MEM_RD	Read memory	Δ	–	○	○
	1E hex	MEM_WR	Write memory	Δ	–	○	○
Servo Commands	20 hex	POS_SET	Set coordinates	○	–	○	○
	21 hex	BRK_ON	Request for applying brake	○	–	○	○
	22 hex	BRK_OFF	Release brake	○	–	○	○
	23 hex	SENS_ON	Request for turning sensor ON	○	–	○	○
	24 hex	SENS_OFF	Request for turning sensor OFF	○	–	○	○
	30 hex	SMON	Monitor servo status	○	–	○	○
	31 hex	SV_ON	Servo ON	○	–	○	○
	32 hex	SV_OFF	Servo OFF	○	–	○	○
	34 hex	INTERPOLATE	Interpolation	○	–	×	○
	35 hex	POSING	Positioning	○	–	○	○
	36 hex	FEED	Constant speed feed	○	–	○	○
	37 hex	EX_FEED	Positioning at constant speed by external input	○	–	○	○
	39 hex	EX_POSING	Positioning by external input	○	–	○	○
	3A hex	ZRET	Zero point return	○	–	○	○
	3C hex	VELCTRL	Velocity control	○	–	○	○
	3D hex	TRQCTRL	Torque control	○	–	○	○
	40 hex	SVPRM_RD	Read servo parameter	Δ	–	○	○
	41 hex	SVPRM_WR	Write servo parameter	○	–	○	○

*1. This column shows whether the commands can be used with the Σ-7 Series.
○: Can be used, Δ: Can be used with restrictions (Refer to the section for each command for actual restrictions.), ×: Cannot be used.

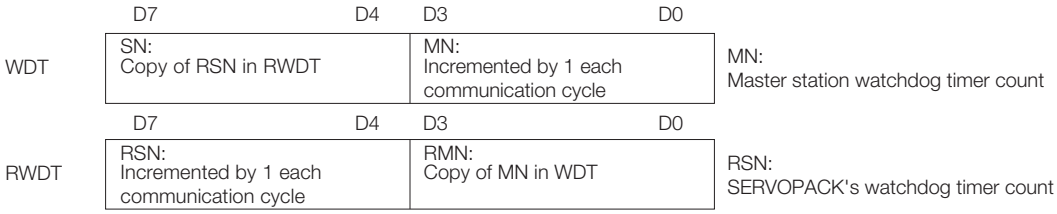
*2. The standard servo command profile does not use PRM_RD, PRM_WR, PPRM_RD and PPRM_WR, but uses SVPRM_RD and SVPRM_WR instead.

*3. O: Can be executed, Δ: Ignored, ×: Command error, –: Indefinite response data
Refer to the following section for details.
☞ *1.3 State Transition Diagram* on page 1-4.

2.2.2 Watchdog Data (WDT/RWDT)

The details of the watchdog timer (WDT) data in commands and responses are described below.

Byte 1 of the command/response format is specified as the WDT/RWDT field.



The watchdog data (WDT) is checked after establishing synchronous communications (phase 3).
The watchdog data (RWDT) at the SERVOPACK will be refreshed regardless of the establishment of synchronous communications.

2.2.3 Command Control (CMD_CTRL)

The following describes the command control data.

Byte 2 and byte 3 of the command format are specified as the CMD_CTRL field.

The designation in the CMD_CTRL field is valid even when an alarm specified by CMD_ALM has occurred.

The CMD_CTRL field is specified as shown below by the communication specification.

bit 7	bit 6	bit 5	bit 4	bit 3	bit 2	bit 1	bit 0
CMD_ID		Reserved	Reserved	ALM_CLR	Reserved	Reserved	Reserved

bit 15	bit 14	bit 13	bit 12	bit 11	bit 10	bit 9	bit 8
Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved	Reserved

ALM_CLR: Clear Alarm/Warning State

◆ Definition

Clears the alarms and warnings that have occurred in the SERVOPACK.

0: Clear alarm/warning disabled
1: Clear alarm/warning triggered

◆ Description

Clears the alarm/warning state at the leading edge.
The same processing as when ALM_CLR_MODE = 0 for the ALM_CLR command (the current alarm/warning state is cleared) is performed.

CMD_ID: Command ID

◆ Definition

The master station uses the command ID to have a slave station acknowledge that the command is a new command when the master station sends the same command repeatedly to the slave station.

Applicable commands: EX_FEED, EX_POSING, ZRET
A value in the range 0 to 3 is used.

◆ Description

Since the slave station returns the CMD_ID of the command being executed, the master station can decisively judge the command to which the slave station sent the response.
While CMD_RDY = 0 (while the execution process of the command is incomplete), the slave station disregards commands that have a different CMD_ID and continues the execution of the command being executed.

2.2.4 Command Status (CMD_STAT)

The following describes the status of responses.

Byte 2 and byte 3 of the response format are specified as the CMD_STAT field.

The CMD_STAT field is specified as shown below by the communication specification.

bit 7	bit 6	bit 5	bit 4	bit 3	bit 2	bit 1	bit 0
RCMD_ID		Reserved	Reserved	ALM_CL-R_CMP	CMDRDY	D_WAR	D_ALM

bit 15	bit 14	bit 13	bit 12	bit 11	bit 10	bit 9	bit 8
COMM_ALM				CMD_ALM			

D_ALM

◆ Definition

This bit indicates the device alarm state of the slave station.
1: A device-specific alarm has occurred.
0: Other state (normal state, or the alarm specified by COMM_ALM or CMD_ALM has occurred.)

◆ Description

- When a device-specific alarm other than the alarm state specified by COMM_ALM and CMD_ALM has occurred, the D_ALM status bit is set to "1."
  D_ALM is independent of COMM_ALM and CMD_ALM.
- When a device-specific alarm has occurred and D_ALM is set to "1" in the servo ON state, the servo OFF state is established.
- When the slave station shifts from the alarm state to the normal state as a result of the execution of the ALM_CLR command or CMD_CTRL.ALM_CLR, this bit is set to "0."

Example Device alarm: Position Deviation Overflow (A.D00) → D_ALM = 1

D_WAR

◆ Definition

This bit indicates the device warning state of the slave station.
1: A device-specific warning has occurred.
0: Other state (normal state, or the alarm specified by COMM_ALM or CMD_ALM has occurred.)

◆ Description

- When a device-specific warning other than the warning state specified by COMM_ALM or CMD_ALM has occurred, the D_WAR status bit is set to "1."
  D_WAR is independent of COMM_ALM and CMD_ALM.
- When a device-specific warning has occurred and the D_WAR status bit is set to "1" in the servo ON state, the servo ON state is retained.
- When the slave station shifts from the device warning state to the normal state as a result of the execution of the ALM_CLR command or CMD_CTRL.ALM_CLR, this bit is set to "0."

Example Device warning: Overload (A.910) → D_WAR = 1

CMDRDY

◆ Definition

This bit indicates whether the slave station is ready to receive commands.
1: Command reception enabled
0: Command reception disabled

◆ Description

- CMDRDY = 0 means that command processing is in progress. While CMDRDY = 0, the slave station continues to process the current command, but the slave station will discard new commands received while CMDRDY = 0.
  Only the DISCONNECT command is executed immediately regardless of the CMDRDY value.
- Completion of command execution is confirmed in accordance with the completion confirmation method of each command.
- The hold time for CMDRDY = 0 is specified for each command.
- If command execution is possible despite an alarm or warning state, CMDRDY is set to "1."

ALM_CLR_CMP

◆ Definition

This bit indicates the execution state of the ALM_CLR command.
1: Execution of the ALM_CLR command (CMD_CTRL.ALM_CLR) completed
0: Other

◆ Description

- ALM_CLR_CMP is set to "1" in the following cases.
  - When the alarm clear processing executed by the ALM_CLR command has been completed
    ALM_CLR_CMP is set to "1" when the alarm cannot be cleared as well.
  - When the alarm clear processing time (approx. 200 ms) has elapsed after receiving the ALM_CLR command.
    ALM_CLR_CMP is set to "1" when the alarm cannot be cleared as well.
- ALM_CLR_CMP can be cancelled by setting "0" for CMD_CTRL.ALM_CLR.

RCMD_ID

◆ Definition

This is the echo-back of the CMD_ID in the CMD_CTRL field of the command data.

◆ Description

- This is the identification code of the same commands that the slave station has received contiguously.
- Returns the CMD_ID of the command format.

CMD_ALM

◆ Definition

This bit indicates the validation result of the command.

◆ Description

- CMD_ALM indicates whether the command is valid or not. The results of validations of the command codes, and the combinations of commands and the data in the command frame are notified.
- CMD_ALM is independent of COMM_ALM, D_ALM and D_WAR.
- If a normal command is received after the occurrence of a command error, CMD_ALM is automatically cleared.
- The phase doesn't change even if the status of CMD_ALM is not "0." The servo ON/OFF state doesn't change either.

Code		Description	Remark
Normal	0	Normal	–
Warning	1	Invalid data	The slave station notifies the warning state, but operates at the specified value or the value on clamping at the maximum or minimum value.
	2	–	
	3	–	
	4	–	
	5	–	
	6	–	
	7	–	
Alarm	8	Unsupported command received	The slave station notifies the alarm state and the command is not executed.
	9	Invalid data	
	A	Command execution condition error	
	B	Subcommand combination error	
	C	Phase error	
	D	–	
	E	–	
	F	–	

Example Command error: Data Setting Warning 2 (A.94B) → CMD_ALM = 9 hex

Check the status of CMD_ALM with the host controller for every communication cycle and perform appropriate processing because CMD_ALM will be automatically cleared.

COMM_ALM

◆ Definition

This bit indicates the MECHATROLINK communications error status.

◆ Description

- COMM_ALM shows if the data transmission in the physical or application layer has completed normally or not.
- COMM_ALM is independent of CMD_ALM, D_ALM and D_WAR.
- COMM_ALM is cleared by the ALM_CLR command or CMD_CTRL.ALM_CLR.

Code		Description	Remark
Normal	0	Normal	–
Warning	1	FCS error	Occurs when an error is detected once. The servo ON state is retained when an error is detected in the servo ON state. Error detection method 1:FCS error The SERVOPACK detects FCS errors. 2:Command data not received The SERVOPACK detects that command data has not been received. 3:Synchronous frame not received The SERVOPACK detects that the synchronous frame has not been received.
	2	Command data not received	
	3	Synchronous frame not received	
	4	–	
	5	–	
	6	–	
	7	–	
Alarm	8	FCS error	Occurs when an error is detected in the following detection methods. • If the system is in communication phase 3, it will shift to communication phase 2. • Establishes the servo OFF state. Error detection method 8, 9, A: Set if an error is detected twice consecutively using the error detection method for warnings 1, 2 and 3 described above. B, C: Set immediately upon occurrence of a single error.
	9	Command data not received	
	A	Synchronous frame not received	
	B	Synchronization interval error	
	C	WDT error	
	D	–	
	E	–	
	F	–	

Example

Communications error (warning):MECHATROLINK Communications Warning (A.960) → COMM_ALM = 2 hex
Communications error (alarm):Reception Error in MECHATROLINK Communications (A.E60) → COMM_ALM = 9 hex

2.3 Command Header Section of Subcommand Area

Subcommands use byte 32 to byte 47 of the data field and function as a supplementary command to the main command. This subsection describes the command header section of the subcommand area.

2.3.1 Subcommand Codes (SUB_CMD/SUB_RCMD)

This is the subcommand code that specifies the meaning of the subcommand messaging. Byte 32 of the command format is defined as the SUB_CMD/SUB_RCMD field. The data set in this field of the response data is a copy of that of the command data.

The following table shows the subcommand codes.

Profile	Command Code	Command	Operation	Communication Phases*2		
				1	2	3
Servo Commands	00 hex	NOP	No operation	–	O	O
	05 hex	ALM_RD*1	Read alarm/warning	–	O	O
	06 hex	ALM_CLR	Clear alarm/warning state	–	O	O
	1D hex	MEM_RD*1	Read memory command	–	O	O
	1E hex	MEM_WR*1	Write memory command	–	O	O
	30 hex	SMON	Monitor servo status	–	O	O
	40 hex	SVPRM_RD*1	Read servo parameter	–	O	O
	41 hex	SVPRM_WR	Write servo parameter	–	O	O

*1. Specification restrictions apply (Refer to the subsection describing each command for the details of the restrictions.)

*2. O: Can be executed, Δ: Ignored, ×: Command error, –: Indefinite response data

2.3.2 Subcommand Control (SUB_CTRL)

The following describes the subcommand control data.

Byte 33 to byte 35 of the command format are specified as the SUB_CTRL field.

The SUB_CTRL field is specified as shown below by the communication specification.

SUB_CTRL Field

bit 7	bit 6	bit 5	bit 4	bit 3	bit 2	bit 1	bit 0
Reserved		Reserved		Reserved			
bit 15	bit 14	bit 13	bit 12	bit 11	bit 10	bit 9	bit 8
SEL_MON4				Reserved			
bit 23	bit 22	bit 21	bit 20	bit 19	bit 18	bit 17	bit 16
SEL_MON6				SEL_MON5			

Details of Control Bits

The following table shows the details of the control bits.

Bit	Name	Description	Value	Setting
12 to 15	SEL_MON4	Monitor selection 4	0 to 15	Selects the monitor information with the setting value.
16 to 19	SEL_MON5	Monitor selection 5	0 to 15	Selects the monitor information with the setting value.
20 to 23	SEL_MON6	Monitor selection 6	0 to 15	Selects the monitor information with the setting value.

2.3.3 Subcommand Status (SUB_STAT)

The following describes the subcommand status of responses.

Byte 33 to byte 35 of the response format are specified as the SUB_STAT field.

The SUB_STAT field is specified as shown below by the communication specification.

SUB_STAT Field

bit 7	bit 6	bit 5	bit 4	bit 3	bit 2	bit 1	bit 0
Reserved		Reserved		Reserved	SUBCMDRDY	Reserved	Reserved

bit 15	bit 14	bit 13	bit 12	bit 11	bit 10	bit 9	bit 8
SEL_MON4				SUBCMD_ALM			

bit 23	bit 22	bit 21	bit 20	bit 19	bit 18	bit 17	bit 16
SEL_MON6				SEL_MON5			

Details of Status Bits

The following table shows the details of the status bits.

Bit	Name	Description	Value	Setting
2	SUBCMDRDY*	Subcommand ready	1	Subcommand reception enabled
			0	Other
8 to 11	SUBCMD_ALM	Subcommand alarm	0 to 15	Refer to the following section. ☞ *2.2.4 Command Status (CMD_STAT)* on page 2-7.
12 to 15	SEL_MON4	Monitor selection 4	0 to 15	Indicates the selected monitor information. (Copy of the command)
16 to 19	SEL_MON5	Monitor selection 5	0 to 15	Indicates the selected monitor information. (Copy of the command)
20 to 23	SEL_MON6	Monitor selection 6	0 to 15	Indicates the selected monitor information. (Copy of the command)

* When no subcommand is used, the SUBCMDRDY status bit is set to "1."

2.4 Servo Command Format

This section describes the specifications of the servo commands.

The servo commands are specified by the 32-byte command and response data in the communication specifications as shown in the table below.

The command/response data area can be expanded to 48 bytes by using subcommands. For the subcommands, refer to the following chapter.

☞ *Chapter 4 Subcommands*

The following table shows the format of the servo command and response data.

Byte	Command	Response	Description
0	CMD	RCMD	• CMD_CTRL: Refer to the following section. ☞ *2.2.3 Command Control (CMD_CTRL)* on page 2-6. • CMD_STAT: Refer to the following section. ☞ *2.2.4 Command Status (CMD_STAT)* on page 2-7. • SVCMD_CTRL: Refer to the following section. ☞ *2.5.1 Servo Command Control (SVCMD_CTRL)* on page 2-14. • SVCMD_STAT: Refer to the following section. ☞ *2.5.2 Servo Command Status (SVCMD_STAT)* on page 2-16. • SVCMD_IO: Refer to the following section. ☞ *2.6 Servo Command I/O Signal (SVCMD_IO)* on page 2-22. • CMD_DATA/RSP_DATA: Specified for individual commands.
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	CMD_DATA	RSP_DATA	
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

2.5 Command Header Section

For the details of the command header section (command code, watchdog data and command control fields), refer to the following section.

☞ *2.2 Command Header Section of Main Command Area* on page 2-5

2.5.1 Servo Command Control (SVCMD_CTRL)

Byte 4 to byte 7 of the command format are specified as the SVCMD_CTRL field.
The control bit specifies a motion command for a slave station.

The SVCMD_CTRL field contains auxiliary data for the specified command and the control bits have no meaning with commands other than the command that specified the data.

Note that the designation in this field is valid even when a CMD_ALM has occurred.

The SVCMD_CTRL field is specified as shown below by the communication specification.

SVCMD_CTRL Field

bit 7	bit 6	bit 5	bit 4	bit 3	bit 2	bit 1	bit 0
Reserved (0)		ACCFIL		STOP_MODE		CMD_ CANCEL	CMD_ PAUSE
bit 15	bit 14	bit 13	bit 12	bit 11	bit 10	bit 9	bit 8
Reserved (0)		LT_SEL2		LT_SEL1		LT_REQ2	LT_REQ1
bit 23	bit 22	bit 21	bit 20	bit 19	bit 18	bit 17	bit 16
SEL_MON2				SEL_MON1			
bit 31	bit 30	bit 29	bit 28	bit 27	bit 26	bit 25	bit 24
Reserved (0)				SEL_MON3			

Details of Control Bits

The following table shows the details of the control bits.

Bit	Name	Description	Value	Setting	Enabled Timing
0	CMD_PAUSE	Pause of Move Command	0	None	Level
			1	Move command pause command	
	Pauses execution of the POSING, FEED, EX_FEED, EX_POSING, ZRET and VELCTRL commands according to STOP_MODE.				
1	CMD_CANCEL	Cancellation of Move Command	0	None	Level
			1	Cancellation of move command	
	Cancels execution of the POSING, FEED, EX_FEED, EX_POSING, ZRET and VELCTRL commands according to STOP_MODE.				
2, 3	STOP_MODE	Selection of Stop Mode	0	Stop after deceleration	Level
			1	Immediate stop	
			2	Reserved	
			3	Reserved	
	Selects the stop mode for CMD_PAUSE and CMD_CANCEL.				

Continued on next page.

Continued from previous page.

Bit	Name	Description	Value	Setting	Enabled Timing
4, 5	ACCFIL	Selection of Position Reference Filter	0	No position reference filter	Level
			1	Exponential function position reference filter	
			2	Movement average position reference filter	
			3	Reserved	
	To be set when specifying the position reference filter.				
8	LT_REQ1	Latch Request 1	0	None	Leading edge
			1	Request for latch	
	Requests latch by the C phase or an external input signal.				
9	LT_REQ2	Latch Request 2	0	None	Leading edge
			1	Request for latch	
	Requests latch by the C phase or an external input signal. This can be used as the continuous latch mode as well.				
10, 11	LT_SEL1	Latch Signal Select 1	0	C phase	Leading edge of LT_REQ1
			1	External input signal 1	
			2	External input signal 2	
			3	External input signal 3	
	Selects the C phase or the external input signal for LT_REQ1. Make a setting different from LT_SEL2.				
12, 13	LT_SEL2	Latch Signal Select 2	0	C phase	Leading edge of LT_REQ2
			1	External input signal 1	
			2	External input signal 2	
			3	External input signal 3	
	Selects the C phase or the external input signal for LT_REQ2. Make a setting different from LT_SEL1. When the continuous latch mode is selected, this setting will be ignored since the signal set with the parameter is used.				
16 to 18	SEL_MON1	Monitor Selection 1	0 to 15	Monitor selection	Level
	Sets the monitor information.				
19 to 22	SEL_MON2	Monitor Selection 2	0 to 15	Monitor selection	Level
	Sets the monitor information.				
23 to 26	SEL_MON3	Monitor Selection 3	0 to 15	Monitor selection	Level
	Sets the monitor information.				

2.5.2 Servo Command Status (SVCMD_STAT)

Byte 4 to byte 7 of the response format are specified as the SVCMD_STAT field.
The status bit indicates the status of the slave station.

Note that the designation in this field is valid even when a CMD_ALM has occurred.

The SVCMD_STAT field is specified as shown below by the communication specification.

SVCMD_STAT Field

bit 7	bit 6	bit 5	bit 4	bit 3	bit 2	bit 1	bit 0
Reserved (0)		ACCFIL		Reserved (0)		CMD _CANCEL _CMP	CMD _PAUSE _CMP
bit 15	bit 14	bit 13	bit 12	bit 11	bit 10	bit 9	bit 8
Reserved (0)		SV_ON	M_RDY	PON	POS_RDY	L_CMP2	L_CMP1
bit 23	bit 22	bit 21	bit 20	bit 19	bit 18	bit 17	bit 16
SEL_MON2				SEL_MON1			
bit 31	bit 30	bit 29	bit 28	bit 27	bit 26	bit 25	bit 24
Reserved (0)				SEL_MON3			

Details of Status Bits

The following table shows the details of the status bits.

bit	Name	Description	Value	Setting
0	CMD_PAUSE_ CMP	Completion of Pause of Move Command	0	Incomplete (when pausing commanded)
			1	Pausing of move command completed
	The status used to judge the completion of pausing of the POSING, FEED, EX_FEED, EX_POSING, ZRET and VELCTRL commands			
1	CMD_CANCEL_ CMP	Completion of Cancellation of Move Command	0	Incomplete (when cancellation commanded)
			1	Cancellation of move command completed
	The status used to judge the completion of cancellation of the POSING, FEED, EX_FEED, EX_-POSING, ZRET and VELCTRL commands			
4, 5	ACCFIL	Current Position Reference Filter	0	No position reference filter
			1	Exponential function position reference filter
			2	Movement average position reference filter
			3	Reserved
	The status used to judge the position reference filter currently being applied			
8	L_CMP1	Latch Completion 1	0	Latch not completed
			1	Latch completed
	The status used to judge the completion of latching requested by LT_REQ1 Up until "0" is set for LT_REQ1, L_CMP1 is maintained at "1."			
9	L_CMP2	Latch Completion 2	0	Latch not completed
			1	Latch completed
	The status used to judge the completion of latching requested by LT_REQ2 Up until "0" is set for LT_REQ2, L_CMP2 is maintained at "1." In the continuous latch mode, L_CMP2 is returned to "0" after one communication cycle after completing latching.			

Continued on next page.

Continued from previous page.

bit	Name	Description	Value	Setting
10	POS_RDY	Position Data Enabled	0	Disabled
			1	Enabled
	The status used to judge if the position data currently being monitored as the monitor information of the response data is valid When an incremental encoder is used:"1" is set on completion of the CONNECT command. When an absolute encoder is used:"1" is set on completion of the SENS_ON command and "0" is set on completion of the SENS_OFF and CONFIG commands. When position data cannot be obtained properly due to an encoder error, "0" is set.			
11	PON	Power ON	0	Power OFF
			1	Power ON
	The status used to judge if the power is turned ON or not			
12	M_RDY	Motor Energization Ready	0	Not ready
			1	Ready
	The status used to judge if the servo can be turned ON or not			
13	SV_ON	Servo ON	0	Servo OFF
			1	Servo ON
	The status used to judge if the motor is energized or not			
16 to 19	SEL_MON1	Monitor Selection 1: Returns what data is being monitored.	0 to 15	Monitor selection
	The status used to judge the data currently being monitored as the monitor information of the response data (Copy of the command) Refer to the following section for details. ☞ *2.7.3 Specifying Monitor Data* on page 2-27.			
20 to 23	SEL_MON2	Monitor Selection 2: Returns what data is being monitored.	0 to 15	Monitor selection
	The status used to judge the data currently being monitored as the monitor information of the response data (Copy of the command) Refer to the following section for details. ☞ *2.7.3 Specifying Monitor Data* on page 2-27.			
24 to 27	SEL_MON3	Monitor Selection 3: Returns what data is being monitored.	0 to 15	Monitor selection
	The status used to judge the data currently being monitored as the monitor information of the response data (Copy of the command) Refer to the following section for details. ☞ *2.7.3 Specifying Monitor Data* on page 2-27.			

2.5.3 Supplementary Information on CMD_PAUSE and CMD_-CANCEL

CMD_PAUSE (Pausing a Command Operation)

- CMD_PAUSE is used to pause motion command operation. (Motion command processing continues. Motion command operation can be resumed by clearing CMD_PAUSE.)
- CMD_PAUSE is valid only when the POSING, FEED, EX_FEED, EX_POSING, ZRET or VELCTRL command is specified.

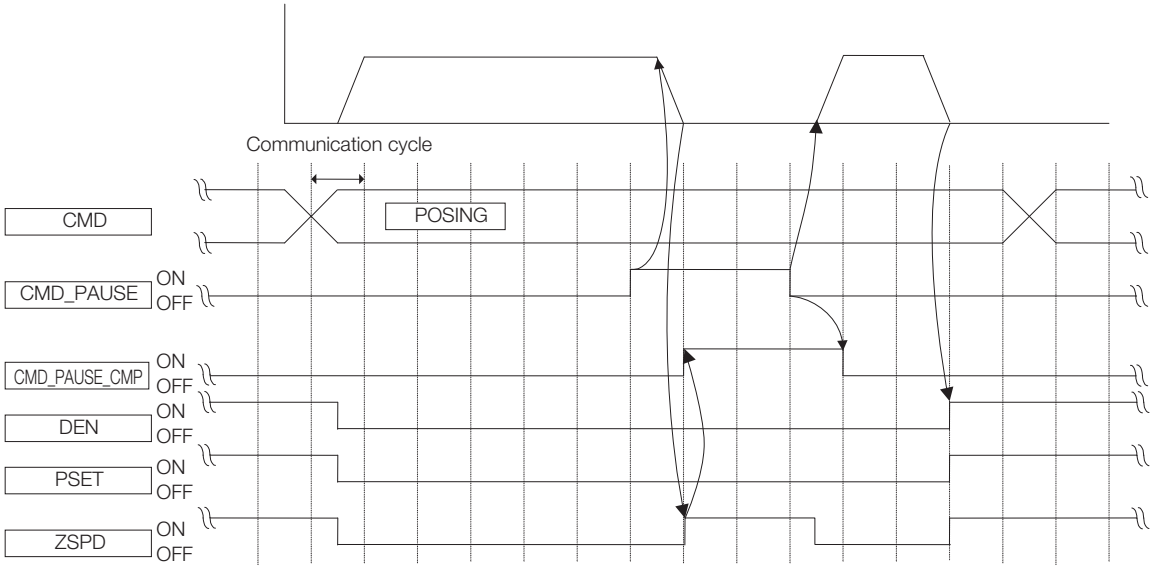
◆ Pausing Procedure

1. The master station sets "1" for STOP_MODE and CMD_PAUSE and transmits one of the motion commands given above.
2. The slave station stops in accordance with STOP_MODE. When deceleration to a stop is specified, the slave station decelerates its motion at the deceleration specified in DECR of the command.
3. "1" is set for CMD_PAUSE_CMP at the slave station when CMD_PAUSE and ZSPD become "1."
   Even after stopping, the slave station maintains the previous control mode and DEN remains at "0" (in the position control mode).

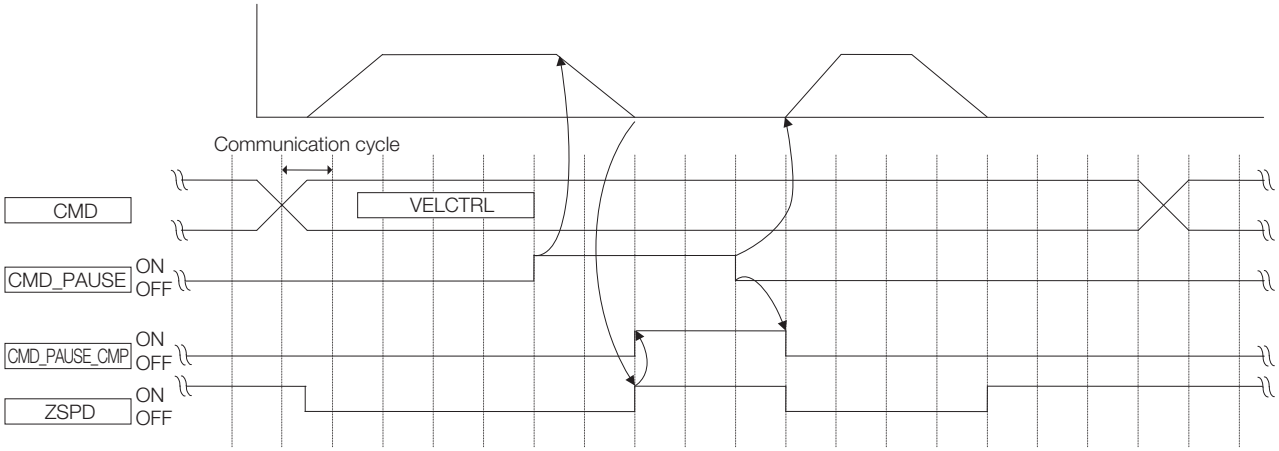
Note

- CMD_PAUSE is disregarded for commands for which CMD_PAUSE is not valid, and CMD_PAUSE_CMP remains OFF.
- When using CMD_PAUSE, execute the relevant motion command continuously until CMD_PAUSE_CMP becomes "1."
- By setting "0" for CMD_PAUSE, the pausing operation is canceled and the motion command operation is resumed.

◆ Example of Pausing the POSING Command



◆ Example of Pausing the VELCTRL Command



CMD_CANCEL (Canceling a Command Operation)

- CMD_CANCEL is used to interrupt motion command operation. (Motion command processing is cleared.)
- CMD_CANCEL is valid only when the POSING, FEED, EX_FEED, EX_POSING, ZRET or VELCTRL command is specified.

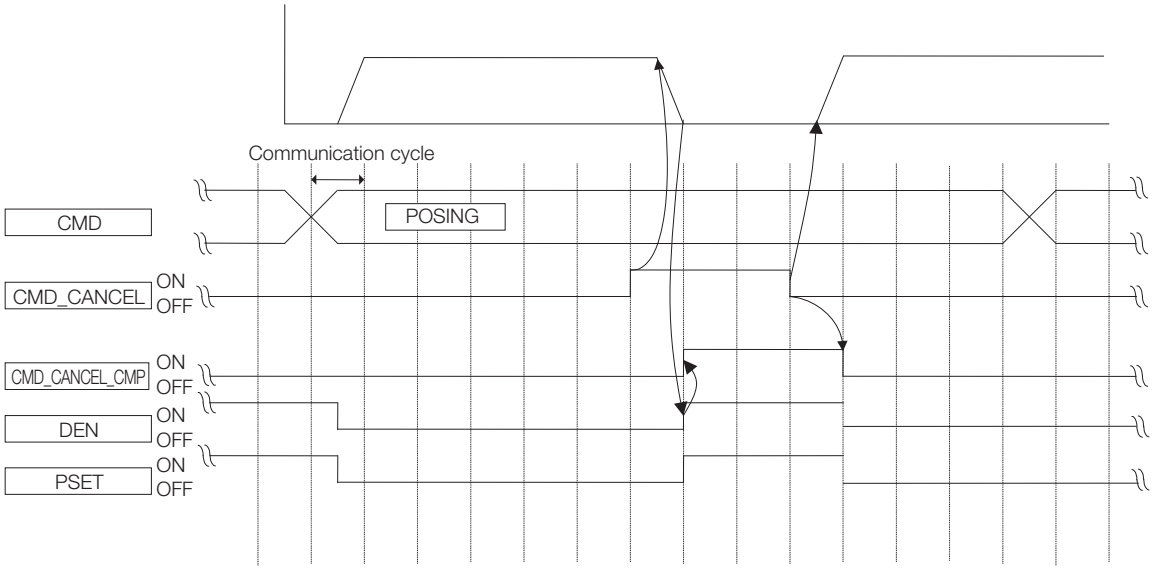
◆ Canceling Procedure

1. The master station sets "1" for STOP_MODE and CMD_CANCEL and transmits one of the motion commands given above.
2. The slave station stops in accordance with STOP_MODE. When deceleration to a stop is specified, the slave station decelerates its motion at the deceleration specified in DECR of the command.
3. "1" is set for CMD_CANCEL_CMP at the slave station in the following circumstances.
   In the position control mode:When CMD_CANCEL and DEN become "1"
   In the speed control mode:When CMD_CANCEL and ZSPD become "1"
   Even after stopping, the slave station maintains the previous control mode.

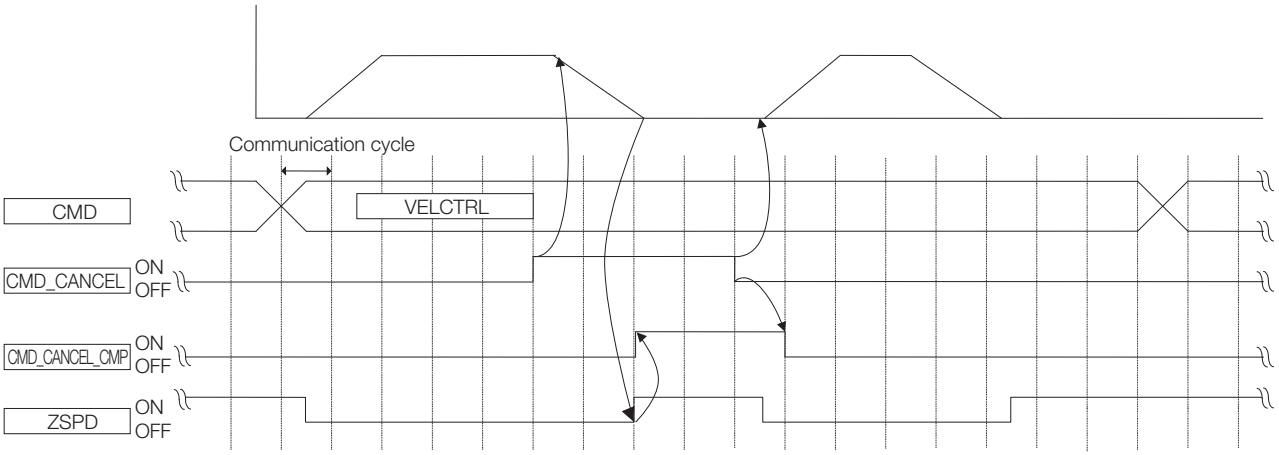
Note

- CMD_CANCEL is disregarded for commands for which CMD_CANCEL is not valid, and CMD_CANCEL_CMP remains OFF.
- When CMD_PAUSE and CMD_CANCEL are simultaneously turned ON or when CMD_CANCEL is turned ON after CMD_PAUSE, CMD_CANCEL takes priority.
- When using CMD_CANCEL, execute the relevant motion command continuously until CMD_CANCEL_CMP becomes "1."
- By setting "0" for CMD_CANCEL, the cancellation operation is canceled and the motion command is processed as a new motion command.

◆ Example of Canceling the POSING Command



◆ Example of Canceling the VELCTRL Command



2.5.4 Supplementary Information on Latching Operation

The latch operation is enabled at the leading edge of LT_REQ1 and LT_REQ2. The operations to be performed when commands are changed after enabling the latch operation are specified in the table below.
(The value of LT_SEL is an example.)

Command before Switching	Command after Switching	Latch Operation
Command without a latch function LT_SEL = 1 LT_REQ = 1	Common commands	Continues the latch request before switching.
Command with a latch function LT_SEL = 1 LT_REQ = 1	Common commands	Interrupts operation as a command with a latch function.
Command without a latch function LT_SEL = 1 LT_REQ = 1	Command without a latch function LT_SEL = 1 LT_REQ = 1	Continues the latch request before switching.
Command without a latch function LT_SEL = 1 LT_REQ = 1	Command without a latch function LT_SEL = 2 LT_REQ = 1	Continues the latch request before switching.
Command without a latch function LT_SEL = 1 LT_REQ = 1	Command with a latch function LT_SEL = 1 LT_REQ = 1	Switches to a latch request for the command after switching. The servo drive executes another latch request. (Internal processing) If the status "L_CMP = 1" is established before command switching, then the status is set to "L_CMP = 0" at command switching.
Command with a latch function LT_SEL = 1 LT_REQ = 1	Command without a latch function LT_SEL = 1 LT_REQ = 1	Switches to a latch request for the command after switching. The servo drive executes another latch request. (Internal processing) If the status "L_CMP = 1" is established before command switching, then the status is set to "L_CMP = 0" at command switching.
Command with a latch function LT_SEL = 1 LT_REQ = 1	Command with a latch function LT_SEL = 1 LT_REQ = 1	Switches to a latch request for the command after switching. The servo drive executes another latch request. (Internal processing) If the status "L_CMP = 1" is established before command switching, then the status is set to "L_CMP = 0" at command switching.

Note: 1. Commands with a latch function: EX_FEED, EX_POSING, ZRET
Commands without a latch function: POS_SET, BRK_ON, BRK_OFF, SENS_ON, SENS_OFF, SMON, SV_ON, SV_OFF, INTERPOLATE, POSING, FEED, VELCTRL, TRQCTRL, SVPRM_RD, SVPRM_WR
Common commands: NOP, ID_RD, CONFIG, ALM_RD, ALM_CLR, SYNC_SET, CONNECT, DISCONNECT, MEM_RD, MEM_WR
2. LT_SEL: LT_SEL1 or LT_SEL2
LT_REQ: LT_REQ1 or LT_REQ2

2.6 Servo Command I/O Signal (SVCMD_IO)

This section describes the servo command I/O signal monitoring.

2.6.1 Bit Allocation of Servo Command Output Signals

Byte 8 to byte 11 of the command format are specified as the SVCMD_IO (output) field. The servo command output signals are signals output to the slave station.

Note that the designation in this field is valid even when a CMD_ALM has occurred.

SVCMD_IO (Output) Field

bit 7	bit 6	bit 5	bit 4	bit 3	bit 2	bit 1	bit 0
N_CL	P_CL	P_PPI	V_PPI	Reserved (0)			
bit 15	bit 14	bit 13	bit 12	bit 11	bit 10	bit 9	bit 8
Reserved (0)				G-SEL			
bit 23	bit 22	bit 21	bit 20	bit 19	bit 18	bit 17	bit 16
Reserved	SO3	SO2	SO1	BANK_SEL			
bit 31	bit 30	bit 29	bit 28	bit 27	bit 26	bit 25	bit 24
Reserved (0)							

Details of Output Signal Bits

The following table shows the details of the output signal bits.

bit	Name	Description	Value	Setting	Enabled Timing
4	V_PPI	Speed Loop P/PI Control	0	PI control	Level
			1	P control	
	Switches the speed control from PI control to P control. Used for adjusting the settling time by suppressing overshoot during acceleration.				
5	P_PPI	Position Loop P/PI Control	0	PI control	Level
			1	P control	
	Switches the position control automatically from PI control to P control. Used for shortening the settling time by suppressing overshoot during positioning movement.				
6	P_CL	Forward Torque Limit	0	Torque not clamped	Level
			1	Torque clamped	
	Used to select whether the forward torque is clamped or not according to the forward torque limit (common parameter: 8C).				
7	N_CL	Reverse Torque Limit	0	Torque not clamped	Level
			1	Torque clamped	
	Used to select whether the reverse torque is clamped or not according to the reverse torque limit (common parameter: 8D).				

Continued on next page.

Continued from previous page.

bit	Name	Description	Value	Setting	Enabled Timing
8 to 11	G_SEL	Gain Select	0	First gain	Level
			1	Second gain	
			2 to 15	Reserved (Do not set.)	
	Used to select the position loop gain, speed loop gain and other settings as desired according to the G_SEL value. 0: First gain 1: Second gain 2 to 15: Reserved (Do not set.)				
16 to 19	BANK_SEL	Bank Selector	0	Bank 0	Level
			1	Bank 1	
			⋮	⋮	
			F	Bank F	
	High-speed acceleration/deceleration parameter (bank switching) function				
20 to 22	SO1 to SO3	I/O Signal Output Command	0	Signal OFF	Level
			1	Signal ON	
	Turns ON/OFF the signal output for I/O signal outputs (SO1 to SO3). [Important] The OUT_SIGNAL operation is disabled when other output signals are allocated at the same time to parameters Pn50E, Pn50F and Pn510. To use OUT_SIGNAL, set all of parameters Pn50E, Pn50F and Pn510 to "0."				

2.6.2 Bit Allocation of Servo Command I/O Signal Monitoring

Byte 8 to byte 11 of the response format are specified as the SVCMD_IO (I/O signal) field. Note that the designation in this field is valid even when a CMD_ALM has occurred.

SVCMD_IO (I/O Signal) Field

bit 7	bit 6	bit 5	bit 4	bit 3	bit 2	bit 1	bit 0
ESTP	EXT3	EXT2	EXT1	N-OT	P-OT	DEC	Reserved (0)
bit 15	bit 14	bit 13	bit 12	bit 11	bit 10	bit 9	bit 8
ZPOINT	PSET	NEAR	DEN	N-SOT	P-SOT	BRK_ON	Reserved (0)
bit 23	bit 22	bit 21	bit 20	bit 19	bit 18	bit 17	bit 16
Reserved (0)				ZSPD	V_CMP	V_LIM	T_LIM
bit 31	bit 30	bit 29	bit 28	bit 27	bit 26	bit 25	bit 24
IO_STS8	IO_STS7	IO_STS6	IO_STS5	IO_STS4	IO_STS3	IO_STS2	IO_STS1

Details of I/O Signal Bits

The following table shows the details of the I/O signal bits.

Bit	Name	Description	Value	Setting
1	DEC	Zero Return Deceleration Limit Switch Input	0	OFF
			1	ON
	The status used to judge the state of the deceleration limit switch used for zero point return operation			
2	P_OT	Forward Drive Prohibition Input	0	OFF
			1	ON
	Overtravel (OT) is a function that forcibly stops a movable machine unit if it moves beyond its range of movement. P_OT is the status used to judge if the movable machine unit is in the forward drive prohibited state. The OT stop judgment is made based on ZSPD.			
3	N_OT	Reverse Drive Prohibition Input	0	OFF
			1	ON
	Overtravel (OT) is a function that forcibly stops a movable machine unit if it moves beyond its range of movement. N_OT is the status used to judge if the movable machine unit is in the reverse drive prohibited state. The OT stop judgment is made based on ZSPD.			
4	EXT1	External Latch 1 Input	0	OFF
			1	ON
	The status used to judge the state of the external latch 1 input signal			
5	EXT2	External Latch 2 Input	0	OFF
			1	ON
	The status used to judge the state of the external latch 2 input signal			
6	EXT3	External Latch 3 Input	0	OFF
			1	ON
	The status used to judge the state of the external latch 3 input signal			
7	ESTP (HWBB)	Emergency Stop	0	OFF
			1	ON
	When the HWBB1 or HWBB2 signal is input, the power supply to the motor is shut OFF forcibly and the motor stops according to the setting of Pn001 = n.□□□X.			
9	BRK_ON	Brake Application Output	0	Brake released
			1	Brake applied
	The holding brake is used in applications where the servo driver controls the vertical axis. This is the status used to judge the state of the holding brake control signal (/BK). Note that the logic is the inverse of that of the hardware output (/BK).			
10	P_SOT	Forward Software Limit	0	Range of motion
			1	Drive prohibited due to forward software limit
	The software limit forcibly stops a movable machine unit if it moves beyond the software limit range in the same manner as the overtravel function, with or without using P_OT and N_OT (overtravel signals). This is the status used to judge if the movable machine unit is in the Forward Software Limit state (common parameter: 26).			
11	N_SOT	Reverse Software Limit	0	Range of motion
			1	Drive prohibited due to reverse software limit
	The software limit forcibly stops a movable machine unit if it moves beyond the software limit range in the same manner as the overtravel function, with or without using P_OT and N_OT (overtravel signals). This is the status used to judge if the movable machine unit is in the Reverse Software Limit state (common parameter: 28).			
12	DEN	Distribution Completed (Position Control Mode)	0	During distribution
			1	Distribution completed
	The status used to judge if the position reference from the servo drive has been completed This bit is valid only in the position control mode.			

Continued on next page.

Continued from previous page.

Bit	Name	Description	Value	Setting
13	NEAR	Near Position (Position Control Mode)	0	Outside the near-position range
			1	Within the near-position range
	The status used to judge if the current position is within the range of the NEAR Signal Width (common parameter: 67) This bit is valid only in position control mode.			
14	PSET	Positioning Completed (Position Control Mode)	0	Outside the positioning completion range
			1	Within the positioning completion range
	The status used to judge if the current position is within the range of the Positioning Completed Width (common parameter: 66) This bit is valid only in the position control mode. Refer to the following section for details. ☞ *5.9 Notes when the Positioning Completed State (PSET = 1) is Established while Canceling a Motion Command* on page 5-13.			
15	ZPOINT	Zero Point	0	Outside the zero point position range
			1	Within the zero point position range
	The status used to judge if the current position is within the range of the Origin Detection Range (common parameter: 8B)			
16	T_LIM	Torque Limit	0	Not in the torque limited state
			1	In the torque limited state
	The status used to judge if the torque is clamped at the Forward Toque Limit or the Reverse Toque (force) Limit			
17	V_LIM	Speed Limit (Torque Control Mode)	0	Speed limit not detected
			1	Speed limit detected
	The status used to judge if the speed is clamped at the limit value specified in the command or parameter This bit is valid only in the torque control mode.			
18	V_CMP	Speed Match (Speed Control Mode)	0	Speed not matched
			1	Speed match
	The status used to judge if the speed is within the Speed Match Signal Detection Range (common parameter: 8F) This bit is valid only in the speed control mode.			
19	ZSPD	Zero Speed	0	Zero speed not detected
			1	Zero speed detected
	The status used to judge if the current speed is within the Zero Speed Detection Range (common parameter: 8E)			
24 to 31	IO_STS1 to IO_STS8	I/O Signal Monitor	0	Signal OFF
			1	Signal ON
	The status used to indicate the I/O signal state of CN1 Allocate the input signals using parameters Pn860 to Pn866, Pn868, and Pn869.			

2.7 Command Data

This section describes the servo-specific data used with servo commands.

2.7.1 Data Order

Data in commands and responses is stored in little endian byte order.

For example, 4-byte data "0x1234ABCD" in hexadecimal is stored from the least significant byte as shown below.

Byte	Data
1	CD
2	AB
3	34
4	12

2.7.2 Specifying Units

The units for the user command and parameter data can be selected.

The system of units is set in the common parameters. For the details on the common parameters, refer to the following chapter for details.

☞ *Chapter 8 Common Parameters*

Speed

The following units can be selected.

Settings are made with common parameters 41 and 42.

Unit	Remark
Reference unit/s (default)	$\times 10^n$ [reference unit/s] can be set.
Reference unit/min	$\times 10^n$ [reference unit/min] can be set.
"%" of rated speed	$\times 10^n$ [%] can be set.
min^{-1} (rpm)	$\times 10^n$ [min^{-1}] can be set.
Max. motor speed/40000000 (Hex.)	Set "0" for common parameter 42.

Position

The following units can be selected.

Settings are made with common parameters 43 and 44.

Unit	Remark
Reference unit (default)	[Reference unit] Fixed Set "0" for common parameter 44.

Acceleration

The following units can be selected.

Settings are made with common parameters 45 and 46.

Unit	Remark
Reference unit/s^2 (default)	$\times 10^n$ [reference unit/s^2] can be set.

Torque

The following units can be selected.

Settings are made with common parameters 47 and 48.

Unit	Remark
% of rated torque (default)	$\times 10^{n}$ [%] can be set.
Max. torque/40000000 (Hex.)	Set "0" for common parameter 48.

2.7.3 Specifying Monitor Data

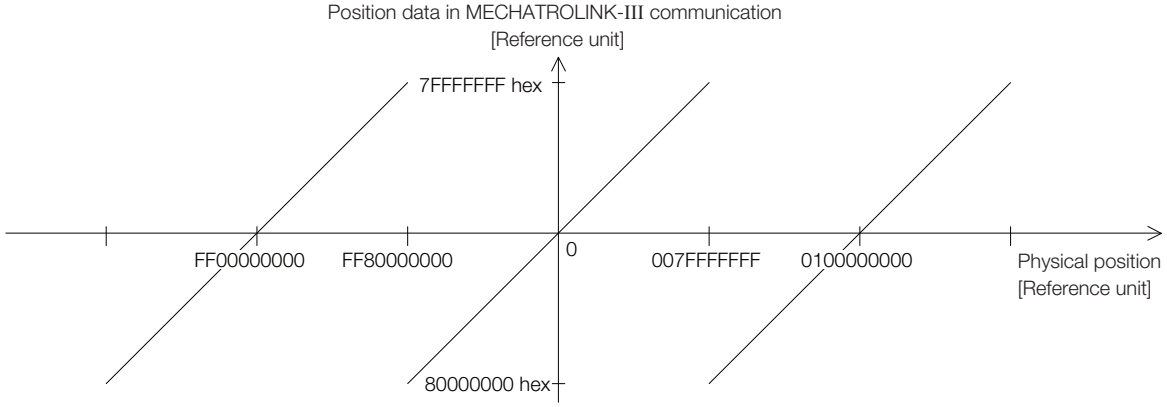
The master station sets the selection code of the monitor data to be read from a slave station at monitor selection bits SEL_MON1 to 3 in the servo command control field (SVCMD_CTRL) and at monitor selection bits SEL_MON4 to 6 in the subcommand control field (SUB_CTRL). The slave station sets the specified monitor selection code and the monitor data in the response.

The following table lists the monitor data.

Selection Code	Monitor Name	Description	Remark
0	APOS	Feedback Position	–
1	CPOS	Command Position	–
2	PERR	Position Error	–
3	LPOS1	Latched Position 1	–
4	LPOS2	Latched Position 2	–
5	FSPD	Feedback Speed	–
6	CSPD	Reference Speed	–
7	TRQ	Reference Torque	–
8	ALARM	Detailed Information on the Current Alarm	When an alarm has occurred after the occurrence of a warning, the information on the alarm is displayed.
9	MPOS	Command Position	Input reference position in a position control loop MPOS = APOS + PERR
A	–	Reserved	–
B	–	Reserved	–
C	CMN1	Common Monitor 1	Selects the monitor data specified at common parameter 89.
D	CMN2	Common Monitor 2	Selects the monitor data specified at common parameter 8A.
E	OMN1	Optional Monitor 1	Selects the monitor data specified at parameter Pn824.
F	OMN2	Optional Monitor 2	Selects the monitor data specified at parameter Pn825.

2.7.4 Position Data

Servo commands use 4-byte data as position data. For infinite length operation, position data beyond this limit are expressed as shown in the diagram below.



Main Commands

3

3.1 Common Commands

3.1.1 No Operation Command (NOP: 00 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	NOP		Description
	Command	Response	
0	00 hex	00 hex	• You cannot use the NOP command during network control. • The response returns the current status. • Confirm that RCMD = NOP (= 00 hex) and CMD_STAT.CMDRDY = 1.
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	Reserved	Reserved	
5			
6			
7			
8			
9			
10			
11			
12			
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

3.1.2 Read ID Command (ID_RD: 03 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	ID_RD		Description
	Command	Response	
0	03 hex	03 hex	• The ID_RD command reads the ID of a device. This command reads the product information as ID data. • The ID data is selected in detail by specifying ID_CODE. • Confirm the completion of the command execution by checking that RCMD = ID_RD (= 03 hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for ID_CODE, OFFSET and SIZE. In the following cases, an alarm will occur. Do not read ID in the response in those cases because the ID value will be indefinite. • When the ID_CODE data is invalid: CMD_ALM = 9 hex (A.94A) • When the OFFSET data is invalid or the SIZE data do not match: CMD_ALM = 9 hex (A.94D) If the OFFSET or SIZE data is invalid for the specified ID_CODE, an alarm occurs. Example:Setting OFFSET = 3 and SIZE = 4 for reading the device version (4-byte data) specifies reading of data outside the device version data (4 bytes) and generates an alarm.
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	ID_CODE	ID_CODE	
5	OFFSET	OFFSET	
6	SIZE	SIZE	
7			
8	Reserved	ID	
9			
10			
11			
12			
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

Command Parameters

ID_CODE: ID data selection code
OFFSET: ID read offset
SIZE: Read data size [bytes]
The following tables describe details of the ID_CODE.

ID_CODE	Description	Data Size	Data Type	Compliance
01 hex	Vendor ID Code	4 bytes	Binary Data	O
	00000000 hex (YASKAWA ELECTRIC CORPORATION) An ID code used to specify the vendor. Vendor ID codes are managed by the MECHATROLINK Members Association.			
02 hex	Device Code	4 bytes	Binary Data	O
	02250000 hex (Σ-7S Series (SGD7S-□□□□20□)) 02250001 hex (Σ-7W Series (SGD7W-□□□□20□)) This is a code specific to each device.			
03 hex	Device Version	4 bytes	Binary Data	O
	Returns the firmware version of this product. Example: 00160000 hex Version information of device			
04 hex	Device Information File Version	4 bytes	Binary Data	O
	This is the version information of the device information (MDI) file supported by this product. bit7 bit6 bit5 bit4 bit3 bit2 bit1 bit0 Revision No. bit15 bit14 bit13 bit12 bit11 bit10 bit9 bit8 Major version / Minor version Major version: When there are major changes to the MDI associated with function additions and function changes, such as addition of profiles. Minor version: When there are changes to the MDI associated with minor function additions or function changes. Revision No.:Normally returns "0." Bit 16 to 31: Reserved (0)			
05 hex	Extended Address Setting (for Future Use)	4 bytes	Binary Data	O
	1 This is the number of extended addresses used. The value is always "1" because this product comprises a single axis.			
06 hex	Serial No.	32 bytes	ASCII Code (Delimiter: 00)	O
	Serial number specific to each device			
10 hex	Profile Type 1 (Primary)	4 bytes	Binary Data	O
	00000010 hex (Standard servo profile) Profile type (primary) that the device supports This product supports the following two profile types. (1) Profile type 1: Servo profile (this ID_CODE) (2) Profile type 2: None (12 hex) (3) Profile type 3: None (14 hex)			
11 hex	Profile Version 1 (Primary)	4 bytes	Binary Data	O
	00000030 hex Profile version (primary) that the device supports.			
12 hex	Profile Type 2	4 bytes	Binary Data	O
	000000FF hex (Not supported code)			
13 hex	Profile Version 2	4 bytes	Binary Data	O
	00000000 hex			

Continued on next page.

Continued from previous page.

ID_CODE	Description	Data Size	Data Type	Compliance
14 hex	Profile Type 3	4 bytes	Binary Data	O
	000000FF hex (Not supported code)			
15 hex	Profile Version 3	4 bytes	Binary Data	O
	00000000 hex			
16 hex	Minimum Value of Transmission Cycle	4 bytes	Binary Data	O
	12500 [0.01 μs unit] (0.125 ms) The minimum transmission cycle that the device can support in the granularity level of the transmission cycle increment (18 hex)			
17 hex	Maximum Value of Transmission Cycle	4 bytes	Binary Data	O
	400000 [0.01 μs unit] (4 ms) The maximum transmission cycle that the device can support in the granularity level of the transmission cycle increment (18 hex)			
18 hex	Transmission Cycle Increment (Granularity)	4 bytes	Binary Data	O
	00000003 hex There are the following four levels of transmission cycle increment that the device supports. This product supports level 03 hex. 00 hex: 31.25, 62.5, 125, 250, 500 (μs), 2 to 64 (ms) (2 ms increment) 01 hex: 31.25, 62.5, 125, 250, 500 (μs), 1 to 64 (ms) (1 ms increment) 02 hex: 31.25, 62.5, 125, 250, 500 (μs), 1 to 64 (ms) (0.5 ms increment) 03 hex: 31.25, 62.5, 125, 250, 500, 750 (μs), 1 to 64 (ms) (0.5 ms increment)			
19 hex	Minimum Value of Communication Cycle	4 bytes	Binary Data	O
	12500 [0.01 μs unit] (0.125 ms) The minimum communication cycle that the device supports			
1A hex	Maximum Value of Communication Cycle	4 bytes	Binary Data	O
	3200000 [0.01 μs unit] (32 ms) The maximum communication cycle that the device supports			
1B hex	Number of Transmission Bytes	4 bytes	Binary Data	O
	0000000E hex The number of transmission bytes that the device supports The numbers of bytes to be transmitted are allocated to the following bits. (Supported: 1, Not supported: 0)			

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
Reserved	Reserved	Reserved	64 bytes	48 bytes	32 bytes	16 bytes	8 bytes
0	0	0	0	1	1	0	0

bit 5 to 63: Reserved (0)

1C hex	Number of Transmission Bytes (Current Setting)	4 bytes	Binary Data	O
	0000000 hex The number of transmission bytes that is currently set with DIP switch (S3). One of the bits indicated by "–" will be set to "1." The numbers of bytes to be transmitted are allocated to the following bits.			

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
Reserved	Reserved	Reserved	64 bytes	48 bytes	32 bytes	16 bytes	8 bytes
0	0	0	0	–	–	–	0

bit 5 to 63: Reserved (0)

1D hex	Profile Type (Current Selection)	4 bytes	Binary Data	O
	This is the profile selected with the CONNECT command.			

Continued on next page.

Continued from previous page.

ID_CODE	Description	Data Size	Data Type	Compliance
20 hex	Supported Communication Mode	4 bytes	Binary Data	O
	00000002 hex (Cyclic communication) The communication mode that the device supports The communication modes are allocated to the following bits. (Supported: 1, Not supported: 0) bit 1: Cyclic communication			
21 hex	MAC Address			
	Not supported			
30 hex	List of Supported Main Commands	32 bytes	Array	O

The list of the main commands that the device supports
The commands are allocated as shown below.

bit 0 to 255: 0: Command not supported
1: Command supported

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
Reserved (0)	ALM_ CLR	ALM_ RD	CONFIG	ID_RD	PRM_ WR	PRM_RD	NOP
0	1	1	1	1	0	0	1

bit15	bit14	bit13	bit12	bit11	bit10	bit9	bit8
DISCON- NECT	CON- NECT	SYNC_ SET	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)
1	1	1	0	0	0	0	0

bit 16 to 23: Reserved (0)

bit31	bit30	bit29	bit28	bit27	bit26	bit25	bit24
Reserved (0)	MEM_ WR	MEM_ RD	PPRM_W R	PPRM_ RD	Reserved (0)	Reserved (0)	Reserved (0)
0	1	1	0	0	0	0	0

bit39	bit38	bit37	bit36	bit35	bit34	bit33	bit32
Reserved (0)	Reserved (0)	Reserved (0)	SENS_ OFF	SENS_ ON	BRK_ OFF	BRK_ON	POS_ SET
0	0	0	1	1	1	1	1

bit 40 to 47: Reserved (0)

bit55	bit54	bit53	bit52	bit51	bit50	bit49	bit48
EX_ FEED	FEED	POSING	INTER- POLATE	Reserved (0)	SV_OFF	SV_ON	SMON
1	1	1	1	0	1	1	1

bit63	bit62	bit61	bit60	bit59	bit58	bit57	bit56
Reserved (0)	Reserved (0)	TRQC- TRL	VELCTRL	Reserved (0)	ZRET	EX_ POSING	Reserved (0)
0	0	1	1	0	1	1	0

bit71	bit70	bit69	bit68	bit67	bit66	bit65	bit64
Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	SVPRM_ WR	SVPRM_ RD
0	0	0	0	0	0	1	1

bit 72 to 255: Reserved (0)

Continued on next page.

Continued from previous page.

ID_CODE	Description	Data Size	Data Type	Compliance
38 hex	List of Supported Subcommands	32 bytes	Array	○

The list of the subcommands that the device supports
The commands are allocated as shown below.

bit 0 to 255: 0: Command not supported
1: Command supported

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
Reserved (0)	ALM_CLR	ALM_RD	Reserved (0)	Reserved (0)	PRM_WR	PRM_RD	NOP
0	1	1	0	0	0	0	1

bit 8 to 23: Reserved (0)

bit31	bit30	bit29	bit28	bit27	bit26	bit25	bit24
Reserved (0)	MEM_WR	MEM_RD	PPRM_WR	PPRM_RD	Reserved (0)	Reserved (0)	Reserved (0)
0	1	1	0	0	0	0	0

bit 32 to 47: Reserved (0)

bit55	bit54	bit53	bit52	bit51	bit50	bit49	bit48
Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	SMON
0	0	0	0	0	0	0	1

bit 56 to 63: Reserved (0)

bit71	bit70	bit69	bit68	bit67	bit66	bit65	bit64
Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	SVPRM_WR	SVPRM_RD
0	0	0	0	0	0	1	1

bit 72 to 255: Reserved (0)

40 hex	List of Supported Common Parameters	32 bytes	Array	○

The list of the common parameter numbers that the device supports
The common parameters are allocated as shown below.

bit 0 to 255: 0: Common parameter not supported
1: Common parameter supported

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
07	06	05	04	03	02	01	Reserved (0)
1	1	1	1	1	1	1	0

bit15	bit14	bit13	bit12	bit11	bit10	bit9	bit8
Reserved (0)	Reserved (0)	Reserved (0)	0C	0B	0A	09	08
0	0	0	1	1	1	1	1

Continued on next page.

Continued from previous page.

ID_CODE	Description	Data Size	Data Type	Compliance
40 hex (Continued)	bit 16 to 31: Reserved (0) bit 48 to 63: Reserved (0) bit 80 to 95: Reserved (0) bit 112 to 127: Reserved (0) bit 152 to 255: Reserved (0)			
80 hex	Main Device Name	32 bytes	ASCII Code (Delimiter: 00)	O
	Product model Example: SGD7S-1R6A20A The main device name (ASCII code) <Notice> To judge the device with the host device, use the device code (02 hex) instead of this ID_CODE.			

bit39	bit38	bit37	bit36	bit35	bit34	bit33	bit32
27	26	25	24	23	22	21	Reserved (0)
1	1	1	1	1	1	1	0

bit47	bit46	bit45	bit44	bit43	bit42	bit41	bit40
Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	29	28
0	0	0	0	0	0	1	1

bit71	bit70	bit69	bit68	bit67	bit66	bit65	bit64
47	46	45	44	43	42	41	Reserved (0)
1	1	1	1	1	1	1	0

bit79	bit78	bit77	bit76	bit75	bit74	bit73	bit72
Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	49	48
0	0	0	0	0	0	1	1

bit103	bit102	bit101	bit100	bit99	bit98	bit97	bit96
67	66	65	64	63	62	61	Reserved (0)
1	1	1	1	1	1	1	0

bit111	bit110	bit109	bit108	bit107	bit106	bit105	bit104
Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)
0	0	0	0	0	0	0	0

bit135	bit134	bit133	bit132	bit131	bit130	bit129	bit128
87	86	85	84	83	82	81	Reserved (0)
1	1	1	1	1	1	1	0

bit143	bit142	bit141	bit140	bit139	bit138	bit137	bit136
8F	8E	8D	8C	8B	8A	89	88
1	1	1	1	1	1	1	1

bit151	bit150	bit149	bit148	bit147	bit146	bit145	bit144
Reserved (0)	Reserved (0)	Reserved (0)	Reserved (0)	93	92	91	90
0	0	0	0	1	1	1	1

Continued on next page.

Continued from previous page.

ID_CODE	Description	Data Size	Data Type	Compliance
90 hex	Sub Device 1 Name	32 bytes	ASCII Code (Delimiter: 00)	O
	Motor model Example: SGM7J-01A7A21 The name of sub device 1 (ASCII code)			
98 hex	Sub Device 1 Version	4 bytes	Binary Data	O
	Firmware version of the motor encoder Example: 00000001 hex The version number of sub device 1			
A0 hex	Sub Device 2 Name	32 bytes	ASCII Code (Delimiter: 00)	O
	External encoder model Example: The name of sub device 2 (ASCII code)			
A8 hex	Sub Device 2 Version	4 bytes	Binary Data	O
	The software version of the external encoder Example: 0000001 hex The version number of sub device 2			
B0 hex	Sub Device 3 Name	32 bytes	ASCII Code (Delimiter: 00)	O
	Not supported: NULL The name of sub device 3 (ASCII code)			
B8 hex	Sub Device 3 Version	4 bytes	Binary Data	O
	Not supported: 0000000 hex The version number of sub device 3			
BC hex to BF hex	Reserved			
C0 hex	Sub Device 4 Name	32 bytes	ASCII Code (Delimiter: 00)	O
	The safety option module model The name of sub device 4 (ASCII code)			
C8 hex	Sub Device 4 Version	4 bytes	Binary Data	O
	The software version of the safety option module Example: 00000001 hex The version number of sub device 4			
D0 hex	Sub Device 5 Name	32 bytes	ASCII Code (Delimiter: 00)	O
	The feedback option module model The name of sub device 5 (ASCII code)			
D8 hex	Sub Device 5 Version	4 bytes	Binary Data	O
	The software version of the feedback option module Example: 00000001 hex The version number of sub device 5			
E0 hex	Sub Device 6 Name	32 bytes	ASCII Code (Delimiter: 00)	O
	Reserved The name of sub device 6 (ASCII code)			
E8 hex	Sub Device 6 Version	4 bytes	Binary Data	O
	Reserved The version number of sub device 6			

Note: The ID_CODE values of C0 hex and above are the vendor-specific area.

3.1.3 Setup Device Command (CONFIG: 04 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Refer to the specifications of CONFIG_MOD.	Subcommand	Cannot be used	

Byte	CONFIG		Description
	Command	Response	
0	04 hex	04 hex	• The CONFIG command sets up devices. • Confirm the completion of the command execution by checking that RCMD = CONFIG (= 04 hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for CONFIG_MOD. • CMD_STAT: Indefinite until the completion of the command In the following cases, an alarm will occur and the command will not be executed. • When the CONFIG_MOD data is invalid: CMD_ALM = 9 hex(A.94B) • While in the servo ON state: CMD_ALM = A hex (A.95A) (In MECHATROLINK-II communications, the servo OFF state is established and the command is executed.) • While editing using SigmaWin or digital operator: CMD_ALM = A hex (A.95A)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	CONFIG_MOD	CONFIG_MOD	
5	Reserved	Reserved	
6			
7			
8			
9			
10			
11			
12			
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

Command Parameters

CONFIG_MOD: Configuration mode

0: Parameter re-calculation and setup, processing time: 5 seconds or less

1: Not supported (CMD_ALM = 9 hex (A.94B))

2: Initialization to the factory-set parameter setting values, processing time: 20 seconds or less
Turn the power OFF after completion of the process and turn it back ON.

State of Each Status during CONFIG Command Execution

The following tables show the state of each status before, during and after CONFIG command processing.

◆ When Re-calculating and Setting up the Parameters

Status and Output Signal	Before CONFIG Processing	During CONFIG Processing	After CONFIG Processing
ALM	Current state	Current state	Current state
CMDRDY	1	0	1
M_RDY	Current state	Indefinite	Current state
Other Statuses	Current state	Indefinite	Current state
ALM (CN1 Output Signal)	Current state	Current state	Current state
/S-RDY (CN1 Output Signal)	Current state	OFF	Current state
Other Output Signals	Current state	Indefinite	Current state

◆ When Initializing to the Factory-set Parameter Settings

Status and Output Signal	Before CONFIG Processing	During CONFIG Processing	After CONFIG Processing
ALM	Current state	Current state	Current state
CMDRDY	1	0	1
M_RDY	Current state	0	0
Other Statuses	Current state	Indefinite	Current state
ALM (CN1 Output Signal)	Current state	Current state	Current state
/S-RDY (CN1 Output Signal)	Current state	OFF	OFF
Other Output Signals	Current state	Indefinite	Current state

3.1.4 Read Alarm or Warning Command (ALM_RD: 05 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Refer to the specifications of ALM_RD_MOD	Subcommand	Cannot be used	

Byte	ALM_RD		Description
	Command	Response	
0	05 hex	05 hex	• The ALM_RD command reads the alarm or warning state. • The current alarm or warning state is read to ALM_-DATA. • Confirm the completion of the command execution by checking that RCMD = ALM_RD (= 05 hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for ALM_RD_MOD. • ALM_INDEX is not used. Its setting is ignored. In the following cases, an alarm will occur. Do not read ALM_DATA in the response in these cases because the ALM_DATA value will be indefinite. • When the ALM_RD_MOD data is invalid: CMD_ALM = 9 hex (A.94B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	ALM_RD_MOD	ALM_RD_MOD	
5			
6	ALM_INDEX	ALM_INDEX	
7			
8	Reserved	ALM_DATA	
9			
10			
11			
12			
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

Note: 1. ALM_DATA specifies an alarm using 2 bytes.
2. The alarm history arranges alarms in the order of occurrence starting from the latest alarm.
3. 0000 hex is set in the normal state.

Command Parameters

The details of ALM_RD_MOD are described below.

ALM_RD_MOD	Description	Processing Time
0	Current alarm/warning state Max. 10 items (byte 8 to 27) (00 hex is set for the remaining bytes (byte 28 to 31).)	Within communication cycle
1	Alarm occurrence status history (Warnings are not retained in the history.) Max. 10 items (byte 8 to 27) (00 hex is set for the remaining bytes (byte 28 to 31).)	Within 60 ms

For Σ-7-Series SERVOPACKs, alarm codes are defined as 2-byte data with the following configuration.

	Bit 15 to 12	Bit 11 to 0
	0	Alarm code
Example: A.94B	0 hex	94B hex

3.1.5 Clear Alarm or Warning Command (ALM_CLR: 06 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Refer to the specifications of ALM_CLR_MOD.	Subcommand	Cannot be used	

Byte	ALM_CLR		Description
	Command	Response	
0	06 hex	06 hex	• The ALM_CLR command clears the alarm or warning state. It changes the state of a slave station, but does not eliminate the cause of the alarm or warning. ALM_-CLR should be used to clear the state after the cause of the alarm or warning has been eliminated. • When a communication error (reception error) or synchronous communication error (watchdog data error) occurs during synchronous communication, synchronous communication must be recovered by using the SYNC_SET command after the ALM_CLR command has been executed. • Confirm the completion of the command execution by checking that RCMD = ALM_CLR (= 06 hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for ALM_CLR_MOD. In the following cases, an alarm will occur and the command will not be executed. • When the ALM_CLR_MOD data is invalid: CMD_ALM = 9 hex (A.94B) • While editing using SigmaWin or digital operator: CMD_ALM = A hex (A.95A) Use this command with CMD_CTRL.ALM_CLR set to "0."
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	ALM_CLR_MOD	ALM_CLR_MOD	
5			
6	Reserved	Reserved	
7			
8			
9			
10			
11			
12			
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

Command Parameters

The details of ALM_CLR_MOD are described below.

ALM_CLR_MOD	Description	Processing Time
0	Clearance of the current alarm or warning state	Within 200 ms
1	Clearance of the alarm history	Within 2 s

3.1.6 Start Synchronous Communication Command (SYNC_SET: 0D Hex)

Data Format

Phases in which the Command can be Executed		2	Command Classification	Common command	Asynchronous command
Processing Time		Communication cycle or greater, and 5 seconds or less	Subcommand	Cannot be used	

Byte	SYNC_SET		Description
	Command	Response	
0	0D hex	0D hex	• The SYNC_SET command starts synchronous communication. The system will be in the synchronous communication mode (phase 3) when the execution of this command is completed and watchdog data error detection starts. • It can be used to return to synchronous communication (phase 3), for example, when a shift has been made to asynchronous communication (phase 2) as a result of a communication error. Synchronous communication is established by taking the transition of the watchdog data (WDT) during the execution of this command as the reference. • Maintains this command at the master station until processing has been completed. • Confirm the completion of the command execution by checking that RCMD = SYNC_SET (= 0D hex) and CMD_STAT.CMDRDY = 1. • If the system is in communication phase 2, it will establish the servo OFF state and shift to communication phase 3. • If the system is in communication phase 3, this command will be ignored and a normal response will be returned. • If 8 or a higher COMM_ALM has occurred, the system shifts to communication phase 2. In such a case, restart synchronous communication by sending this command. In the following case, an alarm will occur and the command will not be executed. • When editing using SigmaWin or a digital operator: CMD_ALM = A hex (A.95A)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	Reserved	Reserved	
5			
6			
7			
8			
9			
10			
11			
12			
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

3.1.7 Establish Connection Command (CONNECT: 0E Hex)

Data Format

Phases in which the Command can be Executed		1	Command Classification	Common command	Asynchronous command
Processing Time		Communication cycle or greater, and 5 seconds or less	Subcommand	Cannot be used	

Byte	CONNECT		Description
	Command	Response	
0	0E hex	0E hex	• The CONNECT command establishes a MECHATROLINK connection. When the execution of this command has been completed, the control of slave stations is started by means of MECHATROLINK communication. • Confirm the completion of the command execution by checking that RCMD = CONNECT (= 0E hex) and CMD_STAT.CMDRDY = 1, and also that the settings of VER, COM_MODE, COM_TIME, and PROFILE_TYPE of the response agree with the set data. In the following cases, an alarm will occur and the system will remain in communication phase 1. • When the VER data is invalid: CMD_ALM = 9 hex (A.94B) • When the COM_TIM data is invalid: CMD_ALM = 9 hex (A.94B) • When the PROFILE_TYPE data is invalid: CMD_ALM = 9 hex (A.94B) • When the number of transmission bytes is 32 and SUBCMD = 1: CMD_ALM=9 hex (A.94B) • While editing using SigmaWin or digital operator: CMD_ALM = A hex (A.95A)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	VER	VER	
5	COM_MOD	COM_MOD	
6	COM_TIM	COM_TIM	
7	PROFILE_TYPE	PROFILE_TYPE	
8	Reserved	Reserved	
9			
10			
11			
12			
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

Command Parameters

◆ VER: MECHATROLINK application layer version

For servo profile: VER = 30 hex

◆ COM_MOD: Communication mode

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
SUBCMD	0	0	0	DTMODE		SYNCMODE	0

- SYNCMODE: Synchronization setting
  1: Performs synchronous communication.
  (Watchdog data error detection enabled. Synchronous communication commands can be used.)
  0: Performs asynchronous communication.
  (Watchdog data error detection disabled. Synchronous communication commands cannot be used.)

- DTMODE: Data transfer method
  00: Single transmission
  01: Consecutive transmission
  10: Reserved
  11: Reserved

- SUBCMD: Subcommand setting
  0: Subcommand disabled
  1: Subcommand enabled

◆ COM_TIM: Communication cycle setting

Sets the number by which to multiply the transmission cycle to get the communications cycle.
The setting range is 1 to 255.
The setting must meet the following conditions.

- Σ-7S SERVOPACKs
  0.125 [ms] ≤ Transmission cycle [ms] × COM_TIME ≤ 32 [ms]

- Σ-7W SERVOPACKs
  0.25 [ms] ≤ Transmission cycle [ms] × COM_TIME ≤ 32 [ms]

Example If you use a communications cycle of 2 ms for a transmission cycle of 0.5 ms, COM_TIME will be 4 (2/0.5).

◆ PROFILE_TYPE: Profile type setting

Sets the profile type to be used.
PROFILE_TYPE = 10 hex (Standard servo profile)

3.1.8 Disconnection Command (DISCONNECT: 0F Hex)

Data Format

Phases in which the Command can be Executed		All phases	Command Classification	Common command	Asynchronous command
Processing Time		Communication cycle or greater, and 5 seconds or less	Subcommand	Cannot be used	
Byte	DISCONNECT		Description		
	Command	Response			
0	0F hex	0F hex	• When releasing a connection, the master station transmits the DISCONNECT command for two or more communication cycles. At this time, the slave station interrupts current processing and then performs the initialization required to reestablish the connection. It then waits for the connect establishment request from the master station. • The DISCONNECT command can be sent regardless of the state of the CMD_STAT.CMDRDY bit. If the DISCONNECT command is sent when the CMD_STAT.CMDRDY state bit is 0, processing is interrupted and this command is processed. • Control with the command sending time of the master station as two or more communication cycles. • Upon receipt of this command, the following operation is performed. - Shifts the communication phase to phase 1. - Establishes the servo OFF state. - Disables reference point setting. - Initializes the position data. • When the control power is turned OFF at the same time the DISCONNECT command is sent, the response data is indefinite.		
1	Reserved	Reserved			
2					
3					
4					
5					
6					
7					
8					
9					
10					
11					
12					
13					
14					
15					
16					
17					
18					
19					
20					
21					
22					
23					
24					
25					
26					
27					
28					
29					
30					
31					

3.1.9 Read Memory Command (MEM_RD: 1D Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Within 200 ms	Subcommand	Cannot be used	
Byte	MEM_RD		Description		
	Command	Response			
0	1D hex	1D hex	• The MEM_RD command reads the data stored in virtual memory by specifying the initial address and the data size for reading. • Confirm the completion of the command execution by checking that RCMD = MEM_RD (= 1D hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for ADDRESS, SIZE and MODE/DATA_TYPE. In the following cases, an alarm will occur. Do not read DATA in the response in these cases because the DATA value will be indefinite. • When the ADDRESS data is invalid: CMD_ALM = 9 hex (A.94A) • When the MODE/DATA_TYPE data is invalid: CMD_ALM = 9 hex (A.94B) • When the SIZE data is invalid: CMD_ALM = 9 hex (A.94D) • While editing using SigmaWin or digital operator: CMD_ALM = A hex (A.95A) Refer to the following section for details. ☞ ◆ *Method to Access Virtual Memory Areas* on page 3-23.		
1	WDT	RWDT			
2	CMD_CTRL	CMD_STAT			
3					
4	Reserved	Reserved			
5	MODE/DATA_-TYPE	MODE/DATA_-TYPE			
6	SIZE	SIZE			
7					
8	ADDRESS	ADDRESS			
9					
10					
11					
12	Reserved	DATA			
13					
14					
15					
16					
17					
18					
19					
20					
21					
22					
23					
24					
25					
26					
27					
28					
29					
30					
31					

Command Parameters

The details of MODE/DATA_TYPE are described below.

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
MODE				DATA_TYPE			

MODE = 1: Volatile memory, 2: Not supported
DATA_TYPE = 1: Byte, 2: Short, 3: Long, 4: Not supported

SIZE: Data size for reading (of type specified by DATA_TYPE)
ADDRESS: Initial address for reading
DATA: Read data

3.1.10 Write Memory Command (MEM_WR: 1E Hex)

Data Format

Phases in which the Command can be Executed	2, 3	Command Classification	Common command	Asynchronous command
Processing Time	Refer to ◆ *Executing the Adjustment Operation* on page 3-22.	Subcommand	Cannot be used	

Byte	MEM_WR		Description
	Command	Response	
0	1E hex	1E hex	• The MEM_WR command writes the data in virtual memory by specifying the initial address, the data size and the data for writing. • This command provides an adjustment function equivalent to that of the ADJ command of the MECHATROLINK-II compatible profile. • Confirm the completion of the command execution by checking that RCMD = MEM_WR (= 1E hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for ADDRESS, SIZE, MODE/DATA_TYPE and DATA. In the following cases, an alarm will occur and the command will not be executed. • When the ADDRESS data is invalid: CMD_ALM = 9 hex (A.94A) • When the MODE/DATA_TYPE data is invalid: CMD_ALM = 9 hex (A.94B) • When the SIZE data is invalid: CMD_ALM = 9 hex (A.94D) • When the DATA data is invalid: CMD_ALM = 9 hex (A.94B) • When the conditions for executing the adjustment operation in the next page are not satisfied: CMD_ALM=A hex (A.95A) • While editing using SigmaWin or digital operator: CMD_ALM = A hex (A.95A) Refer to the following section for details. ☞ ◆ *Method to Access Virtual Memory Areas* on page 3-23.
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	Reserved	Reserved	
5	MODE/DATA_-TYPE	MODE/DATA_-TYPE	
6	SIZE	SIZE	
7			
8	ADDRESS	ADDRESS	
9			
10			
11			
12	DATA	DATA	
13			
14			
15			
16			
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

Command Parameters

The details of MODE/DATA_TYPE are described below.

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
MODE				DATA_TYPE			

MODE = 1: Volatile memory, 2: Non-volatile memory (Non-volatile memory can be selected only for common parameters)
DATA_TYPE = 1: Byte, 2: Short, 3: Long, 4: Not supported

SIZE: Data size for writing (type specified by DATA_TYPE)
ADDRESS: Initial address for writing
DATA: Data to be written

◆ Executing the Adjustment Operation

The table below lists the adjustment operations that can be executed.

Adjustment	Request Code	Preparation before Execution	Processing Time	Execution Conditions
Normal mode	0000 hex	None	200 ms max.	–
Parameter initialization	1005 hex	None	20 s max.	Initialization impossible while the servo is ON. After initialization, the power supply must be turned OFF and then ON again.
Absolute encoder reset	1008 hex	Required	5 s max.	When using an incremental encoder, impossible to reset the encoder while the servo is ON. After execution, the power supply must be turned OFF and then ON again.
Automatic offset adjustment of motor current detection signals	100E hex	None	5 s max.	Adjustment is disabled: • While the main circuit power supply is OFF • While the servo is ON • While the servomotor is running
Multiturn limit setting	1013 hex	Required	5 s max.	When using an incremental encoder, the setting is disabled unless A.CC0 (Multiturn Limit Disagreement) occurs. After execution, the power supply must be turned OFF and then ON again.

■ Details of Command for Adjustment

1. Send the following data and set the request code of the adjustment to be executed.
Command = MEM_WR
ADDRESS = 80004000 hex
MODE/DATA_TYPE = 12 hex
SIZE = 0001 hex
DATA = Request code of the adjustment to be executed
To confirm the completion of the execution, check that CMDRDY = 1. If an error occurs, carry out the operation in step 4 to abort execution.

2. For adjustment that requires a preparation process in the table, send the following data.
Command = MEM_WR
ADDRESS = 80004002 hex
MODE/DATA_TYPE = 12 hex
SIZE = 0001 hex
DATA = 0002 hex
To confirm the completion of the execution, check that CMDRDY = 1. If an error occurs, carry out the operation in step 4 to abort execution.

3. Send the following data to execute adjustment.
Command = MEM_WR
ADDRESS = 80004002 hex
MODE/DATA_TYPE = 12 hex
SIZE = 0001 hex
DATA = 0001 hex
To confirm the completion of the execution, check that CMDRDY = 1. If an error occurs, carry out the operation in step 4 to abort execution.

4. Send the following data to abort the execution.
Command = MEM_WR
ADDRESS = 80004000 hex
MODE/DATA_TYPE = 12 hex
SIZE = 0001 hex
DATA = 0000 hex
To confirm the completion of the execution, check that CMDRDY = 1.

◆ Method to Access Virtual Memory Areas

For the information on the allocation of virtual memory areas, refer to the following chapter for details.

☞ *Chapter 9 Virtual Memory Space*.

The details of the units (DATA_TYPE) for accessing the virtual memory areas are described below.

Area Name	Details	DATA_TYPE	SIZE*	Accessible/inaccessible
Vendor-specific area	Reserved			Inaccessible
	Register area	Short, long	Number of data	Accessible
Reserved	Reserved			Inaccessible
Common parameter area	Common parameters	Long	Number of data	Accessible
ID area	Reserved	Byte, short, long	Number of data	Accessible
	ID			

* Set the number of data of the data type specified by DATA_TYPE.

The details of CMD_ALM of the MEM_RD/MEM_WR command are described below.

CMD_ALM	Displayed Code	Error Details
9 hex	A.94A	When an initial address outside the defined areas is specified
		When an address within the reserved ranges of common parameter or vendor-specific areas is specified
		When a value other than a multiple of the data size specified in DATA_TYPE is set for ADDRESS
	A.94B	When the MODE or DATA_TYPE data is invalid
	A.94D	When the initial address is within the defined areas but the specified size goes beyond those areas
		When a data size beyond the specification of the command format is set for SIZE

3.2 Servo Commands

3.2.1 Set Coordinates Command (POS_SET: 20 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common motion command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Cannot be used	

Byte	POS_SET		Description
	Command	Response	
0	20 hex	20 hex	• The POS_SET command sets the coordinate system for the slave station. Specify the type of coordinates with the monitor selection code using POS_SEL. • This command also provides a function to set the reference point. Specifying this command after setting REFE = 1 sets the machine zero point according to the coordinate setting values and enables the stroke check (software limit) function. • Confirm the completion of the command execution by checking that RCMD = POS_SET (= 20 hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for POS_SEL and POS_DATA. In the following case, an alarm will occur and the command will not be executed. • When the POS_SET_MOD data is invalid: CMD_ALM = 9 hex (A.94B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	POS_SET_MOD	POS_SET_MOD	
13			
14			
15			
16	POS_DATA	POS_DATA	
17			
18			
19			
20	Reserved	MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

Command Parameters

POS_SET_MOD: Coordinates Setting Mode

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
REFE	0	0	0	POS_SEL			

bit15	bit14	bit13	bit12	bit11	bit10	bit9	bit8
Reserved							

bit23	bit22	bit21	bit20	bit19	bit18	bit17	bit16
Reserved							

bit31	bit30	bit29	bit28	bit27	bit26	bit25	bit24
Reserved							

- POS_SEL: Select coordinates system (specify using the monitor selection code).
  When APOS (feedback position of the machine coordinates system) = 0 is selected, the command/machine coordinates system is set at POS_DATA.
- REFE: Enable/Disable setting of reference point
  0: Disables setting of a reference point.
  1: Enables setting of a reference point. The coordinate reference point setting is confirmed and the ZPOINT (zero point position) and software limit become effective.
- POS_DATA: Coordinates set value
- Set the reserved bits to "0."

3.2.2 Apply Brake Command (BRK_ON: 21 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Cannot be used	

Byte	BRK_ON		Description
	Command	Response	
0	21 hex	21 hex	• The BRK_ON command outputs a brake operation signal. • Confirm the completion of the command execution by checking that RCMD = BRK_ON (= 21 hex) and CMD_STAT.CMDRDY = 1. • Valid only in the servo OFF state. To use this command, set Pn50F = n.□X□□ to allocate the brake output (/BK) signal. If you do not allocate the /BK signal, BRK_ON in SVCMD_IO will change, but the /BK signal will not be output.
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16		CPRM_SEL_MON2	
17			
18			
19			
20		MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

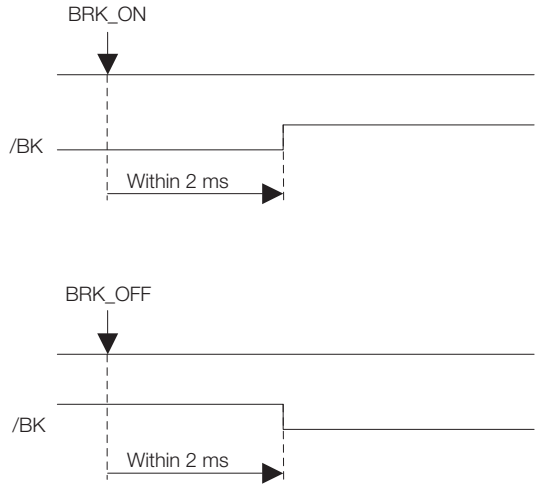
3.2.3 Release Brake Command (BRK_OFF: 22 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Cannot be used	

Byte	BRK_OFF		Description
	Command	Response	
0	22 hex	22 hex	• The BRK_OFF command releases the brake. • Confirm the completion of the command execution by checking that RCMD = BRK_OFF (= 22 hex) and CMD_STAT.CMDRDY = 1. • This command is enabled when Pn50F = n.□X□□ is set to a value other than 0 (allocation of /BK).
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16		CPRM_SEL_MON2	
17			
18			
19			
20		MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

◆ Brake Signal Output Timing



Important

- Normally, brake signals are controlled by the SERVOPACK parameters.
- BRK_ON and BRK_OFF commands are always valid as command as long as no warning occurs.
- Always make sure of the status of brake control command when using BRK_ON or BRK_OFF command.

Sending BRK_OFF command while the servomotor is being powered (servo ON) will not change the operation status. However, it is very dangerous to send SV_OFF command in the above status since the brake is kept released.

◆ Operation for MECHATROLINK Communications Errors

If any of the MECHATROLINK communications errors listed in the following table occurs when the brake signal is being controlled by the BRK_OFF or BRK_ON command, the brake signal will be output according to the setting of Pn884 = n.□□□X (MECHATROLINK Communications Error Holding Brake Signal Setting). If any other alarm occurs, the status that is set for the BRK_ON or BRK_OFF command will be maintained regardless of the setting of Pn884 = n.□□□X.

Alarm Number	Alarm Name
A.E50	MECHATROLINK Synchronization Error
A.E60	Reception Error in MECHATROLINK Communications
A.E61	Synchronization Interval Error in MECHATROLINK Transmission Cycle
A.E62	FCS Error in MECHATROLINK Communications
A.E63	MECHATROLINK Synchronization Frame Not Received

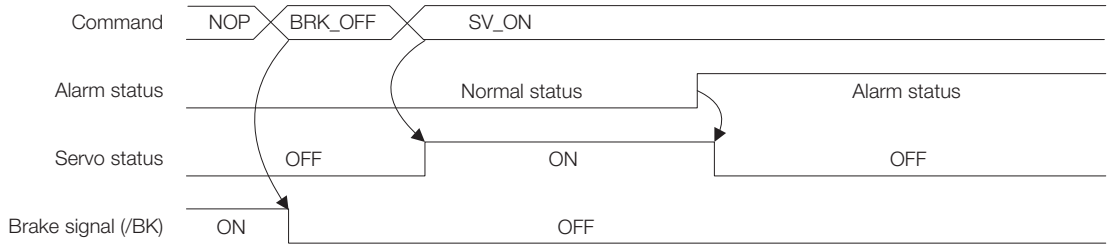
■ Parameter Setting

Set the operation for a MECHATROLINK communications error using the following parameter.

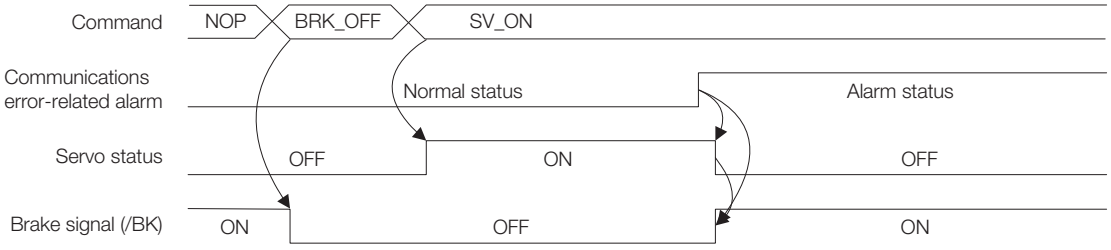
Parameter		Meaning	When Enabled	Classification
Pn884	n.□□□0 [Factory setting]	Maintain the status set by the BRK_ON or BRK_OFF command when a MECHATROLINK communications error occurs.	Immediately	Setup
	n.□□□1	Apply the holding brake when a MECHATROLINK communications error occurs.		

■ Brake Signal Timing Charts for MECHATROLINK Communications Error Operation Settings

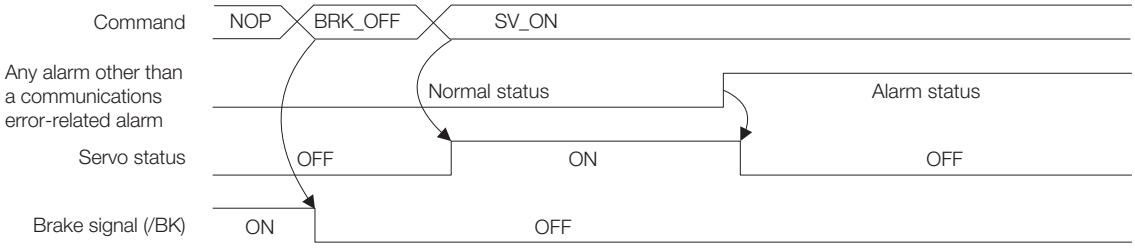
- When Pn884 = n.□□□X Is Set to 0



- When Pn884 = n.□□□X Is Set to 1
- MECHATROLINK Communications Error-Related Alarm



- Alarm Other Than a MECHATROLINK Communications Error-Related Alarm



3.2.4 Turn Sensor ON Command (SENS_ON: 23 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Within 2 s	Subcommand	Cannot be used	

Byte	SENS_ON		Description
	Command	Response	
0	23 hex	23 hex	• The SENS_ON command is the sensor information initialization request command. It initializes the sensor. • Confirm the completion of the command execution by checking that RCMD = SENS_ON (= 23 hex) and CMD_STAT.CMDRDY = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. • When an absolute encoder is used, the initial position is acquired from the encoder. The current position is taken to be: acquired encoder position + zero point position offset (common parameter 23). The coordinate reference point setting is confirmed and the ZPOINT (zero point position) and software limit become effective. • When an incremental encoder is used, only a response is returned without processing.
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16		CPRM_SEL_MON2	
17			
18			
19			
20		MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

3.2.5 Turn Sensor OFF Command (SENS_OFF: 24 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Within 2 s	Subcommand	Cannot be used	

Byte	SENS_OFF		Description
	Command	Response	
0	24 hex	24 hex	• The SENS_OFF command is the sensor power OFF request command. It is used to turn OFF the power to the sensor. • Confirm the completion of the command execution by checking that RCMD = SENS_OFF (= 24 hex) and CMD_STAT.CMDRDY = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. • When an absolute encoder is used the position data is indefinite. "0" is set for POS_RDY. The coordinate reference point setting becomes invalid and the ZPOINT (zero point position) and software limit also become invalid. • When an incremental encoder is used, only a response is returned without processing. In the following case, an alarm will occur and the command will not be executed. • In the servo ON state: CMD_ALM = A hex (A.95A)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16		CPRM_SEL_MON2	
17			
18			
19			
20		MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

3.2.6 Servo Status Monitor Command (SMON: 30 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	SMON		Description
	Command	Response	
0	30 hex	30 hex	• The SMON command reads the alarms, status, and monitor information (position, speed, output, torque, etc.) specified in monitor setting, and the state of the I/O signals of the servo drive. • Confirm the completion of the command execution by checking that RCMD = SMON (= 30 hex) and CMD_STAT.CMDRDY = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*.
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16		CPRM_SEL_MON2	
17			
18			
19			
20		MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

3.2.7 Servo ON Command (SV_ON: 31 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Normally 50 ms (10 s max.)	Subcommand	Can be used	

Byte	SV_ON		Description
	Command	Response	
0	31 hex	31 hex	• The SV_ON command supplies the power to the servomotor and makes it ready for operation. • Confirm the completion of the command execution by checking that RCMD = SV_ON (= 31 hex) and CMD_STAT.CMDRDY = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. • To establish the servo ON state after a warning has occurred, send a command other than SV_ON, such as the SV_OFF command, and then send the SV_ON command. • Upon completion of execution of this command, the reference position (CPOS) must be read, and the controller coordinate system must be set up. • Confirm that M_RDY = 1 before sending this command. In the following cases, A hex (A.95A) will be set for CMD_ALM and the command will not be executed. • When an alarm (COM_ALM = 8 hex or greater, or D_ALM = 1) has occurred • When PON = 0 • When the execution of the SENS_ON command has not completed with an absolute encoder used • When ESTP (HWBB signal off) = 1 • When parameters have been initialized
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16		CPRM_SEL_MON2	
17			
18			
19			
20		MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

3.2.8 Servo OFF Command (SV_OFF: 32 Hex)

Data Format

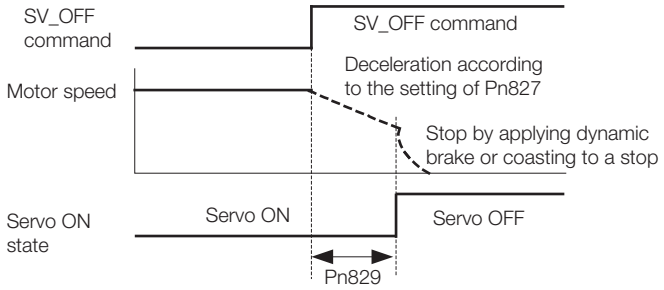
Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Time set with Pn506 500 ms max.	Subcommand	Can be used	

Byte	SV_OFF		Description
	Command	Response	
0	32 hex	32 hex	• The SV_OFF command shuts the power to the servomotor. • Confirm the completion of the command execution by checking that RCMD = SV_OFF (= 32 hex) and CMD_STAT.CMDRDY = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. • When Pn829 (SVOFF Waiting Time (for SVOFF at Deceleration to Stop) is set to a value other than "0", the servo will be turned OFF after the servomotor decelerates to a stop according to the deceleration constant for stopping set by the parameter. (The servomotor decelerates to a stop in position control mode.) • When Pn829 (SVOFF Waiting Time (for SVOFF at Deceleration to Stop) is set to "0", the servo will be turned OFF immediately after reception of this command (default setting). (The control mode before receiving the SV_OFF command remains unchanged.) • Executing the SV_OFF command will cancel the speed reference, speed feedforward, torque feedforward, and torque limits set by a position/speed control command.
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16		CPRM_SEL_MON2	
17			
18			
19			
20		MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

◆ Related Parameters

Parameter No.	Description
Pn829	SVOFF Waiting Time (for SVOFF at Deceleration to Stop)
Pn827 (Pn840)	Linear Deceleration Constant 1 for Stopping (Linear Deceleration Constant 2 for Stopping)

Note: Parameter numbers in parentheses are those when Pn833 = n.□□□X is set to 1.



3.2.9 Interpolation Command (INTERPOLATE: 34 Hex)

Data Format

Phases in which the Command can be Executed		3	Command Classification	Servo standard command	Synchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	INTERPOLATE		Description
	Command	Response	
0	34 hex	34 hex	• The INTERPOLATE command performs interpolation feeding by specifying the interpolation positions every communication cycle set in the CONNECT command. • Confirm the completion of the command execution by checking that RCMD = INTERPOLATE (= 34 hex) and CMD_STAT.CMDRDY = 1. • Confirm motion reference output completion by checking that SVCMD_IO.DEN = 1, and the completion of positioning by checking that SVCMD_IO.PSET = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. <Notes on using the command> • TPOS (target position): Set the target position with a signed value. • VFF (velocity feedforward): Set the speed feedforward value with a signed value. Use it as a speed feedforward function. • TFF (torque feedforward): Set the torque feedforward value with a signed value. Use it as a torque feedforward function. • TLIM (torque limit): Set the torque limit with an unsigned value. • Refer to the following section for the above reference data. ☞ *3.2.19 Motion Command Data Setting Method* on page 3-52. • Refer to the following section for the reference value units in the command area. ☞ *2.7.2 Specifying Units* on page 2-26. In the following cases, an alarm will occur and the command will not be executed. • When used in communication phase 2: CMD_ALM = C hex (A.97A) • In the servo OFF state: CMD_ALM = A hex (A.95A) • When the difference relative to the previous TPOS exceeds the limit value: CMD_ALM = 9 hex (A.94B) In the following cases, an alarm will occur and the relevant value will be clamped at the limit value. • When the VFF data is invalid: CMD_ALM = 1 hex (A.97B) • When the TFF data is invalid: CMD_ALM = 1 hex (A.97B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	TPOS	CPRM_SEL_MON1	
13			
14			
15			
16	VFF	CPRM_SEL_MON2	
17			
18			
19			
20	TFF	MONITOR1	
21			
22			
23			
24	Reserved	MONITOR2	
25			
26			
27			
28	TLIM	MONITOR3	
29			
30			
31			

3.2.10 Positioning Command (POSING: 35 Hex)

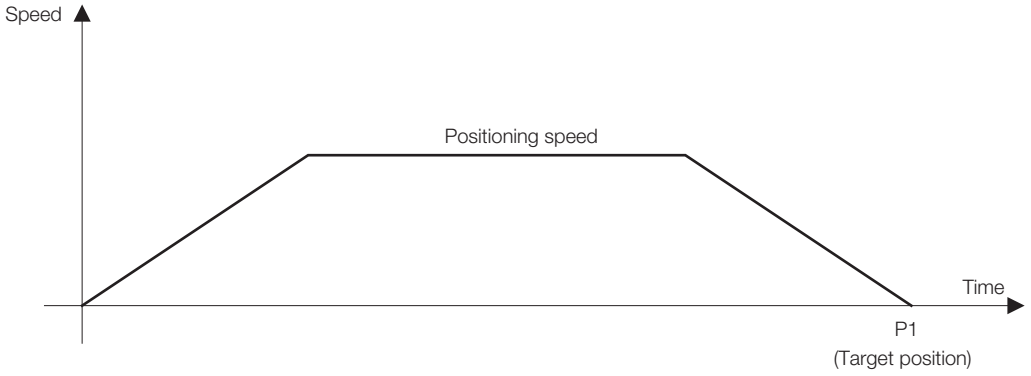
Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	POSING		Description
	Command	Response	
0	35 hex	35 hex	• The POSING command executes positioning to the specified position. • Positioning is executed to the target position (P1) at the positioning speed. • You can set Pn846 to a value other than 0 to use S-curve acceleration/deceleration for positioning. • You can set Pn846 to 0 to use linear acceleration/deceleration for positioning. • Confirm the completion of the command execution by checking that RCMD = POSING (= 35 hex) and CMD_STAT.CMDRDY = 1. • Confirm motion reference output completion by checking that SVCMD_IO.DEN = 1, and the completion of positioning by checking that SVCMD_IO.PSET = 1. • Confirm the completion of the cancellation of the command by checking that RCMD = POSING (= 35 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1. • Confirm the completion of pausing of the command by checking that RCMD = POSING (= 35 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_PAUSE_CMP = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. <Notes on using the command> • TPOS (target position): Set the target position with a signed value. • TSPD (target speed): Set the target speed with an unsigned value. • ACCR (acceleration): Set the acceleration with an unsigned value. • DECR (deceleration): Set the deceleration with an unsigned value. When both ACCR and DECR are "0", acceleration/deceleration is performed according to the parameter settings. To perform two-step acceleration/deceleration, set both ACCR and DECR to "0." Refer to the following section for details. ☞ *6.1.2 Positioning Command* on page 6-2. • TLIM (torque limit): Set the torque limit with an unsigned value. When not applying the torque limit, set the maximum value. • Refer to the following section for the above reference data. ☞ *3.2.19 Motion Command Data Setting Method* on page 3-52. • Refer to the following section for the reference value units in the command area. ☞ *2.7.2 Specifying Units* on page 2-26. In the following cases, an alarm will occur and the command will not be executed. • In the servo OFF state: CMD_ALM = A hex (A.95A) • When the TSPD data is invalid: CMD_ALM = 9 hex (A.94B) • When the ACCR or DECR data is invalid: CMD_ALM = 9 hex (A.94B) • When either of the ACCR or DECR data is set to "0": CMD_ALM = 9 hex (A.94B) In the following case, an alarm will occur and the relevant value will be clamped at the limit value. • When the TLIM data is invalid: CMD_ALM = 1 hex (A.97B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	TPOS	CPRM_SEL_MON1	
13			
14			
15			
16	TSPD	CPRM_SEL_MON2	
17			
18			
19			
20	ACCR	MONITOR1	
21			
22			
23			
24	DECR	MONITOR2	
25			
26			
27			
28	TLIM	MONITOR3	
29			
30			
31			

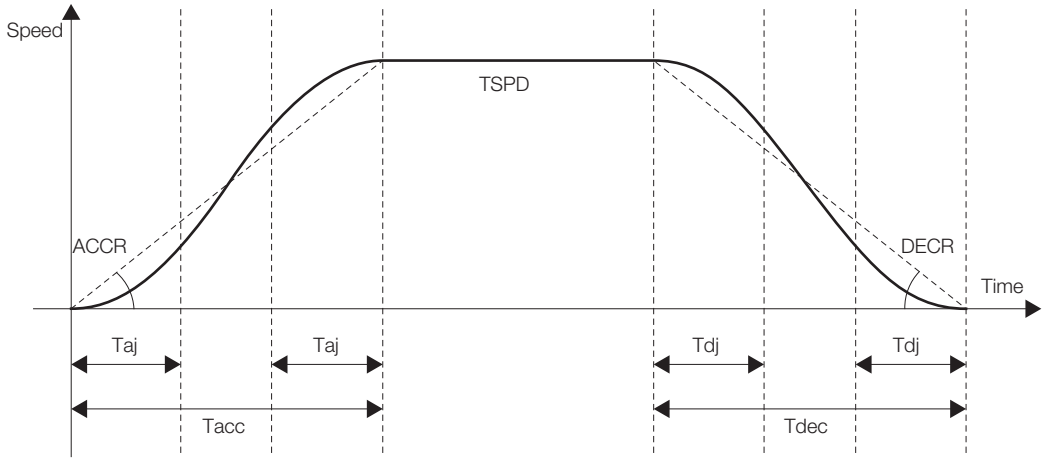
Operation for Linear Acceleration/Deceleration

The following figure shows operation for linear acceleration/deceleration.



Operation for S-Curve Acceleration/Deceleration

The following figure shows operation for S-curve acceleration/deceleration.



Acceleration time: Tacc = TSPD/ACCR
S-curve acceleration time: Taj = S_RATIO × Tacc

Deceleration time: Tdec = TSPD/DECR
S-curve deceleration time: Taj = S_RATIO × Tdec

Important

1. If the TPOS, TSPD, ACCR, or DECR command is changed during positioning, the change will be made when positioning is stopped or during constant-speed movement.
2. If the acceleration/deceleration time is too long, linear acceleration/deceleration will be used. Linear acceleration/deceleration will be used when the rate of acceleration/deceleration meets the following condition for the target speed (TSPD).
   Acceleration/deceleration rate [ref/s^2] < 700 × √(TSPD)
3. Set the S-curve acceleration/deceleration ratio (S_RATIO) in Pn846 (S-Curve Acceleration/ Deceleration Ratio).

Parameter	Name	Data Size (Bytes)	Setting Range	Setting Unit	Default Setting
Pn846	S-Curve Acceleration/ Deceleration Ratio	2	0 to 50	%	0

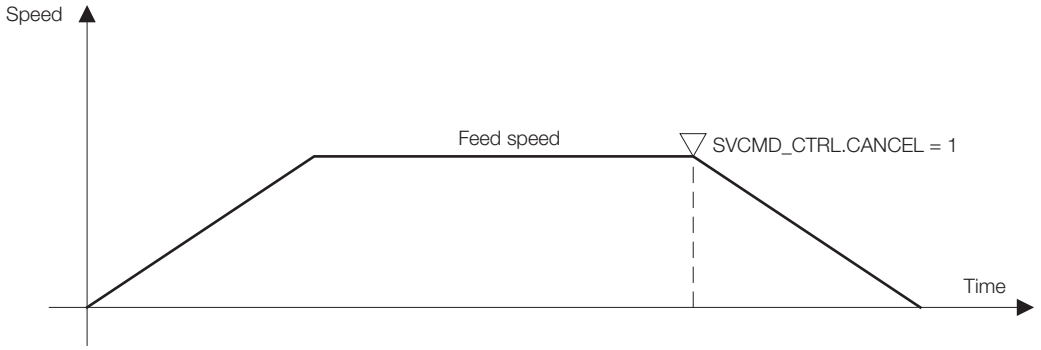
3.2.11 Feed Command (FEED: 36 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	FEED		Description
	Command	Response	
0	36 hex	36 hex	• The FEED command performs constant speed feed control at the specified feed speed. • To change the speed and direction of feed, change the feed speed setting. • To cancel constant speed feed, set SVCMD_CTRL.CMD_CANCEL to "1." • To pause constant speed feed, set SVCMD_CTRL.CMD_PAUSE to "1." • Confirm the completion of the cancellation of the command by checking that RCMD = FEED (= 36 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1. Confirm motion reference output completion by checking that SVCMD_IO.DEN = 1, and the completion of positioning by checking that SVCMD_IO.PSET = 1. • Confirm the completion of pausing of the command by checking that RCMD = FEED (= 36 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_PAUSE_CMP = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. <Notes on using the command> • TSPD (target speed): Set the target speed with a signed value. • ACCR (acceleration): Set the acceleration with an unsigned value. • DECR (deceleration): Set the deceleration with an unsigned value. • When both ACCR and DECR are "0", acceleration/deceleration is performed according to the parameter settings. To perform two-step acceleration/deceleration, set both ACCR and DECR to "0." Refer to the following section for details. ☞ *6.1.2 Positioning Command* on page 6-2. • TLIM (torque limit): Set the torque limit with an unsigned value. • Refer to the following section for the above reference data. ☞ *3.2.19 Motion Command Data Setting Method* on page 3-52. • Refer to the following section for the reference value units in the command area. ☞ *2.7.2 Specifying Units* on page 2-26. In the following cases, an alarm will occur and the command will not be executed. • In the servo OFF state: CMD_ALM = A hex (A.95A) • When the TSPD data is invalid: CMD_ALM = 9 hex (A.94B) • When the ACCR or DECR data is invalid: CMD_ALM = 9 hex (A.94B) • When either of the ACCR or DECR data is set to "0": CMD_ALM = 9 hex (A.94B) In the following case, an alarm will occur and the relevant value will be clamped at the limit value. • When the TLIM data is invalid: CMD_ALM = 1 hex (A.97B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16	TSPD	CPRM_SEL_MON2	
17			
18			
19			
20	ACCR	MONITOR1	
21			
22			
23			
24	DECR	MONITOR2	
25			
26			
27			
28	TLIM	MONITOR3	
29			
30			
31			

3.2.11 Feed Command (FEED: 36 Hex)



3.2.12 External Input Feed Command (EX_FEED: 37 Hex)

Data Format

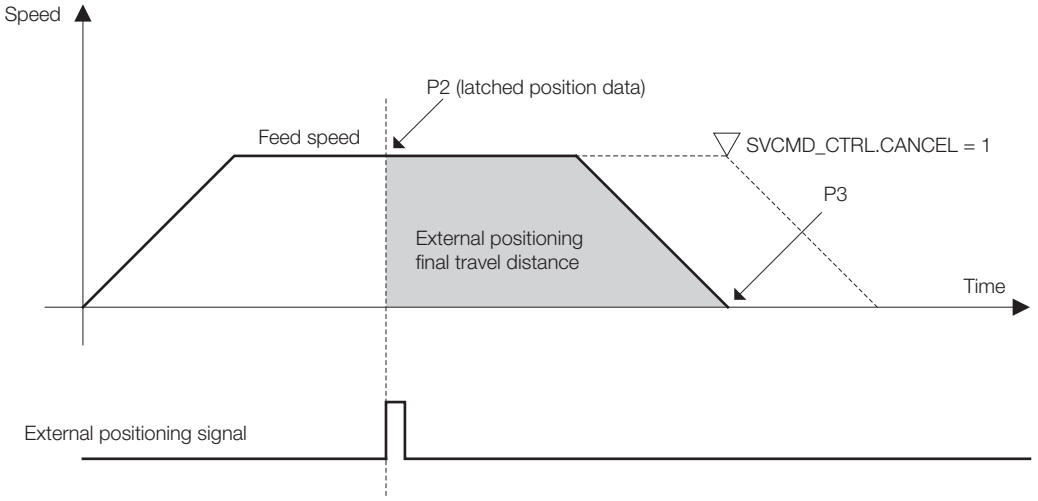
Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	EX_FEED		Description
	Command	Response	
0	37 hex	37 hex	• The EX_FEED command performs positioning in response to the input of the external positioning signal during constant speed feed at the specified feed speed. • To change the speed and direction of feed, change the feed speed setting. • To pause external input feed, set SVCMD_CTRL.CMD_PAUSE to "1." • Confirm the completion of the command execution by checking that RCMD = EX_FEED (= 37 hex) and CMD_STAT.CMDRDY = 1. • To cancel constant speed feeding, set SVCMD_CTRL.CMD_-CANCEL to "1." • Confirm the completion of latching by the latch signal by checking that SVCMD_STAT.L_CMP1 = 1. • Confirm motion reference output completion by checking that SVCMD_IO.DEN = 1, and the completion of positioning by checking that SVCMD_IO.PSET = 1. • Confirm the completion of the cancellation of the command by checking that RCMD = EX_FEED (= 37 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1. • Confirm the completion of pausing of the command by checking that RCMD = EX_FEED (= 37 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_PAUSE_CMP = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. <Notes on using the command> • To send this command, select the latch signal with LT_SEL1 of SVCMD_CTRL and output the latch request by setting LT_REQ1 = 1. • TSPD (target speed): Set the target speed with a signed value. • ACCR (acceleration): Set the acceleration with an unsigned value. • DECR (deceleration): Set the deceleration with an unsigned value. • When both ACCR and DECR are "0", acceleration/deceleration is performed according to the parameter settings. To perform two-step acceleration/deceleration, set both ACCR and DECR to "0." Refer to the following section for details. ☞ *6.1.2 Positioning Command* on page 6-2. • TLIM (torque limit): Set the torque limit with an unsigned value. • Refer to the following section for the above reference data. ☞ *3.2.19 Motion Command Data Setting Method* on page 3-52. • Refer to the following section for the reference value units in the command area. ☞ *2.7.2 Specifying Units* on page 2-26. In the following cases, an alarm will occur and the command will not be executed. • In the servo OFF state: CMD_ALM = A hex (A.95A) • When the TSPD data is invalid:CMD_ALM = 9 hex (A.94B) • When the ACCR or DECR data is invalid: CMD_ALM = 9 hex (A.94B) In the following case, an alarm will occur and the relevant value will be clamped at the limit value. • When the TLIM data is invalid: CMD_ALM = 1 hex (A.97B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	Reserved	CPRM_SEL_MON1	
13			
14			
15			
16	TSPD	CPRM_SEL_MON2	
17			
18			
19			
20	ACCR	MONITOR1	
21			
22			
23			
24	DECR	MONITOR2	
25			
26			
27			
28	TLIM	MONITOR3	
29			
30			
31			

Operating Sequence

The following describes the operating sequence for external input positioning operation using the EX_FEED command.

1. The master station sends the EX_FEED command. It selects the latch signal with LT_-SEL1 of SVCMD_CTRL and outputs the latch request by setting LT_REQ1 = 1.
2. The slave station starts feeding at the specified speed when it receives the EX_FEED command. At the same time, it enters the external signal positioning mode.
3. When the external positioning signal is input, the slave station sets latch completion status L_CMP1 to "1" to notify the master station that current position latching by the external positioning signal is completed.
4. The slave station calculates "(External input positioning target P3) = (Position P2 latched by the external positioning signal) + (Travel distance for external input positioning (common parameter 83))" and performs positioning to external input positioning target P3.
5. After the completion of motion reference output to move the device to target position P3, the slave station sets the motion reference output completed flag (DEN) to "1" to notify the master station of the completion of motion reference output to move the device to target position P3.



Information

- To cancel the external input feed, set SVCMD_CTRL.CMD_CANCEL to "1."
- The motion direction after latching is determined by the sign of the value set for the external positioning final travel distance.
  If the final travel distance for external positioning is a positive value:
  - After latching during motion in the positive direction, the motor rotates in the positive direction (the same direction) for positioning.
  - After latching during motion in the negative direction, the motor rotates in the positive direction (the reverse direction) for positioning.

  If the final travel distance for external positioning is a negative value:
  - After latching during motion in the positive direction, the motor rotates in the negative direction (the reverse direction) for positioning.
  - After latching during motion in the negative direction, the motor rotates in the negative direction (the same direction) for positioning.

3.2.13 External Input Positioning Command (EX_POSING: 39 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	EX_POSING		Description
	Command	Response	
0	39 hex	39 hex	• The EX_POSING command performs positioning in response to the input of the external positioning signal. • To pause the external input positioning, set SVCMD_CTRL.CMD_PAUSE to "1." • Confirm the completion of the command execution by checking that RCMD = EX_POSING (= 39 hex) and CMD_STAT.CMDRDY = 1. • Confirm the completion of latching by the latch signal by checking that SVCMD_STAT.L_CMP1 = 1. • Confirm motion reference output completion by checking that SVCMD_IO.DEN = 1, and the completion of positioning by checking that SVCMD_IO.PSET = 1. • Confirm the completion of the cancellation of the command by checking that RCMD = EX_POSING (= 39 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1. • Confirm the completion of pausing of the command by checking that RCMD = EX_POSING (= 39 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_PAUSE_CMP = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. <Notes on using the command> • To send this command, select the latch signal with LT_SEL1 of SVCMD_CTRL and output the latch request by setting LT_REQ1 = 1. • TPOS (target position): Set the target position with a signed value. • TSPD (target speed): Set the target speed with an unsigned value. • ACCR (acceleration): Set the acceleration with an unsigned value. • DECR (deceleration): Set the deceleration with an unsigned value. • When both ACCR and DECR are "0", acceleration/deceleration is performed according to the parameter settings. To perform two-step acceleration/deceleration, set both ACCR and DECR to "0." Refer to the following section for details. ☞ *6.1.2 Positioning Command* on page 6-2. • TLIM (torque limit): Set the torque limit with an unsigned value. • Refer to the following section for the above reference data. ☞ *3.2.19 Motion Command Data Setting Method* on page 3-52. • Refer to the following section for the reference value units in the command area. ☞ *2.7.2 Specifying Units* on page 2-26. In the following cases, an alarm will occur and the command will not be executed. • In the servo OFF state: CMD_ALM = A hex (A.95A) • When the TSPD data is invalid:CMD_ALM = 9 hex (A.94B) • When the ACCR or DECR data is invalid: CMD_ALM = 9 hex (A.94B) In the following case, an alarm will occur and the relevant value will be clamped at the limit value. • When the TLIM data is invalid: CMD_ALM = 1 hex (A.97B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	TPOS	CPRM_SEL_MON1	
13			
14			
15			
16	TSPD	CPRM_SEL_MON2	
17			
18			
19			
20	ACCR	MONITOR1	
21			
22			
23			
24	DECR	MONITOR2	
25			
26			
27			
28	TLIM	MONITOR3	
29			
30			
31			

Operating Sequence

The following describes the operating sequence for external input positioning operation using the EX_POSING command.

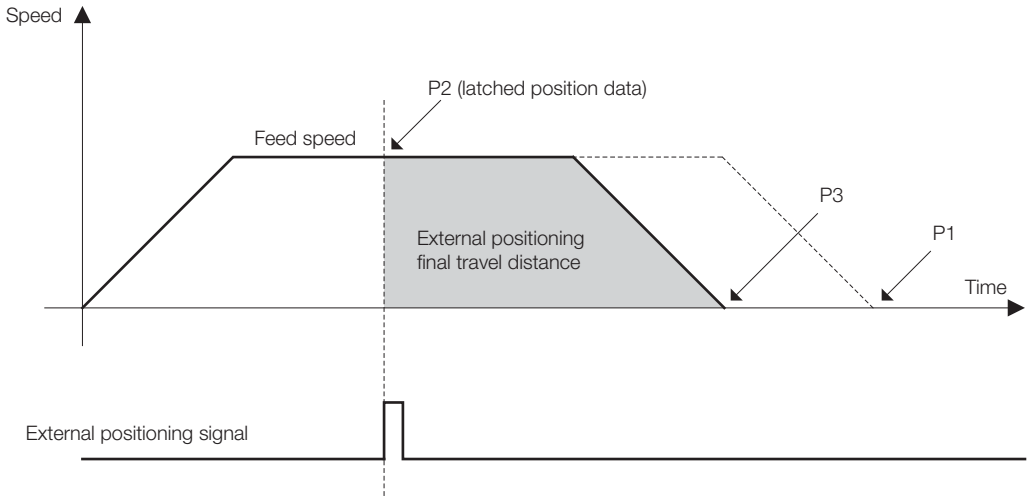
1. The master station sends the EX_POSING command. Target position P1 is set in the "target position" field to be used as the positioning target if the external signal is not input. It selects the latch signal with LT_SEL1 of SVCMD_CTRL and outputs the latch request by setting LT_REQ1 = 1.

2. The slave station starts feeding toward the positioning target position P1 at the specified speed when it receives the EX_POSING command. At the same time, it enters the external input positioning mode.

3. When the external positioning signal is input, the slave station sets latch completion status L_CMP1 to "1" to notify the master station that current position latching by the external positioning signal is completed.

4. The slave station calculates "(External input positioning target P3) = (Position P2 latched by the external positioning signal) + (Travel distance for external input positioning (common parameter 83))" and performs positioning to external input positioning target P3.

5. After the completion of motion reference output to move the device to target position P3, the slave station sets the motion reference output completed flag (DEN) to "1" to notify the master station of the completion of motion reference output to move the device to target position P3.



Information

- To cancel the external input positioning, set SVCMD_CTRL.CMD_CANCEL to "1."
- The motion direction after latching is determined by the sign of the value set for the external positioning final travel distance.
  If the final travel distance for external positioning is a positive value:
  - After latching during motion in the positive direction, the motor rotates in the positive direction (the same direction) for positioning.
  - After latching during motion in the negative direction, the motor rotates in the positive direction (the reverse direction) for positioning.

  If the final travel distance for external positioning is a negative value:
  - After latching during motion in the positive direction, the motor rotates in the negative direction (the reverse direction) for positioning.
  - After latching during motion in the negative direction, the motor rotates in the negative direction (the same direction) for positioning.

3.2.14 Zero Point Return Command (ZRET: 3A Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	ZRET		Description
	Command	Response	
0	3A hex	3A hex	• The ZRET command specifies the type of zero point return operation and performs the operation using the zero point limit switch and the position latch signal. • The signal used to latch the position is specified by "latch signal selection." • To pause the zero point return operation, set SVCMD_CTRL.CMD_PAUSE to "1." • Confirm the completion of the command execution by checking that RCMD = ZRET (= 3A hex) and CMD_STAT.CMDRDY = 1. • Confirm the completion of motion reference output by checking that SVCMD_IO.DEN = 1, and the completion of positioning at the zero point by checking that SVCMD_IO.ZPOINT (zero point position) = 1 and SVCMD_IO.PSET = 1. • Confirm the completion of the cancellation of the command by checking that RCMD = ZRET (= 3A hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1. • Confirm the completion of pausing of the command by checking that RCMD = ZRET (= 3A hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_PAUSE_CMP = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. <Notes on using the command> • To send this command, select the latch signal with LT_SEL1 of SVCMD_CTRL and output the latch request by setting LT_REQ1 = 1. • TSPD (target speed): Set the target speed with an unsigned value. • ACCR (acceleration): Set the acceleration with an unsigned value. • DECR (deceleration): Set the deceleration with an unsigned value. • When both ACCR and DECR are "0", acceleration/deceleration is performed according to the parameter settings. To perform two-step acceleration/deceleration, set both ACCR and DECR to "0." Refer to the following section for details. ☞ *6.1.2 Positioning Command* on page 6-2. • TLIM (torque limit): Set the torque limit. Set an unsigned value. • Refer to the following section for the above reference data. ☞ *3.2.19 Motion Command Data Setting Method* on page 3-52. • Refer to the following section for the reference value units in the command area. ☞ *2.7.2 Specifying Units* on page 2-26. In the following cases, an alarm will occur and the command will not be executed. • In the servo OFF state: CMD_ALM = A hex (A.95A) • When the TSPD data is invalid:CMD_ALM = 9 hex (A.94B) • When the ACCR or DECR data is invalid: CMD_ALM = 9 hex (A.94B) In the following case, an alarm will occur and the relevant value will be clamped at the limit value. • When the TLIM data is invalid: CMD_ALM = 1 hex (A.97B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	MODE	CPRM_SEL_MON1	
13			
14			
15			
16	TSPD	CPRM_SEL_MON2	
17			
18			
19			
20	ACCR	MONITOR1	
21			
22			
23			
24	DECR	MONITOR2	
25			
26			
27			
28	TLIM	MONITOR3	
29			
30			
31			

Command-specific Data

The following describes the data specific to the ZRET command.

MODE (Lower 1 byte)

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
HOME_DIR	Reserved	Reserved	Reserved	TYPE			

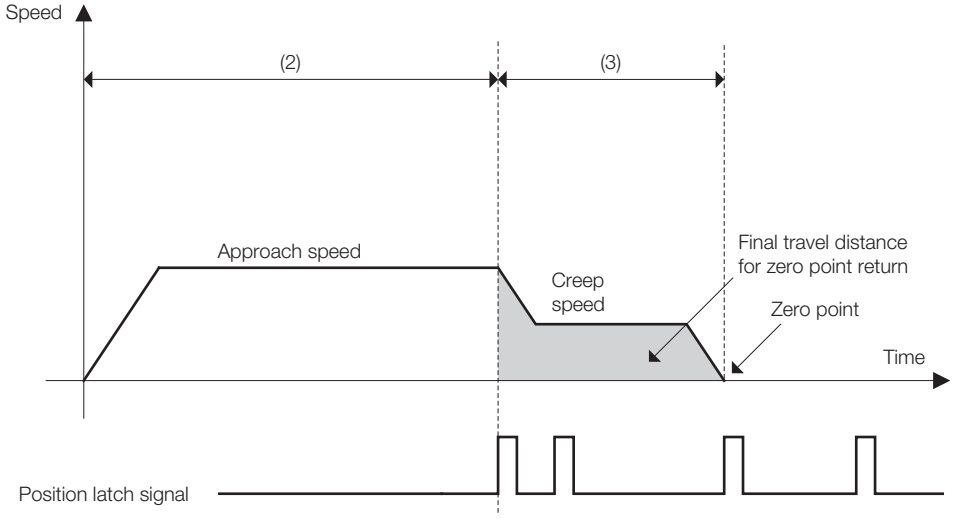
- MODE.HOME_DIR (Zero point return direction)
  Selects the zero point return direction.
  MODE.HOME_DIR = 0:Positive direction
  MODE.HOME_DIR = 1:Negative direction
- MODE.TYPE (Zero point return type)
  Sets the zero point return type on selection of the type from the patterns below.
  MODE.TYPE = 0:Latch signal
  MODE.TYPE = 1:Deceleration limit switch + Latch signal

Operating Sequence

The following describes the zero point return operating sequence for each of the zero point return modes.

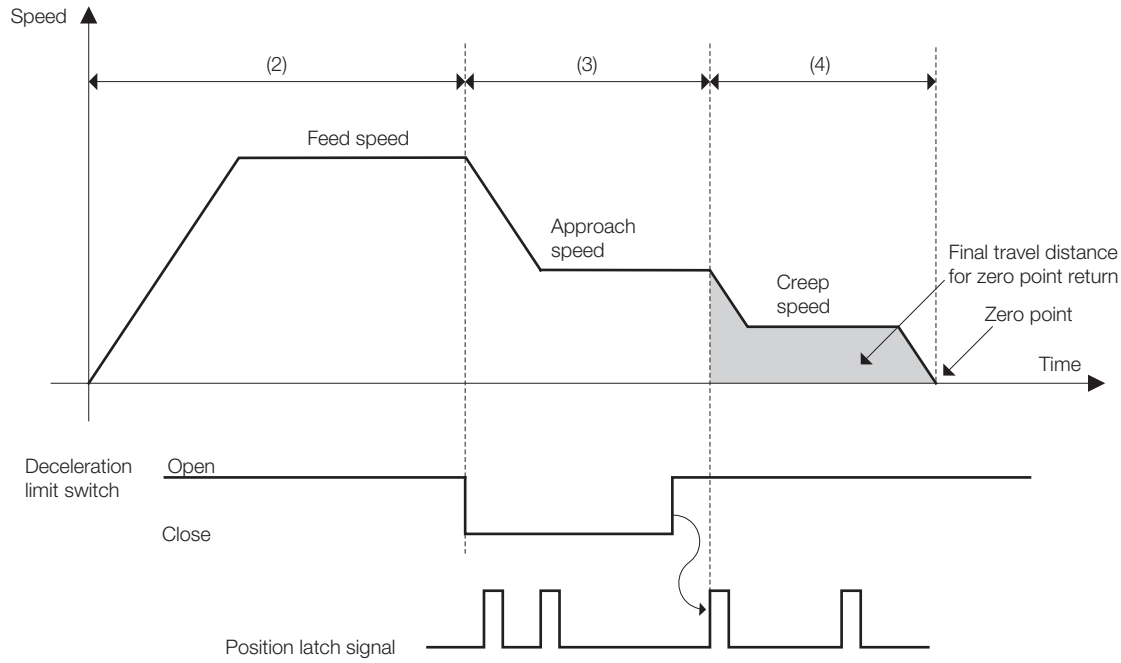
◆ MODE = 0 (Latch Signal)

1. The master station sends the ZRET command. It selects the latch signal with LT_SEL1 of SVCMD_CTRL and outputs the latch request by setting LT_REQ1 = 1.
2. The slave station starts feeding in the direction specified by MODE.HOME_DIR at the speed set for the Homing Approach Speed (common parameter 84).
3. When the current position latch signal, specified by LT_SEL1 of SVCMD_CTRL, is input, the slave station executes positioning through the movement of the Final Travel Distance for Homing (common parameter 86) at the Homing Creep Speed (common parameter 85). After the completion of positioning, the slave station sets the zero point of the reference coordinate system.



◆ MODE = 1 (Deceleration Limit Switch Signal + Latch Signal)

1. The master station sends the ZRET command. It selects the latch signal with LT_SEL1 of SVCMD_CTRL and outputs the latch request by setting LT_REQ1 = 1.
2. The slave station starts feeding in the direction specified by MODE.HOME_DIR at the speed set in the "TSPD" field.
3. When the "deceleration limit switch" is closed (DEC = 1), the feed speed is switched to the Homing Approach Speed (common parameter 84).
4. When the current position latch signal, specified by LT_SEL1 of SVCMD_CTRL, is input after the "deceleration limit switch" is opened (DEC = 0), the slave station executes positioning through the movement of the Final Travel Distance for Homing (common parameter 86) at the Homing Creep Speed (common parameter 85). After the completion of positioning, the slave station sets the zero point of the reference coordinate system.



Information

The motion direction after latching is determined by the sign of the value set for the Final Travel Distance for Homing.

If the Final Travel Distance for Homing is a positive value:

- After latching during motion in the positive direction, the motor rotates in the positive direction (the same direction) for positioning.
- After latching during motion in the negative direction, the motor rotates in the positive direction (the reverse direction) for positioning. (With ZRET in the MECHATROLINK-II compatible profile, the motor rotates in the negative direction (the same direction) for positioning.)

If the Final Travel Distance for Homing is a negative value:

- After latching during motion in the positive direction, the motor rotates in the negative direction (the reverse direction) for positioning.
- After latching during motion in the negative direction, the motor rotates in the negative direction (the same direction) for positioning. (With ZRET in the MECHATROLINK-II compatible profile, the motor rotates in the positive direction (the reverse direction) for positioning.)

3.2.15 Velocity Control Command (VELCTRL: 3C Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	VELCTRL		Description
	Command	Response	
0	3C hex	3C hex	• The VELCTRL command sends the speed reference to a slave station to perform speed control. The slave station performs speed control directly without position control. • To cancel the speed control, set the speed reference as VREF = 0 or set SVCMD_CTRL.CMD_CANCEL to "1." • To pause the speed control, set SVCMD_CTRL.CMD_PAUSE to "1." • Confirm the completion of the command execution by checking that RCMD = VELCTRL (= 3C hex) and CMD_STAT.CMDRDY = 1. • Confirm the completion of command execution canceling by checking that CMD = VELCTRL (= 3C hex), CMD_STAT.CMDRDY = 1, and SVCMD_STAT.CMD_CANCEL_CMP = 1. • Confirm the arrival of the feedback speed at the speed reference (VREF) by checking that SVCMD_IO.V_CMP = 1. • Confirm the completion of pausing of the command by checking that RCMD = VELCTRL (= 3C hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_PAUSE_CMP = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. <Notes on using the command> • VREF (Velocity reference): Set the speed reference with a signed value. • TFF (torque feedforward): Set the torque feedforward value with a signed value. Use it as a torque feedforward function. • ACCR (acceleration): Set the acceleration with an unsigned value. • DECR (deceleration): Set the deceleration with an unsigned value. • TLIM (torque limit): Set the torque limit with an unsigned value. • Refer to the following section for the above reference data. ☞ *3.2.19 Motion Command Data Setting Method* on page 3-52. • Refer to the following section for the reference value units in the command area. ☞ *2.7.2 Specifying Units* on page 2-26. • If the command is sent in the servo OFF state (SVON = 0), the command becomes effective next time the servo ON state (SVON = 1) is established. In the following case, an alarm will occur and the command will not be executed. • When the ACCR or DECR data is invalid: CMD_ALM = 9 hex (A.94B) In the following cases, an alarm will occur and the relevant value will be clamped at the limit value. • When the VREF data is invalid:CMD_ALM = 1 hex (A.94B) • When the TLIM data is invalid:CMD_ALM = 1 hex (A.97B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	TFF	CPRM_SEL_MON1	
13			
14			
15			
16	VREF	CPRM_SEL_MON2	
17			
18			
19			
20	ACCR	MONITOR1	
21			
22			
23			
24	DECR	MONITOR2	
25			
26			
27			
28	TLIM	MONITOR3	
29			
30			
31			

3.2.16 Torque Control Command (TRQCTRL: 3D Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within communication cycle	Subcommand	Can be used	

Byte	TRQCTRL		Description
	Command	Response	
0	3D hex	3D hex	• The TRQCTRL command sends the torque reference to a slave station to performs torque control. The slave station performs torque control directly without speed control and position control. • Confirm the completion of the command execution by checking that RCMD = TRQCTRL (= 3D hex) and CMD_STAT.CMDRDY = 1. • CPRM_SEL_MON1/CPRM_SEL_MON2: Monitor data can be selected by changing the common parameter setting. Refer to the following chapter for details. ☞ *Chapter 8 Common Parameters*. <Notes on using the command> • TQREF (torque reference): Set the torque reference with a signed value. • VLIM (Velocity limit): Set the speed limit with an unsigned value. • Refer to the following section for the above reference data. ☞ *3.2.19 Motion Command Data Setting Method* on page 3-52. • Refer to the following section for the reference value units in the command area. ☞ *2.7.2 Specifying Units* on page 2-26. • If the command is sent in the servo OFF state (SVON = 0), the command becomes effective next time the servo ON state (SVON = 1) is established. In the following cases, an alarm will occur and the relevant value will be clamped at the limit value. • When the TQREF data is invalid: CMD_ALM = 1 hex (A.97B) • When the VLIM data is invalid: CMD_ALM = 1 hex (A.97B)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	VLIM	CPRM_SEL_MON1	
13			
14			
15			
16	TQREF	CPRM_SEL_MON2	
17			
18			
19			
20	Reserved	MONITOR1	
21			
22			
23			
24		MONITOR2	
25			
26			
27			
28		MONITOR3	
29			
30			
31			

3.2.17 Read Servo Parameter Command (SVPRM_RD: 40 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within 200 ms	Subcommand	Cannot be used	

Byte	SVPRM_RD		Description
	Command	Response	
0	40 hex	40 hex	• The SVPRM_RD command reads the servo parameters on specification of the servo parameter number, data size, and the read mode. • Select the parameter type (common parameter or device parameter) in the read mode to read the corresponding servo parameter. • Confirm the completion of the command execution by checking that RCMD = SVPRM_RD (= 40 hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for NO, SIZE and MODE. In the following cases, an alarm will occur. Do not read PARAMETER in the response in these cases because the PARAMETER value will be indefinite. • When the NO data is invalid: CMD_ALM = 9 hex (A.94A) • When the SIZE data is invalid: CMD_ALM = 9 hex (A.94D) • When the MODE data is invalid: CMD_ALM = 9 hex (A.94B) • While editing using SigmaWin or digital operator: CMD_ALM = A hex (A.95A)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	NO	NO	
13			
14	SIZE	SIZE	
15	MODE	MODE	
16	Reserved	PARAMETER	
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

Command Parameters

NO: Servo parameter number
SIZE: Servo parameter data size [byte]
MODE: Servo parameter read mode

Servo Parameter Type	Reading Source	Mode Setting
Common Parameters	RAM area	00 hex
Device Parameter	RAM area	10 hex

PARAMETER: Servo parameter data

3.2.18 Write Servo Parameter Command (SVPRM_WR: 41 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within 200 ms	Subcommand	Cannot be used	

Byte	SVPRM_WR		Description
	Command	Response	
0	41 hex	41 hex	• The SVPRM_WR command writes the servo parameters on specification of the servo parameter number, data size, and write mode. • Select the parameter type (common parameter or device parameter) and the writing destination (RAM area or retentive memory area) in the write mode to write the corresponding servo parameter. • When specifying offline parameters, the CONFIG command must be sent to set up after the parameters are written. • Confirm the completion of the command execution by checking that RCMD = SVPRM_WR (= 41 hex) and CMD_STAT.CMDRDY = 1, and also checking the setting for NO, SIZE, MODE and PARAMETER. In the following cases, an alarm will occur and the command will not be executed. • When the NO data is invalid: CMD_ALM = 9 hex (A.94A) • When the SIZE data is invalid: CMD_ALM = 9 hex (A.94D) • When the MODE data is invalid: CMD_ALM = 9 hex (A.94B) • When the PARAMETER data is invalid: CMD_ALM = 9 hex (A.94B) • While editing using SigmaWin or digital operator: CMD_ALM = A hex (A.95A)
1	WDT	RWDT	
2	CMD_CTRL	CMD_STAT	
3			
4	SVCMD_CTRL	SVCMD_STAT	
5			
6			
7			
8	SVCMD_IO	SVCMD_IO	
9			
10			
11			
12	NO	NO	
13			
14	SIZE	SIZE	
15	MODE	MODE	
16	PARAMETER	PARAMETER	
17			
18			
19			
20			
21			
22			
23			
24			
25			
26			
27			
28			
29			
30			
31			

Command Parameters

NO: Servo parameter number
SIZE: Servo parameter data size [byte]
MODE: Servo parameter write mode

Servo Parameter Type	Writing Destination	Mode Setting
Common Parameters	RAM area	00 hex
	Retentive memory area	01 hex
Device Parameter	RAM area	10 hex
	Retentive memory area	11 hex

PARAMETER: Servo parameter data

3.2.19 Motion Command Data Setting Method

This subsection provides information on the settings of the following data fields of the motion commands: TSPD, VREF, VFF, TREF, TFF, TLIM, VLIM, ACCR and DECR.

Name	Description	Setting	CMD_ALM Warning Code	Operation for the Setting
TSPD	Target speed	FEED, EX_FEED: Set signed 4-byte data.		
		–Maximum commandable speed[*1] to + Maximum commandable speed	0 hex Normal	Operates according to the setting.
		Other than above	9 hex A.94B	Ignores the command and continues the previous command.
		POSING, EX_POSING, ZRET: Set unsigned 4-byte data.		
		0 to Maximum commandable speed and also TSPD ≤ 7FFFFFFF hex	0 hex Normal	Operates according to the setting.
		Other than above	9 hex A.94B	Ignores the command and continues the previous command.
VREF VFF	Velocity reference, Velocity feedforward value	Set signed 4-byte data.		
		–Maximum output speed[*2] to +Maximum output speed	0 hex Normal	Operates according to the setting.
		Other than above	1 hex A.97B	Operates with the speed clamped at the maximum output speed.
TQREF TFF	Torque reference, Torque feedforward value	Set signed 4-byte data.		
		–Maximum torque to +Maximum torque	0 hex Normal	Operates according to the setting.
		Other than above	1 hex A.97B	Operates with the torque clamped at the maximum torque.
TLIM	Torque limit	Set the limit with unsigned 4-byte data.		
		0 to Maximum torque	0 hex Normal	Operates according to the setting.
		Maximum torque or greater	1 hex A.97B	Operates with the torque clamped at the maximum torque.
		80000000 hex to FFFFFFFE hex	1 hex A.97B	SERVOPACK processes as TLIM = 7FFFFFFF hex internally.
		FFFFFFFF hex	0 hex Normal	No torque limit applies. (The torque is clamped at the maximum torque and the alarm CMD_ALM does not occur.)
VLIM	Speed limit	Set the limit with unsigned 4-byte data.		
		0 to Maximum output speed[*2]	0 hex Normal	Operates according to the setting.
		Maximum output speed or greater	1 hex A.97B	Operates with the speed clamped at the maximum output speed.
		80000000 hex to FFFFFFFE hex	1 hex A.97B	SERVOPACK processes as VLIM = 7FFFFFFF hex internally.
		FFFFFFFF hex	0 hex Normal	No speed limit applies. (The speed is clamped at the maximum output speed and the alarm CMD_ALM does not occur.)

Continued on next page.

Continued from previous page.

Name	Description	Setting	CMD_ALM Warning Code	Operation for the Setting
ACCR DECR	Acceleration, Deceleration (position control)	Set the acceleration/deceleration with unsigned 4-byte data.		
		1 to Maximum acceleration*3 Maximum deceleration	0 hex Normal	Operates according to the setting.
		Maximum acceleration or greater Maximum deceleration or greater	9 hex A.94B	Ignores the command and continues the previous command.
		0, 80000000 hex to FFFFFFFE hex	9 hex A.94B	Ignores the command and continues the previous command.
		FFFFFFFF hex	0 hex Normal	Operates at the maximum acceleration/deceleration and the alarm CMD_ALM does not occur.
		Both ACCR and DECR are set at "0."	0 hex Normal	Acceleration/deceleration is performed according to the parameter settings.
ACCR DECR	Acceleration, Deceleration (speed control)	Set the acceleration/deceleration with unsigned 4-byte data. Unit: $\times 10^n$ [Reference unit/s^2]		
		1 to Maximum acceleration Maximum deceleration	0 hex Normal	Operates according to the setting.
		Maximum acceleration or greater Maximum deceleration or greater	9 hex A.94B	Ignores the command and continues the previous command.
		0, 80000000 hex to FFFFFFFE hex	9 hex A.94B	Ignores the command and continues the previous command.
		FFFFFFFF hex	0 hex Normal	Operates at the maximum acceleration/deceleration and the alarm CMD_ALM does not occur.
		Both ACCR and DECR are set at "0."	9 hex A.94B	Ignores the command and continues the previous command.

*1. Maximum commandable speed = 2097152000 [Reference unit/s]
*2. Maximum output speed = Common parameter 05
*3. Maximum acceleration/deceleration = 209715200000 [Reference unit/s^2]

3.2.20 Restrictions in Using Servo Commands

Travel Distance Restrictions for the ZRET (Zero Point Return) Command

If you use the ZRET (Zero Point Return) command for a Σ-7-Series Rotary Servomotor, the following restrictions apply according to the setting of the electronic gear ratio.

Electric Gear Ratio (Pn20E/Pn210)	Travel Distance
1/1	Distance equivalent to ±64 rotations
2/1	Distance equivalent to ±128 rotations
4/1	Distance equivalent to ±256 rotations
16/1	Distance equivalent to ±1,024 rotations

Travel Distance Restrictions for the EX_POSING (External Input Positioning) and EX_FEED (External Input Feed) Commands

If you use the EX_POSING (External Input Positioning) or EX_FEED (External Input Feed) command for a Σ-7-Series Rotary Servomotor, the following restrictions apply according to the setting of the electronic gear ratio.

Electric Gear Ratio (Pn20E/Pn210)	Travel Distance
1/1	Distance equivalent to ±64 rotations
2/1	Distance equivalent to ±128 rotations
4/1	Distance equivalent to ±256 rotations
16/1	Distance equivalent to ±1,024 rotations

Travel Distance Restrictions for the TPOS (Target Position)

If you use TPOS (Target Position) for a Σ-7-Series Rotary Servomotor, the following restrictions apply according to the setting of the electronic gear ratio.

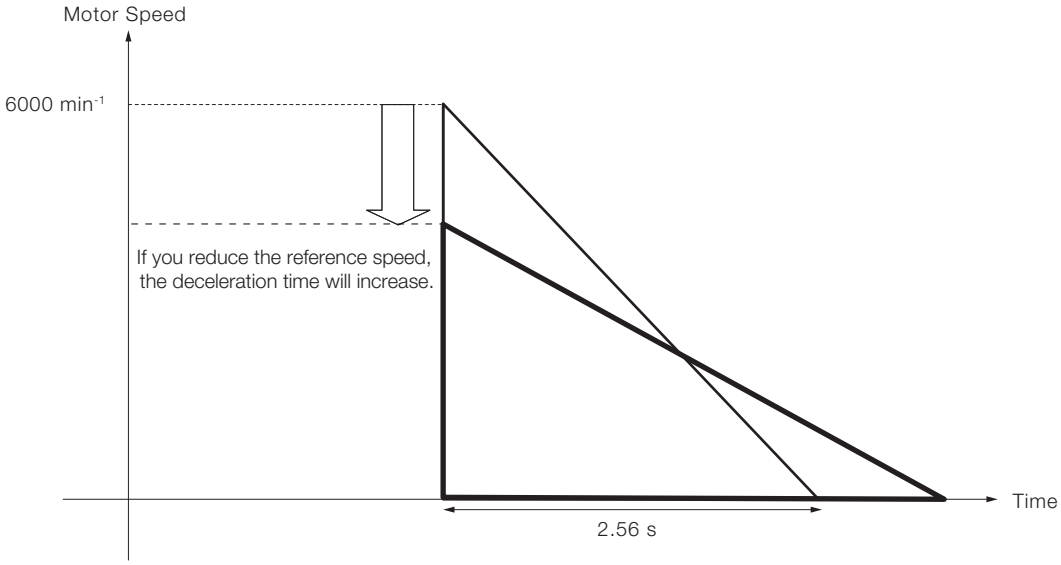
Electric Gear Ratio (Pn20E/Pn210)	Travel Distance
1/1	Distance equivalent to ±128 rotations
2/1	Distance equivalent to ±256 rotations
4/1	Distance equivalent to ±512 rotations
16/1	Distance equivalent to ±2,048 rotations

Deceleration Time Restrictions during Position Control

If you use a positioning command (i.e., POSING, FEED, EX_FEED, EX_POSING, or ZRET) for a Σ-7-Series Rotary Servomotor, the following restrictions apply to the deceleration time.

Electric Gear Ratio (Pn20E/Pn210)	Deceleration Time at 750 min^{-1} [s]	Deceleration Time at 1,500 min^{-1} [s]	Deceleration Time at 3,000 min^{-1} [s]	Deceleration Time at 6,000 min^{-1} [s]
1/1	20.48	10.24	5.12	2.56
2/1	40.96	20.48	10.24	5.12
4/1	81.92	40.96	20.48	10.24
16/1	327.68	163.84	81.92	40.96

The following figure shows the relationship between the reference speed and deceleration time.



Subcommands

4

4.1 Subcommands

The following table shows the subcommands.

Refer to the following section for information on combining main commands and subcommands.

☞ *1.5.4 Combinations of Main Commands and Subcommands* on page 1-9.

Profile	Command Code	Command	Operation	Communication Phases*2		
				1	2	3
Servo Commands	00 hex	NOP	No operation	–	O	O
	05 hex	ALM_RD*1	Read alarm/warning	–	O	O
	06 hex	ALM_CLR	Clear alarm/warning state	–	O	O
	1D hex	MEM_RD*1	Read memory command	–	O	O
	1E hex	MEM_WR*1	Write memory command	–	O	O
	30 hex	SMON	Monitor servo status	–	O	O
	40 hex	SVPRM_RD*1	Read servo parameter	–	O	O
	41 hex	SVPRM_WR	Write servo parameter	–	O	O

*1. Specification restrictions apply (Refer to the subsection describing each command for the details of the restrictions.)

*2. O: Can be executed, Δ: Ignored, ×: Command error, –: Indefinite response data

4.2 No Operation Subcommand (NOP: 00 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Within communication cycle			
Byte	NOP		Description		
	Command	Response			
32	00 hex	00 hex	• The NOP subcommand is used for network control. • Confirm the completion of the subcommand execution by checking that RSUBCMD = NOP (= 00 hex) and SUB_STAT.SBCMDRDY = 1.		
33	SUB_CTRL	SUB_STAT			
34					
35					
36	Reserved	Reserved			
37					
38					
39					
40					
41					
42					
43					
44					
45					
46					
47					

4.3 Read Alarm or Warning Subcommand (ALM_RD: 05 Hex)

Data Format

Phases in which the Command can be Executed	2, 3	Command Classification	Common command	Asynchronous command
Processing Time	Refer to the specifications of ALM_RD_MOD			

Byte	ALM_RD		Description
	Command	Response	
32	05 hex	05 hex	• The ALM_RD subcommand reads the current alarm or warning state as an alarm or warning code. • Confirm the completion of the subcommand execution by checking that RSUBCMD = ALM_RD (= 05 hex) and SUB_STAT.SBCMDRDY = 1. • ALM_INDEX is not used. Its setting is ignored. In the following cases, an alarm will occur and the subcommand will not be executed. • When the ALM_RD_MOD data is invalid: SUBCMD_ALM = 9 hex (A.94B)
33	SUB_CTRL	SUB_STAT	
34			
35			
36	ALM_RD_MOD	ALM_RD_MOD	
37			
38	ALM_INDEX	ALM_INDEX	
39			
40	Reserved	ALM_DATA	
41			
42			
43			
44			
45			
46			
47			

Note: 1. In ALM_DATA, each two bytes provide the information for one alarm.
2. The most recent alarms come first in the history data.
3. Normal status is indicated by 0000 hex.

Command Parameters

The details of ALM_RD_MOD are described below.

ALM_RD_MOD	Description	Processing Time
0	Current alarm or warning state Maximum of 4 records (from byte 40 to byte 47)	Within communication cycle
1	Alarm occurrence status history (Warnings are not retained in the history.) Maximum of 4 records (from byte 40 to byte 47)	Within 60 ms

Σ-7-Series alarm codes are two bytes in length. The data structure is given below.

	Bits 12 to 15	Bits 0 to 11
	0	Alarm Code
Example for A.94B	0 hex	94B hex

4.4 Clear Alarm or Warning Subcommand (ALM_CLR: 06 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Refer to the specifications of ALM_RD_MOD	Subcommand		
Byte	ALM_CLR		Description		
	Command	Response			
32	06 hex	06 hex	• The ALM_CLR subcommand clears the alarm or warning state. It changes the state of a slave station, but does not eliminate the cause of the alarm or warning. ALM_-CLR should be used to clear the state after the cause of the alarm or warning has been eliminated. • Confirm the completion of the subcommand execution by checking that RSUBCMD = ALM_CLR (= 06 hex) and SUB_STAT.SBCMDRDY = 1. In the following cases, an alarm will occur and the sub-command will not be executed. • When the ALM_CLR_MOD data is invalid: SUBCMD_ALM = 9 hex (A.94B) • While editing using SigmaWin or digital operator: SUBCMD_ALM = A hex (A.95A)		
33	SUB_CTRL	SUB_STAT			
34					
35					
36	ALM_CLR_MOD	ALM_CLR_MOD			
37					
38	Reserved	Reserved			
39					
40					
41					
42					
43					
44					
45					
46					
47					

Command Parameters

The details of ALM_CLR_MOD are described below.

ALM_CLR_MOD	Description	Processing Time
0	Clearance of the current alarm or warning state	Within 200 ms
1	Clearance of the alarm history	Within 2 s

4.5 Read Memory Subcommand (MEM_RD: 1D Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Within 200 ms	Subcommand		
Byte	MEM_RD		Description		
	Command	Response			
32	1D hex	1D hex	• The MEM_RD subcommand reads the data stored in virtual memory by specifying the initial address and the data size for reading. • Confirm the completion of the subcommand execution by checking that RSUBCMD = MEM_RD (= 1D hex) and SUB_STAT.SUBCMDRDY = 1, and also checking the setting for ADDRESS and SIZE. In the following cases, an alarm will occur and the subcommand will not be executed. • When the ADDRESS data is invalid: SUBCMD_ALM = 9 hex (A.94A) • When the MODE/DATA_TYPE data is invalid: SUBCMD_ALM = 9 hex(A.94B) • When the SIZE data is invalid: SUBCMD_ALM = 9 hex (A.94D) • While editing using SigmaWin or digital operator: SUBCMD_ALM = A hex (A.95A) Refer to the following section for details. ☞ ◆ *Method to Access Virtual Memory Areas* on page 3-23.		
33	SUB_CTRL	SUB_STAT			
34					
35					
36	Reserved (0)	Reserved (0)			
37	MODE/DATA_-TYPE	MODE/DATA_-TYPE			
38	SIZE	SIZE			
39					
40	ADDRESS	ADDRESS			
41					
42					
43					
44	Reserved	DATA			
45					
46					
47					

Command Parameters

The details of MODE/DATA_TYPE are described below.

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
MODE				DATA_TYPE			

MODE = 1: Volatile memory, 2: Not supported
DATA_TYPE = 1: Byte, 2: Short, 3: Long, 4: Not supported

SIZE: Data size for reading (of type specified by DATA_TYPE)
ADDRESS: Initial address for reading
DATA: Read data

4.6 Write Memory Subcommand (MEM_WR: 1E Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification		
Processing Time		Refer to 3.1.10 *Command Parameters* ◆ *Executing the Adjustment Operation* on page 3-22.	Subcommand	Common command	Asynchronous command

Byte	MEM_WR		Description
	Command	Response	
32	1E hex	1E hex	• The MEM_WR subcommand writes the data in virtual memory by specifying the initial address, the data size and the data for writing. • This subcommand provides an adjustment function equivalent to that of the ADJ command of the MECHATROLINK-II compatible profile. For the operation procedure, refer to the MEM_WR main command. • Confirm the completion of the subcommand execution by checking that RSUBCMD = MEM_WR (= 1E hex) and SUB_STAT.SUBCMDRDY = 1, and also checking the setting for ADDRESS, SIZE and DATA. In the following cases, an alarm will occur and the subcommand will not be executed. • When the ADDRESS data is invalid: SUBCMD_ALM = 9 hex(A.94A) • When the MODE/DATA_TYPE data is invalid: SUBCMD_ALM = 9 hex (A.94B) • When the SIZE data is invalid: SUBCMD_ALM = 9 hex (A.94D) • When the conditions for executing the adjustment operation are not satisfied: SUBCMD_ALM = A hex (A.95A) • While editing using SigmaWin or digital operator: SUBCMD_ALM = A hex (A.95A) Refer to the following section for details. ☞ ◆ *Method to Access Virtual Memory Areas* on page 3-23.
33	SUB_CTRL	SUB_STAT	
34			
35			
36	Reserved (0)	Reserved (0)	
37	MODE/DATA_TYPE	MODE/DATA_TYPE	
38	SIZE	SIZE	
39			
40	ADDRESS	ADDRESS	
41			
42			
43			
44	DATA	DATA	
45			
46			
47			

Command Parameters

The details of MODE/DATA_TYPE are described below.

bit7	bit6	bit5	bit4	bit3	bit2	bit1	bit0
MODE				DATA_TYPE			

MODE = 1: Volatile memory, 2: Non-volatile memory (Non-volatile memory can be selected only for common parameters)

DATA_TYPE = 1: Byte, 2: Short, 3: Long, 4: Not supported

SIZE: Data size for writing (of type specified by DATA_TYPE)
ADDRESS: Initial address for writing
DATA: Data to be written

4.7 Servo Status Monitor Subcommand (SMON: 30 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Common command	Asynchronous command
Processing Time		Within communication cycle	Subcommand		

Byte	SMON		Description
	Command	Response	
32	30 hex	30 hex	• The SMON subcommand reads the alarms, status, and monitor information (position, speed, output, torque, etc.) specified in monitor setting, and the state of the I/O signals of the servo drive. • Confirm the completion of the subcommand execution by checking that RSUBCMD = SMON (= 30 hex) and SUB-_STAT.SUBCMDRDY = 1.
33	SUB_CTRL	SUB_STAT	
34			
35			
36	Reserved	MONITOR4	
37			
38			
39			
40		MONITOR5	
41			
42			
43			
44		MONITOR6	
45			
46			
47			

4.8 Read Servo Parameter Subcommand (SVPRM_RD: 40 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within 200 ms	Subcommand		
Byte	SVPRM_RD		Description		
	Command	Response			
32	40 hex	40 hex	• The SVPRM_RD subcommand reads the servo parameters on specification of the servo parameter number, data size, and the read mode. • Confirm the completion of the subcommand execution by checking that RSUBCMD = SVPRM_RD (= 40 hex) and SUB_STAT.SUBCMDRDY = 1, and also checking the setting for NO, SIZE and MODE. In the following cases, an alarm will occur. Do not read PARAMETER in the response in these cases because the PARAMETER value will be indefinite. • When the NO data is invalid: SUBCMD_ALM = 9 hex(A.94A) • When the SIZE data is invalid: SUBCMD_ALM = 9 hex (A.94D) • When the MODE data is invalid: SUBCMD_ALM = 9 hex(A.94B) • While editing using SigmaWin or digital operator: SUBCMD_ALM = A hex (A.95A)		
33	SUB_CTRL	SUB_STAT			
34					
35					
36	NO	NO			
37					
38	SIZE	SIZE			
39	MODE	MODE			
40	Reserved	PARAMETER			
41					
42					
43					
44					
45					
46					
47					

Command Parameters

NO: Servo parameter number
SIZE: Servo parameter data size [byte]
MODE: Servo parameter read mode

Servo Parameter Type	Reading Source	Mode Setting
Common Parameters	RAM area	00 hex
Device Parameter	RAM area	10 hex

PARAMETER: Servo parameter data

4.9 Write Servo Parameter Subcommand (SVPRM_WR: 41 Hex)

Data Format

Phases in which the Command can be Executed		2, 3	Command Classification	Servo standard command	Asynchronous command
Processing Time		Within 200 ms	Subcommand		
Byte	SVPRM_WR		Description		
	Command	Response			
32	41 hex	41 hex	• The SVPRM_WR subcommand writes the servo parameters on specification of the servo parameter number, data size, and write mode. • Confirm the completion of the subcommand execution by checking that RSUBCMD = SVPRM_WR (= 41 hex) and SUB_STAT.SUBCMDRDY = 1, and also checking the setting for NO, SIZE, MODE and PARAMETER. In the following cases, an alarm will occur and the subcommand will not be executed. • When the NO data is invalid: SUBCMD_ALM = 9 hex (A.94A) • When the SIZE data is invalid: SUBCMD_ALM = 9 hex (A.94D) • When the MODE data is invalid: SUBCMD_ALM = 9 hex (A.94B) • When the PARAMETER data is invalid: SUBCMD_ALM = 9 hex (A.94B) • While editing using SigmaWin or digital operator: SUBCMD_ALM = A hex (A.95A)		
33	SUB_CTRL	SUB_STAT			
34					
35					
36	NO	NO			
37					
38	SIZE	SIZE			
39	MODE	MODE			
40	PARAMETER	PARAMETER			
41					
42					
43					
44					
45					
46					
47					

Note: If the main command and subcommand specifying the same NO are received at the same time as new commands, the main command takes precedence and the alarm specified by SUBCMD_ALM occurs for the subcommand.

Command Parameters

NO: Servo parameter number
SIZE: Servo parameter data size [byte]
MODE: Servo parameter write mode

Servo Parameter Type	Reading Source	Mode Setting
Common Parameters	RAM area	00 hex
	Nonvolatile memory area	01 hex
Device Parameter	RAM area	10 hex
	Nonvolatile memory area	11 hex

PARAMETER: Servo parameter data

Operation Sequence

5

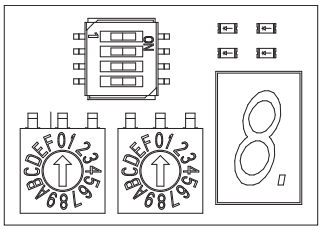
This chapter describes basic operation sequences using MECHATROLINK-III communications.

5.1 Preparing for Operation

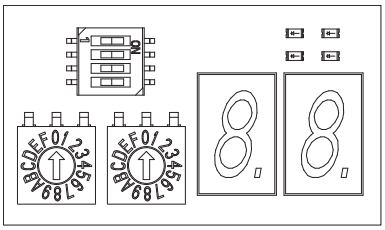
This section describes how to set communications specifications before starting communications, and how to confirm the communications status.

5.1.1 Setting MECHATROLINK-III Communications

The rotary switches (S1 and S2) and DIP switch (S3), which are located near the top under the front cover of the SERVOPACK, are used as shown below to set the MECHATROLINK-III communications specifications.



Σ-7S SERVOPACKs



Σ-7W SERVOPACKs

◆ Setting the Communications Specifications

Set the communications specifications using the DIP switch (S3)

S3	Function	Setting			Factory setting
		1	2	Number of transmission bytes	
Pins 1 and 2	Sets the number of transmission bytes.	OFF	OFF	Reserved. (Do not use this setting.)	1: OFF 2: ON
		ON	OFF	32 byte	
		OFF	ON	48 byte	
		ON	ON	Reserved. (Do not use this setting.)	
Pin 3	Reserved. (Do not change.)				OFF
Pin 4	Reserved. (Do not change.)				OFF

Important

- When using the MECHATROLINK-III standard servo profile, set the number of transmission bytes to either 32 or 48.
- If you change the settings of the communications switches (S1, S2, and S3), turn the power supply OFF and ON again to enable the new settings.

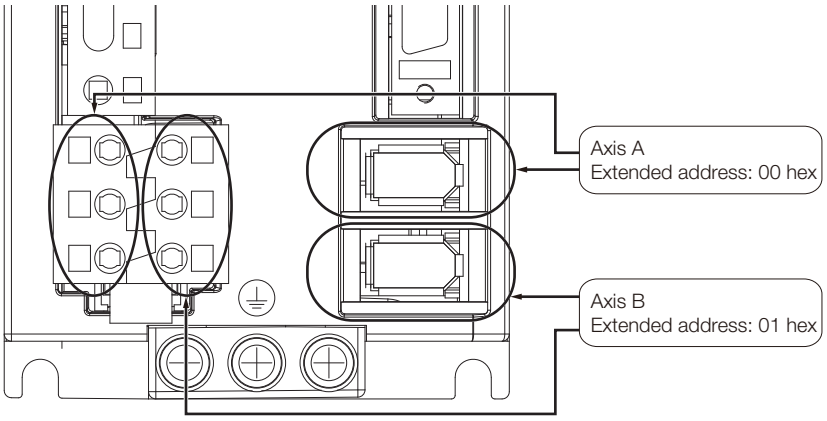
◆ Setting the Station Address

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

Station Address	S1	S2
00 hex to 02 hex: Disabled (Do not use these addresses.)	0	0 to 2
03 hex (Factory setting)	0	3
04 hex	0	4
⋮	⋮	⋮
EF hex	E	F
F0 hex to FF hex: Disabled (Do not use these addresses.)	F	0 to F

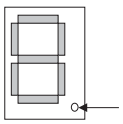
Extended Address Setting (Σ-7W SERVOPACKs Only)

Extended addresses are determined by the Servomotor connection terminals. The UA, VA, and WA terminals are for axis A. The UB, VB, and WB terminals are for axis B.



5.1.2 Checking the Communications Status

To confirm that the SERVOPACK is in the communication enabled state, check the L1, L2 and CN LEDs.

	Description
D3 (L1 LED) D4 (L2 LED)	When communications in the data link layer have started, these LEDs are lit. The L1 LED indicates the status of the communication port at the CN6A connector and the L2 LED that at the CN6B connector. Lit: In normal communication Unlit: Communication not in progress due to disconnected cable, etc.
D2 (CN LED)	When the connection in the application layer has been established, this LED is lit. Lit: In the CONNECT command completed state Unlit: In the CONNECT command uncompleted state
D1 (POWER LED)	Lit while the control power is being supplied normally.
7-segment LED	In normal state: Indicates the status. In alarm/warning state: Indicates the alarm/warning code. 

5.2 Parameter Management and Operation Sequence

5.2.1 Operation Sequence for Managing Parameters Using a Controller

When the parameters are managed by a controller, the parameters are automatically transmitted from the controller to the SERVOPACK when the power is turned ON. Therefore, the settings of SERVOPACK do not need to be changed when the SERVOPACK is replaced.

Procedure	Operation	Command to Send
1	Turn ON the control and main circuit power supplies.	–
2	Confirm the completion of the initialization process of the SERVOPACK.	NOP
3	Reset the previous communications status.	DISCONNECT*
4	Establish communications connection and starts WDT count.	CONNECT
5	Check information such as device ID.	ID_RD
6	Read device setting data such as parameters.	SVPRM_RD
7	Set the parameters required for the device.	SVPRM_WR
8	Enable the parameter settings (Setup).	CONFIG
9	Turn ON the encoder power supply to obtain the position data.	SENS_ON
10	Turn the servo ON.	SV_ON
11	Start operation.	POSING, INTERPOLATE, etc.
12	Turn the servo OFF.	SV_OFF
13	Disconnect the communications connection.	DISCONNECT
14	Turn OFF the control and main circuit power supplies.	–

* When starting the operation sequence with turning the power ON as the first step, it is not necessary to send the DISCONNECT command.

Note: This example sequence shows the steps to enable starting of communications regardless of the status at that point.

5.2.2 Operation Sequence for Managing Parameters Using a SERVOPACK

To manage the parameters by using SERVOPACK's non-volatile memory, save the parameters in the non-volatile memory at setup and use an ordinary operation sequence.

Setup Sequence

Procedure	Operation	Command to Send
1	Turn ON the control and main circuit power supplies.	NOP
2	Reset the previous communications status.	DISCONNECT*
3	Establish communications connection and starts WDT count.	CONNECT
4	Check information such as device ID.	ID_RD
5	Get device setting data such as parameters.	SVPRM_RD
6	Save the parameters required for the device in the non-volatile memory.	SVPRM_WR Note: Do not use RAM.
7	Disconnect the communications connection.	DISCONNECT
8	Turn OFF the control and main circuit power supplies.	–

* If the connection cannot be released normally, send a DISCONNECT command for 2 or more communication cycles, and then send a CONNECT command.

Ordinary Operation Sequence

Procedure	Operation	Command to Send
1	Turn ON the control and main circuit power supplies.	NOP
2	Reset the previous communications status.	DISCONNECT*
3	Establish communications connection and starts WDT count.	CONNECT
4	Check information such as device ID.	ID_RD
5	Get device setting data such as parameters.	SVPRM_RD
6	Turn ON the encoder power supply to obtain the position data.	SENS_ON
7	Turn the servo ON.	SV_ON
8	Start operation.	POSING, INTERPOLATE, etc.
9	Turn the servo OFF.	SV_OFF
10	Disconnect the communications connection.	DISCONNECT
11	Turn OFF the control and main circuit power supplies.	–

* If the connection cannot be released normally, send a DISCONNECT command for 2 or more communication cycles, and then send a CONNECT command.

5.3 Setting the Zero Point before Starting Operation

When Using an Incremental Encoder

When an incremental encoder is used in the slave station, carry out a zero point return operation after turning ON the power supply.
After the zero point is set, set the reference coordinate system to determine the work coordinate zero point as required:

1. Setting the Reference Coordinate System Using ZRET Command
   Use the ZRET command to return the slave station to the zero point and set the reference coordinate system based on the zero point.

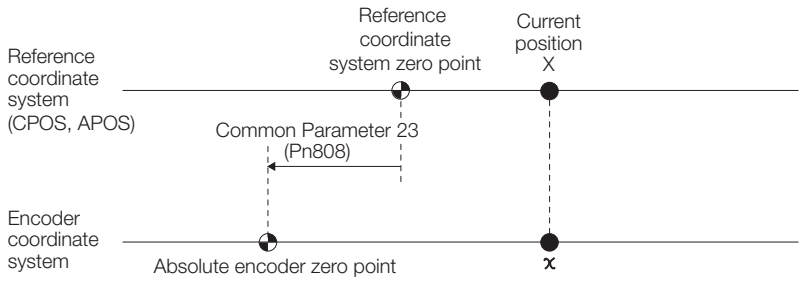
2. Setting the Reference Coordinate System Using POS_SET Command
   Use the POS_SET command to set the reference coordinate system of the slave station.
   - Perform positioning to the reference position using a positioning command such as EX_POSING.
   - Send the POS_SET command with POS_SET_MODE.POS_SEL = APOS (= 0), POS_SET_-MODE.REFE = 1, and POS_DATA = reference position.

ZPOINT and software limits are enabled after the reference coordinate system has been set.

When Using an Absolute Encoder

When an absolute encoder is used in the slave station, the SENS_ON command can be used to set the reference coordinate system of the slave station. The reference coordinate system will be set according to the position detected by the absolute encoder and the coordinate system offset of the encoder (i.e., the offset between the encoder's coordinate system and the reference coordinate system (device built-in parameter)).
The relationship between the reference coordinate system (CPOS and APOS), the encoder's coordinate system, and the coordinate system offset of the encoder are shown in the following figure.

CPOS: Reference position
APOS: Feedback position



X= x+ Common Parameter 23 (Pn808)
Common parameter 23 (Pn808): Absolute encoder origin offset

5.4 Operation Sequence when Turning the Servo ON

Motor control using a host controller is performed using motion commands only in the servo ON state (motor power ON).

In the servo OFF state (when the power to the motor is shut OFF), the SERVOPACK manages position data so that the reference coordinate system (CPOS, MPOS) and the feedback coordinate system (APOS) are equal. For correct execution of motion commands, therefore, it is necessary to use the SMON (status monitoring) command after the servo ON state has been established, to read the servo reference coordinates (CPOS) and send an appropriate reference position. Set the coordinate system of the SERVOPACK using the POS_SET command as necessary.

After completing the setting of the coordinate systems, carry out machine operation using motion commands.

5.5 Operation Sequence when OT (Overtravel Limit Switch) Signal is Input

When an OT signal is input, the SERVOPACK prohibits the motor from rotating in the way specified in parameter Pn001. The motor continues to be controlled by the SERVOPACK while its rotation is prohibited.

When an OT signal is input, use the following procedure to process the OT signal.

Procedure	Operation
1	Monitor OT signals. When an OT signal is input, send an appropriate stop command: While an interpolation command (INTERPOLATE) is being executed: Continues execution of the interpolation command while stopping updating of the interpolation position. Or, sends an SMON command. While a move command (such as POSING) other than interpolation commands is being executed: sets CMD_CANCEL = 1.
2	Check the output completion flag DEN. If DEN = 1, the SERVOPACK completed the OT processing. At the same time, check the flag ZSPD. If ZSPD = 1, the motor is completely stopped. Keep the command used in procedure 1 active until both of the above flags are set to 1.
3	Read out the current reference position (CPOS) and use it as the start position for retraction processing.
4	Use a move command such as POSING or INTERPOLATE for retraction processing. Continue to use this command until the retraction is finished. If the move command ends without finishing the retraction, restart the move command continuously from the last target position.


Note

- When an OT signal is input during execution of a motion command such as ZRET, EX_FEED or EX_POSING, the execution of the command will be cancelled.
- During the overtravel state (P-OT = 1 or N-OT = 1), the servomotor is not positioned to the target position specified by the host controller. Check the feedback position (APOS) to confirm that the axis is stopped at a safe position.


Important

If the state of an OT signal varies over a short time (in a pulsing manner for example), the host controller may not be able to monitor the variation of the OT signal properly. Take due care about the selection of limit switches and their mounting and wiring to avoid chattering of OT signals and malfunctioning.

5.6 Operation Sequence at Emergency Stop (Main Circuit OFF)

For circuits incorporating the recommended processing that the control and main circuit power supplies turn OFF on occurrence of an emergency stop, no specific process is required.

For circuits that turn OFF only the main circuit power supply, follow the procedure below.

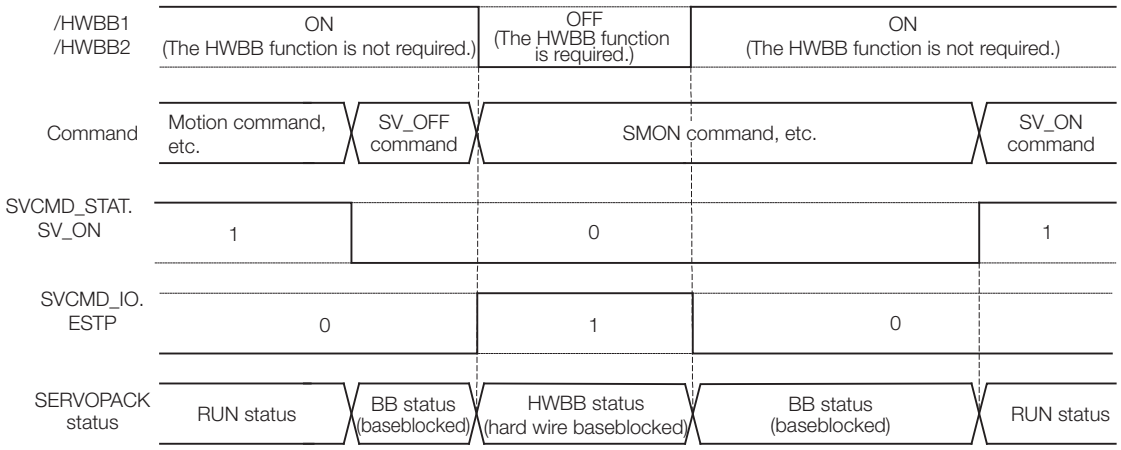
After confirming that the SV_ON or PON bit in the STATUS field of the response data is OFF (= 0), send an SV_OFF command. While in an emergency stop state, always monitor the SERVOPACK status using a command such as the SMON (status monitoring) command.

For recovery from an emergency stop state, follow the action to be taken on occurrence of an alarm.

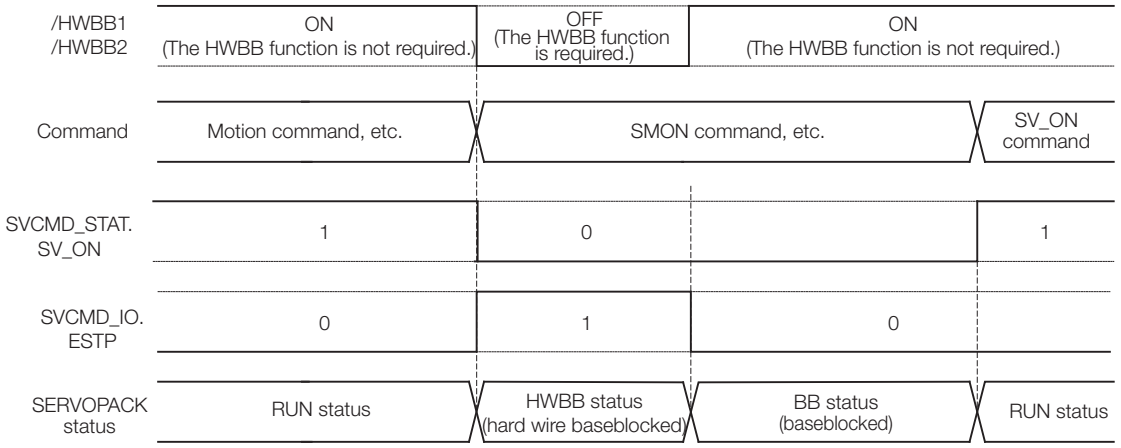
5.7 Operation Sequence when a Safety Signal is Input

When the HWBB1 or HWBB2 signal is input while the motor is operating, the power supply to the motor is shut OFF forcibly and the motor stops according to the setting of the 1st digit of parameter Pn001 (i.e., Pn001 = n.□□□X).

- When an HWBB signal is input after the SERVOPACK stops powering the motor



- When an HWBB signal is input while the SERVOPACK is powering the motor



◆ When an HWBB Signal is Input

Monitor the HWBB input signal and SCM output signal status, or ESTP signal (HWBB) status in the SVCMD_IO (servo command input signal) field. If a forced stop status is detected, send a command such as SV_OFF to stop the motor.

◆ Recovery from Stop Status

Recover from the stop status by following the procedure below.

1. Reset the HWBB1 or HWBB2 signal.
   The HWBB state is still valid at this point.
2. Send an SV_OFF command to shift the SERVOPACK to the base block state.
3. Carry out controller and system recovery processing.
4. Send an SV_ON command to establish the servo ON state.
5. Complete the preparation for operation after establishing the servo ON state.
6. Start operation.

Note: 1. If the SERVOPACK enters the HWBB status while sending an SV_ON command, reset the /HWBB1 or /HWBB2 signal and then send a command other than SV_ON, such as SV_OFF. Then, send the SV_ON command again to restore the normal operation status.

2. If the SERVOPACK enters the HWBB status during execution of an SV_OFF, INTERPOLATE, POSING, FEED, EX_FEED, EX_POSING, or ZRET command, a command warning will occur since the SERVOPACK status changes to the servo OFF state. Execute the clear alarm or warning (ALM_CLR) command to restore normal operation.

5.8 Operation Sequence at Occurrence of Alarm

When the D_ALM bit in the CMD_STAT field of the response is 1 or a COMM_ALM field of 8 or a greater value is detected, send the SV_OFF command.

Use the ALM_RD command to check the alarm code that has occurred.
To clear the alarm status, send the ALM_CLR command or set the ALM_CLR bit of the CMD_CTRL command to "1" after eliminating the cause of the alarm. However, this will not clear the alarm status that require the power supply to be turned OFF and back ON for clearance.

- For Communication Error Alarms
  When a communication error alarm (COMM_ALM ≥ 8) occurs, the communication phase shifts to phase 2. To restore communication phase 3, send a SYNC_SET command after resetting the alarm.

- For Warnings
  When the D_WAR bit is 1 or the COMM_ALM field of a value from 1 to 7 is detected, a warning occurs but the servo OFF state will not be established. Check the alarm code using the ALM_RD command and perform appropriate processing. To clear the warning state, send the ALM_CLR command or set the ALM_CLR bit of the CMD_CTRL command to "1."

- For Command Errors
  Check the status of CMD_ALM with the host controller in every communication cycle and perform appropriate processing because CMD_ALM will be automatically cleared on reception of the next normal command after detecting CMD_ALM ≠ 0.

5.9 Notes when the Positioning Completed State (PSET = 1) is Established while Canceling a Motion Command

When the SERVOPACK enters any of the following states during execution of a motion command, it may cancel the execution of the motion command and establish the positioning completed state (PSET = 1).

- The servo OFF state (SV_ON of SVCMD_STAT set to "0") has been established due to an alarm (D_ALM of CMD_STAT set to "0" or COMM_ALM ≥ 8).
- The servo OFF state (SV_ON of SVCMD_STAT set to "0") has been established because the main power supply was turned OFF (PON of SVCMD_STAT set to "0").
- The motor has stopped due to overtravel (P-OT or N-OT of SVCMD_IO set to "1") or a software limit (P_SOT or N_SOT of SVCMD_IO set to "1").
- The servo OFF state (SV_ON of SVCMD_STAT set to "0") has been established because the HWBB signal was turned OFF (ESTP of SVCMD_IO set to "1").

In this case, the motor has not reached the target position specified by the host controller even though PSET is set to "1." Check the feedback position (APOS) to confirm that the axis is stopped at a safe position.


Important

If the state of an OT signal varies over a short time (in a pulsing manner for example), the host controller may not be able to monitor the variation of the OT signal properly. Take due care about the selection of limit switches and their mounting and wiring to avoid chattering of OT signals and malfunctioning.

Function/Command Related Parameters

6

6.1 Position Control

This section describes the parameters related to interpolation and positioning in position control.

6.1.1 Interpolation Command

When sending the INTERPOLATE command, the speed feedforward and torque feedforward values can be specified along with the target position.

The sum of the speed feedforward value specified by the INTERPOLATE command and the (speed) feedforward value set in the parameters (common parameter 64 (Pn109) and Pn10A) will be applied.

Specifying the speed feedforward value using the INTERPOLATE command may lead to overshooting if the settings of the following parameters (common parameter 64 (Pn109) and Pn10A) are inappropriate. When specifying the speed feedforward value using the INTERPOLATE command, set the parameters to "0" (factory setting).

Common Parameters	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
64	Feedforward Compensation	4	0 to 100	%	0

Parameter	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn109	Feedforward	2	0 to 100	1%	0
Pn10A	Feedforward Filter Time Constant	2	0 to 64000	0.01 ms	0

If the speed feedforward and torque feedforward values are specified using the INTERPOLATE command, the values will be cleared when another command is executed.

6.1.2 Positioning Command

There are the following two kinds of acceleration/deceleration method for positioning commands (POSING, FEED, EX_FEED, EX_POSING, and ZRET).

- Using the acceleration/deceleration specified by the command
- Using the acceleration/deceleration set in the parameters

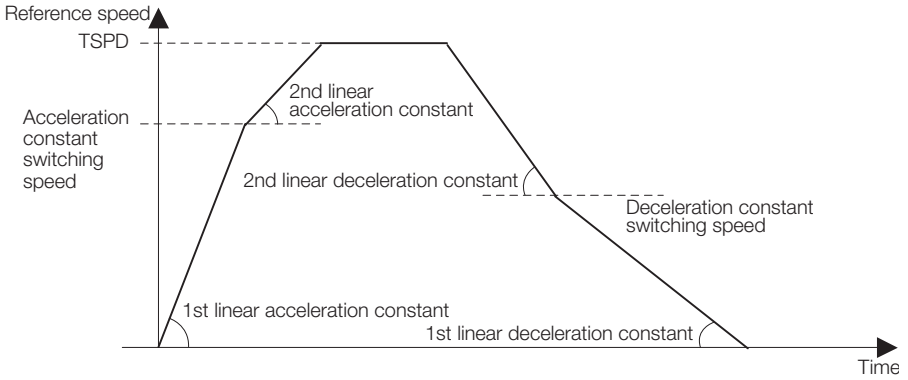
Using the Acceleration/Deceleration (ACCR and DECR) Specified by the Command

When using the acceleration/deceleration (ACCR and DECR) specified by the command, positioning will be performed with 1-step acceleration/deceleration.

When both the acceleration and deceleration (ACCR and DECR) are set to "0" in the command, positioning will be performed with 2-step acceleration/deceleration according to the parameter settings.

Using the Acceleration/Deceleration Set in the Parameters

The setting of the 1st digit of parameter Pn833 (i.e., Pn833 = n.□□□X) determines which parameter to use for acceleration/deceleration when both the acceleration and deceleration rates (ACCR and DECR) in the command are set to 0.



Note: Make settings so that the distance required for deceleration and the deceleration satisfy the following conditions.
Deceleration [reference unit/s^2] ≥ Maximum reference speed [reference unit/s]^2 / (Maximum deceleration distance [reference unit] × 2)

◆ Acceleration/Deceleration Constant Switching Setting

Parameter		Meaning	Data Size (Byte)	Setting Range	Unit
Pn833	n.□□□0 (Factory setting)	Use Pn80A to Pn80F and Pn827. (The settings of Pn834 to Pn840 are ignored.)	2	0000 hex to 0001 hex	–
	n.□□□1	Use Pn834 to Pn840. (The settings of Pn80A to Pn80F and Pn827 are ignored.)			

Note: The setting will be validated by turning the power supply OFF and then ON again, or by executing the CONFIG command.

◆ Acceleration/Deceleration Parameters when Pn833=n.□□□0

Parameter	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn80A	First Stage Linear Acceleration Constant	2	1 to 65535	10000 reference units/s^2	100
Pn80B	Second Stage Linear Acceleration Constant	2	1 to 65535	10000 reference units/s^2	100
Pn80C	Acceleration Constant Switching Speed	2	0 to 65535	100 reference units/s	0
Pn80D	First Stage Linear Deceleration Constant	2	1 to 65535	10000 reference units/s^2	100
Pn80E	Second Stage Linear Deceleration Constant	2	1 to 65535	10000 reference units/s^2	100
Pn80F	Deceleration Constant Switching Speed	2	0 to 65535	100 reference units/s	0
Pn827	Linear Deceleration Constant 1 for Stopping	2	1 to 65535	10000 reference units/s^2	100

◆ Acceleration/Deceleration Parameters when Pn833=n.□□□1

Parameter	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn834	First Stage Linear Acceleration Constant 2	4	1 to 20971520	10000 reference units/s^2	100
Pn836	Second Stage Linear Acceleration Constant 2	4	1 to 20971520	10000 reference units/s^2	100
Pn838	Acceleration Constant Switching Speed 2	4	0 to 2097152000	Reference units/s	0
Pn83A	First Stage Linear Deceleration Constant 2	4	1 to 20971520	10000 reference units/s^2	100
Pn83C	Second Stage Linear Deceleration Constant 2	4	1 to 20971520	10000 reference units/s^2	100
Pn83E	Deceleration Constant Switching Speed 2	4	0 to 2097152000	Reference units/s	0
Pn840	Linear Deceleration Constant 2 for Stopping	4	1 to 20971520	10000 reference units/s^2	100

6.2 Torque Limiting Function

The torque limiting function limits the torque during position/speed control to protect the connected machine, etc. There are three ways to limit the output torque.

- Internal torque limit according to parameter settings
- External torque limit using the P_CL and N_CL bits of the SVCMD_IO field
- Torque limit by position/speed control command

If all of the above three methods are used, the smallest torque limit will be applied.

Internal Torque Limit

This method always limits the maximum output torque to the set values of the following parameters.

Parameter	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn402	Forward Torque Limit (For rotational servomotors)	2	0 to 800	%	800
Pn403	Reverse Torque Limit (For rotational servomotors)	2	0 to 800	%	800
Pn483	Forward Force Limit (For linear servomotors)	2	0 to 800	%	30
Pn484	Reverse Force Limit (For linear servomotors)	2	0 to 800	%	30

External Torque Limit Using P_CL/N_CL Bits of SVCMD_IO Field

This method uses the P_CL and N_CL bits of the SVCMD_IO field to limit the output torque to the values set for the following parameters. Settings can be made using common parameters.

Common Parameters	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
8C	Forward Torque Limit	4	0 to 800	%	100
8D	Reverse Torque Limit	4	0 to 800	%	100

Parameter	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn404	Forward External Torque Limit	2	0 to 800	%	100
Pn405	Reverse External Torque Limit	2	0 to 800	%	100

Torque Limit by Position/Speed Control Command

Torque limits can be specified using the following commands.

INTERPOLATE, POSING, FEED, EX_FEED, EX_POSING, ZRET, VELCTRL

This method limits the torque to the value set for TLIM of the position/speed control command.

The torque limits operate based on parameter settings (i.e., Pn81F = n.□□X□ and Pn002 = n.□□□X). (The torque limit is enabled for the default setting.)

Parameter		Meaning	Data Size (Byte)	Setting Range	Unit
Pn81F	n.□□0□	Reserved	2	0000 hex to 0001 hex	–
	n.□□1□ (Factory setting)	The settings of the TFF and TLIM fields of position control commands are enabled. Operation depends on the setting of Pn002 = n.□□□X.			
Pn002	n.□□□0	Reserved	2	0000 hex to 0003 hex	–
	n.□□□1 (Factory setting)	Forward and reverse torque limits based on the setting of the TLIM field of the position/ speed control commands are enabled.			
	n.□□□2	Reserved			
	n.□□□3	Reserved			

The following table shows the operation when all of the three methods are used. The smallest torque limit in each group will be applied.

Pn002 = n.□□□X	Forward Torque Limit		Reverse Torque Limit	
	When P_CL is set to 0	When P_CL is set to 1	When N_CL is set to 0	When N_CL is set to 1
1	Pn402 (Pn482)* TLIM	Pn402 (Pn482)* Common parameter 8C (Pn404) TLIM	Pn403 (Pn483)* TLIM	Pn403 (Pn483)* Common parameter 8D (Pn405) TLIM

* The parameter numbers in parentheses are for linear servomotors.

When sending a command other than the commands that can specify torque limit, the last torque limit specified by the TLIM field remains valid. During execution of the SV_OFF or TRQCTRL command, the torque limit specified by the TLIM field becomes invalid and the maximum torque will be used as the limit.

6.3 Torque Feedforward Function

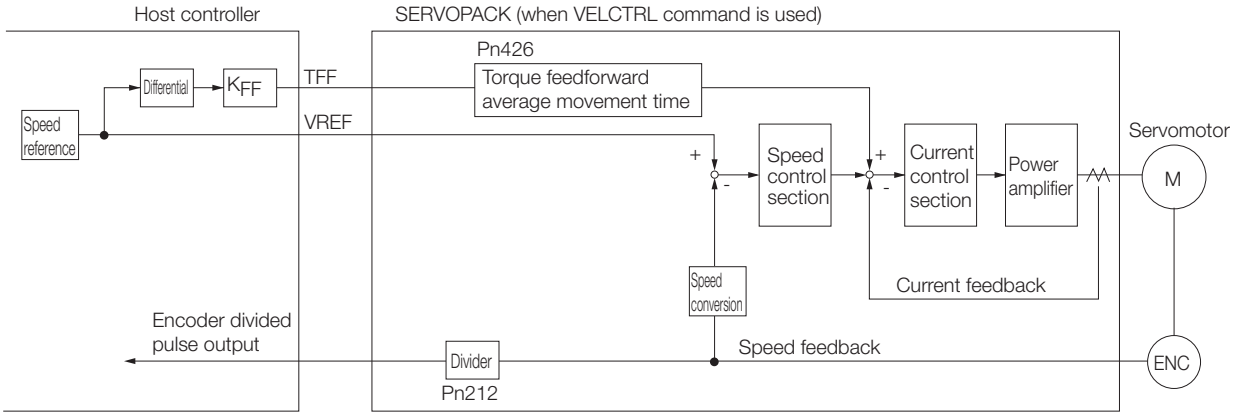
The torque feedforward function applies feedforward compensation to position control or speed control to shorten the positioning time. The torque feedforward reference is created from the differential of the position reference at the host controller. Torque feedforward is specified with TFF (torque feedforward) in the position control or speed control command.

You can specify torque feedforward for the INTERPOLATE and VELCTRL commands.

6.3.1 Relationship between the Host Controller and SERVOPACK

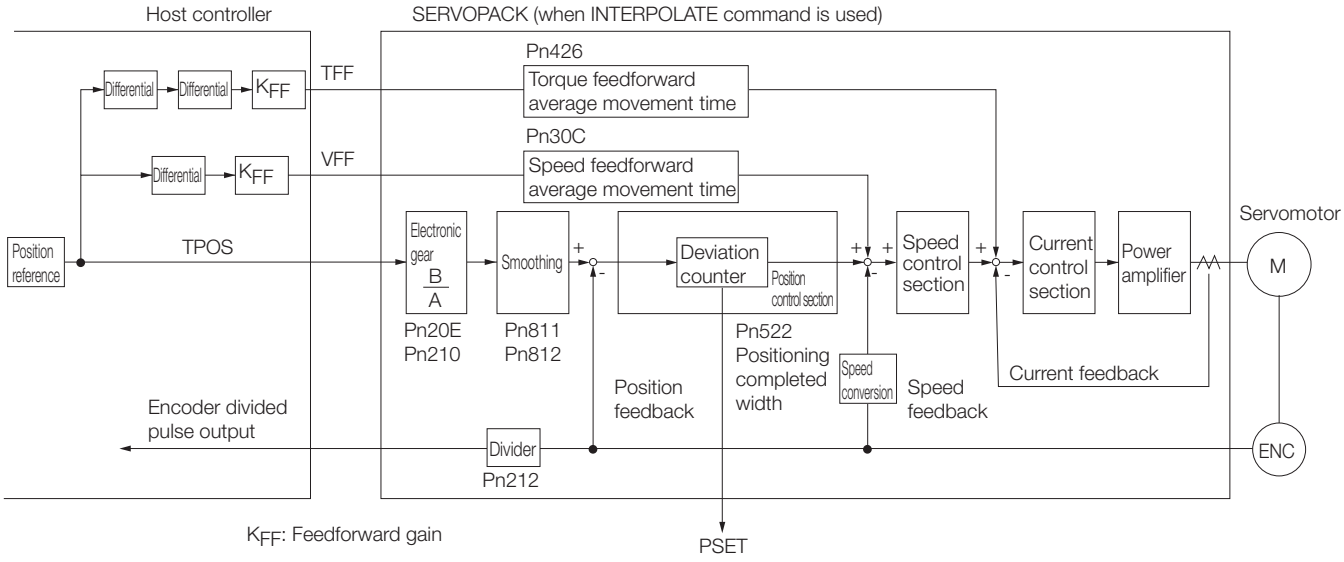
The following figures illustrate specifying torque feedforward in commands from the host controller when the SERVOPACK is performing speed control or position control.

◆ When SERVOPACK Performs Speed Control



K_{FF}: Feedforward gain

◆ When SERVOPACK Performs Position Control



K_{FF}: Feedforward gain

6.3.2 Setting Parameters

This section describes the parameters that are related to the torque feedforward reference.

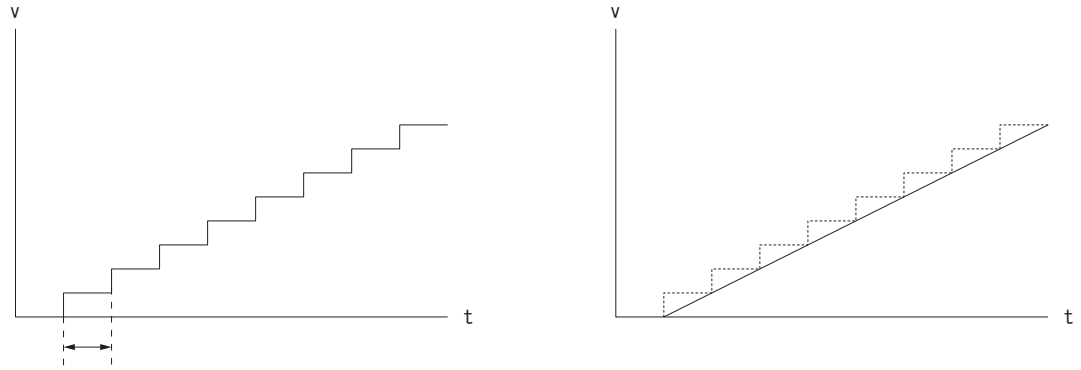
Pn81F (Position Control Command TFF/TLIM Allocation)

You must set Pn81F (Position Control Command TFF/TLIM Allocation) to use the torque feedforward reference. (The torque limit is enabled for the default setting.)

Parameter	Meaning	
Pn81F = n.□□X□	Position Control Command TFF/TLIM Allocation	
	n.□□1□	Enable allocation. (The operation for TFF/TLIM is set in Pn002.)

Pn426 (Torque Feedforward Average Movement Time)

If the communications cycle with the host controller is slow, the torque feedforward reference may be applied stepwise as shown on the left in the following figure.



You can set Pn426 (Torque Feedforward Average Movement Time) to a suitable value to create a smooth torque feedforward reference, as shown on the right in the above figure.

As a guideline, set Pn426 to the same value as the communications cycle.

Pn426	Torque Feedforward Average Movement Time Speed Position				
	Setting Range	Setting Unit	Default Setting	When Enabled	Classification
	0 to 5,100	–	0	Immediately	Setup

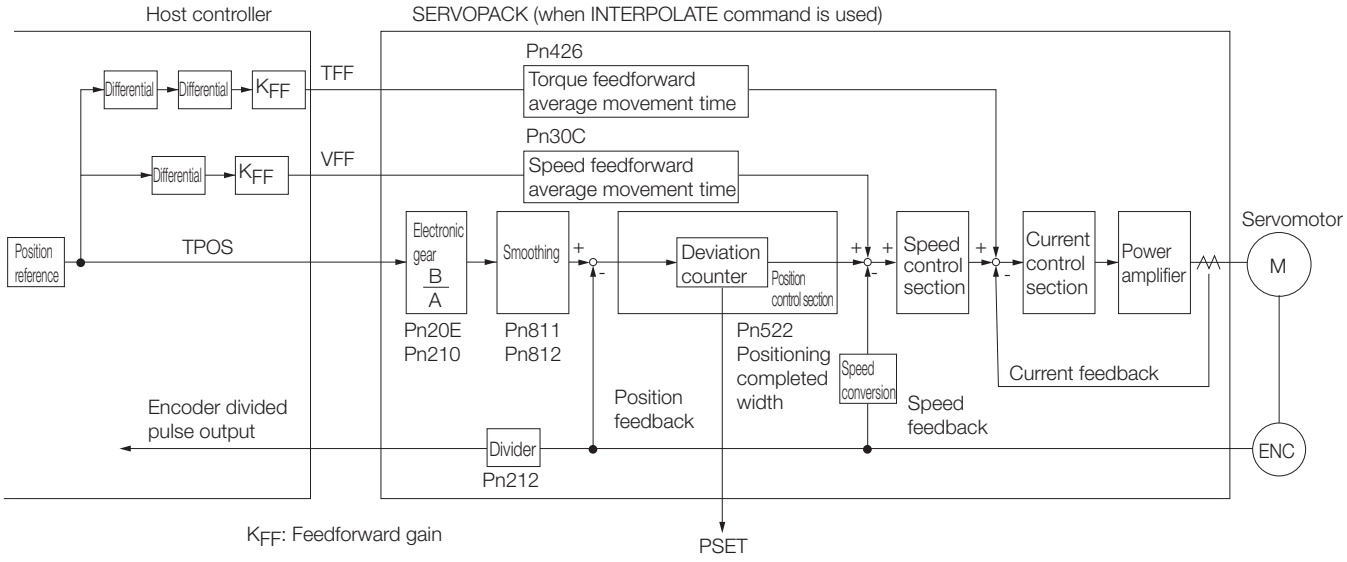
6.4 Speed Feedforward Function

The speed feedforward function applies feedforward compensation to position control to shorten the positioning time. The speed feedforward reference is created from the differential of the position reference at the host controller. Speed feedforward is specified with VFF (speed feedforward) in the position control command.

You can specify speed feedforward for the INTERPOLATE command.

6.4.1 Relationship between the Host Controller and SERVOPACK

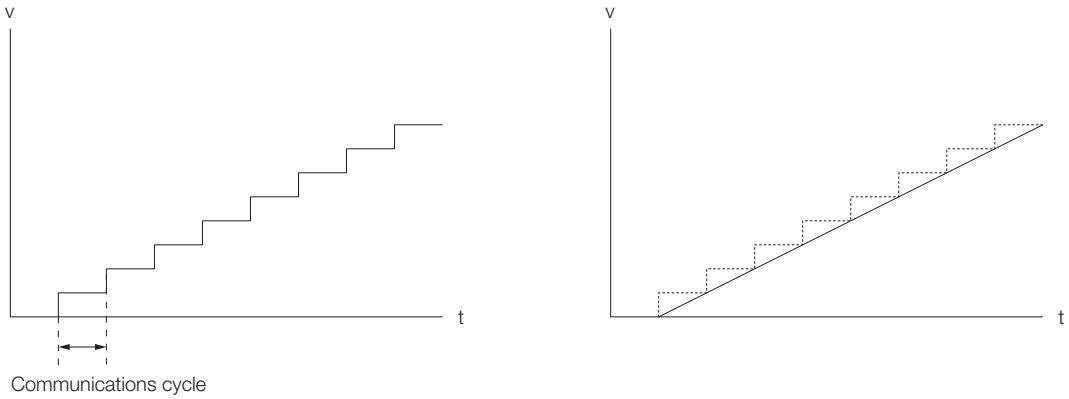
The following figure illustrates specifying speed feedforward in a command from the host controller when the SERVOPACK is performing speed control.



6.4.2 Setting Parameters

Speed Feedforward Average Movement Time (Pn30C)

If the communications cycle with the host controller is slow, the speed feedforward reference may be applied stepwise as shown on the left in the following figure.



You can set Pn30C (Speed Feedforward Average Movement Time) to a suitable value to create a smooth speed feedforward reference, as shown on the right in the above figure.

As a guideline, set Pn30C to the same value as the communications cycle.

Pn30C	Speed Feedforward Average Movement Time			Position	
	Setting Range	Setting Unit	Default Setting	When Enabled	Classification
	0 to 5,100	–	0	Immediately	Setup

6.5 Software Limit Function

This function forcibly stops the servomotor in the same way as the overtravel function when the moving part of the machine enters the software limit range specified by the parameters (common parameter 26 (Pn804), common parameter 28 (Pn806)).

The method for stopping the servomotor is the same as when an OT signal is input.

Conditions for Enabling the Software Limit Function

The software limit function is enabled when the following operations are completed. In other cases, the function remains disabled.

- Zero point return operation by the ZRET command is completed.
- The coordinate setting is completed after reference point setting (REFE = 1) by executing the POS_SET command.
- When using an absolute encoder, the sensor is turned on by the SENS_ON command.

Parameters Related to Software Limit Functions

Common Parameters	Name		Data Size (Byte)	Setting Range	Unit	Factory Setting
25	Limit Setting		4	0 to 33 hex	–	0000 hex
	bit 0	P-OT (0: Enabled, 1: Disabled)				
	bit 1	N-OT (0: Enabled, 1: Disabled)				
	bit 2	Reserved				
	bit 3	Reserved				
	bit 4	P-SOT (0: Disabled, 1: Enabled)				
	bit 5	N-SOT (0: Disabled, 1: Enabled)				
	bit 6 to 31	Reserved				
26	Forward Software Limit		4	–1073741823 to 1073741823	Reference unit	1073741823
28	Reverse Software Limit		4	–1073741823 to 1073741823	Reference unit	–1073741823

Parameter		Meaning	Data Size (Byte)	Setting Range	Unit
Pn801	n.□□□0	Enable both forward and reverse software limits.	2	0000 hex to 0103 hex	–
	n.□□□1	Disable forward software limit.			
	n.□□□2	Disable reverse software limit.			
	n.□□□3 (Factory setting)	Disable both forward and reverse software limits.			
	n.□□0□ (Factory setting)	Reserved			
	n.□0□□ (Factory setting)	Do not perform software limit checks for references.			
	n.□1□□	Perform software limit checks for references.			
	n.0□□□ (Factory setting)	Reserved			
Pn804		Forward Software Limit	4	–1073741823 to 1073741823	Reference unit
Pn806		Reverse Software Limit	4	–1073741823 to 1073741823	Reference unit

Software Limit Monitoring

Check servo command input signal monitoring bits P_SOT and N_SOT for software limits.

Software limit operations are not performed in directions for which the software limit function is disabled, and the corresponding servo command input signal monitoring bit is always "0."

- Pn801 = n.□X□□ (Software Limit Check for References)
  If the target position specified by a command such as POSING and INTERPOLATE is in the software limit range, positioning will be performed by using the software limit value as the target position.

6.6 Latch Function

Three types of current position latch function using an external signal input are available:
- Latching by using the move command with the latch function (EX_FEED, EX_POSING, ZRET)
- Latching based on the latch request set by the LT_REQ1 and LT_REQ2 bits
- Continuous latch based on the latch request set by the LT_REQ2 bit

An overview of the latch operation is presented below.

Type Operation	Move Command with Latch Function	Latching Based on the Latch Request Set by the LT_REQ1 and LT_REQ2 Bits	Continuous Latch Based on the Latch Request Set by the LT_REQ2 Bit
Latch Operation	The slave station starts latching on reception of the command if LT_REQ1 = 1, and ends latching on input of the specified latch signal.	The slave station starts latching if LT_REQ1 = 1 and LT_REQ2 = 1, and ends latching on input of the specified latch signal.	The slave station starts latching if LT_REQ2 = 1, and repeats latching on input of the specified latch signal.
Canceling Latching	Cancelled by LT_REQ1 = 0 Cancelled when the slave station receives another command	Cancelled by LT_REQ1 = 0 and LT_REQ2 = 0	Cancelled by LT_REQ2 = 0
Checking Completion of Latching	Check L_CMP1.	Check L_CMP1 and L_CMP2.	Check L_CMP2 and EX_STATUS.
Outputting Latched Position*	LPOS1	LPOS1, 2	LPOS2
Latching Allowable Area	According to the settings of Pn820 and Pn822		

* The specification differs from that of the MECHATROLINK-II compatible profile. Monitor the latched position by selecting the latched position with monitor selection bits SEL_MON1 to 3.

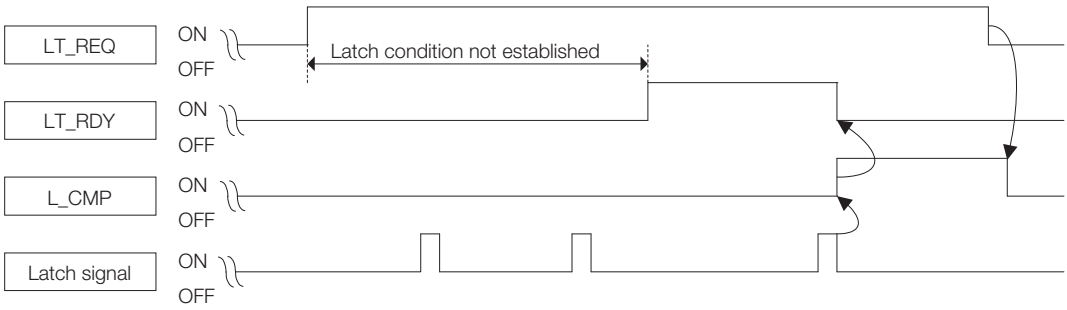
The relationship among the signals related to latching is shown in the diagram below.

Even if a request for latching is made, latch signals will not be accepted until the latching conditions are satisfied.

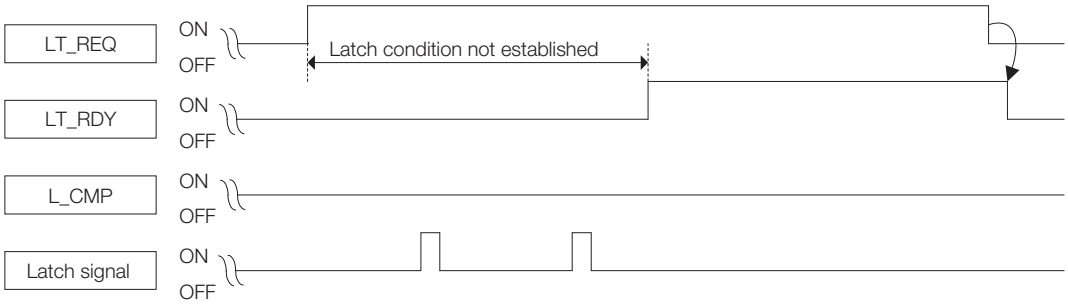
Whether the latching conditions have been satisfied or not can be checked at LT_RDY1 and LT_RDY2 selected with common monitor 1 (CMN1) and common monitor 2 (CMN2). These monitors correspond to the 0th and 1st bits of the SV_STAT field of common parameter 89 (PnB12).

In either of the following cases, latching will not be performed since the latching conditions are not satisfied.
- Outside the latching allowable area set by parameters
- Inside the latching disabled area in the operation sequence for the ZRET command

◆ Operation when Latching is Completed



◆ Operation when Latching is not Completed

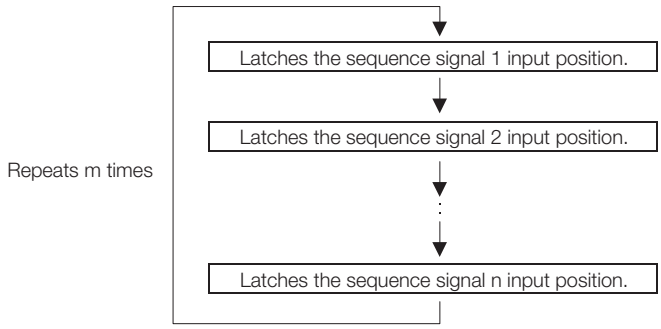


◆ Latch Time Lag

- From reception of the command to latching start: 250 μs max.
- From completion of latching to transmission of a response: One communication cycle max.

6.6.1 Continuous Latch by LT_REQ2 Bit

This function sequentially latches the input positions of sequence signal 1 to sequence signal n (n = 1 to 8) a specified number of times. The continuous latch operation can be aborted by setting the LT_REQ2 bit to OFF (LT_REQ2 = 0). This function can shorten the time between latch completion and the start of the next latch, and enables sequential latch operations at high speed.



◆ How to Start and Stop Continuous Latch Operation

Set the following parameters, and then set LT_REQ2 to "1" to start continuous latch operation. To abort the operation, set LT_REQ2 to "0."

Pn850: Number of Latch Sequences n

Pn851: Continuous Latch Sequence Count m (When m = 0, the continuous latch operation will be infinitely repeated.)

Pn852: Latch Sequence 1 to 4 Settings

Pn853: Larch Sequence 5 to 8 Settings

Note: If Pn850 is set to "0" and LT_REQ2 to "0", normal latching will be performed.

◆ Latch Status

Latch completion can be confirmed by the following status.

[SVCMD_STAT]

L_CMP2: L_CMP2 is set to "1" for one communication cycle every time the external signal is input.

[EX_STATUS] EX_STATUS is allocated to OMN1 (Pn824) or OMN2 (Pn825).
(Pn824 = 84 hex or Pn825 = 84 hex)

L_SEQ_NO (D8-D11):The latch sequence signal number (≤ n) on completion of latching of the current position
(Added on completion of position latching)

L_CMP_CNT (D0-D7): The continuous latch count (≤ m)
(Added on completion of position latching when the latch sequence signal n is input.)

◆ Latched Position Data

The latest latched position data at completion of latching can be obtained by using the following monitor.

Name	Code	Remark
Feedback Latch Position	LPOS2	The latest latch signal input position

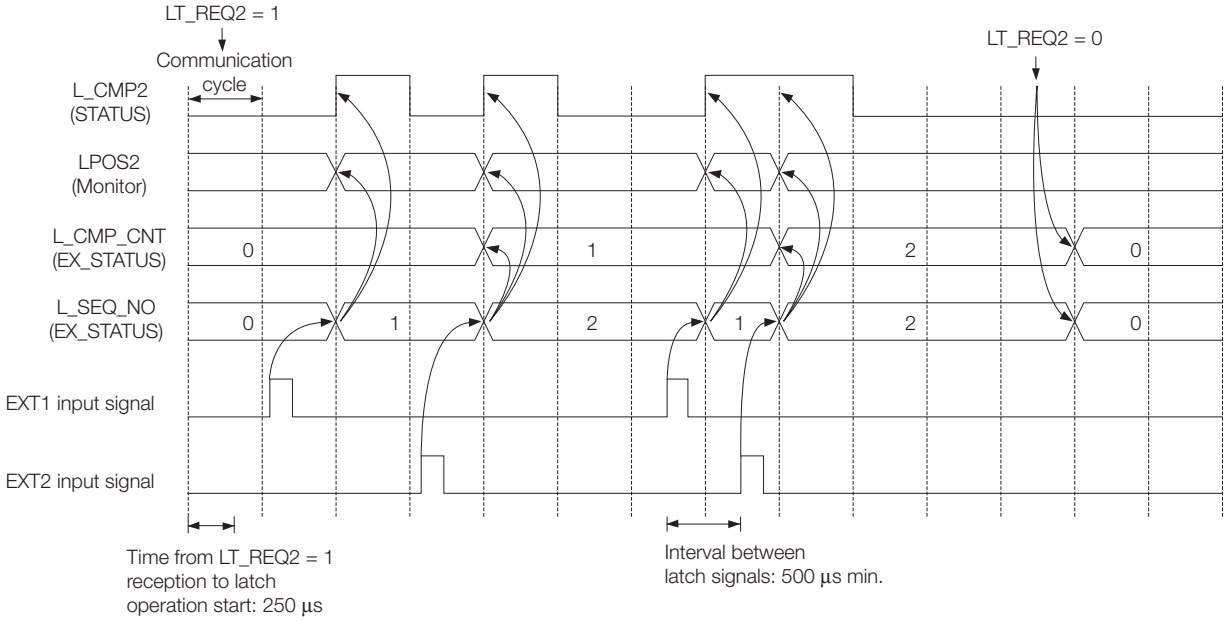
The previously latched position data can be obtained by using the following optional monitors.

Name	Code	Remark
Optional Monitor 1	OMN1	Pn824 = 81 hex: Previous latch (sequence) signal 2 input position (LPOS2)
Optional Monitor 2	OMN2	Pn825 = 81 hex: Previous latch (sequence) signal 2 input position (LPOS2)

◆ Operation Example

An example of a continuous latch operation using two latch sequence signals EXT1 and EXT2 is illustrated below.

(The parameters are set as follows: Pn850 = 2, Pn851 = 2 or more, Pn852 = 0021 hex, Pn853 = any)



◆ Setting Parameters

Parameter No.	Digit	Name			Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn850		Number of Latch Sequences			2	0 to 8	–	0
Pn851		Continuous Latch Sequence Count			2	0 to 255	–	0
Pn852		Latch Sequence 1 to 4 Settings			2	0000 hex to 3333 hex	–	0000 hex
	1	Latch Sequence 1 Signal Selection	0	Phase C	–	0 to 3	–	0
			1	EXT1 signal				
			2	EXT2 signal				
			3	EXT3 signal				
	2	Latch Sequence 2 Signal Selection	As above					
	3	Latch Sequence 3 Signal Selection	As above					
	4	Latch Sequence 4 Signal Selection	As above					
Pn853		Latch Sequence 5 to 8 Settings			2	0000 hex to 3333 hex	–	0000H
	1	Latch Sequence 5 Signal Selection	0	Phase C	–	0 to 3	–	0
			1	EXT1 signal				
			2	EXT2 signal				
			3	EXT3 signal				
	2	Latch Sequence 6 Signal Selection	As above					
	3	Latch Sequence 7 Signal Selection	As above					
	4	Latch Sequence 8 Signal Selection	As above					

Note

- The minimum interval between latch signals is 500 ms. An interval between latch signals that is longer than the communication cycle is required to continuously obtain latched position data.
- If two latch signals are input without allowing the minimum required interval, only the first latch signal input position will be latched. The second latch signal will be ignored.
- The parameters Pn850 to Pn853 can be changed only while the continuous latch operation is stopped.

6.6.2 Setting the Latching Allowable Area

Use the following parameters to set the latching allowable area.

Parameter	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn820	Forward Latching Area	4	–2147483648 to 2147483647	Reference unit	0
Pn822	Reverse Latching Area	4	–2147483648 to 2147483647	Reference unit	0

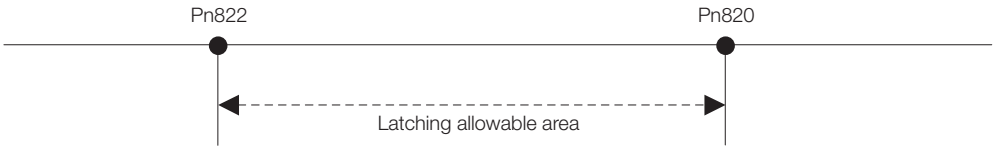
Latch signal input is enabled when the following two conditions are satisfied.

- Within the latching allowable area set by Pn820 and Pn822
- The LT_REQ1 and LT_REQ2 bits of the SVCMD_CTRL field is set to "1" (requesting latching).*

* For the MECHATROLINK-II compatible profile, the conditions are different.

The above conditions for enabling latch signal input are valid for the latch operation for any command.

- When Pn820 > Pn822



- When Pn820 ≤ Pn822

6.7 Acceleration/Deceleration Parameter High-speed Switching Function

This function switches all of the acceleration/deceleration parameters that are used for positioning at the same time.

Register the acceleration/deceleration parameter settings in a bank before starting operation, and specify bank selector BANK_SEL1 in the data field of the command to switch the acceleration/deceleration parameter settings to those of the registered bank.

◆ Specifying a Bank

Specify a bank with the BANK_SEL1 bits of the SVCMD_IO field of the command.

Name	Description	Setting Data
BANK_SEL1 (4 bits)	Bank selector 1 (acceleration/deceleration bank)	Bank 0 to 15

Note: If a bank number larger than the bank number set in Pn900 is specified (BANK_SEL1 ≥ Pn900), the parameter bank will not switch and the currently active bank will be used. The parameters will not switch while DEN = 0 (Distributing) either.

◆ Parameter Bank Setting

Set the following parameters.

Parameter No.	Name	Data Size (Byte)	Setting Range	Factory Setting
Pn900	Number of Parameter Banks	2	0 to 16	0
Pn901	Number of Parameter Bank Members	2	0 to 15	0
Pn902 to Pn910	Parameter Bank Member Definition	2	0000 hex to 08FF hex	0
Pn920 to Pn95F*	Parameter Bank Data	2	0000 hex to FFFF hex Depends on bank member.	0

* The parameters Pn920 to Pn95F will not be stored in the non-volatile memory. They need to be set every time the power is turned ON.

◆ Parameters that can be Registered as Bank Members

The following parameters can be registered as parameter bank members by parameters Pn902 to Pn910.

For 4-byte parameters, one parameter must be registered as two consecutive members. (See Setting Example 2.)

Parameter	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn80A	First Stage Linear Acceleration Constant	2	1 to 65535	10000 reference units/s^2	100
Pn80B	Second Stage Linear Acceleration Constant	2	1 to 65535	10000 reference units/s^2	100
Pn80C	Acceleration Constant Switching Speed	2	0 to 65535	100 reference units/s	0
Pn80D	First Stage Linear Deceleration Constant	2	1 to 65535	10000 reference units/s^2	100
Pn80E	Second Stage Linear Deceleration Constant	2	1 to 65535	10000 reference units/s^2	100
Pn80F	Deceleration Constant Switching Speed	2	0 to 65535	100 reference units/s	0
Pn834	First Stage Linear Acceleration Constant 2	4	1 to 20971520	10000 reference units/s^2	100

Continued on next page.

Continued from previous page.

Parameter	Name	Data Size (Byte)	Setting Range	Unit	Factory Setting
Pn836	Second Stage Linear Acceleration Constant 2	4	1 to 20971520	10000 reference units/s^2	100
Pn838	Acceleration Constant Switching Speed 2	4	0 to 2097152000	Reference unit/s	0
Pn83A	First Stage Linear Deceleration Constant 2	4	1 to 20971520	10000 reference units/s^2	100
Pn83C	Second Stage Linear Deceleration Constant 2	4	1 to 20971520	10000 reference units/s^2	100
Pn83E	Deceleration Constant Switching Speed 2	4	0 to 2097152000	Reference unit/s	0
Pn810	Exponential Acceleration/ Deceleration Bias	2	0 to 65535	100 reference units/s	0
Pn811	Exponential Acceleration/ Deceleration Time Constant	2	0 to 5100	0.1 ms	0
Pn812	Movement Average Time	2	0 to 5100	0.1 ms	0
Pn846	S-Curve Acceleration/ Deceleration Ratio	2	0 to 50	%	0

◆ Setting Procedure

■ STEP1

1. Set Pn900 (Number of Parameter Banks) to m.

2. Set Pn901 (Number of Parameter Bank Members) to n.
Set Pn900 and Pn901 so that Pn900 × Pn901 ≤ 64.

3. Register bank member parameter numbers using parameters Pn902 to Pn910.

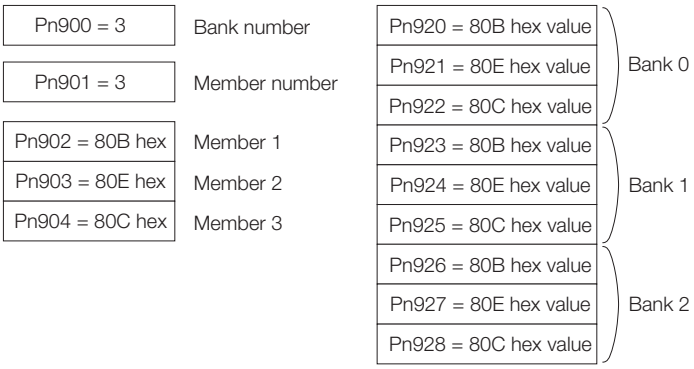
4. To enable the bank function, execute the CONFIG command or turn the power supply OFF and then ON again.

■ STEP2

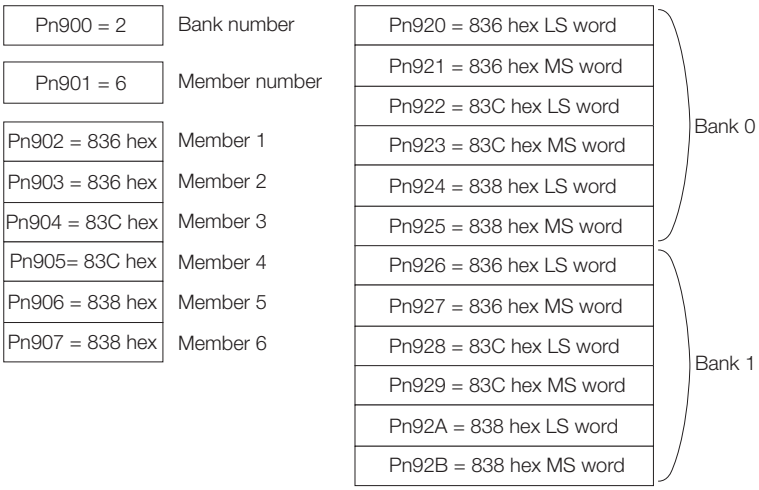
5. Set the data of each bank in the parameter bank data area from the leading parameter Pn920 in order as shown below.
Bank 0: Pn920 to Pn (920 + n – 1)
Bank 1: Pn (920 + n) to Pn (920 + 2n–1)
:
Bank m – 1: Pn {920 + (m – 1) × n} to Pn (920 + m × n – 1)

Note: 1. If parameters Pn900 to Pn910 set in STEP 1, 2, and 3 are saved in the non-volatile memory, carry out STEP 5 only after turning the power ON the next and subsequent times.
However, if you turn the power supply OFF and then ON again after saving parameters Pn900 to Pn910 in the non-volatile memory (i.e. with the bank function enabled), and start the operation without setting parameters Pn920 to Pn95F, the operation will be carried out under the condition that all bank data is set to 0 (zero) or the minimum setting.
2. If parameters Pn900 to Pn910 set in STEP 1, 2, and 3 are not saved in the non-volatile memory, carry out STEP 1 to 5 each time the power supply is turned ON.

- Setting Example 1: Switching three banks of members Pn80B, Pn80E, and Pn80C



- Setting Example 2: Switching two banks of members Pn836, Pn83C, and Pn838



◆ Application Notes

- If Pn900 (Number of Parameter Banks) or Pn901 (Number of Parameter Bank Members) is set to 0, the bank function will be disabled.
- If one parameter is registered for more than one bank member definition, the bank data of the biggest bank member definition parameter number will be applied.
- The acceleration/deceleration parameter high-speed switching function is enabled only while DEN = 1 (distribution completed). The parameters will not switch while DEN = 0 (distributing). However, this does not apply to changing the S-curve acceleration/deceleration ratio (Pn846).
- In the following cases, error A.04A (Parameter Setting Error 2) will occur when the power supply is turned back ON or CONFIG command is executed.
  - One 4-byte parameter is not registered for two consecutive bank members.
  - The total number of bank data entries exceeds 64 (Pn900 × Pn901 > 64).
- If a parameter that is not allowed to be a bank member is registered, the bank data of the parameter-registered member will become invalid.
- Bank data that exceeds the setting range of the registered bank member parameter will be clamped to a value within the setting range.
- If a bank number larger than the bank number set in Pn900 is specified (BANK_SEL1 ≥ Pn900), the parameter bank will not switch and the currently active bank will be used.
- The parameters Pn920 to Pn95F will not be stored in the non-volatile memory. They need to be set every time the power is turned ON.

Detecting Alarms/ Warnings Related to Communications or Commands

7

This chapter describes the alarms and warnings that may occur in MECHATROLINK-III communications. For alarms and warnings that are not described in this manual, refer to the applicable manual for design and maintenance of the SERVOPACK.

7.1 Communication Related Alarms

The table below shows the communication alarms that may occur in MECHATROLINK-III communications.

If an error is found in the command or data that a SERVOPACK receives, the SERVOPACK returns the corresponding alarm code (in the COMM_ALM bit of the CMD_STAT field of the response).

At the same time, the alarm code is displayed on the SERVOPACK.

Category	Alarm in Response			Remedy	SERVOPACK Side		
	COMM_ALM	Name	Meaning		Stopping Method	Alarm Code	Alarm Reset
Communication Setting Error	0	Communication data size setting error	The received data size does not match the data size set at the local station. The communication data reception status after starting communication is abnormal.	Review the number of transmission bytes (S3). Review the communication setting of the controller.	Zero-speed stopping	A.E41	Possible
	0	Station address setting error	The station address setting is invalid or a station assigned the same station address exists in the communication network.	Review the station addresses (S1, S2).	Zero-speed stopping	A.E42	Impossible
Communication Establishment Error	B	Transmission cycle setting error	An unsupported transmission cycle was set on reception of a CONNECT command.	Review the transmission cycle setting of the controller.	Zero-speed stopping	A.E40	Possible
	C	Synchronization failure	On reception of the CONNECT command and then the SYNC_SET command, the WDT data is not refreshed in each communication cycle and the communication timing cannot be synchronized.	Review the WDT processing of the controller. Check communication connections. Take countermeasures against noise.	Zero-speed stopping	A.E51	Possible

Continued on next page.

Continued from previous page.

Category	Alarm in Response			Remedy	SERVOPACK Side		
	COM-M_ALM	Name	Meaning		Stopping Method	Alarm Code	Alarm Reset
Communication Error	9	Data reception error	Data reception errors occurred twice consecutively after completing the execution of the CONNECT command. (Influence of noise, etc.) An error is detected on the communication LSI.	Check communication connections. Take countermeasures against noise. To recover from the alarm state, send the ALM_CLR command and then the SYNC_SET command. If the alarm continues, replace the SERVOPACK.	Zero-speed stopping	A.E60	Possible
	8	FCS error	FCS errors occurred twice consecutively after completing the execution of the CONNECT command. (Influence of noise, etc.)	Check communication connections. Take countermeasures against noise. To recover from the alarm state, send the ALM_CLR command and then the SYNC_SET command.	Zero-speed stopping	A.E62	Possible
	A	Synchronous frame not received	The synchronous frame not received state was detected twice consecutively after completing the execution of the CONNECT command. (Influence of noise, etc.)	Check communication connections. Take countermeasures against noise. To recover from the alarm state, send the ALM_CLR command and then the SYNC_SET command.	Zero-speed stopping	A.E63	Possible
Communication Synchronization Error	C	Synchronization error	The controller is not refreshing the WDT data in each communication cycle after completing communication synchronization (in communication phase 3).	Review the WDT processing of the controller. To recover from the alarm state, send the ALM_CLR command and then the SYNC_SET command.	Zero-speed stopping	A.E50	Possible
	B	Transmission cycle error	The transmission cycle interval varied after completing the execution of the CONNECT command.	Review the transmission cycle interval of the controller. To recover from the alarm state, send the ALM_CLR command and then the SYNC_SET command.	Zero-speed stopping	A.E61	Possible
	0	Internal synchronization error	The transmission cycle interval varied after completing the execution of the CONNECT command.	Review the transmission cycle interval of the controller. To recover from the alarm state, turn OFF the power and then turn it back ON.	Stop by dynamic brake	A.E02	Impossible
	0	Internal synchronization error	The transmission cycle interval varied after completing the execution of the CONNECT command.	Review the transmission cycle interval of the controller. To recover from the alarm state, send the ALM_CLR command and then the SYNC_SET command.	Zero-speed stopping	A.EA2	Possible

Continued on next page.

Continued from previous page.

Category	Alarm in Response			Remedy	SERVOPACK Side		
	COM-M_ALM	Name	Meaning		Stopping Method	Alarm Code	Alarm Reset
System Error	0	Communication LSI initialization error	The initialization process of the communication LSI failed.	Replace the SERVOPACK.	Stop by dynamic brake	A.b6A	Impossible
	0	Communication LSI error	An error is detected on the communication LSI.	Take countermeasures against noise. Replace the SERVOPACK.	Stop by dynamic brake	A.b6b	Impossible
Parameter Error	0	Parameter setting error	The parameter settings are not correct when turning the power ON or on execution of the CONFIG command. Cause 1: There is an error in the bank parameter settings. (Refer to *6.7 Acceleration/ Deceleration Parameter High-speed Switching Function* for details.) Cause 2: The settings of the reserved parameters have been changed as follows. Pn200 = n.□X□□ is not set to 1. Pn207 = n.□□X□ is not set to 1. Pn50A≠*881 hex Pn50C≠8888 hex Pn50D≠8888 hex	Correct invalid parameter settings. Correct the settings manually or through communication as appropriate.	Stop by dynamic brake	A.04A	Possible
Command Execution Error	0	Command timeout error	The execution of the SV_ON or SENS_ON command was not completed within the set period.	Send the command while the motor is stopped.	Zero-speed stopping	A.ED1	Possible

7.2 Warnings Related to Communication and Commands

Warnings are divided into two categories, warnings related to data reception and procedures in MECHATROLINK-III communications and warnings related to the validity of commands.

7.2.1 Communication Errors (COMM_ALM)

The table below shows the warnings related to procedures in MECHATROLINK-III communications.

When an error of this kind is detected, the warning code is displayed on the SERVOPACK as well.

If any of these warnings occur, the relevant command will not be executed because the command data is not properly received. The operation of the servomotor continues. Therefore, the response will be the same as that of the previous command.

Category	Alarm in Response			SERVOPACK Side	
	COM-M_ALM	Meaning	Remedy	Warning Code	Warning Code Reset
Communications Warning	2	Communication error	Check communication connections. Take countermeasures against noise.	A.960	Necessary
	1	FCS error		A.962	
	3	Synchronization frame not received		A.963	

If a warning A.96□ occurs during the interpolation operation (INTERPOLATE), the interpolation operation at the current feed speed continues within the communication cycle in which the warning A.96□ was detected.

7.2.2 Command Errors (CMD_ALM)

The table below shows the warnings related to the validity of commands.

When an error of this kind is detected, the warning code is displayed on the SERVOPACK as well.

Category	Alarm in Response			SERVOPACK Side		Remark
	CMD_ALM	Meaning	Remedy	Warning Code	Warning Code Reset	
Data Setting Warning	9	Parameter numbers or data addresses are incorrect.	Review the content of the command data sent by the controller. (Refer to the setting conditions of each command and parameter.)	A.94A	Cleared automatically	The command received on occurrence of the warning will be ignored. The servomotor continues its operation.
	9	The data in the command is invalid.		A.94b		
	9	The combination of data settings is incorrect.		A.94C		
	9	The data size specified by the command is incorrect. The data is specified outside the range for the relevant data.		A.94d		
	1	The data in the command is beyond the limit. It will be clamped at the limit value.		A.97b	Cleared automatically	The command will be executed with the data clamped at the limit value.

Continued on next page.

Continued from previous page.

Category	Alarm in Response			SERVOPACK Side		Remark
	CMD_ ALM	Meaning	Remedy	Warning Code	Warning Code Reset	
Command Warning	A	The command sequence is incorrect.	Review the command sending sequence of the controller. (Refer to the conditions of each command.)	A.95A	Cleared automatically	–
	8	An unsupported command has been received.		A.95b		
	A	Latch command interferes.		A.95d		
	B	Subcommand and main command interfere.		A.95E		
	8	An illegal command has been received.		A.95F		
	C	A command not allowed in this communication phase has been received.		A.97A		

On reception of a normal command after a command error has occurred, CMD_ALM (A.94□ and A.95□) is cleared automatically.

7.2.3 Monitoring Communication Data on Occurrence of an Alarm or Warning

You can monitor the command data that is received when an alarm or warning occurs, such as a data setting warning (A.94□) or a command warning (A.95□) by using the following parameters. The following is an example of the data when an alarm or warning has occurred in the normal state.

Command Data Monitor during Alarm/Warning: Pn890 to Pn8A6

Response Data Monitor during Alarm/Warning: Pn8A8 to Pn8BE

Command Byte Sequence	Command Data Storage When an Alarm or Warning Occurs	
	CMD	RSP
0	Pn890 = n.□□□□□□XX	Pn8A8 = n.□□□□□□XX
1	Pn890 = n.□□□□XX□□	Pn8A8 = n.□□□□XX□□
2	Pn890 = n.□□XX□□□□	Pn8A8 = n.□□XX□□□□
3	Pn890 = n.XX□□□□□□	Pn8A8 = n.XX□□□□□□
4 to 7	Pn892	Pn8AA
8 to 11	Pn894	Pn8AC
12 to 15	Pn896	Pn8AE
16 to 19	Pn898	Pn8B0
20 to 23	Pn89A	Pn8B2
24 to 27	Pn89C	Pn8B4
28 to 31	Pn89E	Pn8B6
32 to 35	Pn8A0	Pn8B8
36 to 39	Pn8A2	Pn8BA
40 to 43	Pn8A4	Pn8BC
44 to 47	Pn8A6	Pn8BE

Note: Data is stored in little endian byte order and displayed in the hexadecimal.

Common Parameters

8

8.1 Overview

Common parameters are assigned common parameter numbers that are defined in the standard servo profile and are independent of individual devices. The utilization of common parameters means that parameters can be read or set without using parameter numbers or names specific to individual devices.

To read or set common parameters, select "common parameters" in the MODE field of the SVPRM_RD or SVPRM_WR command.

In the common parameters, there are various parameters that have equivalent functions to device parameters (Pn0□□ to Pn8□□) specific to this SERVOPACK. As shown in the following example, setting either the common parameter or the device parameter will change the value of the corresponding parameter. Refer to the following section for details.

☞ *8.3 Common Parameters and Corresponding Device Parameters* on page 8-11

The units (number of significant digits) differ between common parameters and device parameters (Pn0□□ to Pn8□□). Therefore, the values are converted between them as shown in the example below so that the device can operate at the accuracy defined with the device parameters.

Example Changing the position loop gain

Common Parameter		Σ-7 Device Parameter
No. 63 = 40.000		Pn102 = 40.00
Changed ↓		
No. 63 = <u>50.005</u>	→ Converted →	Pn102 = 50.00
		Changed ↓
No. 63 = 60.010	← Converted ←	Pn102 = <u>60.01</u>

8.2 List of Common Parameters

The following table lists the common MECHATROLINK-III parameters. These common parameters are used to make settings from the host controller via MECHATROLINK communications. Do not change the settings with the Digital Operator or any other device.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
01 PnA02	4	Encoder Type Selection (read only)	0 to 1	–	–	All	–	Device information
	0000 hex: Absolute encoder 0001 hex: Incremental encoder							
02 PnA04	4	Motor Type Selection (read only)	0 to 1	–	–	All	–	
	0000 hex: Rotary Servomotor 0001 hex: Linear Servomotor							
03 PnA06	4	Semi-closed/Fully-closed Selection (read only)	0 to 1	–	–	All	–	
	0000 hex: Semi-closed 0001 hex: Fully-closed							
04 PnA08	4	Rated Motor Speed (read only)	0 to FFFFFFFF	1 min^{-1}	–	All	–	
05 PnA0A	4	Maximum Output Speed (read only)	0 to FFFFFFFF	1 min^{-1}	–	All	–	
06 PnA0C	4	Speed Multiplier (read only)	-1,073,741,823 to 1,073,741,823	–	–	All	–	
07 PnA0E	4	Rated Torque (read only)	0 to FFFFFFFF	1 N·m	–	All	–	
08 PnA10	4	Maximum Output Torque (read only)	0 to FFFFFFFF	1 N·m	–	All	–	
09 PnA12	4	Torque Multiplier (read only)	-1,073,741,823 to 1,073,741,823	–	–	All	–	
0A PnA14	4	Resolution (read only)	0 to FFFFFFFF	1 pulse/rev	–	Rotary	–	
0B PnA16	4	Scale Pitch	0 to 65,536,000	1 nm [0.01 μm]	0	Linear	After restart*1	
0C PnA18	4	Pulses per Scale Pitch (read only)	0 to FFFFFFFF	1 pulse/ pitch	–	Linear	–	

Continued on next page.

Continued from previous page.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
21 PnA42	4	Electronic Gear Ratio (Numerator)	1 to 1,073,741,824	–	16	All	After restart	Machine specifications
22 PnA44	4	Electronic Gear Ratio (Denominator)	1 to 1,073,741,824	–	1	All	After restart	
23 PnA46	4	Absolute Encoder Origin Offset	-1,073,741,823 to 1,073,741,823	1 reference unit	0	All	Immediately[*1]	
24 PnA48	4	Multiturn Limit Setting	0 to 65,535	1 Rev	65535	Rotary	After restart	
25 PnA4A	4	Limit Setting	0 to 33 hex	–	0000 hex	All	After restart	
	Bit 0	P-OT (0: Enabled, 1: Disabled)						
	Bit 1	N-OT (0: Enabled, 1: Disabled)						
	Bit 2	Reserved.						
	Bit 3	Reserved.						
	Bit 4	P-SOT (0: Disabled, 1: Enabled)						
	Bit 5	N-SOT (0: Disabled, 1: Enabled)						
	Bits 6 to 31	Reserved.						
26 PnA4C	4	Forward Software Limit	-1,073,741,823 to 1,073,741,823	1 reference unit	1073741823	All	Immediately	
27 PnA4E	4	Reserved parameter (Do not use.)	–	–	0	All	Immediately	
28 PnA50	4	Reverse Software Limit	-1,073,741,823 to 1,073,741,823	1 reference unit	-1073741823	All	Immediately	
29 PnA52	4	Reserved parameter (Do not use.)	–	–	0	All	Immediately	
41 PnA82	4	Speed Unit Selection[*2]	0 to 4	–	0	All	After restart	Unit settings
	0000 hex	Reference units/s						
	0001 hex	Reference units/min						
	0002 hex	Percentage (%) of rated speed[*3]						
	0003 hex	min^{-1}[*3]						
	0004 hex	Maximum motor speed/40000000 hex[*4]						
42 PnA84	4	Speed Base Unit Selection[*3, *4] (Set the value of n from the following formula: Speed unit selection (41 PnA82) × 10^n)	-3 to 3	–	0	All	After restart	
43 PnA86	4	Position Unit Selection	0	–	0	All	After restart	
	0000 hex	Reference units						

Continued on next page.

Continued from previous page.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
44 PnA88	4	Position Base Unit Selection (Set the value of n from the following formula: Position unit selection (43 PnA86) × 10^n)	0	–	0	All	After restart	Unit settings
45 PnA8A	4	Acceleration Unit Selection	0	–	0	All	After restart	
	0000 hex: Reference units/s^2							
46 PnA8C	4	Acceleration Base Unit Selection (Set the value of n from the following formula: Acceleration unit selection (45 PnA8A) × 10^n)	4 to 6	–	4	All	After restart	
47 PnA8E	4	Torque Unit Selection	1 to 2	–	1	All	After restart	
	0001 hex: Percentage (%) of rated torque 0002 hex: Maximum torque/40000000 hex[*5]							
48 PnA90	4	Torque Base Unit Selection[*5] (Set the value of n from the following formula: Torque unit selection (47 PnA8E) × 10^n)	-5 to 0	–	0	All	After restart	
49 PnA92	4	Supported Unit Systems (read only)	–	–	0601011F hex	All	–	

Speed Units	
Bit 0	Reference units/s (1: Enabled)
Bit 1	Reference units/min (1: Enabled)
Bit 2	Percentage (%) of rated speed (1: Enabled)
Bit 3	min^{-1} (rpm) (1: Enabled)
Bit 4	Maximum motor speed/4000000 hex (1: Enabled)
Bits 5 to 7	Reserved (0: Disabled).
Position Units	
Bit 8	Reference units (1: Enabled)
Bits 9 to 15	Reserved (0: Disabled).
Acceleration Units	
Bit 16	Reference units/s^2 (1: Enabled)
Bit 17	ms (acceleration time required to reach rated speed) (0: Disabled)
Bits 18 to 23	Reserved (0: Disabled).
Torque Units	
Bit 24	N·m (0: Disabled)
Bit 25	Percentage (%) of rated torque (1: Enabled)
Bit 26	Maximum torque/40000000 hex
Bits 27 to 31	Reserved (0: Disabled).

Continued on next page.

Continued from previous page.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
61 PnAC2	4	Speed Loop Gain	1,000 to 2,000,000	0.001 Hz [0.1 Hz]	40000	All	Immediately	Tuning
62 PnAC4	4	Speed Loop Integral Time Constant	150 to 512,000	1 µs [0.01 ms]	20000	All	Immediately	
63 PnAC6	4	Position Loop Gain	1,000 to 2,000,000	0.001/s [0.1/s]	40000	All	Immediately	
64 PnAC8	4	Feedforward Compensation	0 to 100	1%	0	All	Immediately	
65 PnACA	4	Position Loop Integral Time Constant	0 to 5,000,000	1 µs [0.1 ms]	0	All	Immediately	
66 PnACC	4	Positioning Completed Width	0 to 1,073,741,824	1 reference unit	7	All	Immediately	
67 PnACE	4	Near Signal Width	1 to 1,073,741,824	1 reference unit	1073741824	All	Immediately	
81 PnB02	4	Exponential Acceleration/Deceleration Time Constant	0 to 510,000	1 µs [0.1 ms]	0	All	Immediately*6	
82 PnB04	4	Average Movement Time	0 to 510,000	1 µs [0.1 ms]	0	All	Immediately*6	
83 PnB06	4	External Positioning Final Travel Distance	-1,073,741,823 to 1,073,741,823	1 reference unit	100	All	Immediately	
84 PnB08	4	Origin Approach Speed	0 to 3FFFFFFF hex	10^{-3} min^{-1}	5,000 reference units/s converted to 10^{-3} min^{-1}	All	Immediately	
85 PnB0A	4	Origin Return Creep Speed	0 to 3FFFFFFF hex	10^{-3} min^{-1}	500 reference units/s converted to 10^{-3} min^{-1}	All	Immediately	
86 PnB0C	4	Final Travel Distance for Origin Return	-1,073,741,823 to 1,073,741,823	1 reference unit	100	All	Immediately	
87 PnB0E	4	Fixed Monitor Selection 1	0 to F	–	1	All	Immediately	

0000 hex	APOS
0001 hex	CPOS
0002 hex	PERR
0003 hex	LPOS1
0004 hex	LPOS2
0005 hex	FSPD
0006 hex	CSPD
0007 hex	TRQ
0008 hex	ALARM
0009 hex	MPOS
000A hex	Reserved (undefined value).
000B hex	Reserved (undefined value).
000C hex	CMN1 (common monitor 1)
000D hex	CMN2 (common monitor 2)
000E hex	OMN1 (optional monitor 1)
000F hex	OMN2 (optional monitor 2)

Continued on next page.

Continued from previous page.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
88 PnB10	4	Fixed Monitor Selection 2	0 to F	–	0	All	Immediately	Command-related parameters

0000 to 000F hex	The settings are the same as those for Fixed Monitor Selection 1.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
89 PnB12	4	SEL_MON (CMN1) Monitor Selection 1	0 to 9	–	0	All	Immediately	Command-related parameters

0000 hex	TPOS (target position in reference coordinate system)
0001 hex	IPOS (reference position in reference coordinate system)
0002 hex	POS_OFFSET (offset set in POS_SET (Set Coordinate System) command)
0003 hex	TSPD (target speed)
0004 hex	SPD_LIM (speed limit)
0005 hex	TRQ_LIM (torque limit)
0006 hex	SV_STAT Monitor Description Byte 1: Current communications phase 00 hex: Phase 0 01 hex: Phase 1 02 hex: Phase 2 03 hex: Phase 3 Byte 2: Current control mode 00 hex: Position control mode 01 hex: Speed control mode 02 hex: Torque control mode Byte 3: Reserved Byte 4: Expansion signal monitor

Bit	Name	Description	Value	Setting
Bit 0	LT_RDY1	Latch detection processing status specified by LT_REQ1 in SVCMD_CTRL	0	Latch detection not yet processed.
			1	Processing latch detection in progress.
Bit 1	LT_RDY1	Latch detection processing status specified by LT_REQ2 in SVCMD_CTRL	0	Latch detection not yet processed.
			1	Processing latch detection in progress.
Bits 2 and 3	LT_SEL1R	Latch signal	0	Phase C
			1	External input signal 1
			2	External input signal 2
			3	External input signal 3
Bits 4 and 5	LT_SEL2R	Latch signal	0	Phase C
			1	External input signal 1
			2	External input signal 2
			3	External input signal 3
Bit 6	Reserved (0).			

0007 hex	Reserved.	
0008 hex	INIT_PGPOS (Low)	Lower 32 bits of initial encoder position converted to 64-bit position reference data
0009 hex	INIT_PGPOS (High)	Upper 32 bits of initial encoder position converted to 64-bit position reference data

Continued on next page.

Continued from previous page.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
8A PnB14	4	SEL_MON (CMN2) Monitor Selection 2	0 to 9	–	0	All	Immediately	Command-related parameters
		0000 to 0009 hex: The settings are the same as those for SEL_MON Monitor Selection 1.						
8B PnB16	4	Origin Detection Width	0 to 250	1 reference unit	10	All	Immediately	
8C PnB18	4	Forward Torque Limit	0 to 800	1%	100	All	Immediately	
8D PnB1A	4	Reverse Torque Limit	0 to 800	1%	100	All	Immediately	
8E PnB1C	4	Zero Speed Detection Range	1,000 to 10,000,000	10^{-3} min^{-1}	20000	All	Immediately	
8F PnB1E	4	Speed Coincidence Signal Detection Width	0 to 100,000	10^{-3} min^{-1}	10000	All	Immediately	
90 PnB20	4	Servo Command Control Field Enable/ Disable Selections (read only)	–	–	0FFF3F3F hex	All	–	
		Bit 0: CMD_PAUSE (1: Enabled) Bit 1: CMD_CANCEL (1: Enabled) Bits 2 and 3: STOP_MODE (1: Enabled) Bits 4 and 5: ACCFIL (1: Enabled) Bits 6 and 7: Reserved (0: Disabled). Bit 8: LT_REQ1 (1: Enabled) Bit 9: LT_REQ2 (1: Enabled) Bits 10 and 11: LT_SEL1 (1: Enabled) Bits 12 and 13: LT_SEL2 (1: Enabled) Bits 14 and 15: Reserved (0: Disabled). Bits 16 to 19: SEL_MON1 (1: Enabled) Bits 20 to 23: SEL_MON2 (1: Enabled) Bits 24 to 27: SEL_MON3 (1: Enabled) Bits 28 to 31: Reserved (0: Disabled).						

Continued on next page.

Continued from previous page.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
91 PnB22	4	Servo Status Field Enable/Disable Selections (read only)	–	0	0FFF3F33 hex	All	–	Command-related parameters

Bit 0	CMD_PAUSE_CMP (1: Enabled)
Bit 1	CMD_CANCEL_CMP (1: Enabled)
Bit 2 and 3	Reserved (0: Disabled).
Bits 4 and 5	ACCFIL (1: Enabled)
Bits 6 and 7	Reserved (0: Disabled).
Bit 8	L_CMP1 (1: Enabled)
Bit 9	L_CMP2 (1: Enabled)
Bit 10	POS_RDY (1: Enabled)
Bit 11	PON (1: Enabled)
Bit 12	M_RDY (1: Enabled)
Bit 13	SV_ON (1: Enabled)
Bits 14 and 15	Reserved (0: Disabled).
Bits 16 to 19	SEL_MON1 (1: Enabled)
Bits 20 to 23	SEL_MON2 (1: Enabled)
Bits 24 to 27	SEL_MON3 (1: Enabled)
Bits 28 to 31	Reserved (0: Disabled).

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
92 PnB24	4	Output Bit Enable/ Disable Selections (read only)	–	–	007F01F0 hex	All	–	Command-related parameters

Bits 0 to 3	Reserved (0: Disabled).
Bit 4	V_PPI (1: Enabled)
Bit 5	P_PPI (1: Enabled)
Bit 6	P_CL (1: Enabled)
Bit 7	N_CL (1: Enabled)
Bit 8	G_SEL (1: Enabled)
Bits 9 to 11	G_SEL (0: Disabled)
Bits 12 to 15	Reserved (0: Disabled).
Bits 16 to 19	BANK_SEL (1: Enabled)
Bits 20 to 22	SO1 to SO3 (1: Enabled)
Bit 23	Reserved (0: Disabled).
Bits 24 to 31	Reserved (0: Disabled).

Continued on next page.

Continued from previous page.

Parameter No.	Size	Name	Setting Range	Setting Unit [Resolution]	Default Setting	Applicable Motors	When Enabled	Classification
93 PnB26	4	Input Bit Enable/Disable Selections (read only)	–	–	FF0FFEFE hex	All	–	Command-related parameters

Bit 0	Reserved (0: Disabled).
Bit 1	DEC (1: Enabled)
Bit 2	P-OT (1: Enabled)
Bit 3	N-OT (1: Enabled)
Bit 4	EXT1 (1: Enabled)
Bit 5	EXT2 (1: Enabled)
Bit 6	EXT3 (1: Enabled)
Bit 7	ESTP (1: Enabled)
Bit 8	Reserved (0: Disabled).
Bit 9	BRK_ON (1: Enabled)
Bit 10	P-SOT (1: Enabled)
Bit 11	N-SOT (1: Enabled)
Bit 12	DEN (1: Enabled)
Bit 13	NEAR (1: Enabled)
Bit 14	PSET (1: Enabled)
Bit 15	ZPOINT (1: Enabled)
Bit 16	T_LIM (1: Enabled)
Bit 17	V_LIM (1: Enabled)
Bit 18	V_CMP (1: Enabled)
Bit 19	ZSPD (1: Enabled)
Bits 20 to 23	Reserved (0: Disabled).
Bits 24 to 31	I0_STS1 to I0_STS8 (1: Enabled)

*1. The parameter setting is enabled after the SENS_ON command is received.

*2. When using fully-closed loop control, set the reference units/s.

*3. If you set the Speed Unit Selection (parameter 41) to either 0002 hex or 0003 hex, set the Speed Base Unit Selection (parameter 42) to a number between -3 and 0.

*4. If you set the Speed Unit Selection (parameter 41) to 0004 hex, set the Speed Base Unit Selection (parameter 42) to 0.

*5. If you set the Torque Unit Selection (parameter 47) to 0002 hex, set the Torque Base Unit Selection (parameter 48) to 0.

*6. Change the setting when the reference is stopped (i.e., while DEN is set to 1). If you change the setting during operation, the reference output will be affected.

8.3 Common Parameters and Corresponding Device Parameters

Category	Common Parameters	Meaning	Corresponding Device Parameter	Remark
Device Information Related Parameters	1	Encoder Type	–	–
	2	Motor Type	–	–
	3	Semi-Closed/Fully-Closed Type	–	–
	4	Rated Speed	–	–
	5	Maximum Output Speed	–	–
	6	Speed Multiplier	–	–
	7	Rated Torque	–	–
	8	Maximum Output Torque	–	–
	9	Torque Multiplier	–	–
	0A	Resolution (Rotary)	–	–
	0B	Scale Pitch (Linear)	–	–
	0C	Pulses per Scale Pitch (Linear)	–	–
Machine Specification Related Parameters	21	Electronic Gear Ratio (Numerator)	Pn20E	–
	22	Electronic Gear Ratio (Denominator)	Pn210	–
	23	Absolute Encoder Origin Offset	Pn808	–
	24	Multiturn Limit Setting	Pn205	–
	25	Limit Setting	Pn50A Pn50B Pn801	–
	26	Forward Software Limit	Pn804	–
	27	Reserved by System	–	–
	28	Reverse Software Limit	Pn806	–
	29	Reserved by System	–	–
Unit System Related Parameters	41	Speed Unit	–	–
	42	Speed Base Unit	–	–
	43	Position Unit	–	–
	44	Position Base Unit	–	–
	45	Acceleration Unit	–	–
	46	Acceleration Base Unit	–	–
	47	Torque Unit	–	–
	48	Torque Base Unit	–	–
Adjustment Related Parameters	61	Speed Loop Gain	Pn100	–
	62	Speed Loop Integral Time Constant	Pn101	–
	63	Position Loop Gain	Pn102	–
	64	Feedforward Compensation	Pn109	–
	65	Position Loop Integral Time Constant	Pn11F	–
	66	Positioning Completed Width	Pn522	–
	67	Near Signal Width	Pn524	–

Continued on next page.

Continued from previous page.

Category	Common Parameters	Meaning	Corresponding Device Parameter	Remark
Command Related Parameters	81	Exponential Acceleration/Deceleration Time Constant	Pn811	–
	82	Movement Average Time	Pn812	–
	83	External Positioning Final Travel Distance	Pn814	EX_POSING, EX_FEED
	84*1	Origin Approach Speed	Pn817, Pn842	ZRET
	85*2	Origin Approach Speed	Pn818, Pn844	ZRET
	86	Final Travel Distance for Origin Return	Pn819	ZRET
	87	Monitor Selection 1	–	–
	88	Monitor Selection 2	–	–
	89	Monitor Select for SEL_MON1	–	–
	8A	Monitor Select for SEL_MON2	–	–
	8B	Origin Detection Range	Pn803	–
	8C	Forward Torque Limit	Pn404	–
	8D	Reverse Torque Limit	Pn405	–
	8E	Zero Speed Detection Range	Rotational servomotor: Pn502, Linear servomotor:Pn581	–
	8F	Speed Coincidence Signal Detection Width	Rotational servomotor: Pn503, Linear servomotor:Pn582	–
	90	Servo Command Control Field Enabled/Disabled	–	–
	91	Servo Command Status Field Enabled/Disabled	–	–
	92	I/O Bit Enabled/Disabled (Output)	–	–
	93	I/O Bit Enabled/Disabled (Input)	–	–

*1. The common parameter 84 is linked with Pn817 or Pn824. At factory setting, the value of Pn817 is effective. When Pn817 is set to zero or a value outside the allowable range, the value of Pn824 will become effective. After the value of Pn824 become effective, the value stays effective even if the value of Pn817 within the allowable range is set to parameter 84.

*2. The common parameter 85 is linked with Pn818 or Pn844. At factory setting, the value of Pn818 is effective. When Pn818 is set to zero or a value outside the allowable range, the value of Pn844 will become effective. After the value of Pn844 become effective, the value stays effective even if the value of Pn818 within the allowable range is set to parameter 85.

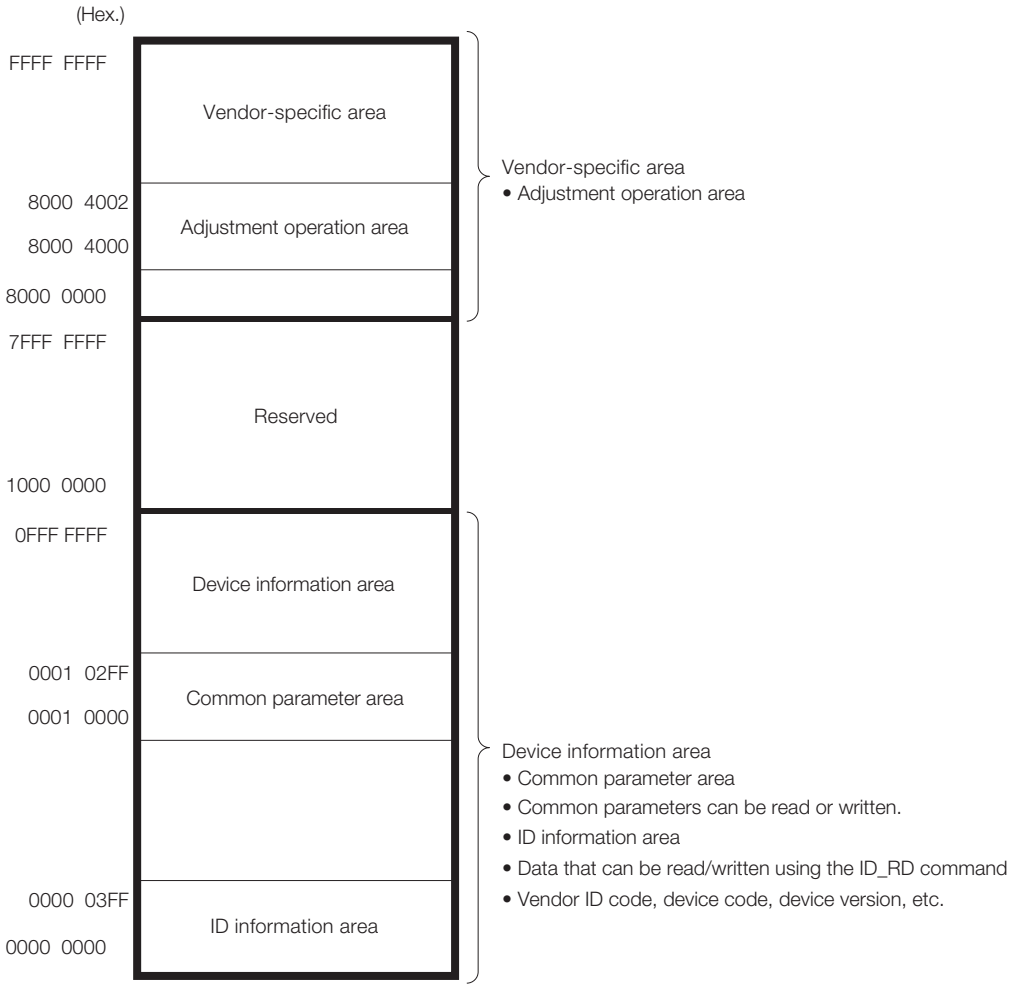
Virtual Memory Space

9

9.1 Virtual Memory Space

The virtual memory space is the memory area that can be accessed by using the read memory command (MEM_RD: 1D hex) and write memory command (MEM_WR: 1E hex).

By adopting the concept of virtual memory, the memory areas that vary among devices and vendors can be accessed at common addresses.



9.2 Information Allocated to Virtual Memory

The ID information, common parameter and adjustment operation areas are allocated to virtual memory.

9.2.1 ID Information Area

When accessing virtual memory using the MEM_RD or MEM_WR command, use virtual memory addresses. The address map is given below.

For details, use the ID_CODE from the following table and refer to the following section.

☞ *3.1.2 Read ID Command (ID_RD: 03 Hex)* on page 3-4

Data in this area can also be read by using the ID_RD command.

(Hex.)		ID_CODE
0000 00DF	List of Supported Main Commands	30 hex
0000 00C0		
0000 00BF	Reserved	–
0000 008C		
0000 0084	MAC Address	–
0000 0080	Supported Communication Mode	20 hex
	Reserved (00000000HEX)	
	Reserved (00000000HEX)	
	Profile Type (Current Value)	1D hex
0000 0070	Number of Transmission Bytes (Current Value)	1C hex
0000 006C	Number of Transmission Bytes	1B hex
0000 0068	Maximum Value of Communication Cycle	1A hex
0000 0064	Minimum Value of Communication Cycle	19 hex
0000 0060	Granularity of Transmission Cycle	18 hex
0000 005C	Maximum Value of Transmission Cycle	17 hex
0000 0058	Minimum Value of Transmission Cycle	16 hex
0000 0054	Profile Version 3	15 hex
0000 0050	Profile Type 3	14 hex
0000 004C	Profile Version 2	13 hex
0000 0048	Profile Type 2	12 hex
0000 0044	Profile Version 1	11 hex
0000 0040	Profile Type 1	10 hex
0000 003C	Reserved (00000000HEX)	
0000 0038	Reserved (00000000HEX)	
0000 0034	Serial No.	06 hex
0000 0018		
0000 0014	Supported Extended Address	05 hex
0000 0010	Device Definition File Version	04 hex
0000 000C	Device Version	03 hex
0000 0008	Device Code	02 hex
0000 0004	Vendor ID Code	01 hex
0000 0000	Reserved (00000000HEX)	

(Hex.)		ID_CODE
0000 02BF	Reserved	
0000 02A0	Sub Device 2 Version	A8 hex
0000 029F	Sub Device 2 Name	A0 hex
0000 0280		
0000 027F	Reserved	
0000 0260	Sub Device 1 Version	98 hex
0000 025F	Sub Device 1 Name	90 hex
0000 0240		
0000 023F	Reserved	
0000 0220		
0000 021F	Main Device Name	80 hex
0000 0200		
0000 01FF	Reserved	
0000 0120		
0000 011F	List of Supported Common Parameters	40 hex
0000 0100		
0000 00FF	List of Supported Subcommands	38 hex
0000 00E0		

(Hex.)		ID_CODE
0000 3FFF	Reserved	
0000 03A0	Sub Device 6 Version	E8 hex
0000 039F	Sub Device 6 Name	E0 hex
0000 0380		
	Reserved	
0000 0360	Sub Device 5 Version	D8 hex
0000 035F	Sub Device 5 Name	D0 hex
0000 0340		
	Reserved	
0000 0320	Sub Device 4 Version	C8 hex
0000 031F	Sub Device 4 Name	C0 hex
0000 0300		
0000 02FF	Reserved	
0000 02E0	Sub Device 3 Version	B8 hex
0000 02DF	Sub Device 3 Name	B0 hex
0000 02C0		

9.2.2 Common Parameter Area

When accessing virtual memory using the MEM_RD or MEM_WR command, use virtual memory addresses. The address map is given below.

Data in this area can also be read using the SVPRM_RD or SVPRM_WR command.

For details, use the common parameter number from the following table and refer to the following section.

☞ *8.2 List of Common Parameters* on page 8-3

(Hex.)		Common Parameter No.
0001 0124	Supported Unit	49 hex
0001 0120	Torque Base Unit	48 hex
0001 011C	Torque Unit	47 hex
0001 0118	Acceleration Base Unit	46 hex
0001 0114	Acceleration Unit	45 hex
0001 0110	Position Base Unit	44 hex
0001 010C	Position Unit	43 hex
0001 0108	Speed Base Unit	42 hex
0001 0104	Speed Unit	41 hex
0001 0100	Reserved (00000000 hex)	–
0001 00FC 0001 00A4	Reserved (00000000 hex)	–
0001 00A0	Reverse Software Limit	28 hex
0001 009C	Reserved (00000000 hex)	–
0001 0098	Forward Software Limit	26 hex
0001 0094	Limit Setting	25 hex
0001 0090	Multiturn Limit	24 hex
0001 008C	Absolute Encoder Origin Offset	23 hex
0001 0088	Electronic Gear Ratio (Denominator)	22 hex
0001 0084	Electronic Gear Ratio (Numerator)	21 hex
0001 0080 0001 0034	Reserved (00000000 hex)	–
0001 0030	Pulses per Scale Pitch	0C hex
0001 002C	Linear Scale Pitch	0B hex
0001 0028	Resolution (Rotary)	0A hex
0001 0024	Torque Multiplier	09 hex
0001 0020	Maximum Output Torque	08 hex
0001 001C	Rated Torque	07 hex
0001 0018	Speed Multiplier	06 hex
0001 0014	Maximum Output Speed	05 hex
0001 0010	Rated Speed	04 hex
0001 000C	Semi-Closed/Fully-Closed Type	03 hex
0001 0008	Motor Type	02 hex
0001 0004	Encoder Type	01 hex
0001 0000	Reserved (00000000 hex)	–

(Hex.)		Common Parameter No.
0001 FFFF 0001 0250	Reserved (00000000 hex)	–
0001 024C	I/O Bit Enabled/Disabled	93 hex
0001 0248	I/O Bit Enabled/Disabled	92 hex
0001 0244	SVCMD_STAT field Enabled/Disabled	91 hex
0001 0240	SVCMD_CTRL field Enabled/Disabled	90 hex
0001 023C	Speed Coincidence Signal Output Width	8F hex
0001 0238	Zero Speed Detection Range	8E hex
0001 0234	Reverse Torque Limit	8D hex
0001 0230	Forward Torque Limit	8C hex
0001 022C	Origin Detection Range	8B hex
0001 0228	Monitor Select for SEL_MON2	8A hex
0001 0224	Monitor Select for SEL_MON1	89 hex
0001 0220	Monitor Selection 2	88 hex
0001 021C	Monitor Selection 1	87 hex
0001 0218	Final Travel Distance for Homing	86 hex
0001 0214	Homing Creep Speed	85 hex
0001 0210	Homing Approach Speed	84 hex
0001 020C	Final Travel Distance for External Positioning	83 hex
0001 0208	Movement Average Time	82 hex
0001 0204	Exponential Function Acceleration/Deceleration Time Constant	81 hex
0001 0200	Reserved (00000000 hex)	–
0001 01FC 0001 01A0	Reserved (00000000 hex)	–
0001 019C	NEAR Signal Width	67 hex
0001 0198	Positioning Completed Width	66 hex
0001 0194	Position Loop Integral Time Constant	65 hex
0001 0190	Feedforward Compensation	64 hex
0001 018C	Position Loop Gain	63 hex
0001 0188	Speed Loop Integral Time Constant	62 hex
0001 0184	Speed Loop Gain	61 hex
0001 0180 0001 0128	Reserved (00000000 hex)	–

9.2.3 Adjustment Operation Area

Use the MEM_RD or MEM_WR command to access this area. The address map is given below.

Refer to the following section for the command communications procedure for adjustment operations.

☞ *3.1.10 Write Memory Command (MEM_WR: 1E Hex)* on page 3-21.

Address	Description		Data Size (Byte)	Data Type
8000 4000 hex	Name	Command code	2	Binary Data
	Description	The area where the command codes specifying adjustment operations are written		
8000 4002 hex	Name	Start command	2	Binary Data
	Description	The area where commands for preparing or starting adjustment operations are written		

Revision History

The revision dates and numbers of the revised manuals are given on the bottom of the back cover.

MANUAL NO. SIEP S800001 31A

Published in Japan February 2015 14-4 ◇1

- ◇1: Revision Number
- February 2015: Date of publication
- 14-4: Date of original publication

Date of Publication	Rev. No.	Section	Revised Contents
February 2015	◇1	All chapters	Complete review.
		Back cover	Revision: Address
April 2014	–	–	First edition

Σ-7-Series AC Servo Drive

MECHATROLINK-III Communications Standard Servo Profile Command Manual

IRUMA BUSINESS CENTER (SOLUTION CENTER)
480, Kamifujisawa, Iruma, Saitama, 358-8555, Japan
Phone 81-4-2962-5151 Fax 81-4-2962-6138
http://www.yaskawa.co.jp

YASKAWA AMERICA, INC.
2121, Norman Drive South, Waukegan, IL 60085, U.S.A.
Phone 1-800-YASKAWA (927-5292) or 1-847-887-7000 Fax 1-847-887-7310
http://www.yaskawa.com

YASKAWA ELÉTRICO DO BRASIL LTDA.
777, Avenida Piraporinha, Diadema, São Paulo, 09950-000, Brasil
Phone 55-11-3585-1100 Fax 55-11-3585-1187
http://www.yaskawa.com.br

YASKAWA EUROPE GmbH
185, Hauptstraβe, Eschborn, 65760, Germany
Phone 49-6196-569-300 Fax 49-6196-569-398
http://www.yaskawa.eu.com

YASKAWA ELECTRIC KOREA CORPORATION
9F, Kyobo Securities Bldg. 26-4, Yeouido-dong, Yeongdeungpo-gu, Seoul, 150-737, Korea
Phone 82-2-784-7844 Fax 82-2-784-8495
http://www.yaskawa.co.kr

YASKAWA ELECTRIC (SINGAPORE) PTE. LTD.
151, Lorong Chuan, #04-02A, New Tech Park, 556741, Singapore
Phone 65-6282-3003 Fax 65-6289-3003
http://www.yaskawa.com.sg

YASKAWA ELECTRIC (THAILAND) CO., LTD.
252/125-126, 27th Floor, Muang Thai-Phatra Tower B, Rachadapisek Road, Huaykwang, Bangkok, 10310, Thailand
Phone 66-2693-2200 Fax 66-2693-4200
http://www.yaskawa.co.th

YASKAWA ELECTRIC (CHINA) CO., LTD.
22F, One Corporate Avenue, No.222, Hubin Road, Shanghai, 200021, China
Phone 86-21-5385-2200 Fax 86-21-5385-3299
http://www.yaskawa.com.cn

YASKAWA ELECTRIC (CHINA) CO., LTD. BEIJING OFFICE
Room 1011, Tower W3 Oriental Plaza, No.1, East Chang An Ave.,
Dong Cheng District, Beijing, 100738, China
Phone 86-10-8518-4086 Fax 86-10-8518-4082

YASKAWA ELECTRIC TAIWAN CORPORATION
9F, 16, Nanking E. Rd., Sec. 3, Taipei, 104, Taiwan
Phone 886-2-2502-5003 Fax 886-2-2505-1280

YASKAWA ELECTRIC CORPORATION

MANUAL NO. SIEP S800001 31B

Published in Japan February 2015 14-4 ①
14-9-10
Original instructions