Altivar 212

Variable speed drives for asynchronous motors

Programming Manual

09/2011



S1A53838

www.schneider-electric.com

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All pertinent state, regional, and local safety regulations must be observed when installing and using this product. For reasons of safety and to help ensure compliance with documented system data, only the manufacturer should perform repairs to components.

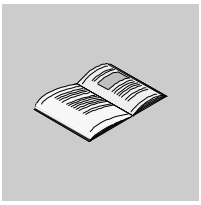
When devices are used for applications with technical safety requirements, the relevant instructions must be followed.

Failure to use Schneider Electric software or approved software with our hardware products may result in injury, harm, or improper operating results.

Failure to observe this information can result in injury or equipment damage.

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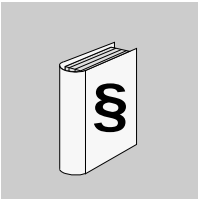
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Safety Information



Important Information

NOTICE

Please read these instructions carefully and examine the equipment in order to familiarize yourself with the device before installing, operating or carrying out any maintenance work on it.

The following special messages that you will come across in this document or on the device are designed to warn you about potential risks or draw your attention to information that will clarify or simplify a procedure.



The addition of this symbol to a Danger or Warning safety label indicates that an electrical hazard exists, which will result in personal injury if the instructions are not followed.



This is the safety alert symbol. It is used to alert you to potential personal injury hazards. Obey all safety messages that follow this symbol to avoid possible injury or death.

⚠ DANGER
DANGER indicates an imminently hazardous situation, which, if not avoided, **will result** in death or serious injury.

⚠ WARNING
WARNING indicates a potentially hazardous situation, which, if not avoided, **can result** in death, serious injury, or equipment damage.

⚠ CAUTION
CAUTION indicates a potentially hazardous situation, which, if not avoided, **can result** in injury or equipment damage.

CAUTION
CAUTION, used without the safety alert symbol, indicates a potentially hazardous situation which, if not avoided, **can result** in equipment damage.

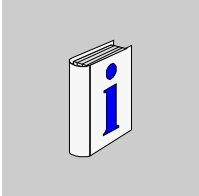
PLEASE NOTE

The word "drive" as used in this manual refers to the controller portion of the adjustable speed drive as defined by NEC.

Electrical equipment should be installed, operated, serviced, and maintained only by qualified personnel. No responsibility is assumed by Schneider Electric for any consequences arising out of the use of this product.

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About the Book



At a Glance

Document scope

The purpose of this document is to:

- help you to set-up the drive,
- show you how to program the drive,
- show you the different menus, modes and parameters,
- help you in maintenance and diagnostics.

Validity note

This documentation is valid for the Altivar 212 drive.

Related documents

Title of Documentation	Reference Number
ATV212 Quick Start	S1A53825
ATV212 Installation manual	S1A53832
ATV212 Modbus manual	S1A53844
ATV212 BACnet manual	S1A53845
ATV212 Metasys N2 manual	S1A53846
ATV212 Apogée FLN P1 manual	S1A53847
ATV212 LonWorks manual	S1A53848
Multiloader manual	BBV48778
SoMove Mobile manual	S1A51444
ATV212 other option manuals: see www.schneider-electric.com	

You can download the latest versions of these technical publications and other technical information from our website at www.schneider-electric.com.

Product related information

⚠⚠DANGER

HAZARD OF ELECTRIC SHOCK, EXPLOSION OR ARC FLASH

- Read and understand this manual before installing or operating the drive. Installation, adjustment, repair, and maintenance must be performed by qualified personnel.
- The user is responsible for compliance with all international and national electrical code requirements with respect to grounding of all equipment.
- Many parts of this drive, including the printed circuit boards, operate at the line voltage. DO NOT TOUCH. Use only electrically insulated tools.
- DO NOT touch unshielded components or terminal strip screw connections with voltage present.
- DO NOT short across terminals PA/+ and PC/– or across the DC bus capacitors.
- Before servicing the drive:
  - Disconnect all power, including external control power that may be present.
  - Place a “DO NOT TURN ON” label on all power disconnects.
  - Lock all power disconnects in the open position.
  - WAIT 15 MINUTES to allow the DC bus capacitors to discharge.
  - Measure the voltage of the DC bus between the PA/+ and PC/– terminals to ensure that the voltage is less than 42 Vdc.
  - If the DC bus capacitors do not discharge completely, contact your local Schneider Electric representative. Do not repair or operate the drive.
- Install and close all covers before applying power or starting and stopping the drive.

Failure to follow these instructions will result in death or serious injury.

⚠DANGER

UNINTENDED EQUIPMENT OPERATION

- Prevent accidental grounding of logic inputs configured for sink logic. Accidental grounding can result in unintended activation of drive functions.
- Protect the signal conductors against damage that could result in unintentional conductor grounding.

Failure to follow these instructions will result in death or serious injury.

⚠WARNING

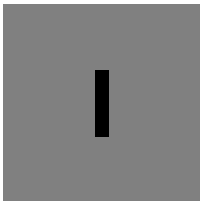
LOSS OF CONTROL

- The designer of any control scheme must consider the potential failure modes of control paths and, for certain critical control functions, provide a means to achieve a safe state during and after a path failure. Examples of critical control functions are emergency stop and overtravel stop.
- Separate or redundant control paths must be provided for critical control functions.
- System control paths may include communication links. Consideration must be given to the implications of unanticipated transmission delays or failures of the link (1).

Failure to follow these instructions can result in death, serious injury, or equipment damage.

(1) For additional information, refer to NEMA ICS 1.1 (latest edition), “Safety Guidelines for the Application, Installation, and Maintenance of Solid State Control” and to NEMA ICS 7.1 (latest edition), “Safety Standards for Construction and Guide for Selection, Installation and Operation of Adjustable-Speed Drive Systems.”

General Overview



What's in this Part?

This part contains the following chapters:

Chapter	Chapter Name	Page
1	Setup	13
2	Overview	15

Setup

1

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Steps for setting-up the drive	14

Steps for setting-up the drive

INSTALLATION

1. Please, refer to the installation manual..

PROGRAMMING



Tips:

- Before beginning programming, complete the customer setting tables, page 171.
- Perform an auto-tuning operation to optimize performance, page 71.
- If you get lost, return to the factory settings, page 62.

2. Apply input power to the drive, but do not give a run command.

3. Configure

- ☐ the nominal frequency of the motor [Parameter reset] (tYP) = [50 Hz reset] (50) if this is not 50Hz,
- ☐ the motor parameters, page 66, only if the factory configuration of the drive is not suitable,
- ☐ the application functions in the Drive Control Parameters section, page 77 and the I/O Control Parameters section, page 89, only if the factory configuration of the drive is not suitable.

4. Adjust the application parameters

- ☐ [Acceleration time 1] (ACC), page 83 and [Deceleration time 1] (dEC), page 83.
- ☐ [Low limit frequency] (LL), page 82 and [Upper limit freq] (UL), page 82.
- ☐ [Motor thermal prot.] (tHr), page 70.

5. Start the drive

Overview

2

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
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Factory configuration

Drive factory settings

The Altivar 212 is factory-set for the most common operating conditions:

- [Mot cont. mode sel.] (PtC): [Variable torque] (PtC = VT). See page 67.
- [Upper limit freq] (UL) = 50.0 Hz. See page 82.
- [Low limit frequency] (LL) = 0.0 Hz. See page 82.
- [Switch. freq. level] (F300): depending on drive rating (see page 85)
- [Auto ramp] (AU1) = [Enable] (AU1 = YES). See page 85.

Parameter which depends on Macro Programming [Auto set function] (AUt) = 0 (see page 63):

- Command reference: logic inputs ([Command mode sel] (CMd) = 0). See page 77.
- Speed reference: analog input VIA = 0–10 V or 0–20 mA ([Frequency mode sel] (FMd) = 1, (F201)= 0). See [Frequency mode sel] (FMd) page 77 and Analog Input Speed Reference page 106.
- F: run forward (F111= 2). See [LI F selection] page 90.
- R: preset speed 1 (F112= 6). See [LI R selection] page 90.
- RES: clear detected fault (F113= 10). See [LI RES selection] page 90.
- Drive ready for operation (F110= 1). See [Logic Funct 2 active] page 112.

If the above values are compatible with the application, the drive can be used without changing the settings.

Preliminary recommendations

CAUTION

INCOMPATIBLE LINE VOLTAGE
Before turning on and configuring the drive, ensure that the line voltage is compatible with the supply voltage range shown on the drive nameplate. The drive may be damaged if the line voltage is not compatible.
Failure to follow these instructions can result in equipment damage.

Power switching via line contactor

CAUTION

RISK OF DAMAGE TO THE DRIVE
- Avoid operating the contactor frequently.
- Power cycling must be MORE than 60 seconds.

Failure to follow these instructions can result in equipment damage.

User adjustment and extension of functions

- The display unit and buttons can be used to modify the settings and to extend the functions described in the following pages.
- **Return to factory settings** is made easy by the [Parameter reset] (tYP) (see page 62).

⚠ DANGER

UNINTENDED EQUIPMENT OPERATION
Check that changes made to the settings during operation do not present any danger.
We recommend stopping the drive before making any changes.
Failure to follow these instructions will result in death or serious injury.

Test on a low power motor or without a motor

- In factory settings mode, [Output phase loss] (OPL) (page 129) is active OPL = YES. To check the drive in a test or maintenance environment without having to switch to a motor with the same rating as the drive (particularly useful in the case of high power drives), set OPL to NO.
- Set [Mot cont. mode sel.] (Ctt) = [Constant V/Hz] (UF) (see page 67).

CAUTION

UNINTENDED EQUIPMENT OPERATION
Motor thermal protection will not be provided by the drive if the motor 's nominal current is 20% lower than that of the drive. Find an alternative source of thermal protection.
Failure to follow these instructions can result in equipment damage.

Using motors in parallel

- Set [Mot cont. mode sel.] (Ctt) = [Constant V/Hz] (UF) (see page 67).

CAUTION

RISK OF DAMAGE TO THE MOTOR
Motor thermal protection is no longer provided by the drive. Provide an alternative means of thermal protection.
Failure to follow these instructions can result in equipment damage.

Using in single phase supply

- Set [Input phase loss] (IPL) to Disabled (nO) (see page 127).

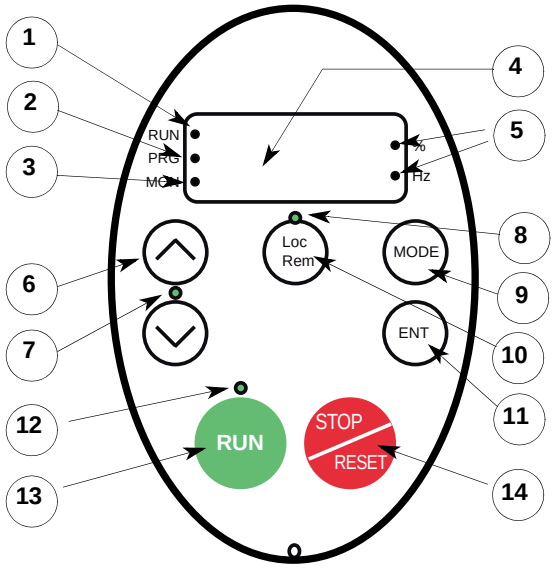
CAUTION

RISK OF DAMAGE TO THE DRIVE
Using ATV212 in single phase supply is only allowed in training mode with motor and without load.
Failure to follow these instructions can result in equipment damage.

Embedded display terminal

This section describes the features of the integrated display terminal.

Embedded display terminal features



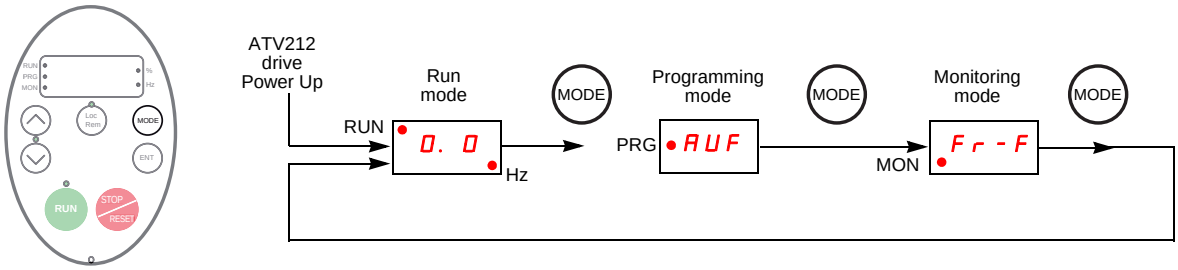
	LED/Key	Characteristics
1	Display RUN LED	Illuminates when a run command is applied to the drive. Flashes when there is a speed reference present with a Run command.
2	Display PRG LED	Illuminates when Programming mode is active. Flashes in AUF, CrU modes
3	Display MON LED	Illuminates when Monitoring mode is active. Flashes in detected fault history display mode
4	Display unit	4 digits, 7 segments
5	Display unit LED	The % LED illuminates when a displayed numeric value is a percentage. The Hz LED illuminates when a displayed numeric value is in hertz.
6	UP/DOWN keys	Depending on the mode, you can use the arrows to: Navigate between the menus Change a value Change the speed reference when the UP/DOWN LED (7) is illuminated
7	UP/DOWN LED	Illuminates when the navigation arrows are controlling the speed reference
8	Loc/Rem LED	Illuminates when Local mode is selected
9	MODE	Press to select the embedded display terminal mode. Run mode (default on power-up) Programming mode Monitoring mode Can also be used to go back to the previous menu.
10	Loc/Rem	Switches between Local and Remote modes
11	ENT	Press to display a parameter's value or to save a changed value.
12	RUN LED	Illuminates when the Run key is enabled
13	RUN	Pressing this key when the RUN LED is illuminated starts the drive.
14	STOP	Stop/reset key. In Local mode, pressing the STOP key causes the drive to stop based on the setting of parameter [Loc. mot stop mode] (F 12 1). In Remote mode, pressing the STOP key causes the drive to stop based on the setting of parameter [Ext. fault stop Mode] (F603). The display will indicate a flashing "E". If [HMI reset button] (F135) is set to 0, pressing the stop key twice will reset the drive, if the detected fault condition has been cleared.

An optional graphic display option (VW3A1101) is also available.

Embedded display terminal modes

The Altivar 212 embedded display terminal has three modes of operation: Monitoring, Run and Programming.

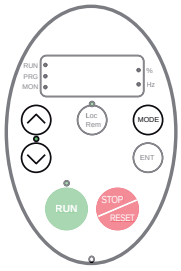
The drive powers up in the Run mode. To select a different mode, use the MODE key as illustrated below.

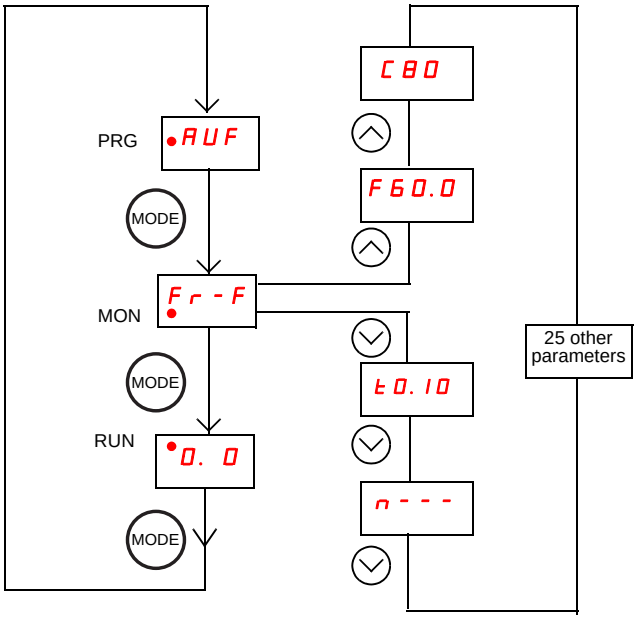


The red LED in left side of the display indicates the current mode selected, RUN for Run mode, PRG for Programming mode and MON for Monitoring mode.

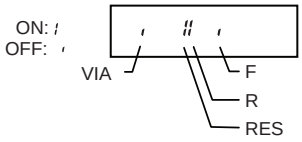
Monitoring Mode

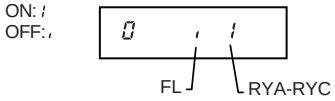
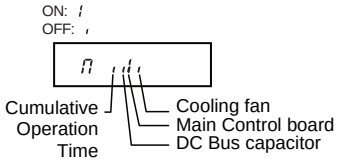
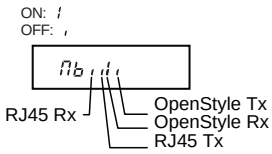
The Monitoring mode displays drive operational data in real time. To access the Monitoring mode, press the MODE key until the MON LED is illuminated. Then use the UP and DOWN keys to view up to 30 different types of data.





Monitoring Mode Displays

Display example	Display on graphic terminal	Description
Fr-F	[Direction]	Fr-F = [Forward] Fr-r = [Reverse]
F60.0	[Speed reference]	Command frequency to drive, displayed either as Hz or in custom unit set by parameter [Customized freq val] (F702)
C 80	[Motor current]	The average of the 3 phases of motor current displayed either as amperes or as a percentage of the drive's nameplate-rated output current. Select % or A with parameter [Unit value selection] (F701).
Y 100	[Line voltage]	The average of the 3 phases of line to line input voltages displayed either in volts or as a percentage of the drive's rated input voltage (200 V for 208/240 V models - 400 V for 480 V models). Select % or volts with parameter [Unit value selection] (F701).
P 100	[Motor voltage]	The average of the 3 phases of line to line output voltages displayed either in volts or as a percentage of the drive's rated output voltage (200 V for 208/240 V models - 400 V for 480 V models). Select % or volts with parameter [Unit value selection] (F701).
9 60	[Motor torque %]	Estimated motor torque as a percentage of the motor's rated torque
c 90	[Torque current]	The average of the 3 phases of torque-producing motor current displayed either as amperes or as a percentage of the motor's rated torque-producing current. Select % or A with parameter [Unit value selection] (F701).
L 70	[Drive load %]	The motor current as a percentage of the drive's rated output current, which may be reduced from the drive's nameplate current rating by adjustments in switching frequency.
h 80	[Input power KW]	drive input power displayed in accordance with parameter [Power cons. unit] (F749).
H 75	[Output power KW]	drive output power displayed in accordance with parameter [Power cons. unit] (F749).
o60.0	[Motor frequency]	Motor operating frequency, displayed either as Hz or in custom unit set by parameter [Customized freq val] (F702)
.. 11	[Logic input map]	 The bar representing VIA is displayed only if F109 = 1 or 2

Display example	Display on graphic terminal	Description
0. 1	[Relay map]	
u 101	[CPU CTRL ver.]	CTRL version 101
ucO1	[CPU MMI ver.]	MMI version 1.0
uE01	[Memory ver.]	Version of memory
d50. 0	[PID feedback]	Level of PID feedback, displayed either as Hz or in custom unit set by parameter [Customized freq val] (F 702)
b70. 0	[PID computed ref.] speed reference	Speed reference command to drive as computed by the PID function, displayed either as Hz or in custom unit set by parameter [Customized freq val] (F 702)
hBS	[Total input power]	Accumulated input power consumed by the drive displayed in kWh
H75	[Total motor power]	Accumulated output power supplied by the drive displayed in kWh
A 16. 5	[Drive out. rat. cur. A]	Drive nameplate rated output current in amperes
1500	[Motor speed rpm]	Motor speed in rpm
n50	[Comm. counter 2]	Displays the counter numbers of communication through the network
n50	[Comm. counter 1]	Displays the counter numbers of communication only at normal state in every communication through the network
nErr	[Past fault] Examples: - 1 blink Err5 - 2 blink Err5 - 3 blink CFI2 - 4 blink nErr	The most recent detected fault stored in the detected fault history. If the drive is in a detected fault state, this is not the active detected fault. A detected fault is stored in the detected fault history after it is cleared by clear detected fault action. Press ENT to review drive state at time of detected fault. See “Detected fault Display and History” on page 21 and “Diagnostics and troubleshooting” on page 149 for more detail. There are 4 detected faults recorded. The detected fault 4 is cleared when a new detected fault appears.
n. . . 1	[Drive service alarm]	
nbIIII	[Mdb com stat]	
t0. 10	[Drive run time 100h]	Cumulative drive run time. 0.01 = 1 hour. 1.00 = 100 hours

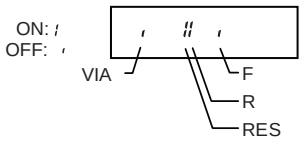
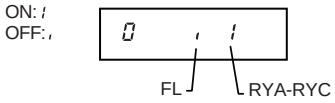
Detected fault display and history

When the drive detected faults, the graphic terminal displays a code. To review data about drive operation at the time of the detected fault, press the MODE key to enter the Monitoring mode. Then use the Up/Down keys to scroll through the data listed in table page 20.

Up to five detected faults can be displayed on the graphic terminal in Monitoring mode: the present detected fault (if the drive is in a detected fault state) and the previous four detected fault codes. To review drive operation data recorded at the time of detected fault for a previous detected fault, press ENT when the code for the detected fault is displayed. See table below for the available information.

When a detected fault is cleared or power is cycled to the drive, the present detected fault becomes Past detected fault 1.

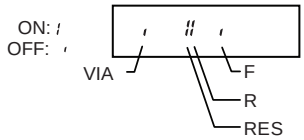
Detected fault History

Display	Display on graphic terminal	Description
n 2	[Comm. counter 1]	Number of times in succession that this particular detected fault has occurred
o60. 0	[Motor frequency]	Motor operating frequency, displayed either as Hz or in custom unit set by parameter [Customized freq val] (F 702)
Fr-F	[Direction]	Fr-F = [Forward] Fr-r = [Reverse]
F60. 0	[Speed reference]	Command frequency to drive, displayed either as Hz or in custom unit set by parameter [Customized freq val] (F 702)
C80	[Motor current]	The average of the 3 phases of motor current displayed either as A or as a percentage of the drive's nameplate-rated output current. Select % or A with parameter [Unit value selection] (F 701).
U100	[Line voltage]	The average of the 3 phases of line to line input voltages displayed either in volts or as a percentage of the drive's rated input voltage (200 V for 208/240 V models - 400 V for 480V models). Select % or volts with parameter [Unit value selection] (F 701).
P100	[Motor voltage]	The average of the 3 phases of line to line output voltages displayed either in volts or as a percentage of the drive's rated output voltage (200 V for 208/240 V models - 400 V for 480 V models). Select % or volts with parameter [Unit value selection] (F 701).
..11	[LOGIC INPUT MAP] Logic input map	 The bar representing VIA is displayed only if F109 = 1 or 2
0. 1	[Relay map]	
t0. 10	[Drive run time 100h]	Cumulative drive run time. 0.01 = 1 hour. 1.00 = 100 hours

I/O Map

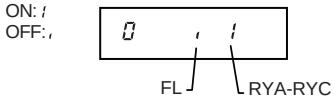
In both the monitoring mode and the detected fault history, it is possible to view the state of the logic inputs and the relay outputs. See previous tables on pages 20 and 21.

Logic Input Map



The ON or OFF status of each logic input is displayed in bits. VIA is included in this display if parameter F109 is set to either 1 or 2.

Relay Output Map



The ON or OFF status of each relay output is displayed in bits.

Run Mode

To access the Run mode, press the MODE key until the drive operating frequency, a detected fault code, or a pre-alarm code is displayed.

See Diagnostics and troubleshooting beginning on page 149 for the detected fault and pre-alarm codes.

Changing the Display in Run Mode

Motor operating frequency is the default value displayed on the graphic terminal in Run mode. This displayed value can be changed by setting parameter [Displayed param.] (F 7 10). See page 120 for a list of the display choices.

The displayed value can be expressed as a percentage of the drive rating, or in amperes or volts, as appropriate for the value displayed. The units can be changed by setting parameter [Unit value selection] (F 7D 1) (see page 120).

In addition, the resolution of the speed reference and output frequency displays can be adjusted by setting parameters [Loc. speed ref. step] (F 7D 7) and [Display ref. resol.] (F 7D8) (see pages 77 and 120).

Programming Mode

Use this mode to program the drive.

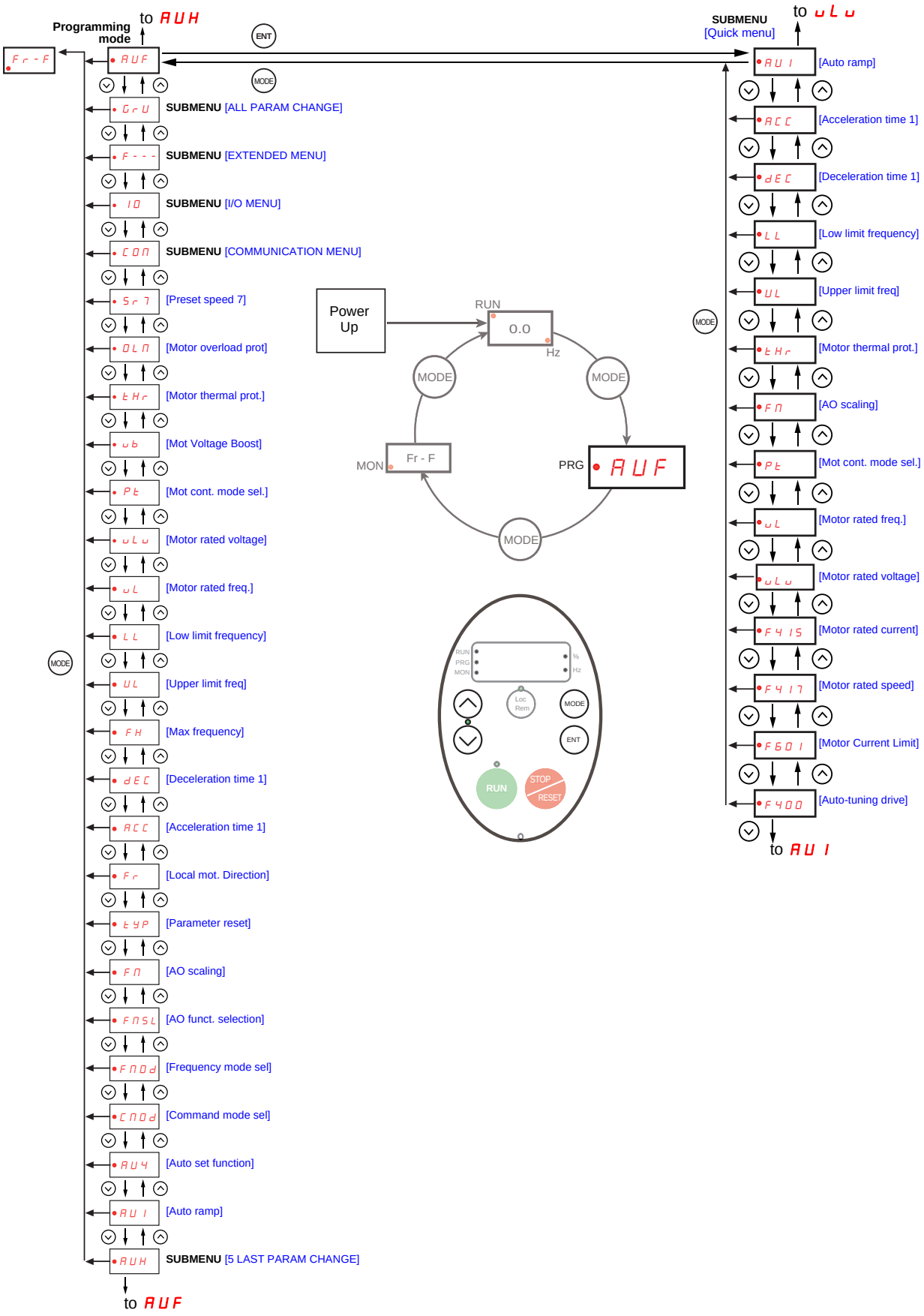
To access the Programming mode, use the MODE key until the PRG indicator LED on the display is illuminated.

See Menu Navigation page 24.

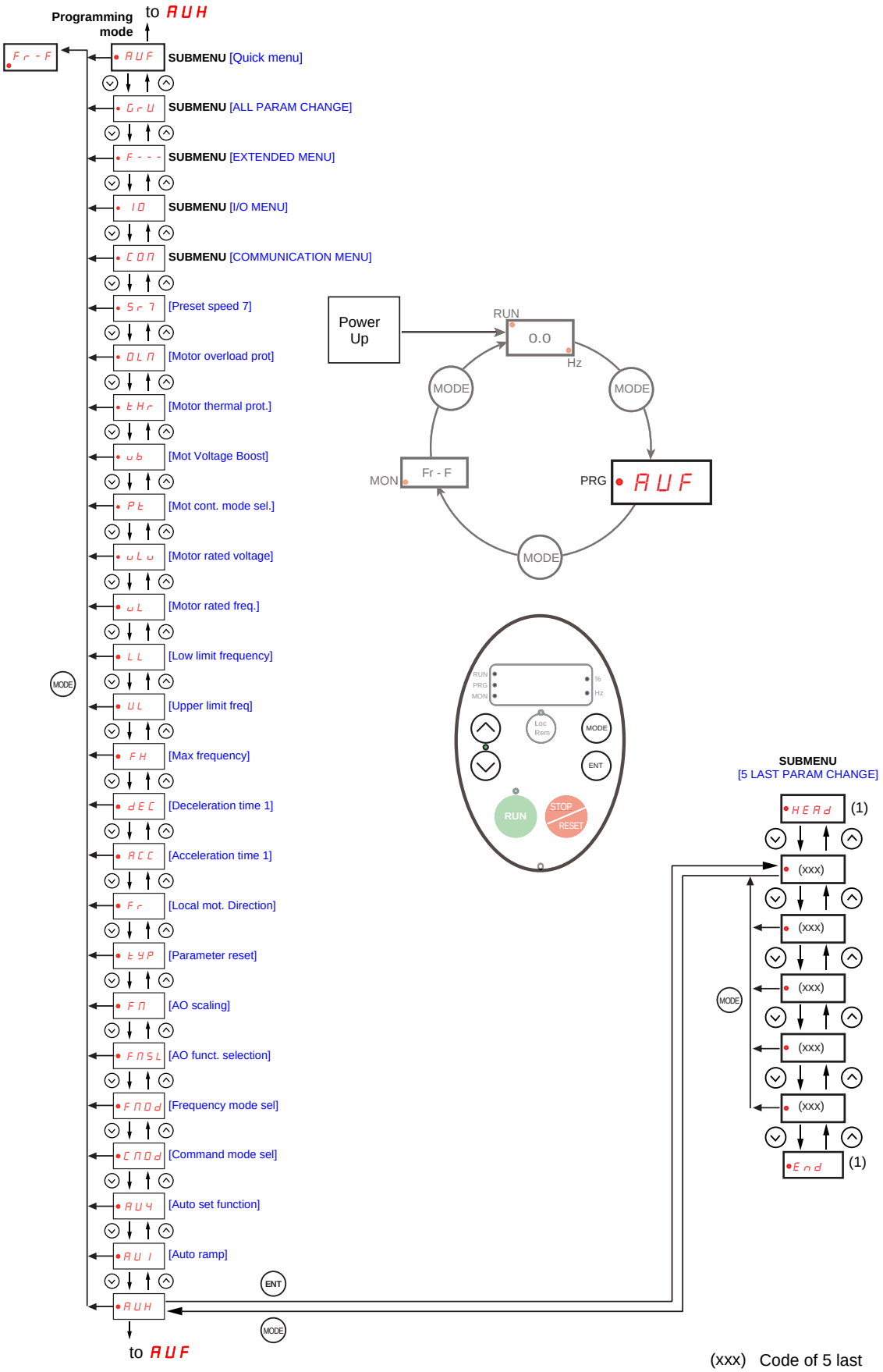
Menu Navigation

Menu navigation diagrams below illustrate how to navigate through the programming menus and submenus.

AUH [Quick menu] submenu



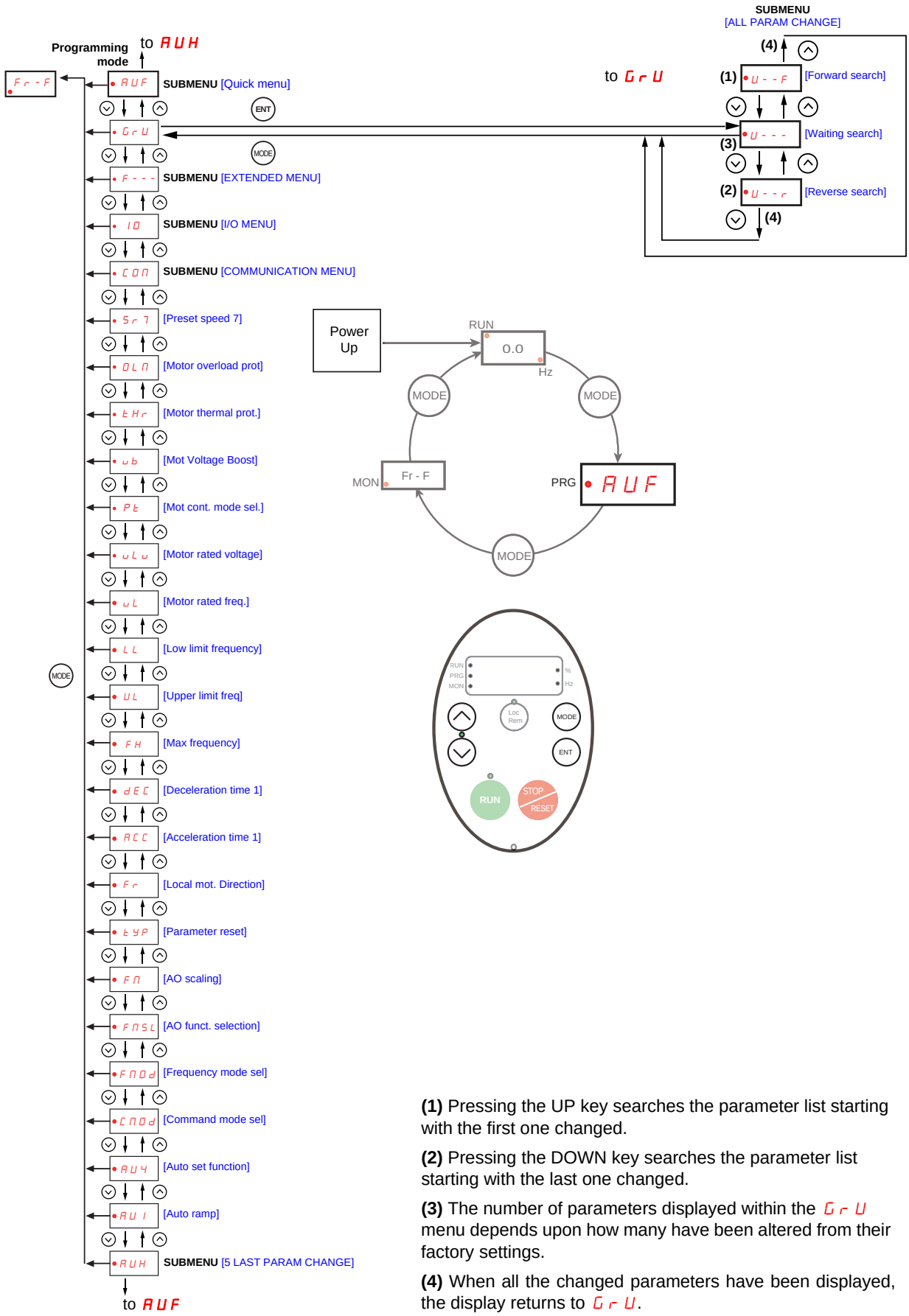
AUF [5 LAST PARAM CHANGE] submenu



Note: If no parameter has been changed, AUI is selected.

(1) Flashes three times then displays previous parameter.

GrU [ALL PARAM CHANGE] submenu



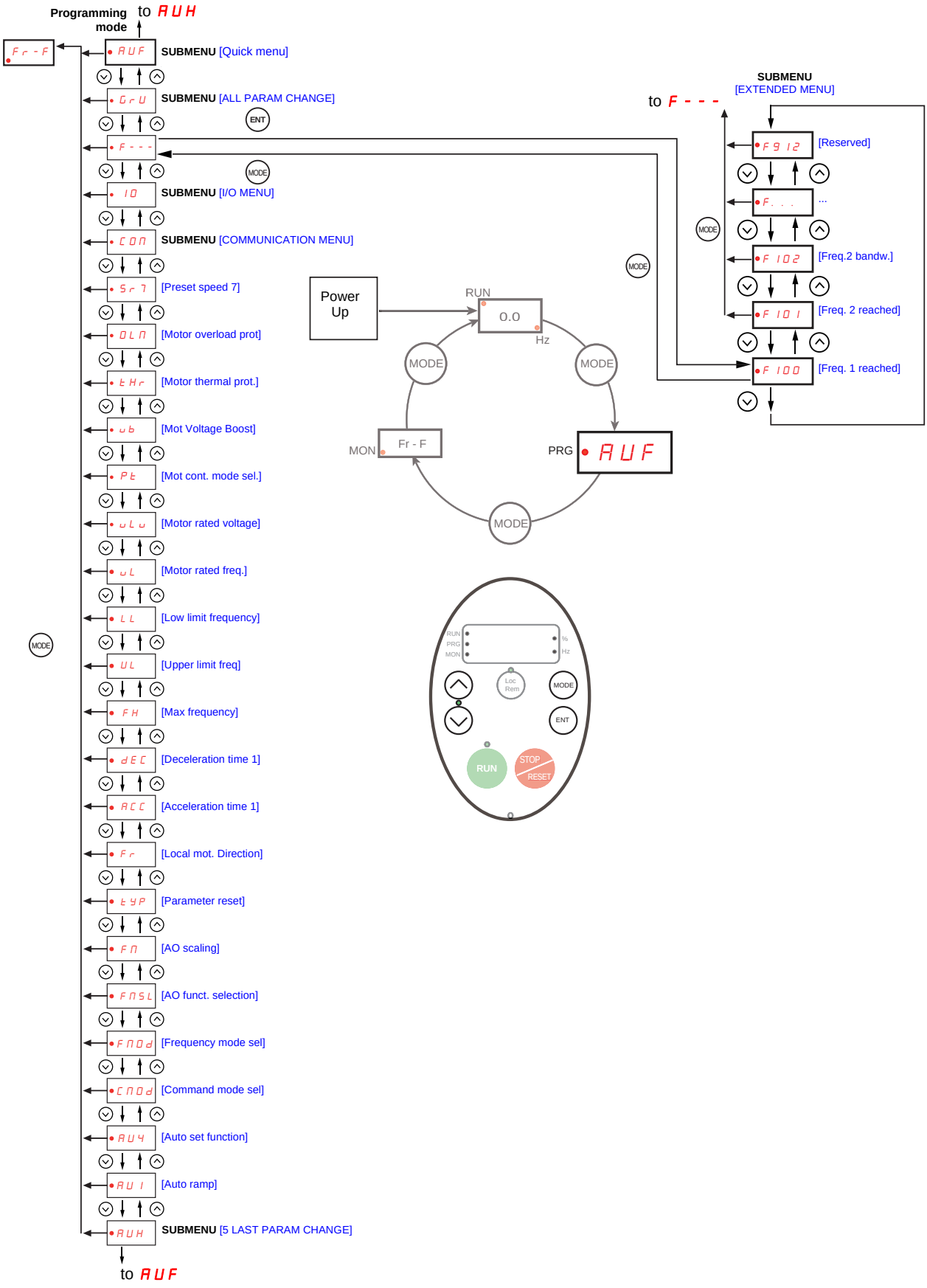
(1) Pressing the UP key searches the parameter list starting with the first one changed.

(2) Pressing the DOWN key searches the parameter list starting with the last one changed.

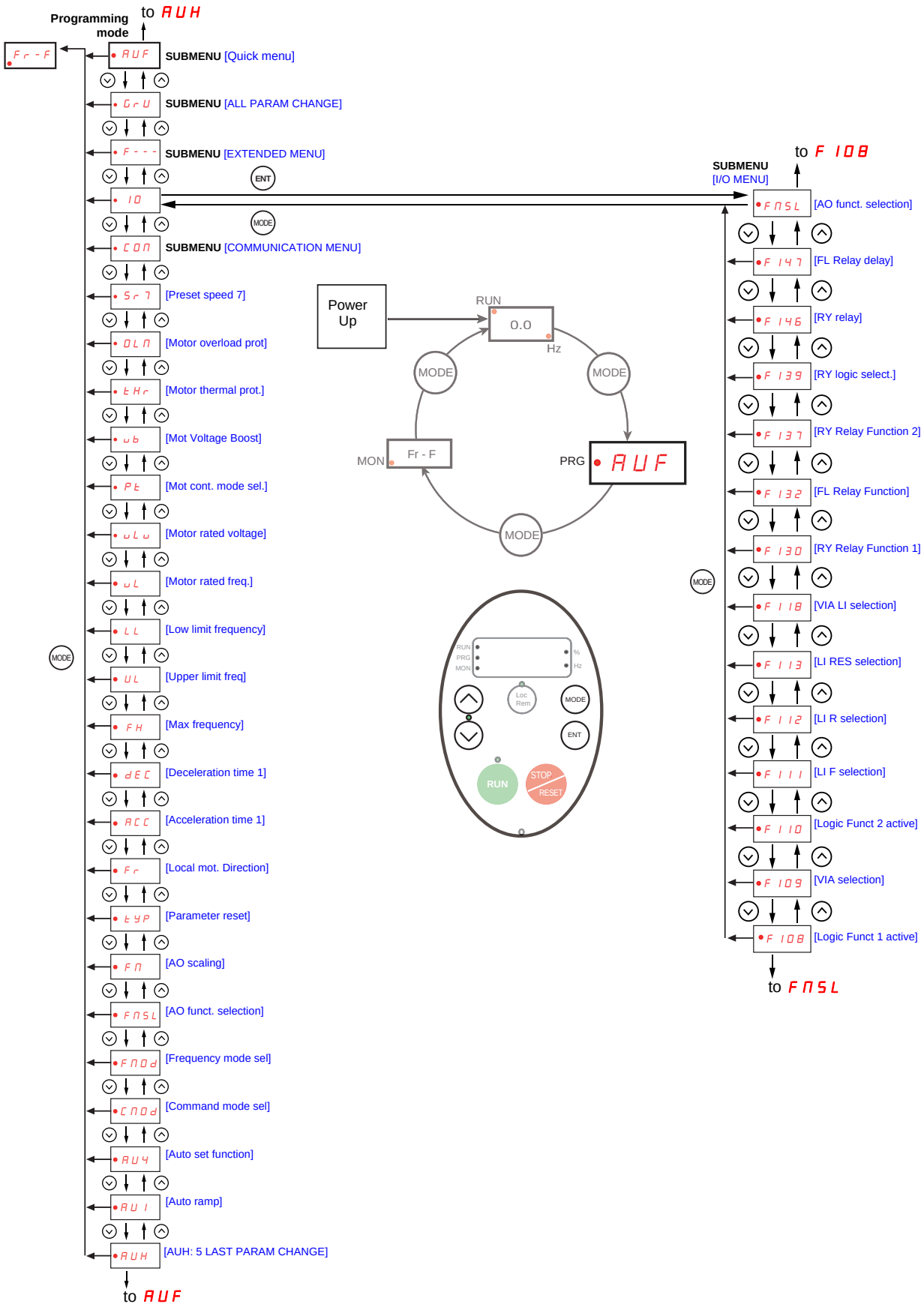
(3) The number of parameters displayed within the GrU menu depends upon how many have been altered from their factory settings.

(4) When all the changed parameters have been displayed, the display returns to GrU.

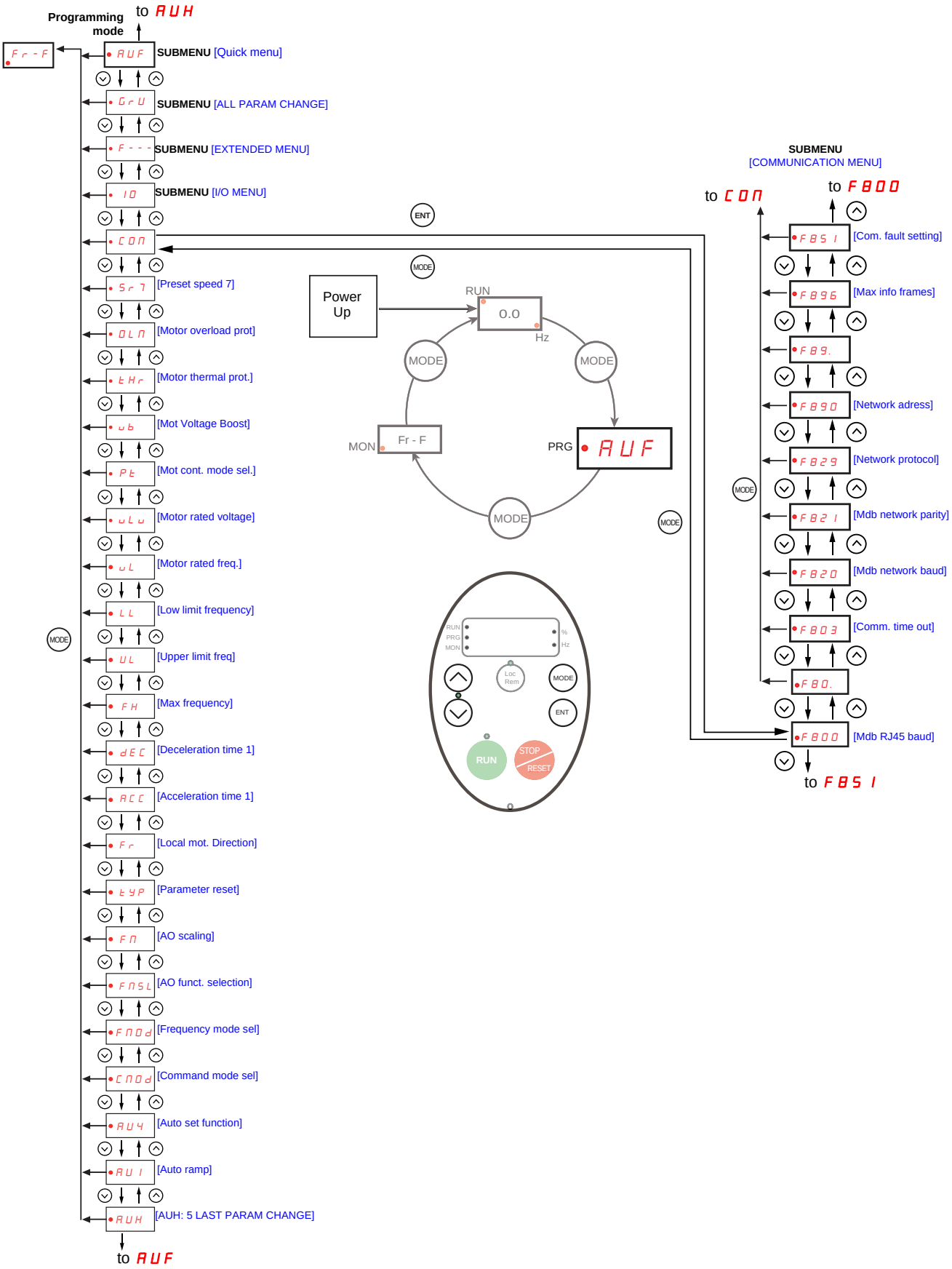
F - - - [EXTENDED MENU] submenu



I O [I/O MENU] submenu



COM [COMMUNICATION MENU] submenu



Submenus

The ATV212 drive features 6 submenus (see diagrams starting on page 24) that are designed to reduce the time and effort required to program application parameters. Parameters can be modified within these submenus.

AUH [5 LAST PARAM CHANGE]

The AUH submenu displays, in reverse chronological order, the last 5 parameters that have been changed from their factory settings. Each time the AUH submenu is accessed, it searches for the latest parameters changed from their factory settings. If every parameter is at its factory settings, no display is generated.
Parameter Lock F 700 is not displayed in the AUH menu, even if its value has been changed (see page 64).

AUF [QUICK MENU]

The AUF submenu provides ready access to the ten basic parameters commonly used in programming the drive. In many cases, programming the ATV212 drive is complete when these 10 parameters have been properly set (see chapter Quick Menu page 55).

GrU [ALL PARAM CHANGE]

The GrU submenu displays every parameter that has been changed from its factory settings. Each time the GrU submenu is accessed, its content is refreshed with the latest list of parameters changed from their factory settings. If every parameter is at its factory setting, no display is generated.
Parameters Fn and F470 – F473 are not displayed in the GrU menu, even if their values have been changed.

F– – – [EXTENDED MENU]

The extended parameter submenu provides access to parameters used for special settings and applications.

IO [I/O MENU]

The IO submenu provides access to parameters used for input/output setting.

COM [COMMUNICATION MENU]

The COM submenu provides access to parameters used for the communication setting.

Graphic display option

⚠WARNING

LOSS OF CONTROL

- Do not use the ATV21 and ATV12 terminal display (VW3A21101 and VW3A1006).
- Only VW3A1101 is compatible with ATV212.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

Description of the graphic display option

With the graphic display option, which works with FLASH V1.1IE29 or higher, it is possible to display more text information than can be shown on the integrated display terminal.



1 Graphic display

2 Function keys
F1, F2 and F3: not assigned
F4: Loc/Rem

3 STOP/RESET key

4 RUN key

5 Jog dial:

- Press (ENT):
  - To save the current value
  - To enter the selected menu or parameter
- Turn +/-:
  - To increment or decrement a value
  - To go to the next or previous line
  - To increase or decrease the reference if control via the graphic display option is activated

6 FWD/REV key: Press to reverse the direction of rotation of the motor

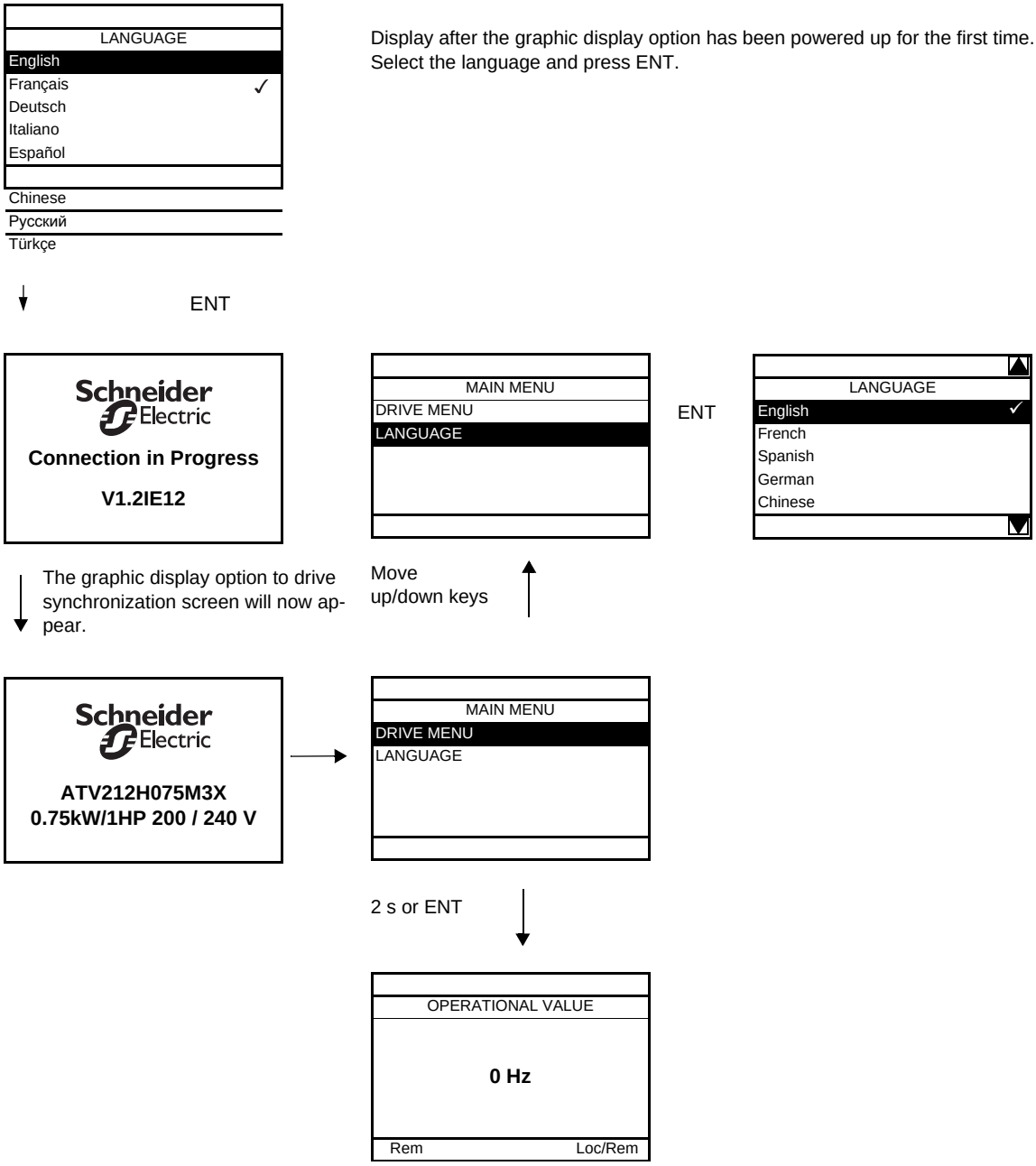
7 ESC key: Press to select the graphic display mode.
- Run mode (default on power-up)
- Programming mode
- Monitoring mode

Can also be used to go back to the previous menu.
Also corresponds to the MODE button of the embedded HMI

Note: Keys **3**, **4**, **5** and **6** can be used to control the drive directly, if control via the graphic display option is activated.

Powering up the drive with graphic display option for the first time

When powering up the graphic display option for the first time, the user has to select the required language.

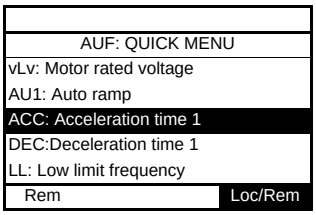


Finding a parameter in this document

The following assistance with finding explanations on a parameter is provided:

- With the integrated display terminal and the optional graphic display terminal : Direct use of the parameter code index, page 171, to find the page giving details of the displayed parameter.
- With the graphic display option: The parameter code and the name are displayed.

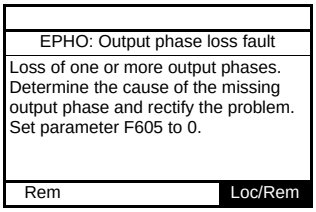
Example: ACC



Then use the parameter code index, page 171, to find the page giving details of the displayed parameter.

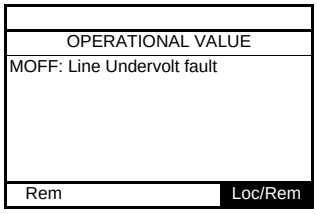
Detected fault screens

Example: Output phase loss fault



This screen is displayed the detected fault type and diagnostic information related to the detected fault. Then use the alarm code table page 150 for more information.

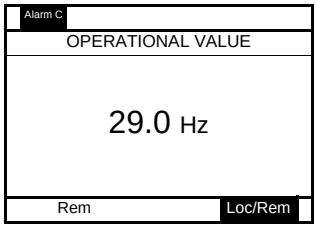
Line undervoltage



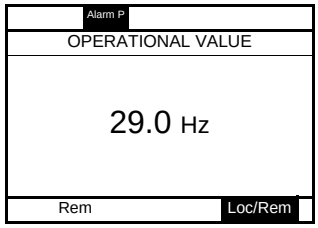
Pre-alarms screens

Here some type of screens:

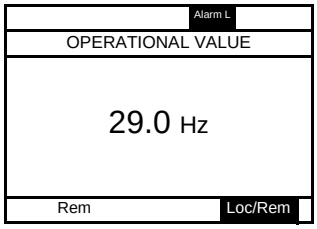
Current Limit pre-alarm



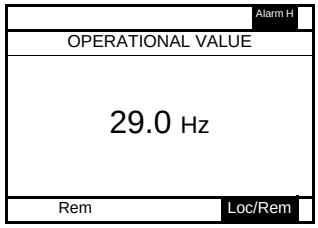
DC bus overvoltage pre-alarm



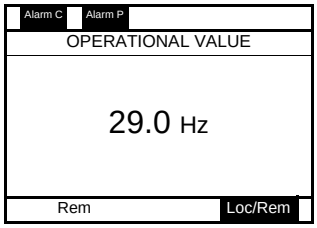
Motor overload pre-alarm



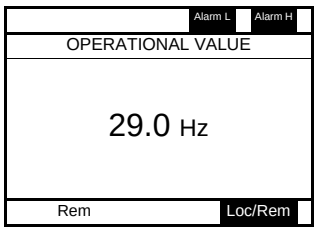
Drive overheating pre-alarm



Current Limit and DC bus overvoltage pre-alarm



Motor overload and drive overheating pre-alarm

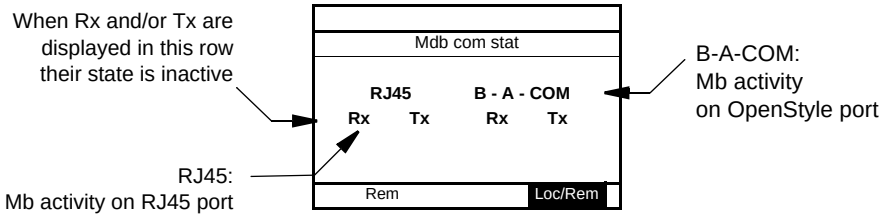


Modbus communication status

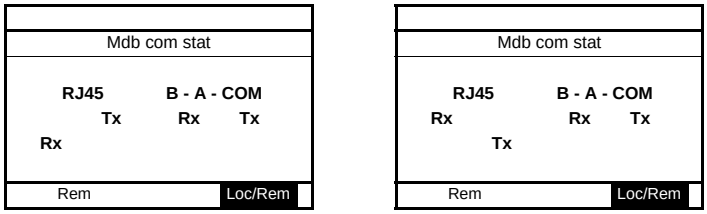
[Mdb com stat] (Mb ...) parameter display

This parameter is able to check the modbus communication on RJ45 and OpenStyle port.

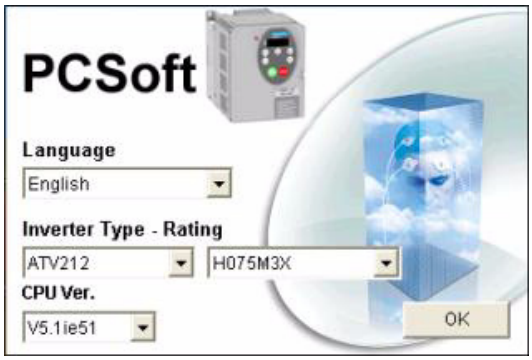
Without Communication



Example : With Communication on RJ45 port



PCSoft software workshop

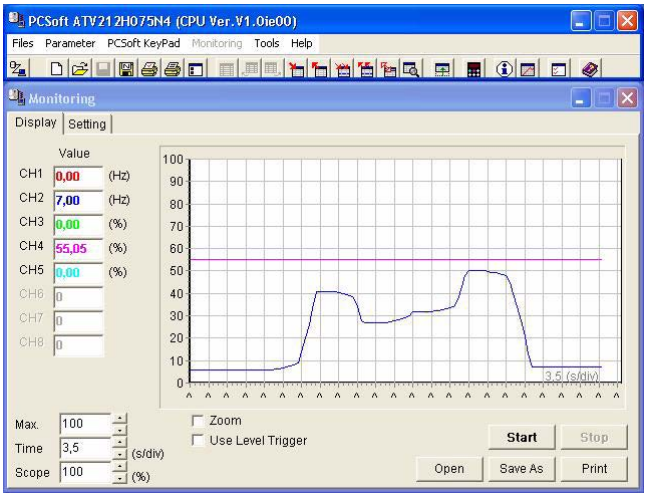


Description

This PC software workshop is a user-friendly tool for setting up Altivar 212 drives.

It includes different functions such as:

- Configuration preparation
- Setup
- Maintenance



It can be downloaded free of charge from the internet at www.schneider-electric.com.

Connection

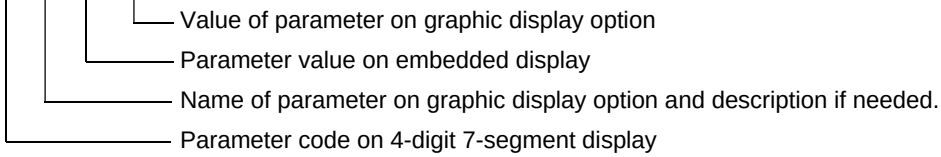
The PCSoft software workshop must be connected directly to the Modbus port on the drive using the PC serial port connection kit, reference VW3A8106 or by USB cable reference TCSMCNAM3M002P, or by bluetooth (see catalog on www.schneider-electric.com).

Structure of the parameter tables

The parameter tables contained in the descriptions of the various menus are organized as follows.

Example:

Code	Name / Description	Adjustment range	Factory setting
F 4 0 0	**[Auto-tuning drive]** Auto tuning enable	-	0
	0 **[Disabled]** 1 **[Initialize constant]**: Application of individual settings of Auto Torque Boost [Auto Torque Boost] (F 4 0 2) 2 **[Complete tune]**: complete auto tuning. Parameter F 4 0 0 is reset to “0” after the auto tuning is performed.		



Note: The text in square brackets **[ ]** indicates what you will see on the graphic display option.

Parameters that cannot be changed while the drive is running

The table below lists the parameters that cannot be changed unless the drive is stopped.

Code	Description
AU1	[Auto ramp]
AU4	[Auto set function]
CMOd	[Command mode sel]
FMOd	[Frequency mode sel]
tYP	[Parameter reset]
FH	[Max frequency]
UL	[Upper limit freq]v
uLu	[Motor rated voltage]
PtC	[Mot cont. mode sel.]
F108	[Logic Funct 1 active]
F109	[VIA selection]
F110	[Logic Funct 2 active]
F111	[LI F selection]
F112	[LI R selection]
F113	[LI RES selection]
F118	[VIA LI selection]
F130	[RY Relay Function 1]
F132	[FL Relay Function]
F137	[RY Relay Function 2]
F139	[RY logic select.]
F170	[Mot 2 rated Freq.]
F171	[Motor 2 rated Volt]
F300	[Switch. freq. level]
F301	[Catch on fly]
F302	[Supply loss behav.]
F303	[Number auto reset]
F305	[Overvoltage fault]

Code	Description
F307	[Mot volt limitation]
F311	[Motor direction]
F316	[Switch. freq. mode]
F400	[Auto-tuning drive]
F415	[Motor rated current]
F416	[Mot no-load current]
F417	[Motor rated speed]
F418	[Frequency loop gain]
F419	[Freq. loop stability]
F480	[No load cur. coef]
F481	[In noise comp. filter]
F482	[In noise Inhibit filter]
F483	[In noise inhibit gain]
F484	[Pwr supply adj. gain]
F485	[Stall control coef. 1]
F492	[Stall control coef. 2]
F494	[Mot. adj coefficient]
F495	[Motor voltage coef.]
F496	[PWM adj. coef.]
F601	[Motor Current Limit]
F603	[fault stop Mode]
F605	[Output phase loss]
F608	[Input phase loss]
F613	[Short circuit det.]
F626	[Overvoltage level]
F627	[Undervolt detect.]
F732	[Loc/rem key]

Common control schemes

⚠⚠ DANGER

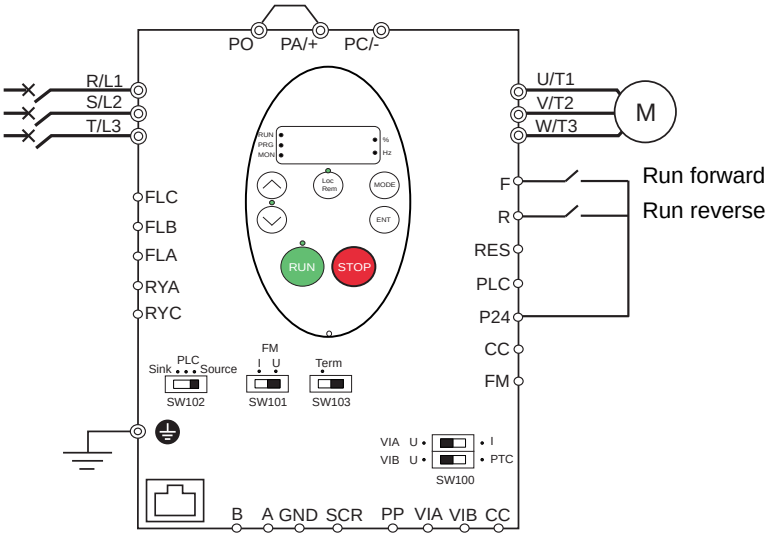
HAZARD OF ELECTRIC SHOCK, EXPLOSION OR ARC FLASH
Read and understand the instructions in "before you begin" chapter, before performing the procedure in this section.
Failure to follow these instructions will result in death or serious injury.

⚠ DANGER

UNINTENDED EQUIPMENT OPERATION
- To modify the setting of the switches, the product must be switched off.
- Do not change the setting of switch SW102 unless your system is properly wired.

Failure to follow these instructions will result in death or serious injury.

2-wire control

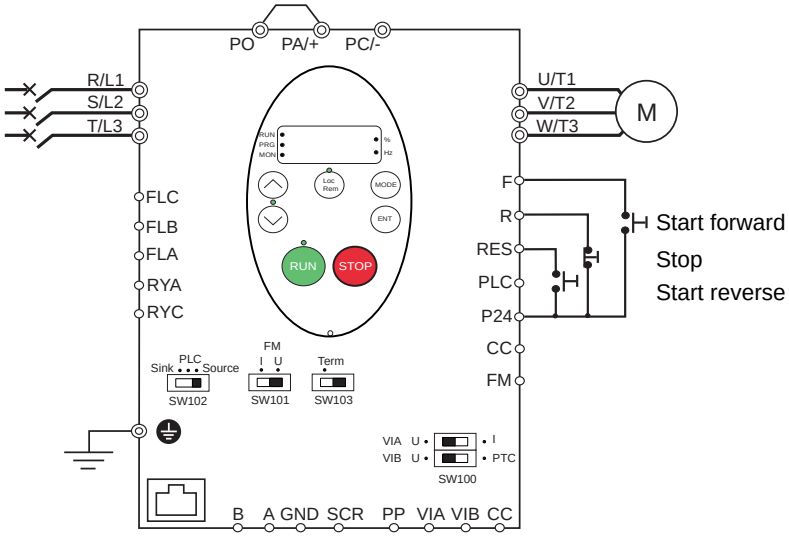


1. Wire the logic inputs as indicated in the above figure.
2. Set switch SW102 to source.
3. Program common parameters of ATV212 (see Quick Menu page 55).
4. Program specific parameters for 2-wire control as indicated in the following table:

Parameter	Page	Setting	Factory value
CMOd [Command mode sel]	77	0 [Logic inputs]	0
FII1 [LI F selection]	90	2 [forward]	2
FII2 [LI R selection]	90	3 [reverse]	6

Note: If FII1 and FII2 are switched simultaneously, the drive will go at 0 speed.

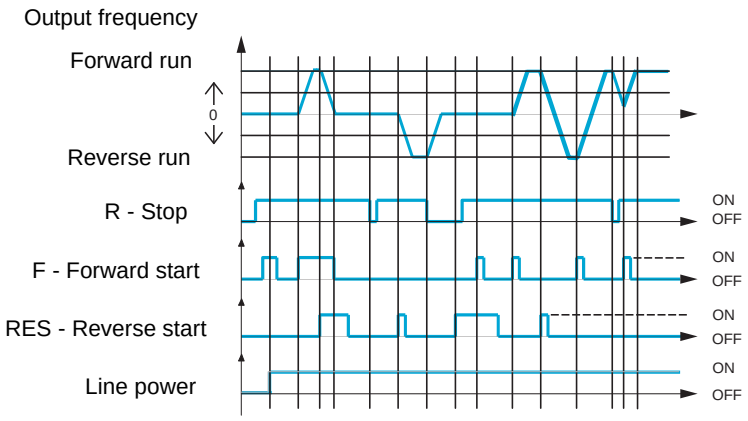
3-wire control



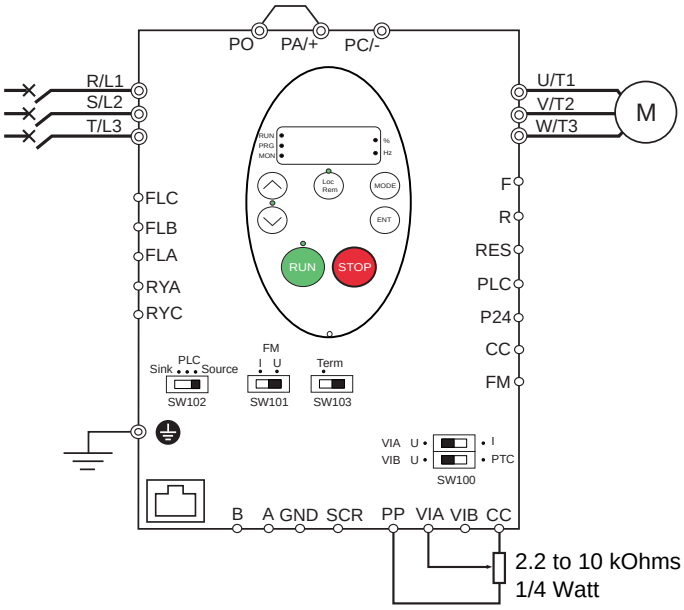
1. Wire the logic inputs as indicated in the above figure.
2. Set switch SW102 to source.
3. Program common parameters of ATV212 (see Quick Menu page 55).
4. Program specific parameters for 3-wire control as indicated in the following table:

Parameter	Page	Setting	Factory value
CMOd [Command mode sel]	77	0 [Logic inputs]	0
FIII [LI F selection]	90	2 [forward]	2
FII2 [LI R selection]	90	49 [3-wire]	6
FII3 [LI RES selection]	90	3 [reverse]	10

3 wire control timing diagram



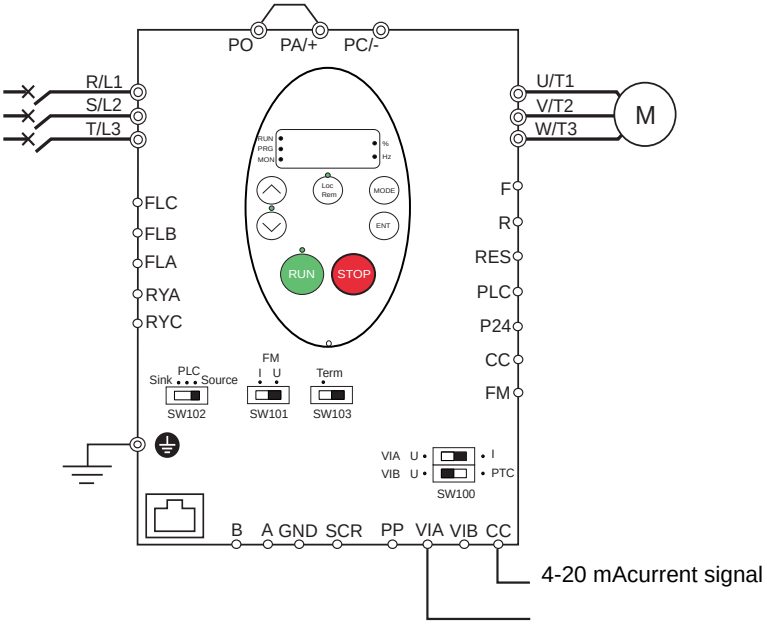
External speed control potentiometer



1. Wire the analog input as indicated in the above figure.
2. Set switch SW100 to V (voltage).
3. Program common parameters of ATV212 (see Quick Menu page 55).
4. Program specific parameters for external speed control potentiometer as indicated in the following table:

Parameter	Page	Setting	Factory value
F M O d [Frequency mode sel]	77	I [Ref source VIA]	1
F I O 9 [VIA selection]	90	0 [AI]	0
F 2 0 0 [Auto/man speed ref]	108	0 [Enable]	0

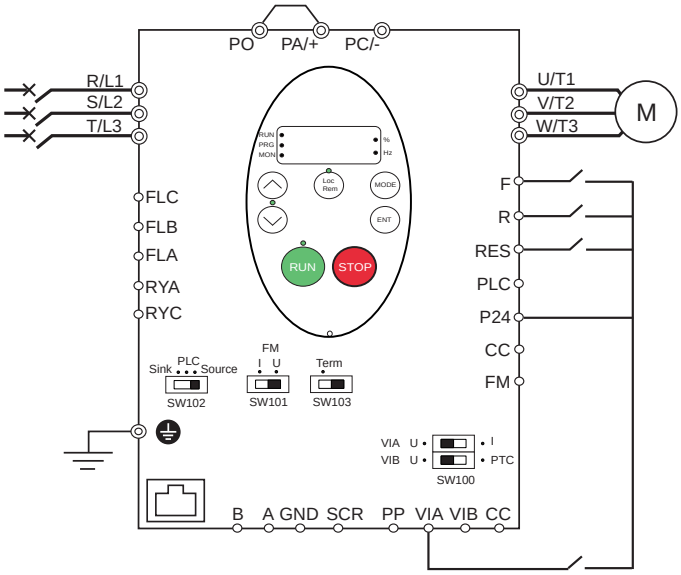
4-20 mA speed control



1. Wire the analog input as indicated in the above figure.
2. Set switch SW100 to I (current).
3. Program common parameters of ATV212 (see Quick Menu page 55).
4. Program specific parameters for 4-20 mA speed control as indicated in the following table:

Parameter	Page	Setting	Factory value
FMOd [Frequency mode sel]	77	I [Ref source VIA]	1
F 109 [VIA selection]	90	0 [AI]	0
F200 [Auto/man speed ref]	108	0 [Enable]	0
F20 I [VIA ref point 1]	106	20 %	0 %

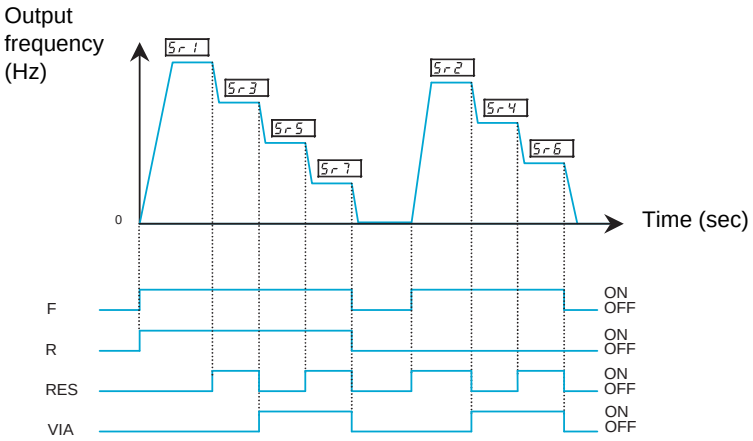
Preset speeds (up to seven)



1. Wire the logic and analog inputs as indicated in the above figure.
2. Set switch SW102 to source.
3. Program common parameters of ATV212 (see Quick Menu page 55).
4. Program specific parameters for preset speed as indicated in the following table:

Parameter	Page	Setting	Factory value
F 109 [VIA selection]	90	2 [LI source]	0
F 111 [LI F selection]	90	2 [forward]	2
F 112 [LI R selection]	90	6 [PS1]	6
F 113 [LI RES selection]	90	7 [PS2]	10
F 118 [VIA LI selection]	90	8 [PS3]	7
Sr 1 [Preset speed 1]	112	-	15.0
Sr 2 [Preset speed 2]	112	-	20.0
Sr 3 [Preset speed 3]	112	-	25.0
Sr 4 [Preset speed 4]	112	-	30.0
Sr 5 [Preset speed 5]	112	-	35.0
Sr 6 [Preset speed 6]	112	-	40.0
Sr 7 [Preset speed 7]	112	-	45.0

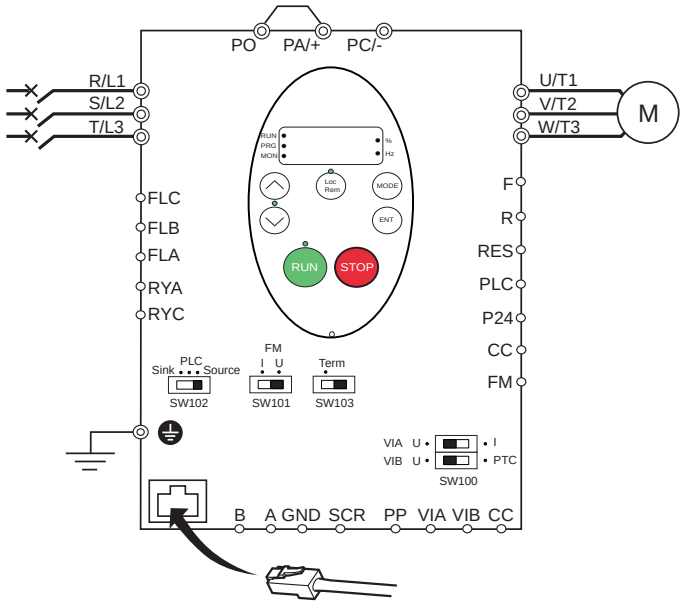
Example of 7-step preset speed operation:



See page 112 for additionnal information.

Serial communication

RJ45 connection



Port open style connection

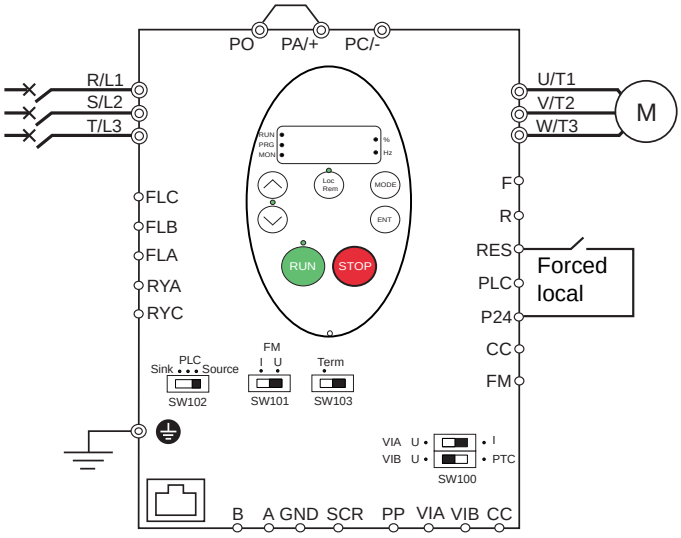
Contact	Signal
B	+
A	-
GND	GND
SCR	Screen

- Cable sheath should be peeled off by about 10 mm.
- For wiring work, use a fat blade screwdriver with a 0.6 mm thick and 3.5 mm width blade.
- Tightening torque for the terminal block is 0.5 to 0.6 Nm.

1. For Modbus serial communication, plug the network cable into RJ45 connector on the main control board. Connection can also be carried out using the «open style» port.
2. Program common parameters of ATV212 (see Quick Menu page 55).
3. Program specific parameters for serial communication as indicated in the following table:

Parameter	Page	Setting	Factory value
CMOd [Command mode sel]	77	2 [Communication]	0
FMOd [Frequency mode sel]	77	4 [Serial com ref.]	1
FBO1 [Com channel choice]	139		1

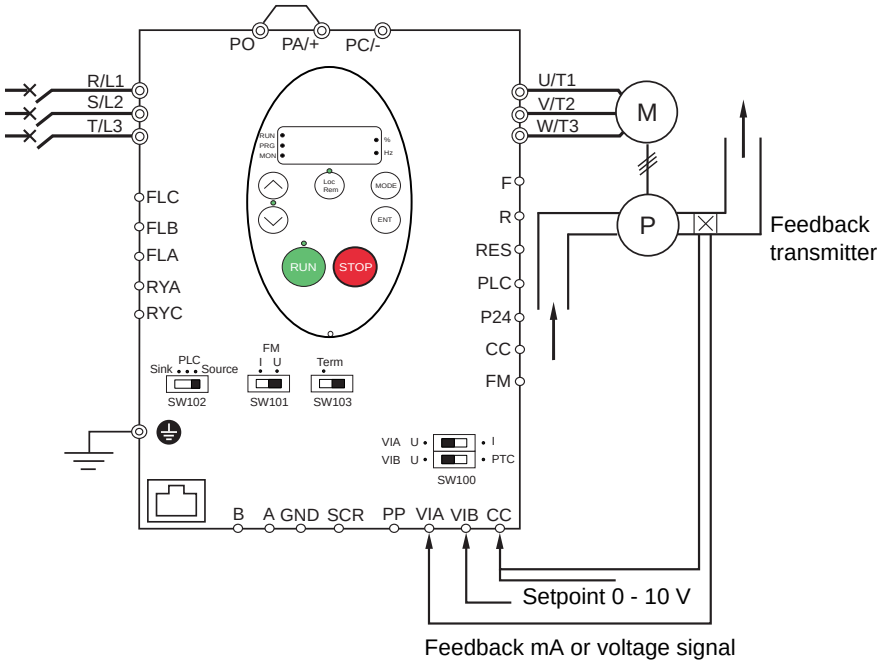
Forced local



1. Wire the logic input as indicated in the above figure.
2. Set switch SW102 to source.
3. Program common parameters of ATV212 (see Quick Menu page 55).
4. Program specific parameter for forced local as indicated in the following table:

Parameter	Page	Setting	Factory value
FI13 [LI RES selection]	90	48 [forced local]	10

PID control



1. Wire analog inputs as indicated in the above figure.
2. Set switch SW102 to source.
3. If the feedback is a milliamp signal, set switch SW100 to the I (current) position. If the feedback is a voltage signal, set switch SW100 to the V (voltage) position.
4. Program common parameters of ATV212 (see Quick Menu page 55).
5. Program specific parameters for PID control as indicated in the following table:

Parameter	Page	Setting	Factory value
FMOd [Frequency mode sel]	77	2 [Communication]	1
F IO9 [VIA selection]	90	0 [AI]	0
F200 [Auto/man speed ref]	108	0 [Enable]	0
F360 [PID control enable]	110	1 [PID by VIA]	0
F359 [PID ctrl wait time]	111	In accordance with the application	0 s
F362 [PID Prop Gain]	110		0.30 %
F363 [PID Integral Gain]	110		0.20
F366 [PID Derivative Gain]	111		0.00
F380 [PID reverse error]	111		0
F391 [Stop on LL hyst]	111		0.2 Hz
F392 [PID wake up (thres)]	111		0.0 Hz
F393 [PID wake up, feedb]	111		0.0 Hz

Drive Operation

Local and Remote Modes of Operation

Overview

The ATV212 drive has two modes of operation, local and remote.

In local mode, the ATV212 drive can be operated only from the embedded display terminal or graphic display option:

- Use the RUN and STOP keys for command control
- Use the UP and DOWN keys for speed control

In remote mode, the ATV212 drive is operated from a combination of the command and speed reference sources defined by programming parameters [Frequency mode sel] (FMOd) and [Command mode sel] (CMOd) (see page 77).

Command Sources

The command source [Command mode sel] (CMOd) choices are:

- External signals to the control terminal logic inputs F, R, RES and VIA
- Serial communication control (Modbus®, Metasys® N2, Apogee® FLN P1, BACnet, or LonWorks®)
- Embedded display terminal RUN and STOP keys or graphic display option

Speed Reference Sources

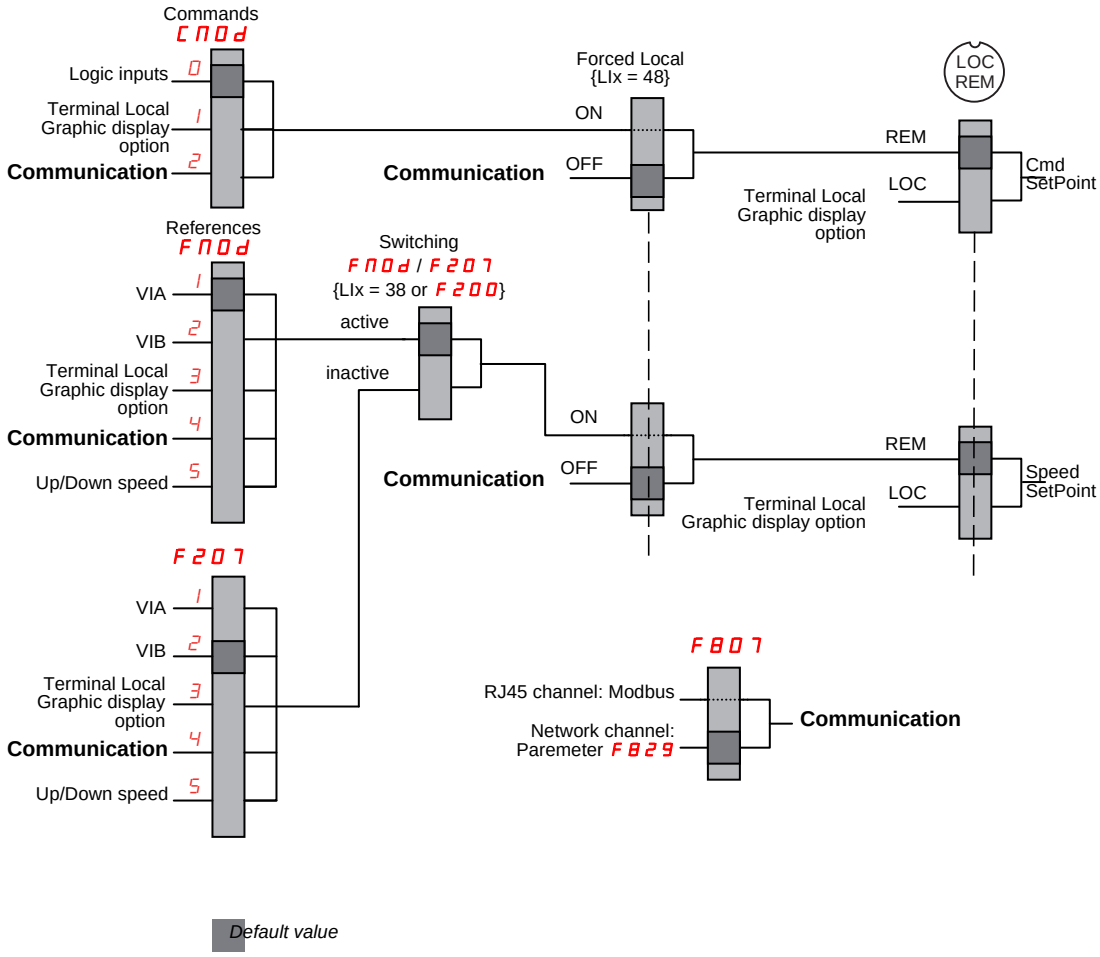
The speed reference source [Frequency mode sel] (FMOd) choices are:

- External signals to the control terminal analog inputs VIA or VIB
- (4–20 mA, 0–10 Vdc),
- External signals to the control terminal logic inputs assigned to +/- Speed
- Serial communication control (Modbus®, Metasys® N2, Apogee FLN P1®, BACnet, or LonWorks®)
- Embedded display terminal UP and DOWN keys or graphic display option

Command Mode Selection and Priorities

The diagram below illustrates the control inputs and selection logic which determine the source of the drive's start/stop and speed reference commands.

Command and Reference Switching



Parameters [Command mode sel] (CMd) and [Frequency mode sel] (FMd) are the first layers of logic used by the drive to determine its command CMd and speed reference FMd source.

[Remote spd ref 2] (F207) is a secondary speed reference source that may override the source selected by FMd (see page 77).

The speed reference source identified by F207 takes control if either:

- A logic input assigned to function 38 (frequency reference source switching) is enabled, or
- Parameter [Auto/man speed ref] (F200) is set to 1 and the drive's output frequency is equal to or less than 1 Hz (see page 108).

If a serial communication link is established, it can take control of the ATV212 drive, overriding inputs identified by CMd, FMd, and F207. Control is restored to CMd, FMd, and F207 only if:

- The serial communication link relinquishes control, or
- A logic input assigned to function 48 (forced local) is enabled.

The final layer of logic used by the drive to determine its command source is the LOC/REM key on the graphic display option.

When the drive and embedded HMI is set to local mode (by pressing the LOC/REM key, lighting the local mode LED), the drive responds only to commands from the embedded and graphic display option.

Selecting Local or Remote mode

⚠ DANGER

UNINTENDED EQUIPMENT OPERATION

- Know the state of the frequency and run commands from the remote source before exiting the local mode.
- Upon entering the remote mode, the drive will respond to the most recent command from the remote source, even if it was received before entering or while in the local mode.

Failure to follow these instructions will result in death or serious injury.

Switching between local and remote mode is achieved with the LOC/REM key on the drive's embedded display terminal or with F4 key on the graphic display option.

The LOC/REM key can be disabled by setting parameter [Loc/rem key] (F 7 3 2) to 1 (see page 80).

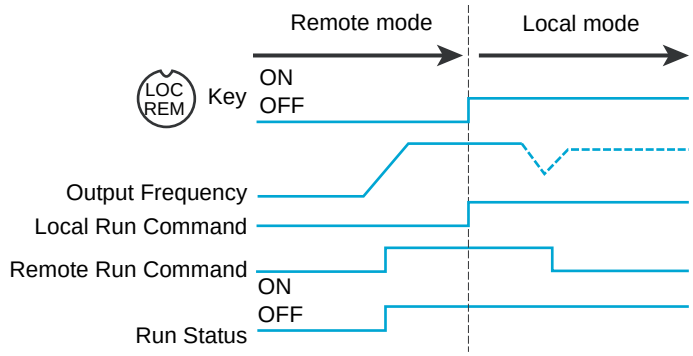
When parameter [Switch rem/Local] (F 2 9 5) is set to 1 (factory setting), a bumpless tranfer of motor operation is achieved when switching from remote to local mode (see page 78).

For example, if the bumpless transfert feature is active and if the motor is running at full speed with the drive in remote mode, the motor will still run at full speed after the drive is transferred to local mode.

Conversely, when switching from local to remote mode, the run and speed command is not transferred to the remote mode. Upon entering the remote mode, the drive will operate on the run and speed command set by the remote source even if it was received before entering or while in the local mode.

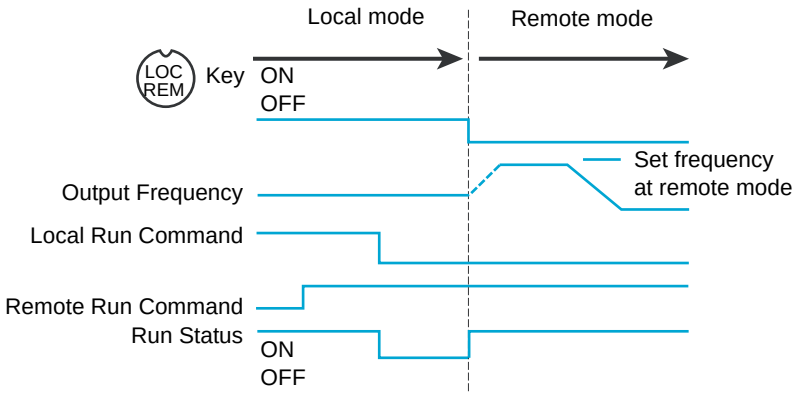
The diagram below is an example timing diagram.

Switching Between Local and Remote Mode



The remote run command and frequency command are transferred to the local mode when the LOC/REM key is pressed.

In this example, the run command and frequency command from the remote mode are copied to the local mode, and the motor continues to run.



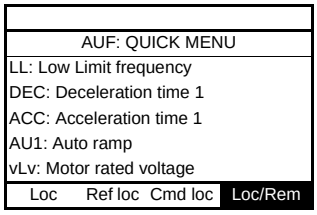
When switching from the local mode to the remote mode, the run command and frequency command are determined by the setting in the remote mode.

In this example, when the LOC/REM button is pressed, the motor in started.
This is due to the application of a remote run command when the drive exits the local mode and enters the remote mode.

Local Mode

When the ATV212 drive is in local mode, the LED above the LOC/REM key is illuminated.

On the graphic display option:



Starting and Stopping the Motor in Local Mode

Start and stop the motor with the RUN and STOP keys on the graphic/embeded display terminals.

The setting of parameter [Loc. mot stop mode] (F 7 2 1) determines how the motor stops when the drive is in local mode (see page 78):

- If F 7 2 1 is set to 0 (factory setting), the motor will stop on a ramp, based on the time value set in parameter [Deceleration time 1] (d E C) or parameter [Deceleration time 2] (F 5 0 1).
- If F 7 2 1 is set to 1, power will be removed from the motor when the STOP key is pressed, allowing the motor to coast to a stop with the ramp-down time determined by inertia and friction.

Use of the RUN and STOP keys in local mode can be disabled using parameter [Run/stop key] (F 7 3 3) (see page 80).

Adjusting Motor Speed in Local Mode

Set the motor speed using the UP and DOWN keys on the graphic/embeded display terminals. Motor speed can be adjusted while the drive is operating.

Normally, motor frequency changes by 0.1 Hz each time the UP or DOWN key is pressed. This rate of speed change can be altered by entering a new frequency step change into parameter [Loc. speed ref. step] (F 7 0 7) (see page 77).

If the ENT key is pressed after the motor speed has been adjusted, that speed setpoint value will be entered into parameter F C. The next time the drive is started in the local mode, it will accelerate the motor directly to the speed setpoint memorized by [Local speed ref.] (F C) (see page 77).

Selecting Motor Rotation Direction in Local Mode

Motor rotation direction is set by parameter [Local mot. direction] (F r) (see page 77). The four selections are:

- 0: Forward only (factory setting)
- 1: Reverse only
- 2: Forward, with reverse selectable from the graphic/embeded display terminals (1)
- 3: Reverse, with forward selectable from the graphic/embeded display terminals (1)

(1)If F r is set to either 2 or 3, motor rotation can be set to forward by pressing the UP key while holding the ENT key. Reverse can be set by pressing the DOWN key while holding the ENT key.

Motor rotation is indicated on the embedded display terminal as F r - F for forward and as F r - r for reverse.

The ability to run in the Forward or Reverse direction can be set with parameter [Motor direction] (F 3 1 1) (see page 86).

Resetting drive detected fault in Local Mode

It is not possible to clear a drive detected fault if the cause of the detected fault persists. Be certain to diagnose and rectify the cause of the detected fault before attempting a drive reset.

With the STOP Key

To clear a drive detected fault in local mode:

1. Press the STOP key. See Fault detection codes that can be cleared with the automatic restart function after the cause has disappeared on page 124 for a list of detected faults that can be cleared with the STOP key. If it is possible to reset the drive, the embedded display terminal will display CLr.

2. To clear the detected fault, press the STOP key a second time.

3. If the cause of the detected fault is still present, the CLr display will not appear. Diagnose and clear the detected fault before attempting to reset the drive.

Use of the STOP key as a clear detected fault can be set with parameter [HMI reset button] (F735) (see page 80).

In the event of an OL1 or OL2 detected fault, the following time periods are necessary before a clear detected fault is possible:

- OL1 (drive overload)—about 30 seconds after the detected fault has occured
- OL2 (motor overload)—about 120 seconds after the detected fault has occured

By Cycling Line Power

A drive detected fault can also be cleared by removing and restoring line power. Be certain that the cause of the detected fault is no longer present and leave power removed long enough for all of the LEDs on the face of the drive to extinguish.

Cycling power to clear a detected fault can cause the detected fault history to be lost. Refer to parameter [Drive Fault Memory] (F602) on page 127.

Logic Input Functions Active in Local Mode

The logic input functions listed in the table below are active, even if [Command mode sel] (CMOd) is set to 1 (embedded display terminal control). See table on page 90 for logic input function settings.

Logic Input Function No.	Description
1 54	[Run permissive] [Inverse Run permissive]
10 55	[Fault reset] [Inv fault reset]
11 45	[Ext Fault] [Inv Ext. fault]
16	[Run reset]
38	[Frequency source]
41	[(+) speed]
42	[(-) speed]
43	[+/- clear]
44	[+/- SPD, FLT CLR]
46	[Ext. Th fault]
47	[Inv Ext. Th fault]
51	[Reset kWh]
52	[Forced mode]
53	[Fire mode]
62	[RY on]
64	[Cancel HMI cmd]

Remote Mode

When the ATV212 drive is in the remote mode, the LOC/REM LED is off.

Starting and Stopping the Motor in Remote Mode

The diagram on page 46 illustrates the start/stop command source when the drive is in remote mode.

With Logic Input Terminals

Use the logic input terminals F, R, RES, or VIA to start the drive if parameter [Command mode sel] (CMOd) is set to [Logic Inputs] (0) (factory setting).

With the display terminals

The drive responds to commands from the embedded display terminal or graphic display option, just as in local mode, if parameter [Command mode sel] (CMOd) is set to [HMI] (1).

With Serial Communication

The drive responds to commands sent over the serial communication link (Modbus®, Metasys® N2, Apogee® FLN, BACnet or LonWorks®) if parameter [Command mode sel] (CMOd) is set to [Communication] (2).

The drive responds to commands sent over the RJ45 communication port if parameter [Com channel choice] (FBO 1) is set to 0. Other protocols are available when FBO 1 is set to 1 on open style port.

With the graphic/embeded display terminals STOP Key

The graphic/embeded display terminals STOP key is active when the drive is in remote mode. Pressing the STOP key causes the drive to stop according to the setting of parameters [Ext. fault stop Mode] (F603), [DC brk time ext flt] (F604), and [DC braking current] (F251) (see page 115 and page 88) . After the drive has come to a stop, the graphic/embeded display terminals display E and the fault relay is activated.

Adjusting the Motor Speed in Remote Mode

The diagram on page 46 illustrates the speed reference source when the drive is in remote mode.

By Analog Input VIA

A 0–10 Vdc or 4–20 mA signal connected to VIA and CC can be used to adjust the motor speed if:

- Parameter [Frequency mode sel] (FMOd) is set to 1 (factory setting).
- Alternate speed reference source parameter [Remote spd ref 2] (F207) has not been enabled (see page 78).

The analog signal type depends on the setting of switch SW100 and parameters F109, F201–F204, and F470–F471.

By Analog Input VIB

A 0–10 Vdc signal connected to VIB and CC can be used to adjust the motor speed if:

- Parameter [Frequency mode sel] (FMOd) is set to 2.
- Alternate speed reference source parameter [Remote spd ref 2] (F207) has not been enabled.

The control that VIB has over motor speed depends on the setting of switch SW100 and parameters F210–F213, F472–F473, and F645.

By display terminal Control

Control of the motor speed is enabled, if:

- Parameter [Frequency mode sel] (FMOd) is set to 3.
- Alternate speed reference source parameter [Remote spd ref 2] (F2O7) has not been enabled.

By Serial communication control

Serial communication control (Modbus, Metasys N2, Apogee FLN, BACnet or LonWorks) of the motor speed is enabled, if:

- Parameter [Com channel choice] (FBO7) is set to 0 (only for Modbus on RJ45 port),
- Parameter [Com channel choice] (FBO7) is set to 1,
- Parameter [Frequency mode sel] (FMOd) is set to 4.
- Alternate speed reference source parameter [Remote spd ref 2] (F2O7) has not been enabled.

By +/- Motor Speed Control

+/- Motor speed control is enabled, if:

- Parameter [Frequency mode sel] (FMOd) is set to 5,
- Alternate speed reference source parameter [Remote spd ref 2] (F2O7) has not been enabled.

Selecting Motor Rotation Direction in Remote Mode

The diagram on page 46 illustrates the motor rotation command source when the drive is in remote mode.

With Logic Input Terminals

Use the logic input terminals F, R, RES, or VIA to select motor rotation direction if parameter [Command mode sel] (CMOd) is set to 0 (factory setting).

With the embedded display terminal or graphic display option

Motor rotation direction can be set by pressing the display terminal UP and ENT keys if:

- Parameter [Command mode sel] (CMOd) is set to 1,
- Serial communication control has not been established.
- Parameter [Local mot. direction] (Fr) is set to either 2 or 3.

With Serial Communication

The drive responds to commands sent over the serial communication link (Modbus, Metasys N2, Apogee FLN, BACnet or LonWorks) if Parameter [Command mode sel] (CMOd) is set to 2.

Resetting drive detected faults in Remote Mode

The diagram on page 46 illustrates the clear detected fault command source when the drive is in remote mode.

It is not possible to clear a drive detected fault if the cause of the detected fault persists. Be certain to diagnose and rectify the cause of the detected fault before attempting to reset the drive.

See Automatically Resettable detected faults on page 124 for a list of detected faults that can be cleared in remote mode.

With the Logic Input Terminals

Use the logic input terminals F, R, RES, or VIA to clear a drive detected fault if parameter [Command mode sel] (CMOd) is set to 0 (factory setting).

With the graphic/embeded display terminals

The STOP key can be used to clear a drive detected fault if parameter [Command mode sel] (CMOd) is set to 1.

To clear a drive detected fault, press the STOP key. If it is possible to reset the drive, it will display CLr. To clear the detected fault, press the STOP key a second time.

If the cause of the interruption is still present, the CLr display will not appear. Diagnose and clear the detected fault before attempting to reset the drive.

The use of the STOP key as a clear detected fault can be managed by parameter [HMI reset button] (F735).

With Serial Communication

A drive detected fault can be cleared over the serial communication link (Modbus, Metasys N2, Apogee FLN, BACnet or LonWorks) if parameter [Command mode sel] (CMOd) is set to 2.

In the event of an OL 1 or OL 2 detected fault, the following time periods needs to pass before a clear detected fault is possible:

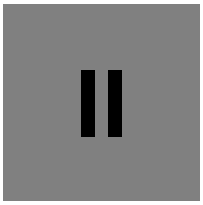
- OL 1 (drive overload) - about 30 seconds after the occurrence of the event.
- OL 2 (motor overload) - about 120 seconds after the occurrence of the event.

By Cycling Line Power

A drive detected fault can also be cleared by removing and restoring line power. Be certain that the cause of the detected fault is no longer present and leave power removed long enough for all of the LEDs on the face of the drive to go out.

Cycling power to clear a detected fault can cause the detected fault history to be lost. Refer to parameter F602 on page 127 for drive fault memory options.

Programming



What's in this Part?

This part contains the following chapters:

Chapter	Chapter Name	Page
3	Quick Menu	55
4	Programming Parameters	61
5	Motor Control Parameters	65
6	Drive Control Parameters	77
7	Application Parameters	81
8	I/O Control Parameters	89
9	Display Parameters	119
10	Detected Fault Management Parameters	123
11	Serial Communication Parameters	137
12	Start/Stop Control By Speed Reference Level	143
13	Droop Control	145

Quick Menu

3

What's in this Chapter?

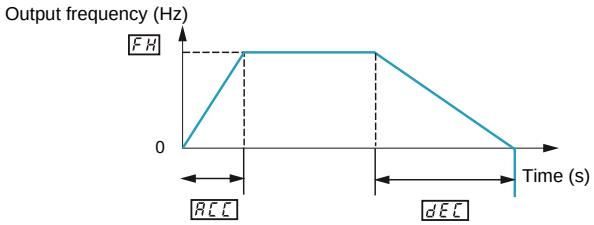
This chapter contains the following topics:

Topic	Page
Quick menu	56

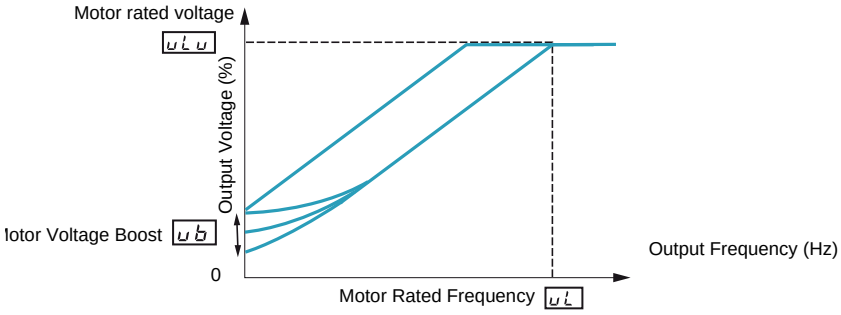
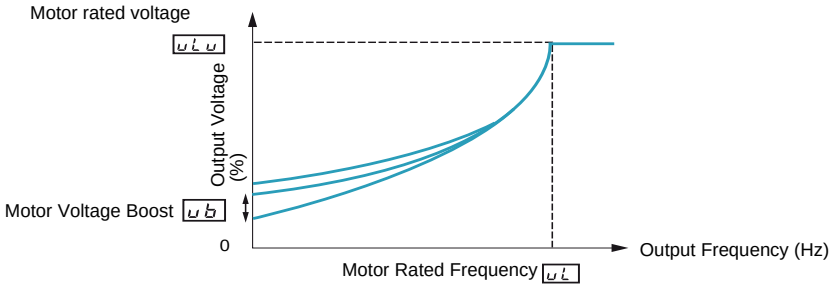
Quick menu

The AUF submenu provides ready access to the ten basic parameters commonly used in programming the drive.

In many cases, programming the ATV212 drive is complete when these 10 parameters and motor parameters have been properly set. .

Code	Name / Description	Adjustment range	Factory setting
AU1	**[Auto ramp]** Automatic ramp adaptation	-	1
	0 **[Disabled]** 1 **[Enable]**: [Acceleration time 1] (ACC) and [Deceleration time 1] (dEC) 2 **[ACC only]**: [Acceleration time 1] (ACC) only If parameter AU1 is set to 1 or 2, the drive will monitor its own loading level and optimize the acceleration and deceleration ramps. The acceleration and deceleration AU1 = 1 only rates will be automatically adjusted between 1/8 to 8 times the settings of ACC and dEC, depending on the drive's current rating and the load level on the motor. ACC and dEC should be appropriately set for an average load in the application. If the load on the motor increases rapidly during ramp up or ramp down, the auto ramp adaptation feature may not help to prevent the drive from experiencing an overcurrent or overvoltage. If the application requires a consistent acceleration and deceleration time, set AU1 to 0, and set ACC and dEC manually as needed. The manual acceleration and deceleration times can still be overridden by the [Motor Current Limit] (F601) (see page 69) and [Overvoltage fault] (F305) (see page 128) and [Overvoltage level] (F626) (see page 128) functions.		
ACC	**[Acceleration time 1]**	0.0 to 3200 s	According to drive rating (1)
	The setting of parameter ACC determines the slope of the acceleration ramp and the time it takes for the output frequency of the drive to increase from 0 Hz to the setting of [Max frequency] (FH) (see page 82). If parameter [Auto ramp] (AU1) is set to 1 or 2, the acceleration ramp may be increased or decreased from the setting of ACC, depending on the amount of load on the motor during ramp up. If two different acceleration rates are needed, see parameter [Acceleration time 2] (F500) on page 83. 		
dEC	**[Deceleration time 1]**	0.0 to 3200 s	According to drive rating (1)
	The setting of parameter dEC determines the slope of the deceleration ramp and the time it takes for the output frequency of the drive to decrease from the setting of [Max frequency] (FH) to 0 Hz. If parameter [Auto ramp] (AU1) is set to 1 or 2, the deceleration ramp may be increased or decreased from the setting of dEC, depending on the amount of load on the motor during ramp down. See diagram above. If two different deceleration rates are needed, see parameter [Deceleration time 2] (F501) on page 83.		
LL	**[Low limit frequency]**	0.0 to **[Upper limit freq]** (UL) Hz	0.0 Hz
	Parameter LL sets the minimum frequency that can be commanded to the drive by the local or remote speed reference source.		
UL	**[Upper limit freq]**	0.5 to **[Max frequency]** (FH) Hz	50.0 Hz
	Parameter UL sets the maximum frequency that can be commanded to the drive by the local or remote speed reference source. The top end of its range is limited by the setting of [Max frequency] (FH).		

(1) See table page 167

Code	Name / Description	Adjustment range	Factory setting
tHr	**[Motor thermal prot.]** Motor Rated Current Overload Setting	10 to 100% of the drive's output current rating	100%
	Set parameter tHr to the motor's rated current as indicated on the motor nameplate for the selected operating voltage. If parameter [Unit value selection] (F7O I) is set to 1 (see page 120), parameter tHr will be adjusted in amperes. If parameter F7O I is set to 0, parameter tHr will be adjusted in percentage. In this case, divide the motor rated current by the drive rated current (as listed on its nameplate) and set parameter tHr to the resulting percentage. The setting of parameter [Switch. freq. level] (F3O O) does not change the drive's rated current for the sake of this calculation (see page 85).		
FM	**[AO scaling]** Analog output scaling		-
	Parameter FM is used to match the FM terminal output signal with the input requirements of the attached panel meter by adjusting the slope and bias of the analog output signal. Before adjusting FM, set FMSL to either 15 or 17. As you adjust the value of FM, monitor the display on the attached panel meter. When the meter display reaches 100%, press the ENT key on the drive display terminal. The drive will flash between FM and the adjusted value, indicating that the adjustment has been saved.		
Ctt	**[Mot cont. mode sel.]** Motor control mode		1
O	**[Constant V/Hz]**: Constant V/Hz Use constant V/Hz mode for loads that require the same torque at low speeds as at rated speeds. Low speed torque can be adjusted manually by setting parameter [Motor Voltage Boost] (ubO) (see page 68).		
			
1	**[Variable Torque]**: Variable torque Use variable torque mode for loads such as centrifugal fans and pumps whose torque requirements increase as a square of the increase in motor speed. Low speed torque can be adjusted manually by setting parameter ub.		
			
2	**[Cst V/Hz+Boost]**: Constant V/Hz with automatic torque boost See the diagram on page 66. This mode is similar to the constant V/Hz mode (for loads that require the same torque at low speeds as at rated speeds), except it automatically increases motor voltage and torque to compensate for increases in load.		
3	**[SVC]**: Sensorless vector control Use sensorless vector control mode to increase torque at motor speeds below 3 Hz or to improve speed regulation (0.5 to 1%). See diagram on page 66.		
4	**[Economy]**: Energy saving In energy savings mode, the ATV212 drive monitors motor loading and automatically modulates the voltage applied to the motor to optimize energy consumption. If the ATV212 drive and the connected motor have the same power rating, and if the motor has a nominal 1500 rpm rating, no motor auto-tuning is required to use this motor control mode. Otherwise, follow the steps outlined in "Motor Tuning" on page 70.		
5	**[Do not use]**: Reserved		
6	**[Do not use]**: Reserved		

Code	Name / Description	Adjustment range	Factory setting
uL	**[Motor rated freq.]** Motor rated frequency	25.0 to 200.0 Hz	50.0 Hz
	Set parameter uL (vL) to the motor's rated frequency as indicated on the motor nameplate. Note: It is possible to set the drive's various motor control frequencies to 50 Hz by setting [Parameter reset] (tYP) to 1, the 50 Hz reset. For more information, see page 62.		
uLu	**[Motor rated voltage]**	According to drive rating	According to drive rating (1)
	Set parameter uLu (vLv) to the motor's rated voltage as indicated on the motor nameplate. ATV212●●●M3X: 50 to 330 V. ATV212●●●N4: 50 to 660 V **Note:** Drive output voltage cannot be set to exceed the input line voltage level.		

(1) See table page 167

Motor parameters

Configure the motor parameters and perform an auto-tuning ([Auto-tuning drive] (F 4 0 0) = 2, see page 71 for auto-tuning).

Code	Name / Description	Adjustment range	Factory setting
F 4 1 5	**[Motor rated current]** Motor rated full load current	0.1 to 200.0 A	According to drive rating (1)
	Set parameter F 4 1 5 to the motor rated full load current in amperes as indicated on the motor's nameplate.		
F 4 1 7	**[Motor rated speed]**	100 to 15000 rpm	According to drive rating (1)
	Set parameter F 4 1 7 to the motor rated speed in rpm as indicated on the motor's nameplate.		
F 6 0 1	**[Motor Current Limit]**	10 to 110% of the drive's output current rating	110%

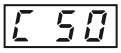
CAUTION

RISK OF DAMAGE TO THE MOTOR AND THE DRIVE
- Check that the motor will withstand this current.
- Check that the profile mission complies with the derating curve given in the installation manual

Failure to follow this instruction can result in equipment damage.

Parameter F 6 0 1 can be adjusted to limit current during motoring or braking.

Display in Current Limit Mode:
When the drive goes into current limit mode, it will:
Adjust the output frequency to limit the flow of motor current (down when motoring, up when braking).

Display the letter C and the output frequency flashing on the embedded software terminal, ex: 

If parameter [Unit value selection] (F 7 0 1) is set to 1 (see page 120), parameter F 6 0 1 will be adjusted in amperes. If parameter F 7 0 1 is set to 0, parameter F 6 0 1 will be adjusted as a percentage of the drive's output rated current as listed on its nameplate.

The setting of parameter [Switch. freq. level] (F 3 0 0) (see page 85) does not change the drive's rated current for the sake of this calculation.

Do not set parameter F 6 0 1 below the no-load current rating of the motor.

F 4 0 0	**[Auto-tuning drive]** Auto tuning enabled	-	0

⚠⚠ DANGER

HAZARD OF ELECTRIC SHOCK OR ARC FLASH
- During auto-tuning, the motor operates at rated current.
- Do not service the motor during auto-tuning.

Failure to follow these instructions will result in death or serious injury.

⚠ WARNING

LOSS OF CONTROL
- It is essential that the following parameters u L u (vLv), u L (vL), F 4 1 5 and F 4 1 7 are correctly configured before starting auto-tuning.
- When one or more of these parameters have been changed after auto-tuning has been performed, F 4 0 0 will return 0 and the procedure will have to be repeated.

Failure to follow these instructions can result in death or serious injury.

0	**[Disabled]**: Disabled
1	**[Initialize constant]** (2): Auto-tuning is performed immediatly if possible. Parameter Auto Torque Boost [Auto Torque Boost] (F 4 0 2) may need adjustment
2	**[Complete tune]** (2): complete auto tuning

(1) See table page 168.
(2) Parameter F 4 0 0 is reset to "0" after the auto tuning is performed.

Programming Parameters

4

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Parameter Reset	62
Macro Programming (AU4)	63
Parameter Lock	64
Display of Submenu AUF (F738)	64

Parameter Reset

Parameter Reset Options

The ATV212 drive offers three options to return parameters to their factory default settings:

- Factory reset: set parameter [Parameter reset] (tYP) to 3
- 50 Hz reset: set parameter [Parameter reset] (tYP) to 1
- 60 Hz reset: set parameter [Parameter reset] (tYP) to 2

Code	Name / Description	Factory setting
tYP	**[Parameter reset]**	0

⚠ DANGER

UNINTENDED EQUIPMENT OPERATION
When tYP is set to 3 or 8:
- Check that the modification of the current configuration is compatible with the wiring diagram used.
- All logic inputs must be deactivated to avoid unintended restart.
Failure to follow these instructions will result in death or serious injury.

0 **[No action]**

1 **[50 Hz reset]**: 50 Hz parameter reset
Setting parameter tYP to a value of 1 will set specific parameters to values suitable for many 50 Hz (motor base frequency) applications.
See Parameters whose values after a reset vary by reset type table on page 166 and table on page 168 for a list of parameters that are affected by this reset action and their resultant values.

2 **[60 Hz reset]**: 60 Hz parameter reset
Setting parameter tYP to 2 sets specific parameters to values suitable for many 60 Hz (motor base frequency) applications. See table "Parameters whose values after a reset vary by reset type" on page 166 and table "Parameters whose values after a reset are drive model dependant but do not vary by reset type" on page 167 for a list of parameters that are affected by this reset action and their resultant values.

3 **[Factory set]**: Factory reset
Setting parameter tYP to 3 resets most parameters to their factory settings. See tables listed below for a listing of the values that will be copied into the drive by this factory reset action:
Parameters whose values after a reset do not vary by reset type (on page 162).
Parameters whose values after a reset vary by reset type (on page 166).
Parameters whose values after a reset are drive model dependant but do not vary reset type (on page 167).
Parameters whose values after a reset are drive model and reset type dependant (on page 168).
Parameters whose values do not change if a reset is performed (on page 169).

A factory reset will also clear the detected fault history.

4 **[Trip cleared]**: detected fault history cleared
Setting parameter tYP to 4 clears the detected fault history. As soon as the detected fault history is reset, parameter tYP resumes its default value of 0.

5 **[Cumul time clear]**: Elapsed Motor Run Time Reset
Setting parameter tYP to 5 resets the elapsed motor run time clock. As soon as the elapsed motor run time clock is reset, parameter tYP resumes its default value of 0.

6 **[EtYP fault reset]**: Clear EtYP detected fault
Setting parameter tYP to 6 clears a EtYP detected fault. As soon as the EtYP detected fault is cleared, parameter tYP resumes its default value of 0.

7 **[Save parameters]**: Save user-defined settings
The drive parameter settings can be stored into memory into the drive as a custom parameter set.
Set parameter tYP to 7 to save the current drive parameter settings to memory

8 **[Recall parameters]**: Recalls user-defined settings
The drive parameter settings can be reloaded into the drive as a custom parameter set.
Set parameter tYP to 8 to reload into the drive the parameter settings last saved by setting tYP to 7.

9 **[Elapse time reset]**: Elapsed drive run time reset
Setting parameter tYP to 9 resets the elapsed drive run time clock. As soon as the elapsed motor run time clock is reset, parameter tYP resumes its default value of 0.

Macro Programming (AU4)

The ATV212 drive can be configured for four common control schemes by setting parameter AU4:

Code	Name / Description	Factory setting
AU4	**[Auto set function]** Macro Programming (1)	0

⚠ DANGER

UNINTENDED EQUIPMENT OPERATION
Check that the selected macro configuration is compatible with the wiring diagram used.
Failure to follow these instructions will result in death or serious injury.

0 **[Factory set]**
Command reference: logic inputs (CMOd = 0). See page 77.
Speed reference: analog input VIA = 0–10 V or 0–20 mA (FMOd = 1, F201 = 0). See [Frequency mode sel] (FMOd) page 77 and Analog Input Speed Reference page 106.
F: run forward (F111 = 2). See F Logic Input Function page 90.
R: preset speed 1 (F112 = 6). See R Logic Input Function page 90.
RES: clear detected fault (F113 = 10). See RES Logic Input Function page 90.
Drive ready for operation (F110 = 1). See Active Logic Function 2 page 112.

1 **[Run permissive]**
Command reference: logic inputs (CMOd = 0). See page 77.
Speed reference: analog input VIA = 0–10 V or 0–20 mA (FMOd = 1). See [Frequency mode sel] (FMOd) page 77.
F: run forward (F111 = 2). See F Logic Input Function page 90.
R: run permissive (F112 = 1). See R Logic Input Function page 90.
RES: clear detected fault (F113 = 10). See RES Logic Input Function page 90.

2 **[3-wire]**
Command reference: logic inputs (CMOd = 0). See page 77.
Speed reference: analog input VIA = 0–10 V or 0–20 mA (FMOd = 1). See See [Frequency mode sel] (FMOd) page 77.
F: run forward (F111 = 2). See F Logic Input Function page 90.
R: stop ramp (F112 = 49). See R Logic Input Function page 90.
RES: clear detected fault (F113 = 10). See RES Logic Input Function page 90.

3 **[+/- Speed]**
Command reference: logic inputs (CMOd = 0). See page 77.
Speed reference: +/- Speed (FMOd = 5). See See [Frequency mode sel] (FMOd) page 77
F: run forward (F111 = 2). See F Logic Input Function page 90.
R: + Speed (F112 = 41). See R Logic Input Function page 90.
RES: - Speed (F113 = 42). See RES Logic Input Function page 90.

4 **[4-20 mA speed ref]**
Command reference: logic inputs (CMOd = 0). See page 77.
Speed reference: analog input VIA = 4–20 mA (FMOd = 1, F201 = 20). SeeSee [Frequency mode sel] (FMOd) page 77 and Analog Input Speed Reference page 106.
F: run forward (F111 = 2). See F Logic Input Function page 90.
R: preset speed 1 (F112 = 6). See R Logic Input Function page 90.
RES: clear detected fault (F113 = 10). See RES Logic Input Function page 90.

(1) When programming parameter AU4, the embedded display terminal will display two numbers. The left number is the value last entered into AU4. The right number will be 0. Use the UP/DOWN keys to change the right number to the desired value and press ENT. Entering 0 into AU4 has no effect on the drive. Programming 0 into AU4 will not return the seven parameters to their factory default values.

Parameter Lock

Code	Name / Description	Factory setting
F 7 0 0	**[Parameter lock]**	0
0	**[Unlocked]**: All parameters are unlocked and can be changed. See table on page 37 for the parameters that cannot be changed while the drive is running.	
1	**[Locked]**: Only parameter F 7 0 0 can be changed.	

Display of Submenu AUF (F738)

Code	Name / Description	Factory setting
F 7 3 8	**[Quick menu AUF]**	0
	The setting of this parameter determines whether the A U F submenu, Quick Menu, will be displayed on the HMI (see page 30).	
0	**[AUF displayed]**: AUF parameter displayed	
1	**[AUF hidden]**: AUF parameter hidden	

Motor Control Parameters

5

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Motor Control Mode	66
Other Motor Control Mode Parameters	68
Motor Tuning	70
Auto-tuning	71
Expert parameters	72
Supply Voltage Correction and Motor Voltage Limitation	73
Motor 2 Control Parameters	74

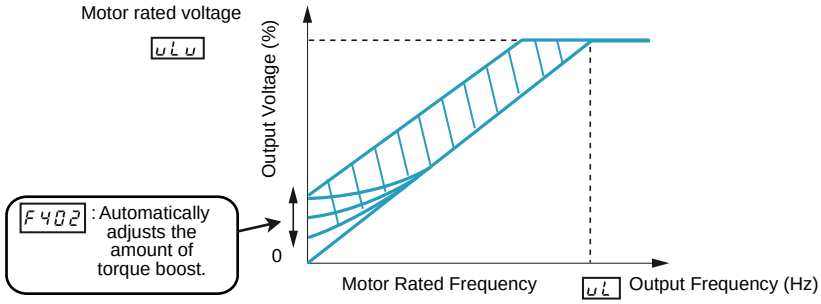
Motor Control Mode

Constant V/Hz Mode with AutomaticTorque Boost ([Mot cont. mode sel.] (PtH) = 2)

Use parameter [Auto Torque Boost] (F402) to adjust the amount of automatic torque boost (see page 74).

If the ATV212 drive and the connected motor have the same power rating, and if the motor has a nominal 1500 rpm rating, no motor auto-tuning is required to use this motor control mode. Otherwise, follow the steps outlined in “Motor Tuning” on page 70.

Due to the feedback circuit used in this mode, it is possible for motor speed to oscillate. If this occurs, select the Constant V/Hz mode ([Mot cont. mode sel.] (PtH) = 0) and adjust torque boost manually with parameter [Motor Voltage Boost] (ubA).



Sensorless Vector Control Mode ([Mot cont. mode sel.] (PtH) = 3)

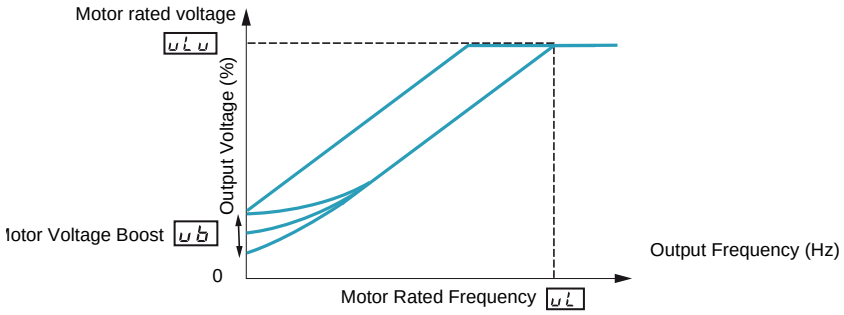
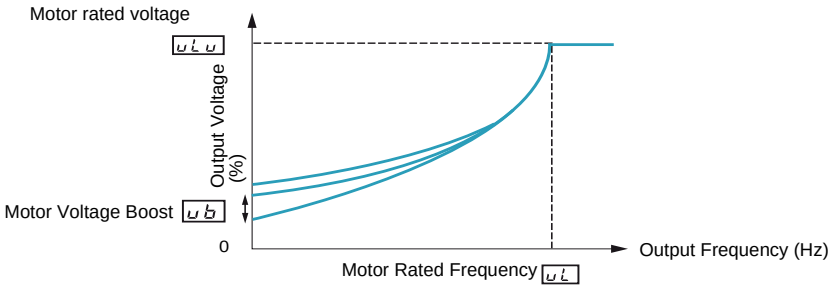
Sensorless vector control mode is only for use in applications where:

- Each motor is powered by its own ATV212 drive (not for multi-motor applications).
- The motor has a power rating equal to that of the ATV212 drive, or no lower than one hp rating less.
- The motor has between two and eight poles (750 to 3000 rpm).

Sensorless vector control will not improve motor control above the motor’s rated speed.

Sensorless vector control is more effective if the motor leads are less than 30 m (100 ft) in length. If motor leads longer than 30 m (100 ft) are required, perform an auto-tuning with the long motor leads included in the circuit. Motor torque may not be maximized at the motor’s rated frequency due to voltage drop in the motor leads.

Connecting a load reactor or a motor filter on the output of the ATV212 drive may reduce the torque generated by the motor in sensorless vector control mode. Auto-tuning will most likely not be possible with a reactor or filter attached to the drive. Manual tuning will be required

Code	Name / Description	Factory setting
PE	**[Mot cont. mode sel.]** Motor control mode	1
0	**[Constant V/Hz]**: Constant V/Hz Use constant V/Hz mode for loads that require the same torque at low speeds as at rated speeds. Low speed torque can be adjusted manually by setting parameter [Motor Voltage Boost] (ub) (see page 68).  	
1	**[Variable Torque]**: Variable torque Use variable torque mode for loads such as centrifugal fans and pumps whose torque requirements increase as a square of the increase in motor speed. Low speed torque can be adjusted manually by setting parameter ub.  	
2	**[Cst V/Hz+Boost]**: Constant V/Hz with automatic torque boost See the diagram on page 66. This mode is similar to the constant V/Hz mode (for loads that require the same torque at low speeds as at rated speeds), except it automatically increases motor voltage and torque to compensate for increases in load.	
3	**[SVC]**: Sensorless vector control See the diagram on page 66. Use sensorless vector control mode to increase torque at motor speeds below 3 Hz or to improve speed regulation (0.5 to 1%).	
4	**[Economy]**: Energy saving In energy savings mode, the ATV212 drive monitors motor loading and automatically modulates the voltage applied to the motor to optimize energy consumption. If the ATV212 drive and the connected motor have the same power rating, and if the motor has a nominal 1500 rpm rating, no motor auto-tuning is required to use this motor control mode. Otherwise, follow the steps outlined in “Motor Tuning” on page 70.	
5	**[Do not use]**: Reserved	
6	**[Do not use]**: Reserved	

Other Motor Control Mode Parameters

The table below lists other parameters that may need to be adjusted, depending on the setting of parameter [Mot cont. mode sel.] (Pt).

Relationship Between [Mot cont. mode sel.] (Pt) setting and Other Motor Parameters

Parameter	Function	Parameter [Mot cont. mode sel.] (Pt) setting				
		0	1	2	3	4
		Constant V/Hz Control	Variable Torque Control	Constant V/Hz with Automatic Torque Boost Control	Sensorless Vector Control	Energy Saving Control
uL (vL)	[Motor rated freq.]	⊗	⊗	⊗	⊗	⊗
uLu	[Motor rated voltage]	⊗	⊗	⊗	⊗	⊗
ub	[Mot Voltage Boost]	⊗	⊗	X	X	X
F170	[Mot 2 rated Freq.]	O	X	X	X	X
F171	[Motor 2 rated Volt]	O	X	X	X	X
F172	[Motor 2 Volt Boost]	O	X	X	X	X
F400	[Auto-tuning drive]	X	X	O	O	O
F401	[Slip Compensation]	X	X	X	O	X
F402	[Auto Torque Boost]	X	X	⊗	⊗	⊗
F415	[Motor rated current]	O	O	⊗	⊗	⊗
F416	[Mot no-load current]	X	X	O	O	O
F417	[Motor rated speed]	O	O	⊗	⊗	⊗
F418	[Frequency loop gain]	X	X	O	O	O
F419	[Freq. loop stability]	X	X	O	O	O
F480	[No load cur. coef]	X	X	O	O	X
F485	[Stall control coef. 1]	O	O	O	O	O
F492	[Stall control coef. 2]	O	O	O	O	O
F494	[Mot. adj coefficient]	O	O	O	O	O
F495	[Motor voltage coef.]	O	O	O	O	O
F496	[PWM adj. coef.]	O	O	O	O	O

X: Not applicable for the [Mot cont. mode sel.] (Pt) setting
⊗: Adjustment of this parameter is required.
O: Adjust this parameter if necessary.

Code	Name / Description	Adjustment range	Factory setting
ub	**[Motor Voltage Boost]**	0.0 to 30.0%	According to drive rating
	Low speed motor torque can be adjusted with parameter ub when parameter [Mot cont. mode sel.] (Pt) (see page 67) is set to 0 (Constant V/Hz) or 1 (Variable Torque). See curves on page 66 for more information. If nuisance overcurrent faults occur during starting, reducing the setting of parameter ub may help.		

(1) See table page 167.

Code	Name / Description	Adjustment range	Factory setting
F 6 0 1	**[Motor Current Limit]**	10 to 110% of the drive's output current rating	110%

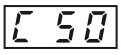
CAUTION

RISK OF DAMAGE TO THE MOTOR AND THE DRIVE
- Check that the motor will withstand this current.
- Check that the profile mission complies with the derating curve given in the installation manual

Failure to follow this instruction can result in equipment damage.

Parameter F 6 0 1 can be adjusted to limit current during motoring or braking.

Display in Current Limit Mode:
When the drive goes into current limit mode, it will:
Adjust the output frequency to limit the flow of motor current (down when motoring, up when braking).

Display the letter C and the output frequency flashing on the embedded software terminal, ex: 

If parameter [Unit value selection] (F 7 0 1) is set to 1 (see page 120), parameter F 6 0 1 will be adjusted in amperes. If parameter F 7 0 1 is set to 0, parameter F 6 0 1 will be adjusted as a percentage of the drive's output rated current as listed on its nameplate.

The setting of parameter [Switch. freq. level] (F 3 0 0) (see page 85) does not change the drive's rated current for the sake of this calculation.

Do not set parameter F 6 0 1 below the no-load current rating of the motor.

Motor Tuning

Tuning the drive to specific motor values will optimize motor performance if parameter [Mot cont. mode sel.] (PtC) (see page 67) is set to:

- 2 (constant V/Hz with automatic boost),
- 3 (sensorless vector control), or
- 4 (energy savings)

At a minimum, manually set parameters uL (vL), uLu (vLv), F415, F416, and F417.

Parameters [Slip Compensation] (F401), [Auto Torque Boost] (F402), [Frequency loop gain] (F418) and [Freq. loop stability] (F419) can be set manually or they can be set automatically using the auto tuning function, parameter [Auto-tuning drive] (F400).

More precise motor control adjustments can be made with parameters F307, F480, F485, F492, and F494 – F496.

Code	Name / Description	Adjustment range	Factory setting
uLu	**[Motor Rated Voltage]**	According to drive rating (1)	According to drive rating (1)
	Set parameter uLu (vLv) to the motor's rated voltage as indicated on the motor nameplate. ATV212●●●M3X: 50 to 330 V. ATV212●●●N4: 50 to 660 V **Note:** Drive output voltage cannot be set to exceed the input line voltage level.		
uL	**[Motor rated freq.]**	25.0 to 200.0 Hz	50.0 Hz
	Set parameter uL (vL) to the motor's rated frequency as indicated on the motor nameplate. **Note:** It is possible to set the drive's various motor control frequencies to 50 Hz by setting [Parameter reset] (tyP) to 1, the 50 Hz reset. For more information, see page 62.		
tHr	**[Motor thermal prot.]** Motor rated current overload setting	10 to 100% of the drive's output current rating	100%
	Set parameter tHr to the motor's rated current as indicated on the motor nameplate for the selected operating voltage. If parameter [Unit value selection] (F701) is set to 1 (see page 120), parameter tHr will be adjusted in amperes. If parameter F701 is set to 0, parameter [Motor thermal prot.] (tHr) will be adjusted in percentage. In this case, divide the motor rated current by the drive rated current (as listed on its nameplate) and set parameter tHr to the resulting percentage. The setting of parameter [Switch. freq. level] (F300) does not change the drive's rated current for the sake of this calculation (see page 85).		
F607	**[Mot overload time]** Motor overload time	10 to 2400 s	300 s
	CAUTION **RISK OF DAMAGE TO THE MOTOR** Check that the motor will withstand this time without overheating **Failure to follow this instruction can result in equipment damage.** Parameter F607 determines how long the drive will support a 150% motor overload before a fault detection occurs.		
F415	**[Motor rated current]**	0.1 to 200.0 A	According to drive rating (1)
	Set parameter F415 to the motor rated current in amperes as indicated on the motor's nameplate.		
F416	**[Mot no-load current]** Motor no-load current	10.0 to 100.0%	According to drive rating (1)
	Set parameter F416 to the ratio of the motor's no load current to its rated current.		
F417	**[Motor rated speed]** Motor rated speed	100.0 to 15000 rpm	According to drive rating (1)
	Set parameter F417 to the motor rated speed in rpm as indicated on the motor's nameplate.		

(1) See table page 167.

Auto-tuning

Before performing an auto-tune, verify that:

- A motor is connected and any load-side disconnect is closed.
- The motor is completely stopped and de-energized.
- The motor should be cool (room temperature).
- There is only one motor connected to the drive.
- All of the motor leads that will be used in the final installation are included in the output circuit during the auto-tuning process.
- Motor leads are no longer than 30 m (100 ft). Motor leads longer than 30 m (100 ft) may result in reduced motor torque and less than optimal motor control.
- No load reactors or filters are included in the motor circuit. Output reactors and filters may cause an auto-tuning detected fault Etn 1 and reduce effectiveness of sensorless vector control.
- The motor is not more than 1 hp size smaller than the drive.
- The motor has at least 2 and not more than 8 poles (750 to 3000 rpm).
- The motor does not have a high slip rating.

Auto tuning is performed upon the first start command after parameter [Auto-tuning drive] (F400) below is set to 1 or 2 and is normally completed within 3 seconds. During the auto-tuning process, the graphic display option displays Atn 1.

During the auto-tuning process voltage is applied to the motor, although it barely rotates and produces very little torque.

During the auto-tuning process, the drive checks for an output phase loss detection regardless of the setting of parameter F605. An output phase loss detection EPHO will abort the auto-tuning process.

If the auto-tuning process is unsuccessful, the drive will display Etn 1. In this event, no results of the aborted auto-tuning 1 will be saved in the drive, and a manual tuning of parameters [Slip Compensation] (F401), [Auto Torque Boost] (F402), [Frequency loop gain] (F418) and [Freq. loop stability] (F419) will be required.

Code	Name / Description	Adjustment range	Factory setting
F400	**[Auto-tuning drive]**	-	0

⚠⚠ DANGER

HAZARD OF ELECTRIC SHOCK OR ARC FLASH
- During auto-tuning, the motor operates at rated current.
- Do not service the motor during auto-tuning.

Failure to follow these instructions will result in death or serious injury.

⚠ WARNING

LOSS OF CONTROL
- It is essential that the following parameters uLu, uL, F415 and F417 are correctly configured before starting auto-tuning.
- When one or more of these parameters have been changed after auto-tuning has been performed, F400 will return 0 and the procedure will have to be repeated.

Failure to follow these instructions can result in death or serious injury.

Auto tuning enable

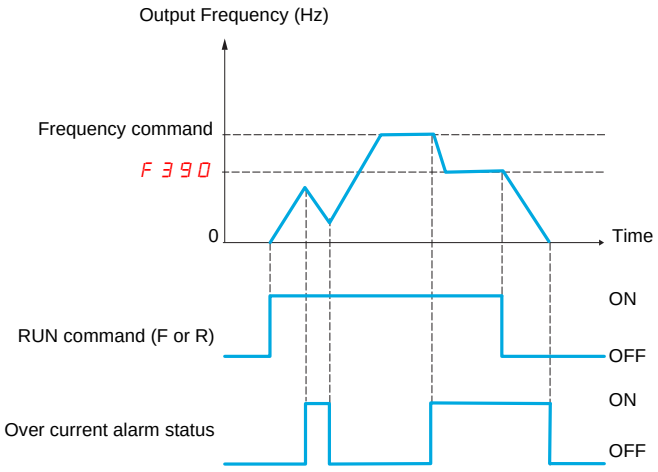
0 **[Disabled]**

1 **[Initialize constant]**: Auto-tuning is performed immediatly if possible. Application of individual settings of Auto Torque Boost [Auto Torque Boost] (F402)

2 **[Complete tune]**: Complete auto tuning.

Parameter F400 is reset to “0” after the auto tuning is performed.

Expert parameters

Code	Name / Description	Adjustment range	Factory setting
F390	**[LL for ov.cur. prev.]** Lower Limit function for Over Current Prevention	0.0 - UL	0.0
	In the present software, motor speed is decreased to 0Hz in case the stall prevention state is continued. When motor speed is lower than F390 during stall prevention, motor speed is kept to F390 to increase motor current. In this situation, motor current is beyond stall prevention level (F601 or F185), therefore over current or over load detected fault may occur in some case. 		
F480	**[No load cur. coef]** Magnetizing current coefficient	100 to 130%	100%
	Use parameter F480 to fine tune motor torque during low-speed operation. To increase motor torque in the low-speed operating range, increase the setting of parameter F480. However, only adjust parameter F480 if an auto tune does not yield sufficient low-speed torque. Increasing the setting of parameter F480 may increase the motor's no-load current during low-speed operation. Do not set this parameter so that the motor's no-load current exceeds its rated operating current.		
F485	**[Stall control coef. 1]** Stall prevention control coefficient 1	10 to 250	100
	Use parameter F485 to adjust the drive's response to large, sudden changes in load when the motor is operated above its rated frequency. If a sudden change in load causes the motor to stall before the drive goes into current limit, gradually reduce the setting of F485.		
F492	**[Stall control coef. 2]** Stall prevention control coefficient 2	50 to 150	100
	Use parameter F492 to adjust the drive's response to a drop in the line supply voltage when the motor is operated above its rated frequency. Such a drop in voltage often causes fluctuations in motor current or vibration in the motor. To reduce these disturbances, set parameter F492 to a value between 80 and 90. Note: Reducing the F492 setting increases the motor running current level.		
F494	**[Mot. adj coefficient]** Motor adjustment coefficient	-	-
	DO NOT ADJUST.		
F495	**[Motor voltage coef.]** Maximum voltage adjustment coefficient	90 to 120%	104%
	Use parameter F495 to limit the drive's maximum output voltage. Increasing this setting increases torque when the motor is operated above its rated frequency, but may also cause motor vibration. Do not increase the value of F495 if motor vibrations occur.		
F496	**[PWM adj. coef.]** Waveform switching adjustment coefficient	0.1 to 14.0 kHz	14.0 kHz
	Adjusting the value of parameter F496 may reduce motor noise and vibration during PWM waveform frequency shifts in the mid-speed operating range.		

Supply Voltage Correction and Motor Voltage Limitation

The setting of parameter F307 determines:

- If the drive's voltage output will be corrected for fluctuations in the line supply voltage, or
- If the drive's voltage output will be limited, despite increases in the line supply voltage.

The drive's output voltage will not exceed the input supply voltage.

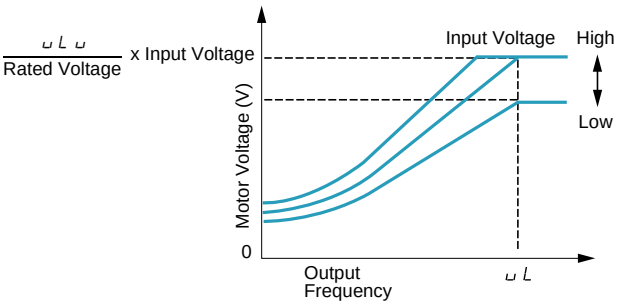
If parameter F307 is set to 0 or 2, no corrections are made in the motor voltage gating process in response to fluctuations in supply voltage. As a result, the V/Hz value of the output waveform to the motor will change in proportion to the input voltage. Conversely, if F307 is set to 1 or 3, the V/Hz value of the output waveform will be held constant, despite changes in the supply voltage level.

If parameter F307 is set to 0 or 1, output motor voltage will be limited to the value set by parameter [Motor rated voltage] (uLu) (see page 70), even if the input supply voltage rises. If F307 is set to 2 or 3, output motor voltage can rise above the level set by uLu if the input supply voltage rises above the motor rated voltage.

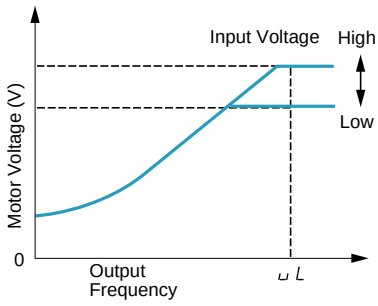
If parameter [Mot cont. mode sel.] (PE) is set to a value of 2, 3, 4, 5, or 6, the supply voltage is corrected, regardless of the setting of parameter F307.

The diagrams below illustrate the impact of each setting of parameter F307.

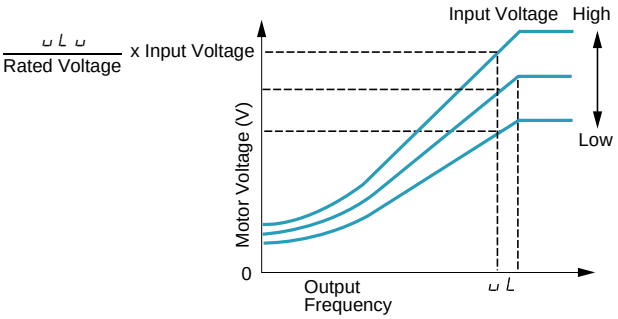
F307 = 0
Supply Voltage uncorrected, Motor Voltage Limited



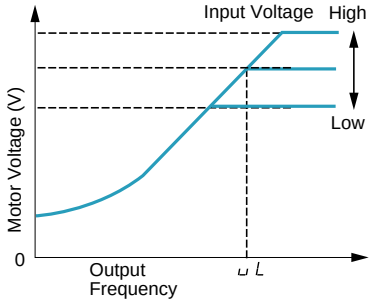
F307 = 1
Supply Voltage corrected,
Motor Voltage Limited



F307 = 2
Supply Voltage uncorrected, Motor Voltage Unlimited



F307 = 3
Supply Voltage corrected,
Motor Voltage Unlimited

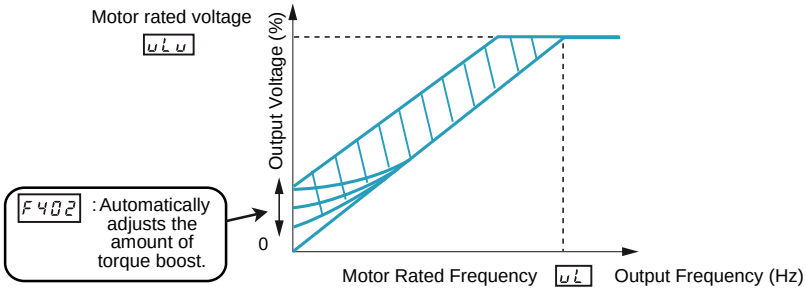


Code	Name / Description	Factory setting
F307	**[Mot volt limitation]** Supply Voltage Correction and Motor Voltage Limitation	3
0	**[Motor volt limit]**: Supply voltage uncorrected – motor voltage limited	
1	**[Line&mot correct.]**: Supply voltage corrected – motor voltage limited	
2	**[No action]**: Supply voltage uncorrected – motor voltage unlimited	
3	**[U Line correction]**: Supply voltage corrected – motor voltage unlimited	

Motor 2 Control Parameters

When logic inputs assigned to functions 39 or 40 are active, parameters F I 7 0 to F I 7 3 and F I 8 5 are the active set of motor control parameters.

When motor 2 control parameters are active, only constant V/Hz Motor Control Mode ([Mot cont. mode sel.] (P t) = 0) is available (see page 67).

Code	Name / Description	Adjustment range	Factory setting
F I 7 0	**[Mot 2 rated Freq.]** Motor 2 rated frequency	25.0 to 200.0 Hz	50.0 Hz
	Set parameter F I 7 0 to the motor's rated frequency as indicated on the motor nameplate. **Note:** It is possible to set the drive's various motor control frequencies to 50 Hz by setting [Parameter reset] (t 4 P) to 1, the 50 Hz reset. For more information, see page 62.		
F I 7 1	**[Motor 2 rated Volt]** Motor 2 rated voltage	According to drive rating (1)	According to drive rating (1)
	Set parameter F I 7 1 to the motor's rated voltage as indicated on the motor nameplate. ATV212●●●M3X: 50 to 330 V. ATV212●●●N4: 50 to 660 V **Note:** Drive output voltage cannot be set to exceed the input line voltage.		
F I 7 2	**[Motor 2 Volt Boost]** Motor 2 voltage boost	0 to 30%	According to drive rating (1)
F I 7 3	**[Motor 2 Overload]** Motor 2 rated current overload setting	10 to 100% of the drive's output current rating	100%
	Set parameter F I 7 3 to the motor's rated current as listed on the motor nameplate for the selected operating voltage.		
F I 8 5	**[Mot. 2 current limit]** Motor 2 current limit	10 to 100% of the drive's output current rating	110%
	CAUTION **RISK OF DAMAGE TO THE MOTOR AND THE DRIVE** ● Check that the motor will withstand this current. ● Check that the profile mission complies with the derating curve given in the installation manual. **Failure to follow this instruction can result in equipment damage.** Adjust parameter F I 8 5 to limit current during motoring or braking. Do not set parameter F I 8 5 below the no-load current rating of the motor; otherwise, the drive will determine that motor braking is taking place and will increase the frequency applied to the motor.		
F 4 0 1	**[Slip Compensation]**	0 to 150%	50%
	Before adjusting parameter F 4 0 1, verify that parameter [Motor rated speed] (F 4 1 7) (see page 70) is set to the rated speed of the motor in rpm. Parameter F 4 0 1 can be used to fine tune the drive's slip compensation feature. Increasing the value of parameter F 4 0 1 increases the drive's compensation of motor slip.		
F 4 0 2	**[Auto Torque Boost]**	0.0 to 30.0%	According to drive rating (1)
	Use parameter F 4 0 2 to adjust the amount of automatic torque boost that is applied.  		

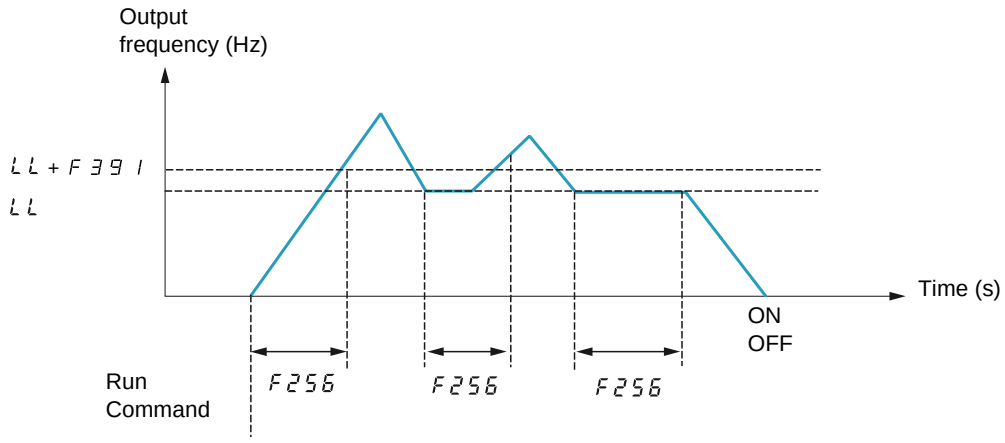
(1) See table page 167.

Code	Name / Description	Adjustment range	Factory setting
F 4 1 8	**[Frequency loop gain]**	1 to 150	40
	Parameters F 4 1 8 and [Freq. loop stability] (F 4 1 9) reduce the speed of the drive's response to a change in speed command. The factory setting of these two parameters assumes that the inertia of the load is three times as large as that of the motor shaft. Adjust these two parameters if the factory setting is not appropriate for the application. Note: It is possible for the drive's output frequency to exceed its upper limit (parameter [Max frequency] (F H)) if the acceleration parameter (A C C or F 5 0 7) is set to its minimum value. Increasing the setting of parameter F 4 1 8 reduces the drive's response time to changes in the speed reference.		
F 4 1 9	**[Freq. loop stability]** Frequency loop stability	1 to 100	20
	Increasing the setting of parameter F 4 1 9 further reduces the drive's response to changes in the speed reference.		

Drive Control Parameters

6

Code	Name / Description		Adjustment range	Factory setting
CMOd	**[Command mode sel]**	Remote Mode Start/Stop Control	-	0
	The setting of parameter CMOd determines the source of start, stop, forward, and reverse operation commands when the drive is in remote mode. The drive needs to be stopped to make changes to parameter CMOd. See diagram on page 46 and description page 50 for more information on the source of the drive's operation commands. 0 **[Logic inputs]**: Control terminal logic inputs 1 **[HMI]**: Graphic display option 2 **[Communication]**: Serial communication			
FMOd	**[Frequency mode sel]**	Remote Mode Primary Speed Reference Source	-	1
	The setting of parameter FMOd determines the source of the drive's speed reference when the drive is in remote mode. The drive needs to be stopped to make changes to parameter FMOd. See diagram on page 46 and description page 50 for more information on the source of the drive's speed reference. 1 **[Ref source VIA]**: VIA 2 **[Ref source VIB]**: VIB 3 **[HMI reference]**: Graphic display option 4 **[Serial com ref.]**: Serial communication 5 **[+/- Speed]**: +/- Speed			
FC	**[Local speed ref.]**	Local Mode Speed Reference	LL - UL	0.0 Hz
	The speed reference set by the UP/DOWN keys in local mode will be stored in parameter FC when the ENT key is pressed. The next time the drive is started in local mode, it will accelerate the motor directly to the speed setpoint memorized by FC.			
Fr	**[Local mot. direction]**	Local Mode Motor Rotation Direction Command	-	0
	0 **[Run FW]**: Run forward only. 1 **[Run rev.]**: Run reverse only. 2 **[Run FW+rev]**: Run forward with reverse selectable. 3 **[Run rev+FW]**: Run reverse with forward selectable. If Fr is set to 2 or 3: The motor direction can be changed in local mode to forward by pressing the UP key while holding the ENT key and to reverse by pressing the DOWN key while holding the ENT key. The new motor direction will be displayed (forward = Fr - F, reverse = Fr - r) before the motor direction is reversed. The motor's last operating direction in local mode will be stored before a power removal or loss detection. When power is restored to the drive, the local mode motor rotation direction will be the same as before the power loss detection. If [Switch rem/Local] F295 (see page 78) is enabled and control is transferred from remote to local mode, the local mode operation will assume the same motor rotation direction as in remote mode, regardless of the setting of Fr.			
F707	**[Loc. speed ref. step]**	Local Mode Speed Reference Step Changes	-	0.0 Hz
	0 **[Disable]**: Disabled (0.00). 1 **[Enable]**: Enabled (0.01 to Maximum Frequency [Max frequency] (FH) in Hz). If parameter F707 is disabled in local mode, the drive's speed reference will change in steps of 0.1 Hz each time the UP or DOWN key is pressed. If parameter F707 is enabled in local mode, the drive's speed reference will change in steps equal to the setting of F707 each time the UP or DOWN key is pressed. Enabling parameter F707 only affects drive operation if parameter [Customized freq val] (F702) is set to 0.00. See page 121. If the display flashes "HI" or "LO", it indicates that repeated usage of the UP or DOWN keys has caused to drive's speed reference to reach either the [Low limit frequency] (LL) (see page 82) or the [Upper limit freq] (UL) (see page 82). This may happen if parameter F707 is set to a value larger than 0.00 Hz.			

Code	Name / Description	Adjustment range	Factory setting
F 7 2 1	**[Loc. mot stop mode]** Local Mode Motor Stop Type	-	0
	The setting of parameter F 7 2 1 determines the type of motor stop that will be executed when then embedded display terminal STOP key is pressed. The RUN and STOP keys needs to be enabled be setting parameter [Run/stop key] (F 7 3 3) (see page 80) to 0 for the motor to stop when the embedded display terminal STOP key is pressed. 0 **[Ramp stop]**: Ramp stop 1 **[Freewheel]**: Freewheel stop		
F 2 9 5	**[Switch rem/Local]** Bumpless transfer from remote to local control	-	1
	If parameter F 2 9 5 is enabled, the speed reference, run and direction commands will be transferred from remote to local mode when the LOC/REM key is pressed. Operation of the drive is not affected by a remote to local control mode transition. If parameter F 2 9 5 is disabled, a remote to local control mode transition will cause the drive to remove power from the motor. A new run command and speed reference will need to be entered in the local mode. Regardless of the setting of parameter F 2 9 5, a local to remote transition will cause the drive to immediately respond to the remote commands present at the moment of the transition. 0 **[No bumpless]**: Bumpless disabled 1 **[Bumpless]:** Bumpless enabled		
F 2 5 6	**[Time limit low spd]**	0.0 to 600 s	0.0 s
	0 **[Disable]**: (0.0) 1 **[Enable]**: (0.01 to 600 seconds) If parameter F 2 5 6 is enabled and if the drive operates continuously at [Low limit frequency] (L L) (see page 82) for a time period equal to the setting of F 2 5 6, the drive will ramp the motor to a stop. While the motor is stopped, "L 5 t P" will flash on the drive embedded display terminal. When the speed reference to the drive exceeds the low speed level L L+F 3 9 1, the drive will accelerate the motor to the new speed reference. If parameter F 2 5 6 is enabled, drive operation at or below the low speed level is also monitored during startup or during reversing of the motor. See diagram below.  		
F 2 0 7	**[Remote spd ref 2]**	-	2
	1 **VIA** 2 **VIB** 3 **HMI** 4 **Communication** 5 **+/- Speed** Parameter [Remote spd ref 2] (F 2 0 7) defines the remote mode secondary speed reference source. The setting of parameter [Auto/man speed ref] (F 2 0 0) (see page 108) determines whether this source is used for the speed reference. If F 2 0 0 is set to 0, a logic input terminal set to function 38 (see page 108) determines if [Remote spd ref 2] (F 2 0 7) identifies the speed reference source. If F 2 0 0 is set to 1, [Remote spd ref 2] (F 2 0 7) is the speed reference source when the drive's output frequency is 1 Hz or below. See diagram on page 46 for more detail.		

Code	Name / Description	Adjustment range	Factory setting
F 6 5 0	**[Forced fire control]**	-	0

⚠ WARNING

LOSS OF CONTROL
The value of F 6 5 0 will impact the direction of the motor.
- Check wiring motor power UVW is correct.
- Verify that the value of F 6 5 0 is convenient for this application.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

0 **[Disable]**
1 **[Enable forward]**
2 **[Enable Reverse]**

To enable Forced fire control, set parameter F 6 5 0 to 1 or 2 and assign a logic input to function 52 or 53 (see page 94). When parameter F 6 5 0 is set to 1 or 2, the embedded display will briefly flash the code F 1 r E.
If parameter F 6 5 0 is set to 1 or 2 and a logic input assigned to function 52 or 53 is activated, the drive will run at the frequency set by parameter [Forced speed freq.] (F 2 9 4) (see below).

Note:
- First set [Motor direction] (F 3 1 1) page 86 to allow forward or reverse operation.
- Push the ENT button for 2 sec to complete the setting.
- See F 6 5 9 for more information of the behavior.

F 6 5 9	**[Forced fire function]**	-	0

0 **[Enable transition]**
When parameter F 6 5 9 is set to 0, the function is enabling on transition 0 -->1 of the logic input. The transition 1 -->0 will not disable the function.

⚠ WARNING

LOSS OF CONTROL
If the Forced fire mode on logic input (function 52) has been enabled and F 6 5 9 is set to 0, the drive will run and only removing power from the drive will stop it.
If the Fire mode on logic input (function 53) has been enabled and F 6 5 9 is set to 0, the drive will run and only removing power from the drive or a fault detection or a pressing on the STOP key on the display terminal will stop the drive.
Check that this value of F 6 5 9 is convenient for the application.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

1 **[Enable level 1]**
When parameter F 6 5 9 is set to 1, if the logic input is set to 0 the function is disabled.
If the logic input is set to 1 the function is enable

⚠ WARNING

RISK OF APPLICATION MALFUNCTION
When F 6 5 9 is set to 1 for safety reason, the forced mode will be inhibited if the logic input is inactivated for any reason (order removed, input broken, wiring contact lost).
- Check that this value of F 6 5 9 is conveniant for the application.
- If you need to continue to run if forced mode in any circonstance, select an other value of F 6 5 9.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

2 **[Enable level 0]**
When parameter F 6 5 9 is set to 2, if the logic input is set to 1 the function is disabled.
If the logic input is set to 0 the function is enable.

⚠ DANGER

UNINTENDED EQUIPMENT OPERATION
When F 6 5 9 is set to 2 for safety reason, the motor will run at Forced speed F 2 9 4 in case of intempestive wire disconnection.
- Check and control the wiring connection periodically.
- Protect the signal conductors against damage that could result in unintentional conductor grounding.

Failure to follow these instructions will result in death or serious injury.

F 2 9 4	**[Forced speed freq.]**	L L - U L	50.0 Hz

The F 2 9 4 parameter is used to set the fixed frequency command for the drive when it is in Forced or Fire mode.

Code	Name / Description	Adjustment range	Factory setting
F 7 3 0	**[Up/down key ref]**		0
	The setting of parameter F 7 3 0 determines whether it is possible to set the drive's speed by means of the embedded display terminal in local mode. 0 **[Enable]** 1 **[Disable]**		
F 7 3 2	**[Loc/rem key]**		0
	Use parameter F 7 3 2 to enable or disable the LOC/REM key on the drive embedded display terminal. If the LOC/REM key is disabled, switching between local and remote mode can be achieved with parameters [Frequency mode sel] (F M O d) and [Command mode sel] (C M O d). See page 77. 0 **[Permitted memo]:** still retained with the power off. 1 **[Prohibited]** 2 **[Permitted no memo]:** cancelled with the power off.		
F 7 3 3	**[Run/stop key]**		0
	0 **[Enable]** 1 **[Disable]** The setting of parameter F 7 3 3 determines whether it is possible to start and stop the drive by the Run/Stop keys located on the drive and graphic display option.		
F 7 3 4	**[Priority stop]**		0
	⚠ WARNING **LOSS OF CONTROL** You are going to disable the stop button located on the drive and graphic display option Do not select 1 unless exterior stopping methods exist. **Failure to follow these instructions can result in death, serious injury, or equipment damage.** The setting of parameter F 7 3 4 determines whether it is possible to stop the drive by the Stop key located on the drive and graphic display option. 0 **[Enable]** 1 **[Disable]**		
F 7 3 5	**[HMI reset button]**		1
	The setting of parameter [HMI reset button] (F 7 3 5) determines whether it is possible to clear a drive detected fault by means of the embedded display terminal STOP key (see page 51 for more detail). 0 **[Enable]** 1 **[Disable]**		

Application Parameters

7

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Skip Frequencies	87
DC Injection Braking Parameters	88

Application parameters

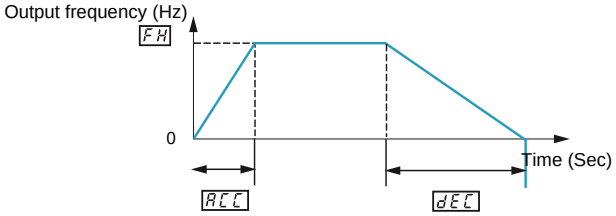
Code	Name / Description	Adjustment range	Factory setting
FH	**[Max frequency]** Maximum Frequency	30.0 Hz to 200.0 Hz	50.0 Hz
	The setting of parameter FH determines the maximum output frequency of the drive. FH limits the setting of parameter [Upper limit freq] (UL) (see page 82), which can be adjusted while the drive is operating. Acceleration and deceleration rates are also affected by the setting of FH, as the definition of [Acceleration time 1] (ACC) or [Deceleration time 1] (dEC) (see page 83) is the time it takes for the drive to ramp the motor up or down between zero speed and the setting of FH. FH can only be adjusted while the drive is stopped. Output frequency (Hz) FH UL 0 Speed Reference 100% Output frequency (Hz) FH LL 0 Speed Reference 100%		
UL	**[Upper limit freq]** High speed	0.5 to **[Max frequency]** (FH) Hz	50.0 Hz
	Parameter UL sets the maximum frequency that can be commanded to the drive by the local or remote speed reference source. The top end of its range is limited by the setting of Maximum frequency [Max frequency] (FH). See diagram above.		
LL	**[Low limit frequency]** Low speed	0.0 to **[Upper limit freq]** (UL) Hz	0.0 Hz
	Parameter LL sets the minimum frequency that can be commanded to the drive by the local or remote speed reference source. See diagram above.		
F240	**[Mot start freq.]** Output Starting Frequency	0.5 to 10.0 Hz	0.5 Hz
	The setting of parameter F240 determines the drive's output frequency at the moment it receives a start command. There is no acceleration time to reach the parameter F240 level. Parameter F240 is typically set for the rated slip frequency of the motor. This allows motor torque to be generated as soon as a start command is given. Adjust parameter F240 when a delay in the motor's response to a start command adversely affects the application. To determine the motor's slip frequency: 1) Subtract the motor's rated speed at full load from it's no-load speed (in rpm). 2) Divide the result by the no-load speed. 3) Multiply this result by the motor's rated frequency in Hz. **Example:** Motor no-load speed = 1500 rpm Motor rated speed at full load = 1450 rpm Motor rated frequency = 50 Hz 1500 rpm – 1450 rpm = 50 rpm 50 rpm / 1500 rpm = 3.33% 50 Hz x 0.0333 = 1.7 Hz (motor slip frequency)		

Code	Name / Description	Adjustment range	Factory setting
ACC	**[Acceleration time 1]**	0.0 to 3200 s	According to drive rating (5)

The setting of parameter ACC determines the slope of the acceleration ramp and the time it takes for the output frequency of the drive to increase from 0 Hz to the setting of [Max frequency] (FH) (see page 82).

If parameter [Auto ramp] (AUI) (see page 85) is set to 1 or 2, the acceleration ramp may be increased or decreased from the setting of ACC, depending on the amount of load on the motor during ramp up.

If two different acceleration rates are needed, see parameter [Acceleration time 2] (F500) on page 83.



dEC	**[Deceleration time 1]**	0.0 to 3200 s	According to drive rating (5)

The setting of parameter dEC determines the slope of the deceleration ramp and the time it takes for the output frequency of the drive to decrease from the setting of [Max frequency] (FH) to 0 Hz.

If parameter [Auto ramp] (AUI) is set to 1, the deceleration ramp may be increased or decreased from the setting of dEC, depending on the amount of load on the motor during ramp down. See diagram above.

If two different deceleration rates are needed, see parameter [Deceleration time 2] (F501) on page 83.

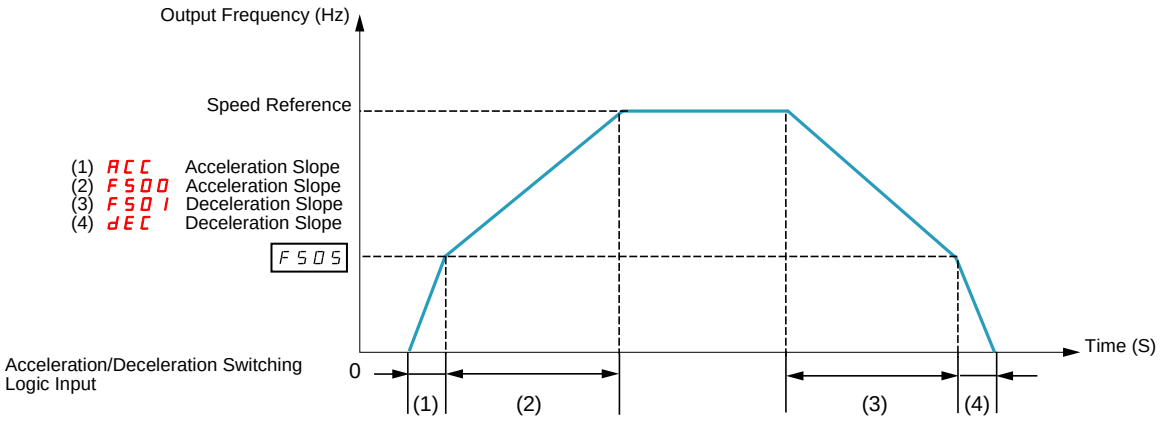
F500	**[Acceleration time 2]**	0.0 to 3200 s	20.0 s

Parameter F500 sets the second acceleration time. Switching between acceleration rates 1 and 2 is accomplished by means of:

Parameter [Ramp switching] (F504) (see page 85),

A particular operating frequency (see parameter [Commut. ramp freq.] (F505) on page 85), or

A logic input assigned to functions 5, 20, 21, 30, 31 – 35, or 40 (see table beginning on page 91)

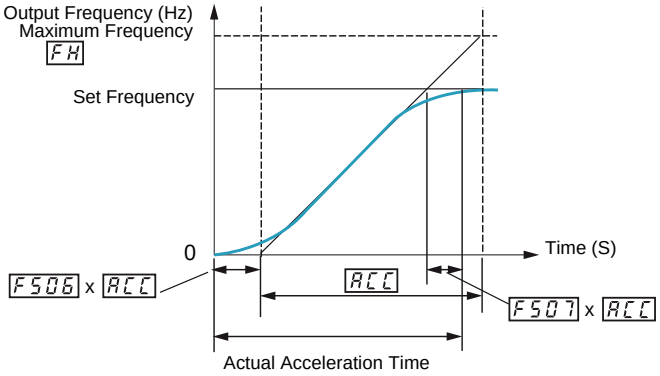
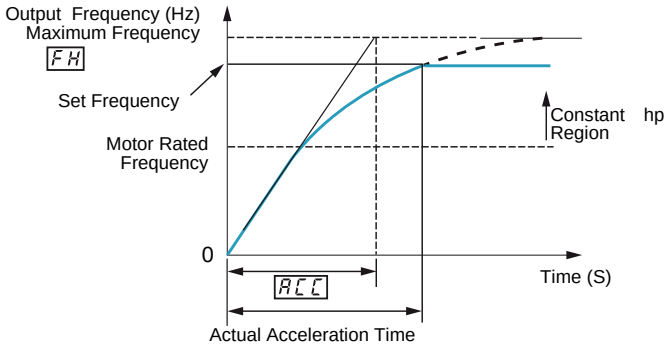


F501	**[Deceleration time 2]**	0.0 to 3200 s	20.0 s

Parameter F501 sets the second deceleration time. Switching between deceleration rates 1 and 2 is accomplished by means of:

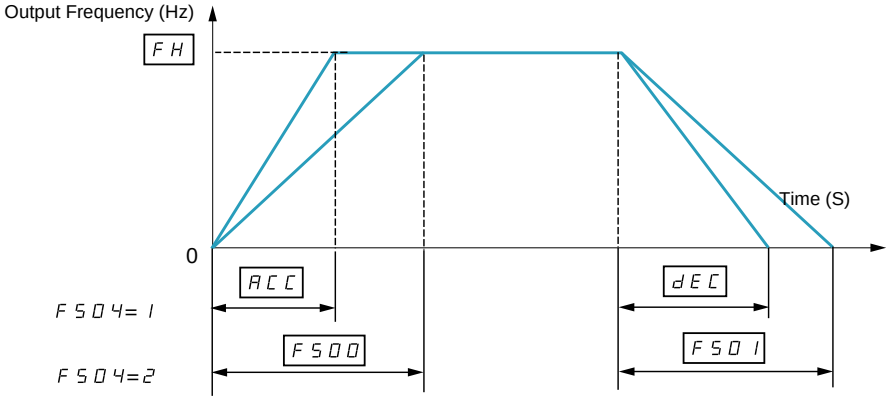
- Parameter [Ramp switching] (F504) (see page 85),
- A particular operating frequency (see parameter [Commut. ramp freq.] (F505) on page 85), or
- A logic input assigned to functions 5, 20, 21, 30, 31 – 35, or 40 (see table beginning on page 91).

(5) See table page 167.

Code	Name / Description	Adjustment range	Factory setting
F 5 0 2	**[Acc/dec 1 pattern]**		0
0	**[Linear]**		
1	**[S-ramp 1]** (see diagram below)		
2	**[S-ramp 2]** (see diagram below for [Acc/dec 2 pattern] (F 5 0 3) parameter).		
	The linear acceleration and deceleration pattern is illustrated in diagram on page 83 and is used in most applications. S-pattern 1 (see diagram below) is for use in applications that need the shortest ramp time possible while minimizing jerks during speed changes. See below for more information about parameters [Acc/Dec S-pat start] (F 5 0 6) and [Acc/Dec S-pat end] (F 5 0 7).		
			
F 5 0 3	**[Acc/dec 2 pattern]**		0
0	**[Linear]**		
1	**[S-ramp 1]** See diagram below.		
2	**[S-ramp 2]** See previous diagram for parameter Acc/Dec Pattern 1 [Acc/dec 1 pattern] (F 5 0 2).		
	S-pattern 2 (diagram below) is for use in high-speed spindle applications where acceleration and deceleration rates need to be reduced as the motor operates above its rated operating frequency—a constant hp region where motor torque is reduced. Use parameter F 5 0 3 to select the second Acc/Dec pattern. Switching between Acc/Dec patterns 1 and 2 is accomplished by means of:		
	Parameter [Ramp switching] (F 5 0 4) (see page 85),		
	A particular operating frequency (see parameter [Commut. ramp freq.] (F 5 0 5) on page 85), or		
	A logic input assigned to functions 5, 20, 21, 30, 31 – 35, or 40 (see table beginning on page 91).		
	For more information on Acc/Dec patterns, see parameter [Acc/dec 1 pattern] (F 5 0 2) above.		
			
F 5 0 6	**[Acc/Dec S-pat start]** Acc/Dec S-pattern lower limit	0 to 50% of acceleration time	10%
	Use parameter F 5 0 6 to adjust the lower portion of S-pattern 1. See diagram on page 85.		
F 5 0 7	**[Acc/Dec S-pat end]** Acc/Dec S-pattern Upper Limit	0 to 50% of acceleration time	10%
	Use parameter F 5 0 7 to adjust the upper portion of the S-pattern 1. See diagram on page 85.		

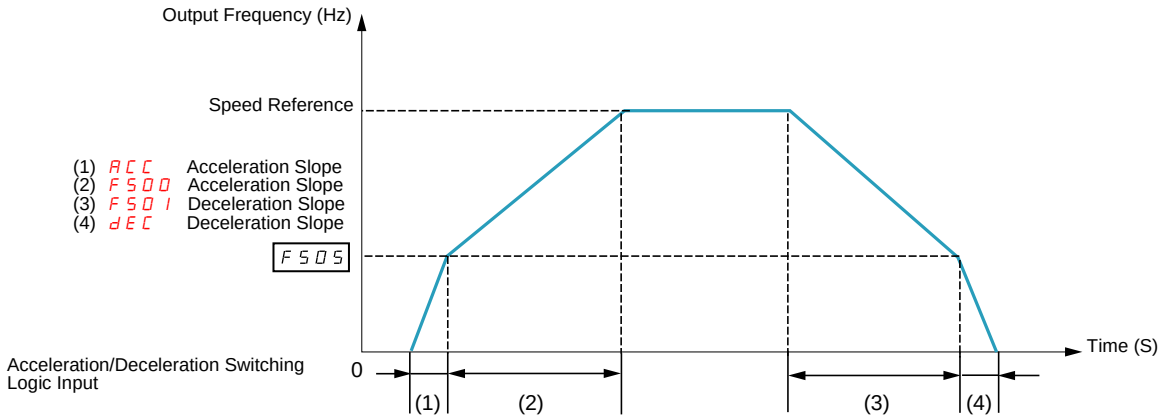
Code	Name / Description		Adjustment range	Factory setting
F 5 0 4	**[Ramp switching]**	Acc/Dec Pattern Selection	-	1

1 **[Ramp 1]**
2 **[Ramp 2]**
Parameter F 5 0 4 determines the Acc/Dec pattern.



F 5 0 5	**[Commut. ramp freq.]**	Acc/Dec pattern switching frequency	0.0 to **[Upper limit freq]** (U L) (Hz)	0.0 Hz

If parameter F 5 0 5 is set to a frequency greater than 0.0, the drive will use Acc/Dec pattern 1 above that frequency and Acc/Dec pattern 2 above.



A U 1	**[Auto ramp]**	Auto ramp adaptation		1

0 **[Disabled]**
1 **[Enable]** - [Acceleration time 1] (A C C) and [Deceleration time 1] (d E C) (see page 83)
2 **[ACC only]** - [Acceleration time 1] (A C C) only

If parameter A U 1 is set to 1 or 2, the drive will monitor its own loading level and optimize the acceleration and deceleration ramps. The acceleration and deceleration (A U 1 = 1 only) rates will be automatically adjusted between 1/8 to 8 times the settings of [Acceleration time 1] (A C C) and [Deceleration time 1] (d E C), depending on the drive's current rating and the load level on the motor. A C C and d E C should be appropriately set for an average load in the application. If the load on the motor increases rapidly during ramp up or ramp down, the auto ramp adaptation feature may not help prevent the drive from experiencing an over-current or overvoltage.

If the application requires a consistent acceleration and deceleration time, set A U 1 to 0, and set A C C and d E C manually as needed. The manual acceleration and deceleration times can still be overridden by the [Motor Current Limit] (F 6 0 1) (see page 69) and [Overvoltage fault] (F 3 0 5) (see page 128) and [Overvoltage level] (F 6 2 6) (see page 128) functions.

F 3 0 0	**[Switch. freq. level]**	Switching Frequency Level	6.0 to 16.0 kHz in 0.1 kHz steps	According to drive rating (1)

Increasing the switching frequency may reduce audible motor noise.
Increasing the switching frequency will increase the heat dissipated by the drive. The capacity of the drive may need to be derated accordingly if the switching frequency is increased. See the derating curves in the ATV212 Installation Manual.

(5) See table page 167.

Code	Name / Description	Adjustment range	Factory setting
F 3 1 1	**[Motor direction]**	-	1
	Use parameter F 3 1 1 to permit only forward or reverse operation. 0 **[Fw & Rev.]** 1 **[Fw only]** 2 **[Rev. only]**		
F 3 1 2	**[Noise reduction]** Switching Frequency Random Mode		0
	Random control of the switching frequency may reduce audible motor noise. Random control of the switching frequency will not be performed if the switching frequency is set above 7.1 kHz, regardless of the setting of F 3 1 2. 0 **[Disable]** 1 **[Enable]**		
F 3 1 6	**[Switch. freq. mode]** Switching frequency control mode		1
	0 **[Fixed]** - ATV212●●●M3X and ATV212●●●N4: switching frequency NOT automatically reduced 1 **[Auto]** - ATV212●●●M3X and ATV212●●●N4: switching frequency automatically reduced 2 **[460 V fixed]** - ATV212●●●N4 (2): switching frequency NOT automatically reduced 3 **[460 V Auto]** - ATV212●●●N4 (2): switching frequency automatically reduced If parameter F 3 1 6 is set to 1 or 3, the switching frequency level will be automatically controlled to help prevent a drive over-heating. If the drive senses an impending overheating, it will reduce the switching frequency, thus reducing heat produced by the controller. As the temperature approaches normal, the switching frequency will return to the level selected by parameter [Switch. freq. level] (F 3 0 0). If F 3 1 6 is set to 1 or 3, motor control performance is optimized if parameter F 3 0 0 is set to 6 kHz or 8 kHz.		

(1) See table page 168.
(2) For 400 V applications with motor leads longer than 30 m (100 ft).

Skip Frequencies

Do not set the skip frequency bands so that they overlap.

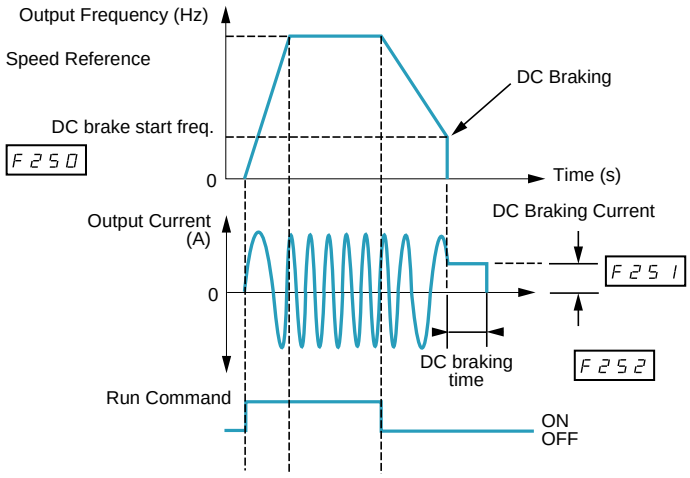
While the drive will not operate within these skip frequency bands during steady state operation, skip frequency bands are ignored by the drive during motor acceleration and deceleration.

Code	Name / Description	Adjustment range	Factory setting
F270	**[Jump frequency 1]** Skip frequency 1 midpoint	0.0 to **[Max frequency]** (FH) Hz	0.0 Hz
F271	**[Jump bandwidth 1]** Skip frequency 1 bandwidth	0.0 to 30.0 Hz	0.0 Hz
F272	**[Jump frequency 2]** Skip frequency 2 midpoint	0.0 to **[Max frequency]** (FH) Hz	0.0 Hz
F273	**[Jump bandwidth 2]** Skip frequency 2 bandwidth	0.0 to 30.0 Hz	0.0 Hz
F274	**[Jump frequency 3]** Skip frequency 3 midpoint	0.0 to **[Max frequency]** (FH) Hz	0.0 Hz
F275	**[Jump bandwidth 3]** Skip frequency 3 bandwidth	0.0 to 30.0 Hz	0.0 Hz

DC Injection Braking Parameters

The drive can inject DC current into the motor to apply braking torque to the load. Parameters [DC brake start freq.] (F 2 5 0), [DC braking current] (F 2 5 1) and [DC braking time] (F 2 5 2) determine the Output Starting Frequency, current level, and braking time.

During DC injection braking, the drive's switching frequency is 6 kHz regardless of the setting of parameter [Switch. freq. level] (F 3 0 0) (see page 85).



Code	Name / Description	Adjustment range	Factory setting
F 2 5 0	**[DC brake start freq.]**	0.0 to **[Max frequency]** (F H) Hz	0.0 Hz

⚠ WARNING

NO HOLDING TORQUE
- DC injection braking does not provide holding torque at zero speed.
- DC injection braking does not work when there is a loss of power or when the drive detects a fault.
- When necessary, use a separate brake to maintain torque levels.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

When stopping the motor, the drive will apply DC injection braking once the output frequency drops below the level set by parameter F 2 5 0.

Code	Name / Description	Adjustment range	Factory setting
F 2 5 1	**[DC braking current]** DC braking current level	0 to 100%	50% (1)

CAUTION

RISK OF DAMAGE TO THE MOTOR
Check that the motor will withstand this current without overheating.
Failure to follow this instruction can result in equipment damage.

Parameter F 2 5 1 sets the level of current applied to the motor during DC injection braking. The displayed value, percent or amperes, is set by parameter [Unit value selection] (F 7 0 1) (see page 120).
During DC injection braking, the drive's overload protection sensitivity increases. The drive automatically lowers the applied DC current to avoid an overload detected fault.

Code	Name / Description	Adjustment range	Factory setting
F 2 5 2	**[DC braking time]**	0.0 to 20.0 s	1.0 s

CAUTION

RISK OF DAMAGE TO THE MOTOR
- Long periods of DC injection braking can cause overheating and damage the motor.
- Protect the motor by avoiding long periods of DC injection braking.

Failure to follow this instruction can result in equipment damage.

Parameter F 2 5 2 determines how long DC injection braking is applied to the motor.

(1) Percentage of the drive's rated current or ampere range. This will vary according to drive power rating.

I/O Control Parameters

8

What's in this Chapter?

This chapter contains the following topics:

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Logic Inputs Functions

See table on page 91 for a complete list of F, R and RES logic inputs assignments

Code	Name / Description	Adjustment range	Factory setting
F I I I	**[LI F selection]** F Logic Input Function	0 to 73	2
	The setting of parameter F I I I determines the control function of logic input terminal F.		
F I I2	**[LI R selection]** R Logic Input Function	0 to 73	6
	The setting of parameter F I I2 determines the control function of logic input terminal R.		
F I I3	**[LI RES selection]** RES Logic Input Function	0 to 73	10
	The setting of parameter F I I3 determines the control function of logic input terminal RES.		
F I09	**[VIA selection]** VIA Input Function (Analog or Logic Selection)	-	0
	⚠ DANGER **UNINTENDED EQUIPMENT OPERATION** Prevent accidental grounding of logic inputs configured for sink logic. Accidental grounding can result in unintended activation of drive functions. Protect the signal conductors against damage that could result in unintentional conductor grounding. **Failure to follow these instructions will result in death or serious injury.**		
0	**[AI]**: Analog input		
1	**[LI sink]**: Logic input - sink (negative logic)		
2	**[LI source]**: Logic input - source (positive logic)		
	The setting of parameter F I09 determines whether control input terminal VIA will serve as an analog input (0-10 Vdc or 0–20 mA) or as a logic input (either sink or source). When configuring VIA as a logic input, be certain to slide switch SW100 on the main control board to the V (voltage) position. When configuring VIA as a logic input using sink (negative) logic, be certain to connect a 4.7 kΩ (1/2 W) resistor between control terminals P24 and VIA. For more information on the use of control input terminal VIA, see ATV212 Installation manual.		
F I I8	**[VIA LI selection]** VIA Logic Input Function	0 to 73	7
	Set first parameter [VIA selection] (F I09) before setting parameter F I I8. The setting of parameter F I I8 determines the control function of logic input terminal VIA. See page 91 for a complete list of VIA logic input assignments.		

Logic inputs F, R, RES, and VIA (if parameter [VIA selection] (F IO 9) is set to 1 or 2) can be set to the functions described in the table below. See table on page 97 for logic input function compatibility.

Function		Action			
No.	**Description**				
0	[No assigned] No function assigned	Logic input disabled			
1	[Run permissive] (see also input function 54, page 95)	OFF: drive motor output disabled, motor coasts to stop ON: drive ready for operation If [Logic Funct 2 active] (F I I0) is not set to I [Run permissive], a logic input should be assigned to the [Run permissive] logic function to enable the motor to start.			
2	[Forward] (2-wire control: input function 49 NOT used) or (3-wire control: input function 49 USED)	**Mode**	**Logic Input Action**		
		2-wire control	OFF: Motor ramps down to a stop ON: Motor runs forward		
		Mode	**Stop Input State**	**Logic Input Action**	
		3-wire control	OFF	OFF: no function ON: no function	
		3-wire control	ON	OFF to ON transition starts the drive, motor runs forward	
3	[Reverse] (2-wire control: input function 49 NOT used) or (3-wire control: input function 49 USED)	**Mode**	**Logic Input Action**		
		2-wire control	OFF: Motor ramps down to a stop ON: Motor runs reverse		
		Mode	**Stop Input State**	**Logic Input Action**	
		3-wire control	OFF	OFF: no function ON: no function	
		3-wire control	ON	OFF to ON transition starts the drive, motor runs in reverse	
5	[Acc / Dec]	OFF: Acceleration/deceleration pattern 1 ON: Acceleration/deceleration pattern 2			
6	[PS1] Preset speed command input 1	Input 3	Input 2	Input 1	Motor Speed
		0	0	0	minimum speed or speed reference per [Frequency mode sel] (F MOd)
		0	0	1	SP 1: preset speed 1
7	[PS2] Preset speed command input 2	0	1	0	SP 2: preset speed 2
		0	1	1	SP 3: preset speed 3
		1	0	0	SP 4: preset speed 4
8	[PS3] Preset speed command input 3	1	0	1	SP 5: preset speed 5
		1	1	0	SP 6: preset speed 6
		1	1	1	SP 7: preset speed 7
10	[Fault reset] (see also input function 55, page 95)	**⚠ DANGER** **UNINTENDED EQUIPMENT OPERATION** This configuration enables to reset the drive. Check this action will not endanger personnel or equipment in any way **Failure to follow these instructions will result in death or serious injury.** ON to OFF transition clears a detected fault (if cause of detected fault has been cleared)			
11	[Ext Fault] (see also input function 45, page 94)	OFF: No external detected fault ON: Motor stops according to method set by parameter [Ext. fault stop Mode] (F 603) Embedded display terminal displays E detected fault, detected fault relay activated			

Function		Action
No.	**Description**	
13	[DC braking]	**⚠ WARNING** **NO HOLDING TORQUE** ● DC injection braking does not provide any holding torque at zero speed. ● DC injection braking does not work when there is a loss of power or when the drive detects a fault. ● Where necessary, use a separate brake to maintain torque levels. **Failure to follow these instructions can result in death, serious injury, or equipment damage.** OFF: No DC braking command ON: DC braking applied to motor, Level and time set by parameters [DC braking current] (F 2 5 1) and [DC braking time] (F 2 5 2)
14	[PID disable]	OFF: PID control permitted ON: PID control prohibited PID control prohibited input terminal function is available to switch PID control and open-loop control. Also Clear PID integral value input terminal function (function 65) is available. **Note:** For software version lower than V1.7IE04, when Clear PID integral value (function 65) and PID Control Prohibited (function 14) are used, it is necessary to set [Command mode sel] (C M O d) to [Logic inputs] (0) Control terminal logic inputs.
15	[Param Edit] Functional only when parameter [Parameter lock] (F 7 0 0) = 1	OFF: Parameters locked (if parameter F 7 0 0 = 1) ON: Programming changes permitted
16	[Run reset]	OFF: drive motor output disabled, motor coasts to stop ON: drive ready for operation ON to OFF transition clears a detected fault (if cause of detected fault has cleared)
20	[FW-RMP2] Combination of forward run command and acceleration/deceleration pattern 2 selection	OFF: Motor stops, ramping down per ACC/dEC pattern 2 ON: Motor runs forward, ramping up per ACC/dEC pattern 2
21	[Rev- RMP2] Combination of reverse run command and acceleration/deceleration pattern 2 selection	OFF: Motor stops, ramping down per ACC/dEC pattern 2 ON: Motor runs in reverse, ramping up per ACC/dEC pattern 2
22	[FW, PS1] Combination of forward run command and preset speed 1 command	OFF: Motor ramps down to a stop ON: Motor runs forward, at speed set by S r 1, preset speed 1
23	[RV, PS1] Combination of reverse run command and preset speed 1 command	OFF: Motor ramps down to a stop ON: Motor runs in reverse, at speed set by S r 1, preset speed 1
24	[FW, PS2] Combination of forward run command and preset speed 2 command	OFF: Motor ramps down to a stop ON: Motor runs forward, at speed set by S r 2, preset speed 2
25	[RV, PS2] Combination of reverse run command and preset speed 2 command	OFF: Motor ramps down to a stop ON: Motor runs in reverse, at speed set by S r 2, preset speed 2
26	[FW, PS3] Combination of forward run command and preset speed 3 command	OFF: Motor ramps down to a stop ON: Motor runs forward, at speed set by S r 3, preset speed 3

Function		Action
No.	**Description**	
27	[RV, PS3] Combination of reverse run command and preset speed 3 command	OFF: Motor ramps down to a stop ON: Motor runs in reverse, at speed set by SP3, preset speed 3
30	[FW-RMP2-SP1] Combination of forward run command, preset speed 1 command, and acceleration/deceleration pattern 2 selection	OFF: Motor stops, ramping down per ACC/dEC pattern 2 ON: Motor runs forward, at speed set by SP1, preset speed 1, ramping up per ACC/dEC pattern 2
31	[Rev-RMP2-SP1] Combination of reverse run command, preset speed 1 command, and acceleration/deceleration pattern 2 selection	OFF: Motor stops, ramping down per ACC/dEC pattern 2 ON: Motor runs in reverse, at speed set by SP1, preset speed 1, ramping up per ACC/dEC pattern 2
32	[FW-RMP2-SP2] Combination of forward run command, preset speed 2 command, and acceleration/deceleration pattern 2 selection	OFF: Motor stops, ramping down per ACC/dEC pattern 2 ON: Motor runs forward, at speed set by SP2, preset speed 2, ramping up per ACC/dEC pattern 2
33	[Rev-RMP2-SP2] Combination of reverse run command, preset speed 2 command, and acceleration/deceleration pattern 2 selection	OFF: Motor stops, ramping down per ACC/dEC pattern 2 ON: Motor runs in reverse, at speed set by SP2, preset speed 2, ramping up per ACC/dEC pattern 2
34	[FW-RMP2-SP3] Combination of forward run command, preset speed 3 command, and acceleration/deceleration pattern 2 selection	OFF: Motor stops, ramping down per ACC/dEC pattern 2 ON: Motor runs forward, at speed set by SP3, preset speed 3, ramping up per ACC/dEC pattern 2
35	[Rev-RMP2-SP3] Combination of reverse run command, preset speed 3 command, and acceleration/deceleration pattern 2 selection	OFF: Motor stops, ramping down per ACC/dEC pattern 2 ON: Motor runs in reverse, at speed set by SP3, preset speed 3, ramping up per ACC/dEC pattern 2
38	[Frequency source] Frequency reference source switching	OFF: drive follows speed reference set by parameter [Frequency mode sel] (FMOd) ON: drive follows speed reference set by parameter [Remote spd ref 2] (F2O7) > (if [Auto/man speed ref] (F2OO) = 1)
39	[Motor switch]	**CAUTION** **RISK OF DAMAGE TO THE MOTOR** ● The motor switching function disables motor thermal protection. ● The use of external overload protection is required when using motor switching. **Failure to follow these instructions can result in death, serious injury, or equipment damage.** OFF: 1st motor V/Hz parameter set active: ([Mot cont. mode sel.] (Pt), [Motor rated freq.] (uL), [Motor rated voltage] (uLu), [Mot Voltage Boost] (ub), [Motor thermal prot.] (tHr)) ON: 2nd motor V/Hz parameter set active: (Pt = 0, F170, F171, F172, F173)

Function		Action
No.	**Description**	
40	[Mot param. switch] Motor control parameter switching V/Hz, current limit, acceleration/deceleration pattern	**CAUTION** **RISK OF DAMAGE TO THE MOTOR** ● The parameter switching function disables motor thermal protection. ● The use of external overload protection is required when using motor switching. **Failure to follow these instructions can result in death, serious injury, or equipment damage.** OFF: 1st motor control parameter set active: ([Mot cont. mode sel.] (PtH), [Motor rated freq.] (uL), [Motor rated voltage] (uLu), [Mot Voltage Boost] (ub), [Motor thermal prot.] (tHr), [Acceleration time 1] (ACC), [Deceleration time 1] (dEC), [Acc/dec 1 pattern] (F502), [Motor Current Limit] (F600 1)) ON: 2nd motor control parameter set active: (PtH = 0, F170, F171, F172, F173, F185, F500, F501, F503)
41	[(+) speed]	OFF: No motor speed increase ON: Motor accelerates
42	[(-) speed]	OFF: No motor speed reduction ON: Motor decelerates
43	[+/- clear]	OFF to ON transition clears frequency level set by +/- speed inputs
44	[+/- SPD, FLT CLR]	OFF to ON transition clears frequency level set by +/- speed inputs ON to OFF transition clears a detected fault (if cause of detected fault has been cleared)
45	[Inv Ext. fault] Inversion of external detected fault signal (see also input function 11, page 91)	OFF: Motor stops according to method set by parameter [Ext. fault stop Mode] (F603) Embedded display terminal displays E detected fault ON: No external detected fault
46	[Ext. Th fault] External overheating input (see also input function 47)	OFF: No external overheating ON: Motor stops, embedded display terminal displays OH2
47	[Inv Ext. Th fault] Inversion of external overheating input (see also input function 46)	OFF: Motor stops, embedded display terminal displays OH2 ON: No external overheating
48	[Forced local]	OFF: No forced local function ON: Control of the drive is forced to mode set by [Frequency mode sel] (FMOd), [Command mode sel] (CMOd), and [Remote spd ref 2] (F207).
49	[3-wire]	OFF: Motor ramps down to a stop ON: drive ready for operation
51	[Reset kWh] Clear accumulated power consumption kWh display	OFF: No function ON: Clears kWh memory
52	[Forced mode]	**⚠ DANGER** LOSS OF PERSONNEL AND EQUIPMENT PROTECTION When F650 is set to 1 or 2 and a logic input set to function "52" is activated, all the drive controller protection will be disable. • Logic input should not be enable on function 52 for typical applications... • Logic input should be enable on function 52 only in extraordinary situations where a thorough risk analysis demonstrates that the presence of adjustable speed drive protection poses a greater risk than personnel injury or equipment damage. **Failure to follow these instructions will result in death or serious injury.** This function enables the "Forced fire" mode. In this mode, all the detected fault will be ignored or if it is a hardware trip, the drive will be reset to try to restart. OFF: No function ON: Motor runs at speed set by F294 **Note:** F650, F659 and F294 must be configured to activate this function.

Function		Action
No.	**Description**	
53	[Fire mode]	This function enables the "Fire" mode OFF: No function ON: Motor runs at speed set by F294 **Note:** F650, F659 and F294 must be configured to activate this function.
54	[Inverse Run permis.] Inversion of run permissive (see also input function 1 page 91)	OFF: drive ready for operation ON: drive motor output disabled, motor coasts to stop This mode allows to have a freewheel stop using a terminal command.
55	[Inv fault reset] Inversion of clear detected fault (see also input function 10 page 91)	**⚠ DANGER** **UNINTENDED EQUIPMENT OPERATION** This configuration enables to reset the drive. Check this action will not endanger personnel or equipment in any way **Failure to follow these instructions will result in death or serious injury.** OFF to ON transition clears a detected fault (if cause of detected fault has been cleared)
56	[Run, FW] Combination of run permissive and run forward command (2-wire control only)	OFF: drive motor output disabled, motor coasts to stop ON: Motor runs forward
57	[Run, RV] Combination of run permissive and run reverse command (2-wire control only)	OFF: drive motor output disabled, motor coasts to stop ON: Motor runs reverse
61	[I limit 1/2] Current limit level selection	OFF: Current limit level 1 [Motor Current Limit] (F601) selected ON: Current limit level 2 [Mot. 2 current limit] (F185) selected
62	[RY on] Holding of RYA-RYC relay output	OFF: Normal real-time relay operation ON: RYA-RYC is held on once activated
64	[Cancel HMI cmd] Cancellation of last graphic display option command	OFF: Last graphic display option command cancelled ON: Last graphic display option command retained
65	[PID integral] Clear PID integral value	OFF: No action ON: PID integral value held at zero
66	[Run-fw-sp1] Combination of run permissive, run forward command, and preset speed 1 command	OFF: drive motor output disabled, motor coasts to stop ON: Motor runs forward at speed set by Sr1, preset speed 1
67	[Run-rev-sp1] Combination of run permissive, run reverse command, and preset speed 1 command	OFF: drive motor output disabled, motor coasts to stop ON: Motor runs reverse at speed set by Sr1, preset speed 1
68	[Run-fw-sp2] Combination of run permissive, run forward command, and preset speed 2 command	OFF: drive motor output disabled, motor coasts to stop ON: Motor runs forward at speed set by Sr2, preset speed 2
69	[Run-rev-sp2] Combination of run permissive, run reverse command, and preset speed 2 command	OFF: drive motor output disabled, motor coasts to stop ON: Motor runs reverse at speed set by Sr2, preset speed 2

Function		Action
No.	**Description**	
70	[Run-fw-sp4] Combination of run permissive, run forward command, and preset speed 4 command	OFF: drive motor output disabled, motor coasts to stop ON: Motor runs forward at speed set by SrH, preset speed 4
71	[Run-rev-sp4] Combination of run permissive, run reverse command, and preset speed 4 command	OFF: drive motor output disabled, motor coasts to stop ON: Motor runs reverse at speed set by SrH, preset speed 4
72	[PID rev] PID error signal reversed	OFF: if FIII = 72 and F terminal is OFF, PI error input = reference - feedback ON: if FIII = 72 and F terminal is ON, PI error input = feedback - reference
73	[Damper feedBack]	OFF: if FIII or FII2 or FII3 is not set to 73 the damper has no effect. ON: if FIII or FII2 or FII3 = 73 the damper is ON. The damper feedback has not effect if not configured to an output.

Logic Input Function Compatibility

O = Compatible

X = Incompatible

+ = Compatible under some conditions

@ = Priority

Function No. / Function		1/54	2	3	5	6-9	10/55	11/45	13	14	15	46/47	48	41-43	49	38	39	40	52/53
1/54	[No assigned] / [Inverse Run permissive]		@	@	@	@	O	O	@	O	O	O	O	O	@	O	O	O	X
2	[Forward]	+		X	O	O	O	X	X	O	O	X	O	O	X	O	O	O	X
3	[Reverse]	+	+		O	O	O	X	X	O	O	X	O	O	X	O	O	O	X
5	[Acc / Dec]	+	O	O		O	O	X	X	O	O	X	O	O	O	O	O	X	O
6~8	[PS1]~[PS3]	+	O	O	O		O	X	X	O	O	X	O	O	O	O	O	O	X
10/55	[Fault reset] / [Inv fault reset]	O	O	O	O	O		X	O	O	O	X	O	O	O	O	O	O	X
11/45	[Ext. fault] / [Inv. Ext. fault]	+	@	@	@	@	@		@	@	O	+	O	@	@	O	O	O	X
13	[DC braking]	+	@	@	@	@	O	X		@	O	X	O	@	@	O	O	O	X
14	[PID disable]	O	O	O	O	O	O	X	X		O	X	O	O	O	O	O	O	X
15	[Param Edit]	O	O	O	O	O	O	O	O	O		O	O	O	O	O	O	O	O
46/47	[Ext. Th fault] / [Inv Ext. Th fault]	@	@	@	@	@	@	+	@	@	O		O	O	@	O	O	O	X
48	[Forced local]	O	O	O	O	O	O	O	O	O	O	O		O	O	O	O	O	X
41-43	[(+) speed] [(-) speed] [+/- clear]	O	O	O	O	O	O	O	O	O	O	O	O		O	O	O	O	X
49	[3-wire]	+	@	@	O	O	O	X	X	O	O	X	O	O		O	O	O	X
38	[Frequency source]	O	O	O	O	O	O	O	O	O	O	O	O	O	O		O	O	X
39	[Motor switch]	O	O	O	O	O	O	O	O	O	O	O	O	O	O	O		X	O
40	[Mot param. switch]	O	O	O	@	O	O	O	O	O	O	O	O	O	O	O	@		O
52/53	[Forced mode] / [Fire mode]	@	@	@	O	@	@	@	@	@	O	@	@	@	@	@	O	O	

The following logic input functions are active, regardless of the [Frequency mode sel] (FMOd) and [Command mode sel] (CMOd) setting.

- (1) Run permissive
- (10) Clear detected fault
- (11) External detected fault

When determining function compatibility using the table above, the function listed horizontally is activated first and the function listed vertically is activated second.

Relay Output Functions

The two relay outputs (FL and RYA-RYC) can be set to the functions described in the table below.

Function No. / Description		Action
0	[Low speed reach] Low speed reached	OFF: output frequency is low speed setting [Low limit frequency] (LL) ON: output frequency is > low speed setting LL
1	[Inv low spd reach] Inversion of low speed reached	OFF: output frequency is > low speed setting [Low limit frequency] (LL) ON: output frequency is low speed setting LL
2	[High speed reach] High speed reached	OFF: output frequency is < high speed setting [Upper limit freq] (UL) ON: output frequency is high speed setting UL
3	[Inv Hi spd reach] Inversion of high speed reached	OFF: output frequency is high speed setting [Upper limit freq] (UL) ON: output frequency is < high speed setting UL
4	[F100 speed reach] F100 speed reached (See page 114 for more details on parameter F100)	OFF: output frequency is < [Freq. 1 reached] (F100) speed setting ON: output frequency is F100 speed setting
5	[Inv F100 sp reach] Inversion of F100 speed reached	OFF: output frequency is [Freq. 1 reached] (F100) speed setting ON: output frequency is < F100 speed setting
6	[Speed reach] Commended speed reached	OFF: output frequency is commanded speed +/- [Freq.2 bandw.] (F102) hysteresis band ON: output frequency is > commanded speed +/- F102 hysteresis band
7	[Inv speed reach] Inversion of commanded speed reached	OFF: output frequency is > commanded speed +/- [Freq.2 bandw.] (F102) hysteresis band ON: output frequency is commanded speed +/- F102 hysteresis band
8	[F101 speed reach] F101 speed reached (See page 114 for more details on parameters F101 and F102.)	OFF: output frequency is [Freq. 2 reached] (F101) speed +/- [Freq.2 bandw.] (F102) hysteresis band ON: output frequency is > F101 speed +/- F102 hysteresis band
9	[Inv F101 sp reach] Inversion of F101 speed reached	OFF: output frequency is > [Freq. 2 reached] (F101) speed +/- [Freq.2 bandw.] (F102) hysteresis band ON: output frequency is F101 speed +/- F102 hysteresis band
10	[Drive fault] Fault relay. The drive is not in a fault state during auto fault reset attempts. See also function 36 page 102.	OFF: No drive detected fault ON: drive detected fault **⚠WARNING** **LOSS OF CONTROL** • When F130, F132, F137 is set to 10, the output will be active when the drive will detect a fault. • The drive status will not be detected if the wiring is damaged for any reason. • Do not select 10 unless you are sure that your signal will be present in any case. **Failure to follow these instructions can result in death, serious injury, or equipment damage.**
11	[No drive fault] Inversion of Drive fault function.	OFF: drive detected fault ON: No drive detected fault
12	[Overload flt] Overtorque fault Overtorque fault detection is active only if parameter F615 = 1. See page 132 for more detail on an overtorque detected fault and parameters F616 and F618.)	OFF: Estimated motor torque has NOT been at [Overtorque level] (F616) level for a time period longer than that set by [Ovtorque det time] (F618) ON: Estimated motor torque has been at F616 level for a time period longer than that set by F618. drive stopped, displaying Ot
13	[Inv overload flt] Inversion of Overload flt function	OFF: Estimated motor torque has been at [Overtorque level] (F616) level for a time period longer than that set by [Ovtorque det time] (F618). drive stopped, displaying Ot ON: Estimated motor torque has NOT been at F616 level for a time period longer than that set by F618

Function No. / Description		Action
14	[Drive running] Run relay	OFF: drive is not powering the motor ON: drive is powering the motor, accelerating, decelerating, at constant speed, or DC braking
15	[Drive no run] Inversion of Drive no run function	OFF: drive is powering the motor, accelerating, decelerating, at constant speed, or DC braking ON: drive is not powering the motor
16	[Motor overload] Motor overload alarm detection is only active if parameter OLN is set to either 0, 1, 4, or 5. See page 135 for more detail on motor overload protection settings.	OFF: motor thermal state is < 50% of motor overload detected fault level ON: motor thermal state is 50% of motor overload detected fault level
17	[Inv mot. overload] Inversion of Motor overload function	OFF: motor thermal state is 50% of motor overload detected fault level ON: motor thermal state is < 50% of motor overload detected fault level
20	[Torque alarm] Overtorque alarm detection is active only if parameter F615 = 0. See page 132 for more detail on the over-torque alarm and parameters [Over-torque level] (F616), [Overtorque band] (F619).	OFF: Estimated motor torque is < 70% of F616 level minus F619 hysteresis band ON: Estimated motor torque is 70% of F616 level
21	[Inv torque alarm] Inversion of Torque alarm function	OFF: Estimated motor torque is 70% of [Overtorque level] (F616) level ON: Estimated motor torque is < 70% of F616 level minus [Overtorque band] (F619) hysteresis band
22	[Gen. alarm] General alarm	OFF: No detected fault condition from the sources listed below exists ON: A detected fault has been issued by one of the following sources: • Overtorque detected fault (output functions 12 and 13) • Motor overload (output functions 16 and 17) • Overtorque detected fault (output functions 20 and 21) • Load detection loss (output functions 24 and 25) • Run time (output functions 42 and 43) • Undervoltage (output functions 54 and 55) • drive in sleep mode (see for more detail on parameter F256) • Power loss (see for more detail on parameter F302) • Overcurrent – motor current limit level (parameter F601) • Overvoltage – DC bus voltage overvoltage stall level (parameter F626) • Drive overheating
23	[Inv gen. alarm] Inversion of General alarm function	OFF: A detected fault has been issued by one of the following sources: • Overtorque detected fault (output functions 12 and 13) • Motor overload (output functions 16 and 17) • Overtorque detection loss (output functions 20 and 21) • Failure of load detection (output functions 24 and 25) • Run time (output functions 42 and 43) • Undervoltage (output functions 54 and 55) • Drive in sleep mode (see for more detail on parameter F256) • Power loss (see for more detail on parameter F302) • Overcurrent – motor current limit level (parameter F601) • Overvoltage – DC bus voltage overvoltage stall level (parameter F626) • drive overheating ON: No alarm condition from the sources listed above exists
24	[Underload detect.] (See page 130 for more detail on parameters F609 – F612 and the underload function.)	OFF: Motor current is greater than F611 level + F609 hysteresis band ON: Motor current is less than F611 level for the time set by F612
25	[Inv underl. det.] Inversion of Underload detect. function	OFF: Motor current is less than F611 level for the time set by F612 ON: Motor current is greater than F611 level + F609 hysteresis band

Function No. / Description		Action
26	[Manu reset flt.] Non-autoresettable detected fault	OFF: None of the detected fault conditions listed below exist ON: One (or more) of the following detected fault conditions exists and has stopped the drive: • E – external detected fault • E - 18 – VIA analog input signal detected fault • E - 19 – main control board CPU communication • E - 20 – excessive torque boost • E - 21 – main control board CPU detected fault 2 • EEP1 – main control board EEPROM detected fault 1 • EEP2 – main control board EEPROM detected fault 2 • EEP3 – main control board EEPROM detected fault 3 • EF2 – ground detected fault • EPHO – output phase detected fault detection • EPH1 – input phase detected fault detection • Err1 – speed reference • Err2 – main control board RAM • Err3 – main control board ROM • Err4 – main control board CPU detected fault 1 • Err5 – serial communication control • Err7 – motor current sensor • Err8 – serial communication network • Err9 – graphic display option communication interruption • Etn1 – auto-tuning • EtyP – drive ratings • OCA – short-circuit detected in drive output inverter stage during motor startup • OCL – short-circuit detected in motor or output wiring during motor startup • OH2 - external overheating • Ot – overtorque • Uc – underload • UP1 - Undervoltage
27	[Inv manu reset flt.] Inversion of Manu reset flt. function	OFF: One (or more) of the following fault conditions exists and has stopped the drive: • E – external detected fault • E - 18 – VIA analog input signal • E - 19 – main control board CPU communication • E - 20 – excessive torque boost • E - 21 – main control board CPU detected fault 2 • EEP1 – main control board EEPROM detected fault 1 • EEP2 – main control board EEPROM detected fault 2 • EEP3 – main control board EEPROM detected fault 3 • EF2 – ground fault • EPHO – output phase loss detection • EPH1 – input phase loss detection • Err1 – speed reference • Err2 – main control board RAM • Err3 – main control board ROM • Err4 – main control board CPU detected fault 1 • Err5 – serial communication control • Err7 – motor current sensor • Err8 – serial communication network • Err9 – graphic display option communication interruption • Etn1 – auto-tuning • EtyP – drive ratings • OCA – short-circuit detected in drive output inverter stage during motor startup • OCL – short-circuit detected in motor or output wiring during motor startup • OH2 - external overheating • Ot – overtorque • Uc – underload • UP1 - Undervoltage ON: None of the detected fault conditions listed above exist

Function No. / Description		Action
28	[Auto-reset fault] Auto-clear detected fault **Note:** Relay activates when maximum number of autoclear set by [Number auto reset] (F 3 0 3) page 124 is reached.	OFF: None of the detected fault conditions listed below exist ON: One (or more) of the following detected fault conditions exists: • F d 1 – damper detected fault 1 (closed damper) • F d 2 – damper detected fault 2 (opened damper) • 0 C 1 – overcurrent during acceleration • 0 C 2 – overcurrent during deceleration • 0 C 3 – overcurrent during constant speed • 0 C 1P – Short circuit or ground detected fault during acceleration • 0 C 2P – Short circuit or ground detected fault during deceleration • 0 C 3P – Short circuit or ground detected fault during constant speed • 0 H – drive overheating • 0 L 1 – drive overload • 0 L 2 – motor overload • 0 P 1 – overvoltage during acceleration • 0 P 2 – overvoltage during deceleration • 0 P 3 – overvoltage during constant speed
29	[Inv auto-reset flt] Inversion of Auto-reset fault function **Note:** Relay deactivates when maximum number of autoclear set by [Number auto reset] (F 3 0 3) page 124 is reached.	OFF: One (or more) of the following detected fault conditions exists: • F d 1 – damper detected fault 1 (closed damper) • F d 2 – damper detected fault 2 (opened damper) • 0 C 1 – overcurrent during acceleration • 0 C 2 – overcurrent during deceleration • 0 C 3 – overcurrent during constant speed • 0 C 1P – Short circuit or ground detected fault during acceleration • 0 C 2P – Short circuit or ground detected fault during deceleration • 0 C 3P – Short circuit or ground detected fault during constant speed • 0 H – drive overheating • 0 L 1 – drive overload • 0 L 2 – motor overload • 0 P 1 – overvoltage during acceleration • 0 P 2 – overvoltage during deceleration • 0 P 3 – overvoltage during constant speed ON: None of the detected fault conditions listed above exist
30	[Drive rdy 1] drive ready condition 1	OFF: drive not ready for operation ON: drive ready for operation (ready includes active run permissive and active run command)
31	[Inv drive rdy 1] Inversion of Drive rdy 1 function	OFF: drive ready for operation (ready includes active run permissive and active run command) ON: drive not ready for operation
32	[Drive rdy 2] drive ready condition 2	OFF: drive not ready for operation ON: drive ready for operation (ready does not include active run permissive or active run command)
33	[Inv drive rdy 2] Inversion of Drive rdy 2 function	OFF: drive ready for operation (ready does not include active run permissive or active run command) ON: drive not ready for operation
34	[VIB ref source] VIB input reference source	OFF: analog input terminal VIB is NOT the active speed reference source ON: VIB is the active speed reference source
35	[Inv VIB ref source] Inversion of VIB ref source function	OFF: analog input terminal VIB is the active speed reference source ON: VIB is NOT the active speed reference source

Function No. / Description		Action
36	[Fault relay] (The drive is not in a fault state during auto clear detected fault attempts. See also function 10 page 98)	**⚠WARNING** **LOSS OF CONTROL** ● When F I30, F I32, F I37 is set to 36, the output will be active when the drive will detect a fault. ● The drive status will not be detected if the wiring is damaged for any reason. ● Do not select 36 unless you are sure that your signal will be present in any case. **Failure to follow these instructions can result in death, serious injury, or equipment damage.** OFF: No drive detected fault ON: drive detected fault. Relay activates when a clearable fault occurs and the drive attempts to restart. Relay deactivates when drive is restarting.
37	[Inv fault relay] Inversion of Fault relay function 36	OFF: drive detected fault ON: No drive detected fault Relay deactivates when a clearable fault occurs and the drive attempts to restart. Relay activates when drive is restarting.
38	[Ser. data relay FL] Serial communication data	OFF: Serial communication word FA50 bit 0 = 0 ON: Serial communication word FA50 bit 0 = 1
39	[Inv ser. dat rel. FL] Inversion of ser. dat rel. FL function	OFF: Serial communication word FA50 bit 0 = 1 ON: Serial communication word FA50 bit 0 = 0
40	[Ser. data relay RY] Serial communication data	OFF: Serial communication word FA50 bit 1 = 0 ON: Serial communication word FA50 bit 1 = 1
41	[Inv ser. dat rel RY] Inversion of ser. dat rel. RY function	OFF: Serial communication word FA50 bit 1 = 1 ON: Serial communication word FA50 bit 1 = 0
42	[Drive run time al] Drive operational run time alarm (see page 120 for more detail on parameter F621).	OFF: Run time is < F621 time setting ON: Run time is F621 time setting
43	[Inv.drive run time al] Inversion of Drive run time al function	OFF: Run time is F621 time setting ON: Run time is < F621 time setting
44	[Drive serv. alarm] Drive service alarm (see page 133 for more detail on parameter F634).	OFF: drive maintenance detected fault not active ON: drive maintenance detected fault active
45	[Inv. drive serv. alarm] Inversion of Drive serv. alarm function	OFF: drive maintenance detected fault active ON: drive maintenance detected fault not active
48	[LI F state] Logic input F state	OFF: Logic input F is not active ON: Logic input F is active
49	[Inv. LI F state] Inversion of LI F state function	OFF: Logic input F is active ON: Logic input F is not active
50	[LI R state] Logic input R state	OFF: Logic input R is not active ON: Logic input R is active
51	[Inv. LI R state] Inversion of LI R state function	OFF: Logic input R is active ON: Logic input R is not active
52	[Speed ref = VIA] Drive speed reference equals VIA signal	OFF: Speed reference from the source identified by [Frequency mode sel] (FMOd) or the source identified by [Remote spd ref 2] (F207) ≠ VIA signal ON: Speed reference from the source identified by FMOd or the source identified by F207 = VIA signal
53	[Inv. speed ref = VIA] Inversion of Speed ref = VIA function	OFF: Speed reference from the source identified by [Frequency mode sel] (FMOd) or the source identified by [Remote spd ref 2] (F207) = VIA signal ON: Speed reference from the source identified by FMOd or the source identified by F207 ≠ VIA signal

Function No. / Description		Action
54	[Undervolt. alarm] Undervoltage alarm	OFF: Undervoltage detected fault is not active ON: Undervoltage detected fault is active
55	[Inv. undervolt. alarm] Inversion of Undervolt. al. function	OFF: Undervoltage detected fault is active ON: Undervoltage detected fault is not active
56	[Loc / remote] Local/remote switching	OFF: drive is in remote mode ON: drive is in local mode
57	[Inv. loc / remote] Inversion of Loc / remote function	OFF: drive is in local mode ON: drive is in remote mode
58	[PTC alarm] PTC thermal alarm	OFF: Motor temperature as indicated by PTC thermal probes is < 60% of the detected fault level ON: Motor temperature as indicated by PTC thermal probes is 60% of the detected fault level
59	[Inv. PTC alarm] Inversion of PTC alarm function	OFF: Motor temperature as indicated by PTC thermal probes is 60% of the detected fault level ON: Motor temperature as indicated by PTC thermal probes is < 60% of the detected fault level
60	[Speed ref = VIB] Drive speed reference equals VIB signal	OFF: Speed reference from the source identified by [Frequency mode sel] (FMOd) or the source identified [Remote spd ref 2] (F207) ≠ VIB signal ON: Speed reference from source identified by FMOd or the source identified F207 = VIB signal
61	[Inv. speed ref = VIB] Inversion of Speed ref = VIB function	OFF: Speed reference from source identified by [Frequency mode sel] (FMOd) or the source identified [Remote spd ref 2] (F207) = VIB signal ON: Speed reference from the source identified by FMOd or the source identified F207 ≠ VIB signal
62	[VIA detection] Analog VIA detection	ON: The value of VIA is equal to or higher than F160 + F161 OFF: The value of VIA is equal to or lower than F160 - F161
63	[Inv. VIA detection] Inversion of VIA detection function	ON: The value of VIA is equal to or lower than F160 - F161 OFF: The value of VIA is equal to or higher than F160 + F161
64	[VIB detection] Analog VIB detection	ON: The value of VIB is equal to or higher than F162 + F163 OFF: The value of VIB is equal to or lower than F162 - F163
65	[Inv. VIB detection] Inversion of VIB detection function	ON: The value of VIB is equal to or lower than F162 - F163 OFF: The value of VIB is equal to or higher than F162 + F163
66	[Freq. reach hyst] Set frequency attainment signal with hysteresis	ON: The ouptput frequency is equal to or higher than F101 + F102 OFF: The ouptput frequency is equal to or lower than F101 - F102 (See page 114 for more detail on parameters F101 and F102.)
67	[Inv. freq. reach hyst] Inversion of Freq. reach hyst function	ON: The ouptput frequency is equal to or lower than F101 - F102 OFF: The ouptput frequency is equal to or higher than F101 + F102 (See page 114 for more detail on parameters F101 and F102.)
68	[Damper] Damper control	ON: The damper is ON. OFF: The damper is OFF (see page 116)
69	[Inv. damper] Inversion of Damper function	ON: The damper is OFF. OFF: The damper is ON (see page 116)
254	[Relay OFF] Relay output is OFF	OFF
255	[Relay ON] Relay output is ON	ON

Analog Input Functions

Two analog inputs are supplied with the ATV212 drive. The terminals are designated VIA and VIB.

Analog Input VIA

- VIA can accept the following signal types:
  - Voltage (V): 0–10 V, voltage or potentiometer input
  - Current (I): 0–20 mA or 4–20 mA

  The signal type (V or I) is selected by setting SW100 on the main control board.
  For information on wiring, consult the ATV212 Installation manual.
- The slope and bias of the input signal are adjusted with parameters F201–F204 and F470–F471. For more information, see page 106.
- VIA is configured as the speed reference input in the following macro-configurations:
  - Run permissive
  - 3-wire
  - 4-20 mA.
- Relay output functions 34 and 35 can signal when VIA is being used as the speed reference source. For more information, see table on page 101 and consult “I/O Control Parameters” on page 90.
- Relay output functions 52 and 53 can be used to signal the results of a comparison between the signal at VIA and the speed reference commanded by [Frequency mode sel] (FMOd) or [Remote spd ref 2] (F207). This function can also be used to send out a signal indicating whether the amount of processing and the amount of feedback agree with each other. For more information, see table on page 98. Also, consult “I/O Control Parameters” on page 90 and review information about parameter F167 on page 115.
- The drive can enter a detected fault state if the VIA signal drops below a specified level for more than 300 mS. For more information, see parameter F633 on page 130 and code E-18 on page 150.
- VIA can serve as an analog or a logic input, depending on setting of parameter F109 (set to 0 for analog input). Analog input is the factory setting. See page 90 for more information about parameter F109.

Analog Input VIB

- VIB can accept the following signal types:
- Voltage (V): 0–10V, voltage or potentiometer input
- PTC motor thermal sensor input. For more information, see parameters F645 and F646 on page 111.
- Adjust the slope and bias of the input signal with parameters F210 - F213 and F472 - F473. For more information, see page 106.
- Relay output functions 52 and 53 can signal when VIA is being used as the speed reference source. For more information, see table on page 102 and consult “I/O Control Parameters” on page 90.
- Relay output functions 60 and 61 can be used to signal the results of a comparison between the signal at VIB and the speed reference commanded by [Frequency mode sel] (FMOd) or [Remote spd ref 2] (F207). This function can also be used to send out a signal indicating whether the amount of processing and the amount of feedback agree with each other. For more information, see table on page 98. Also, consult “I/O Control Parameters” on page 90 and review information about parameter F167 on page 115.

General

- The selection of VIA or VIB as the speed reference input in remote mode is made through parameters [Frequency mode sel] (FMOd) and [Remote spd ref 2] (F207). FMOd is the primary speed reference source, while F207 is the secondary source. Switching between the two is determined by the setting of parameter [Auto/man speed ref] F200. For more information, see page 108.
- Analog output terminal FM can be configured to provide a signal in proportion to the VIA or VIB signal levels. See parameter FMSL, selections 13 and 14, on page 108.
- When PID control is enabled, VIA or VIB can serve as the setpoint input. Either VIA or VIB needs to be selected as the feedback input. See page 110 for more information on parameter F360 and PID control.
- Information can be transferred between the serial communication network and the analog inputs via read and write functions F810, F811, and F875-F879. For more information, see pages 140 to 141.

Analog Output Functions

One analog output is supplied with the ATV212 drive. The terminal is designated FM.

FM is a multifunctional programmable analog output supplying an output frequency signal as the factory default.

The FM terminal can output a voltage or current signal.

- When switch SW101 is set to V (voltage), FM outputs a 0–10 Vdc signal at 1 mA.
- When switch SW101 is set to I (current), FM outputs a 0–20 mA signal up to 24 Vdc. For detail on proper wiring, consult the ATV212 Installation manual.

The drive value represented by the FM analog output signal is determined by the setting of parameter [AO funct. selection] (FMSL) (see page 108).

Calibrating the FM signal output to provide full scale deflection on an analog meter is achieved by adjusting parameter [AO scaling] (FM) (see page 108).

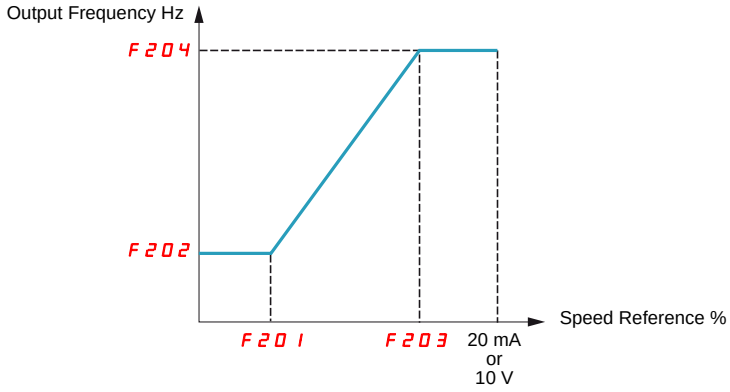
The slope and bias of the FM analog output signal can be adjusted using parameters F691 and F692. For more information, see page 109.

Analog Input Adjustments

Analog Input Speed Reference and Output Frequency

Do not set the same frequency values for both output frequency levels 1 and 2. This will cause an Err 1 detected fault.

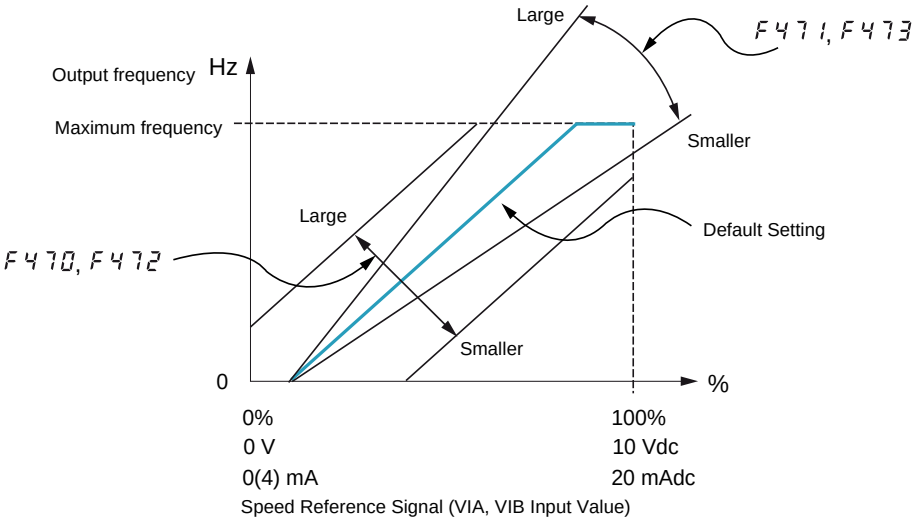
When using a 4–20 mA signal, set speed reference level 1 value to 20% (4 ÷ 20 = 20%).



A further refinement of the bias and slope of the analog input signals can be made with parameters F470 – F473.

Code	Name / Description		Adjustment range	Factory setting
F201	[VIA ref point 1]	VIA speed reference level 1	0 to 100%	0%
F202	[VIA freq. point 1]	VIA output frequency level 1	0.0 to 200.0 Hz	0.0 Hz
F203	[VIA ref point 2]	VIA speed reference level 2	0 to 100%	100%
F204	[VIA freq. point 2]	VIA output frequency level 2	0.0 to 200.0 Hz	50.0 Hz
F160	[VIA rel thresh. logic]	Threshold logic for relay link to VIA	0 to 100%	0%
F161	[VIA threshold hyst.]	Hysteresis threshold for logic relay link to VIA	0 to 20%	3%
F210	[VIB ref. point 1]	VIB speed reference level 1	0 to 100%	0%
F211	[VIB freq. point 1]	VIB output frequency level 1	0.0 to 200.0 Hz	0.0 Hz
F212	[VIB ref. point 2]	VIB speed reference level 2	0 to 100%	100%
F213	[VIB freq. point 2]	VIB output frequency level 2	0.0 to 200.0 Hz	50.0 Hz
F162	[VIB rel thresh. logic]	Threshold logic for relay link to VIB	0 to 100%	0%
F163	[VIB threshold hyst.]	Hysteresis threshold for logic relay link to VIB	0 to 20%	3%

Code	Name / Description		Adjustment range	Factory setting
F 4 7 0	**[VIA bias]**	VIA analog input bias	0 to 255	128
	⚠ DANGER UNINTENDED EQUIPMENT OPERATION If the input bias level is set too high, the drive will start the motor without a signal present at VIA or VIB. **Failure to follow these instructions will result in death or serious injury.**			
F 4 7 1	**[VIA gain]**	VIA analog input gain	0 to 255	148
F 4 7 2	**[VIB bias]**	VIB analog input bias	0 to 255	128
	⚠ DANGER UNINTENDED EQUIPMENT OPERATION If the input bias level is set too high, the drive will start the motor without a signal present at VIA or VIB. **Failure to follow these instructions will result in death or serious injury.**			
F 4 7 3	**[VIB gain]**	VIB analog input gain	0 to 255	148



Parameters [VIA bias] (F 4 7 0) and [VIB bias] (F 4 7 2) are factory set so that a minimal signal needs to be applied to VIA or VIB before the drive starts the motor.

- To increase the signal level required to start the motor, decrease the input bias level.
- To reduce the signal level required to start the motor, increase the input bias level.

⚠ DANGER

UNINTENDED EQUIPMENT OPERATION
If the input bias level is set too high, the drive will start the motor without a signal present at VIA or VIB.
Failure to follow these instructions will result in death or serious injury.

Parameters [VIA gain] (F 4 7 1) and [VIB gain] (F 4 7 3) are factory set so that the drive output reaches rated voltage and frequency just before the signal to VIA or VIB reaches its maximum level.

- To decrease the signal level required before the drive output reaches rated voltage and frequency, increase the input gain level.
- To increase the signal level required before the drive output reaches rated voltage and frequency, decrease the input gain level.

Note: If the input gain level is set too low, the drive output may never reach rated voltage and frequency.

Code	Name / Description		Factory setting
F200	**[Auto/man speed ref]**	Auto/Manual Speed Reference Switching	0

0 **[Enable]**
1 **[Disable]**
Switching between two speed reference sources by means of a logic input is enabled if parameter F200 is set to 0.
To use this function, you need to assign a logic input to function 38, Auto/Man speed ref.

When the assigned logic input is off, the drive will follow the speed reference source defined by parameter [Frequency mode sel] (FMOd) (see page 77).
When the assigned logic input is on, the drive will follow the speed reference source defined by parameter [Remote spd ref 2] (F207) (see page 78).
When parameter F200 is set to 1, the drive will follow the FMOd speed reference source when it is operating above 1 Hz. Below 1 Hz, it will follow the F207 speed reference source.

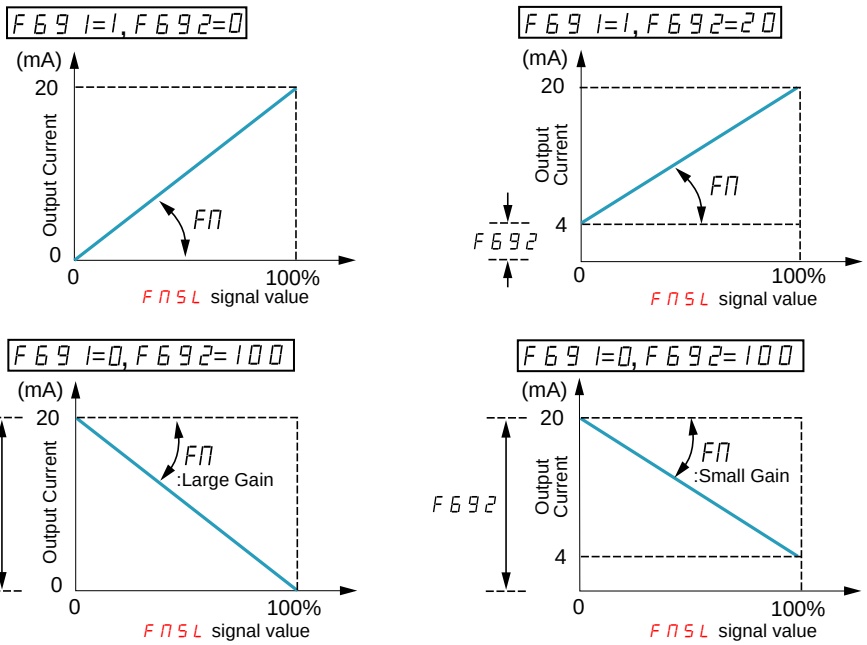
Code	Name / Description		Factory setting
FM5L	**[AO funct. selection]**	Analog Output Function Selection	0

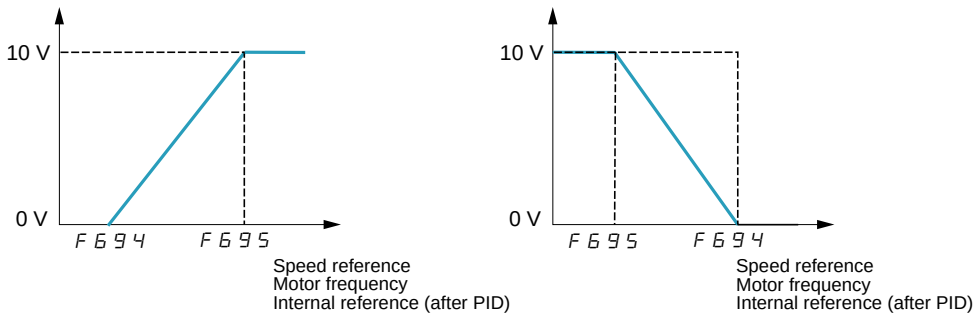
Value	Function	Maximum Signal
0	**[Motor frequency]**: Output frequency	**[Max frequency]** (FH)
1	**[Motor current]**: Output current	150 % of **[Motor current]**
2	**[Speed ref]**: Speed reference	**[Max frequency]** (FH)
3	**[DC bus U]**: DC bus voltage	150 % of **[DC bus U]**
4	**[Motor U]**: Output motor voltage	150 % of **[Motor U]**
5	**[Input power]**: Input power	185 % of **[Input power]**
6	**[Output power]**: Output power	185 % of **[Output power]**
7	**[motor torque]**: Estimated motor torque	250 % of rated motor torque
8	**[Torque I]**: Motor torque current	Current at 250 % of rated motor torque
9	**[Motor thermal]**: Motor thermal state	100 % of motor's rating
10	**[Drive thermal]**: drive thermal state	100 %
11	**[Do not use]**: DO NOT USE	-
12	**[Internal reference]**: Internal speed reference (after PID)	**[Max frequency]** (FH)
13	**[VIA]**: VIA input value	Maximum input value
14	**[VIB]**: VIB input value	Maximum input value
15	**[Fixed 100%]**: Fixed output – 100% signal (Selection 1 – output current)	-
16	**[Fixed 50%]**: Fixed output – 50% signal (Selection 1 – output current)	-
17	**[Fixed 100%]**: Fixed output – 100% signal (Selections 0, 2, 3, 4, 5, 6, 7, 8, 9,10, 12, 13, 14, 18)	-
18	**[Com data]**: Serial communication data	FAS1 = 1000
19	**[Do not use]**: DO NOT USE	-

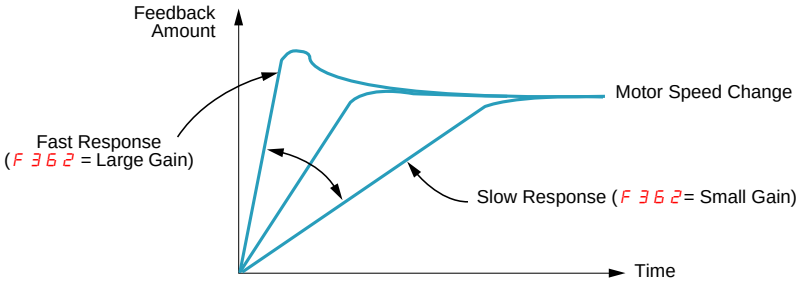
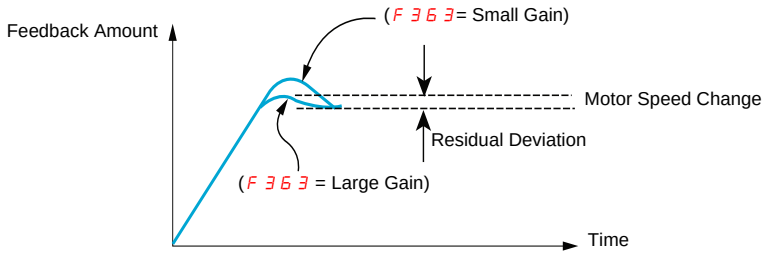
Code	Name / Description		Factory setting
FM	**[AO scaling]**	Analog Output Scaling	-

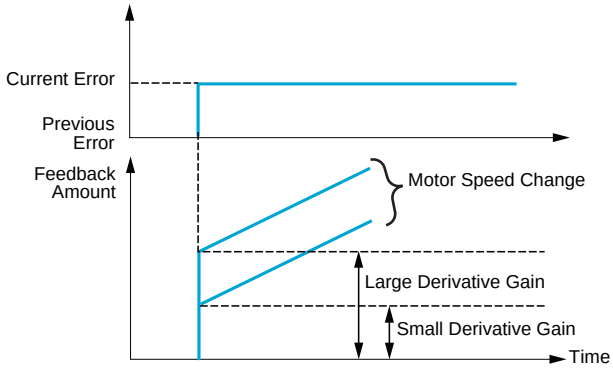
Parameter FM is used to match the FM terminal output signal with the input requirements of the attached panel meter by adjusting the slope and bias of the analog output signal. Before adjusting FM, set [AO funct. selection] (FM5L) to either 15 or 17. As you adjust the value of FM, monitor the display on the attached panel meter. When the meter display reaches 100%, press the ENT key on the drive embedded display terminal. The drive will flash between FM and the adjusted value, indicating that the adjustment has been saved.

Code	Name / Description		Adjustment range	Factory setting
F691	**[AO slope]**	Analog Output Slope	-	1
0	**[Negative slope]**			
1	**[Positive slope]**			
F692	**[Analog output bias]**		0 to 100%	0%
	Refer to the diagram below for examples of adjusting parameters [AO scaling] (FN), [AO slope] (F691), and F692.			
F694	**[Freq. for AO = 0V]**	Low frequency when analog output equal 0 V	0 Hz to [Max frequency] (FH) Hz	0 Hz
	Refer to the diagram below for adjusting parameters F694, and [Freq. for AO = 10V] (F695).			
F695	**[Freq. for AO = 10V]**	High frequency when analog output equal 10 V	0 Hz to [Max frequency] (FH) Hz	0 Hz
	Refer to the diagram above for adjusting parameters [Freq. for AO = 0V] (F694), and F695.			
F130	**[RY Relay Function 1]**	RYA-RYC Relay Function	0 to 69, 254, 255	4
	For a complete description of the various functions assignable to the RYA-RYC relay, see page 98. The RYA-RYC relay can have a secondary assignment with programmed selection logic. See parameters [RY Relay Function 2] (F137) and [RY logic select.] (F139) on page 113 for more detail.			
F146	**[RY delay]**	Delay for RYA-RYC Relay	0.0 to 60.0 s	0.0 s
	This parameter introduce a delay on RYA-RYC output signal relay.			
F132	**[FL Relay Function]**	Function for FL Relay	0 to 69, 254, 255	11
	For a complete description of the various functions assignable to the FL relay, see page 98.			





Code	Name / Description		Adjustment range	Factory setting
F 147	**[FL Relay delay]**	Delay for FL Relay	0.0 to 60.0 s	0.0 s
	This parameter introduce a delay on FL output signal relay.			
F 360	**[PID control enable]**		-	0
	0 **[No PID]**: PID disabled 1 **[PID by VIA]**: Enabled (feedback source is VIA) 2 **[PID by VIB]:** Enabled (feedback source is VIB) Parameter F 360 is used to enable PID control and define the source of the feedback signal. The PID source is defined by the setting of parameter [Frequency mode sel] (F rD d) (see page 77). Parameter [Freq band det range] (F 167) can be adjusted to command a drive relay to signal when the PID setpoint and feedback are in agreement (see page 115).			
F 362	**[PID Prop Gain]**	PID Proportionnal Gain	0.01 to 100.0%	0.30%
	Parameter F 362 adjusts the proportional gain applied during PID control. The speed change applied to the motor is a correctional value proportional to the product of this parameter's setting and the process error (deviation between the setpoint and the feedback value). A higher setting of F 362 provides a fast response to a process error but may also result in instability such as hunting. The diagram below illustrates the effect produced by adjusting F 362.  			
F 363	**[PID Integral Gain]**		0.01 to 100.0	0.20
	Parameter F 363 adjusts the integral gain applied during PID control. Any residual process errors that remain after correction by the proportional gain are cleared to zero over time by the integral gain function. A higher setting of F 363 provides a fast response to a process error but may also result in instability such as hunting. The diagram below illustrates the effect produced by adjusting F 363.  The integral gain value can be set to zero by setting a logic input to function 65. For more information, see table on page 91 and parameters [LI F selection] (F 111), [LI R selection] (F 112), [LI RES selection] (F 113), page 90, and [VIA LI selection] (F 118), page 90.			

Code	Name / Description		Adjustment range	Factory setting
F366	**[PID Derivative Gain]**		0.00 to 2.55	0.00
	Parameter F366 adjusts the derivative gain applied during PID control. This gain adjusts the response time of the drive to rapid changes in the process. Increasing the setting of F366 more than necessary may cause great fluctuations in motor speed resulting in system instability. The diagram below illustrates the effect produced by adjusting F366.  		
F359	**[PID ctrl wait time]**	PID Control Waiting Time	0 to 2400 s	0
	If parameter F359 is set to a value greater than 0 seconds, the drive will not immediately enter PID control upon startup. For the time set by F359, the drive will ignore the feedback signal, accelerating the motor to the speed set by the reference input. This function can be used to help prevent the drive from entering PID control mode before the system approaches the final operating level.			
F380	**[PID reverse error]**	PI regulator reversal direction correction		0
0	**[No]**			
1	**[Yes]**			
	This function is used to reverse the error PI for Water Pump. If F380 = 0 or No, PI error input = reference - feedback. The motor speed increases when the error is positive. If F380 = 1 or Yes, PI error input = feedback - reference. The motor speed decreases when the error is positive.			
F391	**[Stop on LL hyst]**	Stop on LL hysteresis	0.0 to [Max frequency] (FH)	0.2 Hz
F392	**[PID wake up (thres)]**	PI wake up threshold on PI error	0.0 to [Max frequency] (FH)	0.0 Hz
	⚠ DANGER UNINTENDED EQUIPMENT OPERATION Check that unintended restarts will not endanger personnel or equipment in any way. **Failure to follow these instructions will result in death or serious injury.**			
F393	**[PID wake up, feedb]**	PI wake up threshold on PI feedback error	0.0 to [Max frequency] (FH)	0.0 Hz
	⚠ DANGER UNINTENDED EQUIPMENT OPERATION Check that unintended restarts will not endanger personnel or equipment in any way. **Failure to follow these instructions will result in death or serious injury.**			
F645	**[Mot PTC selection]**	PTC Motor Thermal Protection Enable	-	0
0	**[Disabled]**			
1	**[Enabled fault]** (detected fault mode). If F645 is set to 1 and the PTC probe exceeds a given, threshold, the drive will trip and display an [PTC overheating] (OH2) code.			
2	**[Enabled alarm]** (alarm mode). If F645 is set to 2 and the PTC probe exceeds a given, threshold, the drive will signal a detected fault and continue operating.			
	Setting parameter F645 to 1 or 2 converts control terminal VIB into a PTC motor thermal probe input. See the ATV212 Installation manual, for wiring details.			

Code	Name / Description		Adjustment range	Factory setting
F 6 4 6	**[PTC resistor value]**		10 to 9999 Ω	3000 Ω

Active Logic Function

Two logic input functions can be configured to be active. The logic input functions assigned to parameters [Logic Funct 1 active] (F I 0 8) and [Logic Funct 2 active] (F I I 0) will continuously affect drive operation. See table beginning on page 91 for a list of available logic input functions.

Code	Name / Description		Adjustment range	Factory setting
F I 0 8	**[Logic Funct 1 active]**	Active Logic Function 1	0 to 73	0
F I I 0	**[Logic Funct 2 active]**	Active Logic Function 2	0 to 73	1

If F I I 0 is not set to 1 (logic function [Run permissive]), a logic input should be assigned to the [Run permissive] logic function to enable the motor to start.

Preset Speeds

A maximum of seven preset speeds can be selected by 4 logic inputs (F, R, RES, or VIA). Preset speed control is only active when the drive is in logic input control ([Command mode sel] (CMOd) = 0).

For one preset speed, assign a logic input to function 6.

For up to three preset speeds, use two logic inputs for functions 6 and 7.

For up to seven preset speeds, use three logic inputs for functions 6, 7, and 8.

Preset speed commands take priority over speed commands from any other source. For more information on preset speeds, see page 91. See page 42, for wiring instructions and timing diagram.

Code	Name / Description	Adjustment range	Factory setting
S r 1	**[Preset speed 1]**	L L to U L Hz	15 Hz
S r 2	**[Preset speed 2]**	L L to U L Hz	20 Hz
S r 3	**[Preset speed 3]**	L L to U L Hz	25 Hz
S r 4	**[Preset speed 4]**	L L to U L Hz	30 Hz
S r 5	**[Preset speed 5]**	L L to U L Hz	35 Hz
S r 6	**[Preset speed 6]**	L L to U L Hz	40 Hz
S r 7	**[Preset speed 7]**	L L to U L Hz	45 Hz

+/- Speed Control Parameters

+/- speed (motorized potentiometer) control is selected by setting parameter [Frequency mode sel] (F M O d) or [Remote spd ref 2] (F 2 0 7) to 5 (see pages 77 and 78). Two logic inputs are required, one to increase the speed command (logic input function 41) and one to decrease the speed command (logic input function 42). Logic input function 43 clears the speed reference value accumulated by the +/- speed logic inputs.

Parameters F 2 6 4 – F 2 6 9 refine the operation of +/- speed control.

The ratio of parameter F 2 6 5 to parameter F 2 6 4 determines the (+) speed command slope:

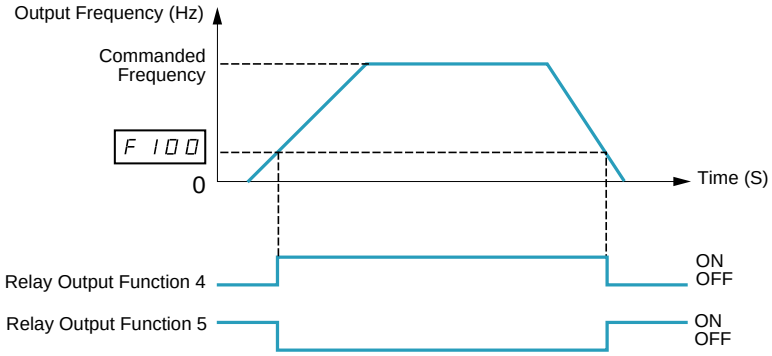
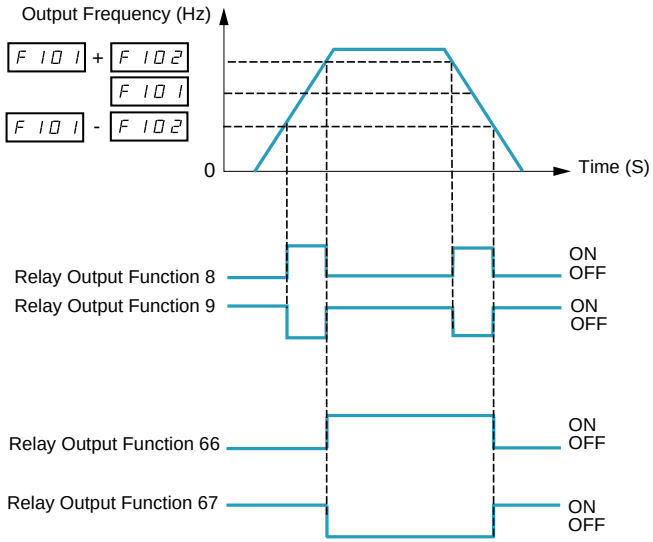
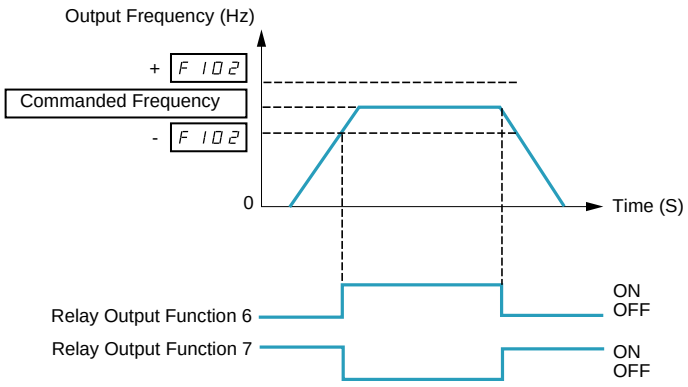
(+) speed command slope = F 2 6 5 / F 2 6 4

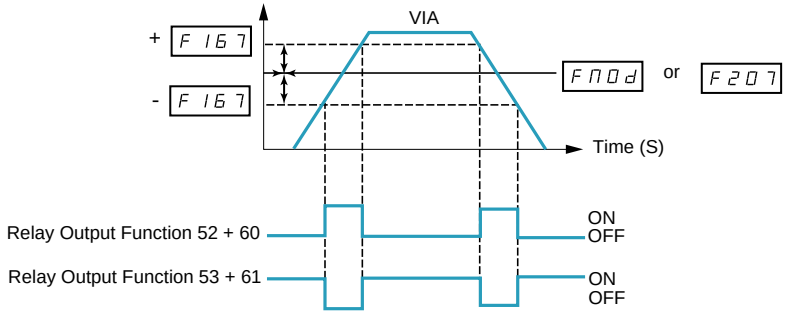
The ratio of parameter F 2 6 7 to parameter F 2 6 6 determines the (-) speed command slope.

(-) speed command slope = F 2 6 7 / F 2 6 6

For more detail, see page 94.

Code	Name / Description	Adjustment range	Factory setting
F 2 6 4	**[+speed LI resp time]** +Speed Logic Input Response Time	0.0 to 10.0 s	0.1 s
	Parameter F 2 6 4 sets the maximum on-time of the logic input assigned to (+) speed, limiting the speed increase, as defined by parameter [+speed freq. step] (F 2 6 5), to only one step. Keeping the logic input active longer than the time set by parameter F 2 6 4 will allow multiple step increases of the speed command.		
F 2 6 5	**[+speed freq. step]** +Speed Frequency Steps	0.0 to [Max frequency] (F H) Hz	0.1 Hz
	Parameter F 2 6 5 sets the frequency width in Hz of each (+) speed command step.		
F 2 6 6	**[- speed LI resp time]** -Speed Logic Input Response Time]	0.0 to 10.0 s	0.1 s
	Parameter F 2 6 6 sets the maximum on-time of the logic input assigned to (-) speed, limiting the speed decrease, as defined by parameter [-speed freq. step] (F 2 6 7), to only one step. Keeping the logic input active longer than the time set by parameter [+speed freq. step] (F 2 6 5) will allow multiple step decreases of the speed command.		
F 2 6 7	**[- speed freq. step]** -Speed Frequency Steps	0.0 to [Max frequency] (F H) Hz	0.1 Hz
	Parameter F 2 6 7 sets the frequency width in Hz of each (-) speed command step.		
F 2 6 8	**[Init +/- Speed]** Initial +/- Speed Command	0.0 to [Max frequency] (F H) Hz	0.0 Hz
	Parameter F 2 6 8 sets the +/- speed command in Hz that is applied to the drive when it is first powered up. Leaving this parameter at its default value will result in the drive's output frequency starting at 0 Hz every time it is powered up.		
F 2 6 9	**[Init +/- Speed memo]** Change of Initial +/- Speed Frequency	-	1
0	**[Disable]**		
1	**[Enable]**		
	The setting parameter F 2 6 9 determines whether the value of parameter [Init +/- Speed] (F 2 6 8) will change every time power is cycled to the drive. If parameter F 2 6 9 is set to 1, parameter F 2 6 8 will be set to the last speed command received by the drive before power was removed.		
F 1 3 7	**[RY Relay Function 2]** RYA-RYC Relay Secondary Function	0 to 61, 254, 255	255
	The RYA-RYC relay can be set to signal a secondary condition. The primary RYA-RYC relay function is set by parameter [RY Relay Function 1] (F 1 3 0) (see page 109). See table beginning on page 98 for a complete description of the primary and secondary functions that can be assigned to the RYA-RYC relay.		
F 1 3 9	**[RY logic select.]** RYA-RYC Relay Function Logic Selection	-	0
0	**[Function 1and 2]**: [RY Relay Function 1] (F 1 3 0) (primary) and [RY Relay Function 2] (F 1 3 7) (secondary)		
1	**[Function 1 or 2]**: F 1 3 0 (primary) or F 1 3 7 (secondary)		
	The RYA-RYC relay can be configured to energize when either:		
	Both the primary AND secondary conditions are met (true) (F 1 3 9 = 0), or		
	Only one OR the other is met (true) (F 1 3 9 = 1)		

Code	Name / Description	Adjustment range	Factory setting
F 100	**[Freq. 1 reached]** Relay Output – Frequency Level 1 Attained	0.0 to [Max frequency] (F H) Hz	0.0 Hz
	The frequency set by parameter F 100 is the threshold level for relay output functions 4 and 5 (see page 98). 		
F 101	**[Freq. 2 reached]** Relay Output – Frequency Level 2 Attained	0.0 to [Max frequency] (F H) Hz	0.0 Hz
	The frequency set by parameter F 101 +/- the [Freq.2 bandw.] (F 102) detection band is the threshold level for relay output functions 8 and 9 and the hysteresis for relay output functions 66 and 67 (see page 103). 		
F 102	**[Freq.2 bandw.]** Frequency Attained Detection Band	0.0 to [Max frequency] (F H) Hz	2.5 Hz
	Parameter F 102 determines the bandwidth around the [Freq.2 reached] (F 101) frequency (see diagram above) and the commanded frequency (see diagram below) driving relay output functions 6 through 9 (see page 98). 		

Code	Name / Description	Adjustment range	Factory setting
F 167	**[Freq band det range]** Frequency bandwidth detection range	0.0 to [Max frequency] (F H) Hz	2.5 Hz
	Parameter F 167 determines the bandwidth around the VIA or VIB speed reference (see below) driving relay output functions 52, 53, 60, and 61 (see page 102). This function can be used to signal whether the amount of processing and the amount of feedback agree when the PID function is in use. 		
F603	**[Ext. fault stop Mode]** External detected fault stop mode	-	0
0	**[Freewheel]**: Freewheel stop		
1	**[Ramp stop]**		
2	**[DC braking]**: DC injection braking		
	The setting of parameter F 603 determines how the drive will stop if a logic input assigned to function 11 or 46 is activated (see table on pages 91 and 94).		
F604	**[DC brk time ext flt]** External Fault DC braking time	0.0 to 20.0 s	1.0 s
	If parameter [Ext. fault stop Mode] (F 603) is set to 2, parameter F 604 will determine how long DC current will be injected into the motor while the external fault logic input is active.		

Damper control

This function applies to the ventilation ducts. The aim is to control the opening of the duct (shutter device called a "damper") when the fan starts up.

Damper opening command

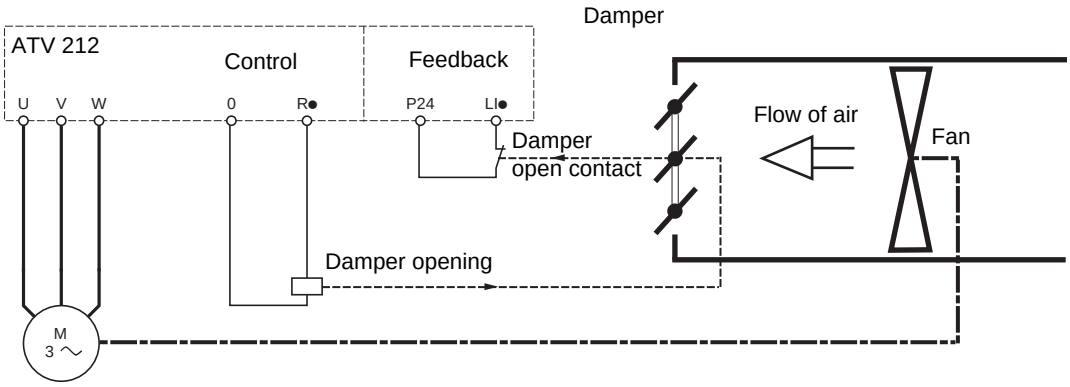
The opening command can be assigned to a relay via the F 130 or F 132 parameters to the function [Damper] 68 or [Inv. damper] 69 page 103. The damper is closed automatically when there is no longer an opening command.

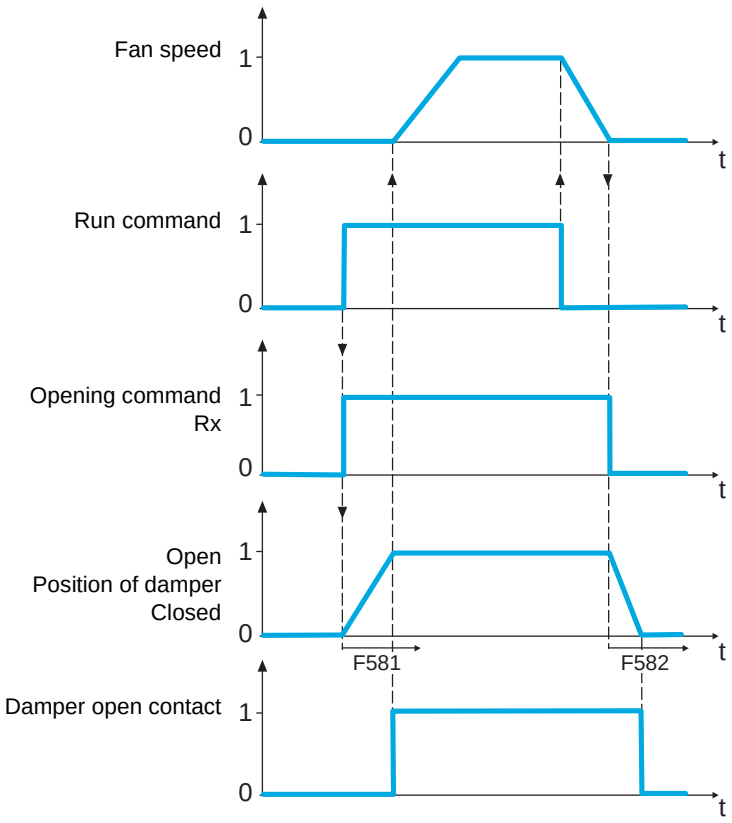
Damper opening feedback

Opening is controlled by a bit or a logic input that can be assigned via the F 111 or F 112 or F 113 parameters to the function [Damper feedBack] 73 page 96. The corresponding logic input or bit can be configured via the parameter [Damper fdb type] F 580.

When there is an inconsistency, the drive goes on a [Damper fault 1] Fd 1 if the damper does not open and on a [Damper fault 2] Fd2 if it does not close.

The parameter [Time open damper] F 581 can be used to delay tripping on an opening fault when a run command is sent and the parameter [Time close damper] F 582 delays the closing fault when a stop command is sent.





Code	Name / Description	Adjustment range	Factory setting
F 5 8 0	**[Damper fdb type]**		0
0	**[No feedback]**: No feedback used (Default value)		
1	**[LI L set]**: Logical input and active at level 0 (shunt). When setting F 5 8 0 to 1, first assign logic inputs.		
2	**[LIH set]**: Logical input and active at level 1 (open). When setting F 5 8 0 to 2, first assign logic inputs.		
3	**[Com. LIL set]**: Serial link to communication bit selected by [Com channel choice] (F 8 0 7) and active at level 0 (shunt). Please refer to communcation manual.		
4	**[Com. LIH set]**: Serial link to communication bit selected by F 8 0 7 and active at level 1 (open). Please refer to communcation manual.		
	Setting of F 5 8 0 parameter is independent of the type of command mode. The F 8 0 7 parameter allows selecting the communication channel used for communication damper feedback		
F 5 8 1	**[Time open Damper]**	0.05 s to 300.00 s	60.00
	Opening fault monitoring time delay. If the damper is not open at the end of the set time, the drive will lock in [Damper fault 1] F d 1 detected fault mode. The timer is launch after the run command. The time delay needs to be greater than the normal opening time of the damper.		
F 5 8 2	**[Time close Damper]**	0.05 s to 300.00 s	60.00
	Closing fault monitoring time delay. If the damper is not close at the end of the set time, the drive will lock in [Damper fault 2] F d 2 detected fault mode. The timer is launch when the motor is stopped. The time delay needs to be greater that the normal closing time of the damper		
F 5 8 3	**[Damper flt behavior]**		1
0	**[No fault]**		
1	**[Freewheel stop]**		
2	**[Ramp stop]**		
	The F 5 8 3 parameter allows defining the behavior when [Damper fault 1] (F d 1) occurs.		

Display Parameters

9

What's in this Chapter?

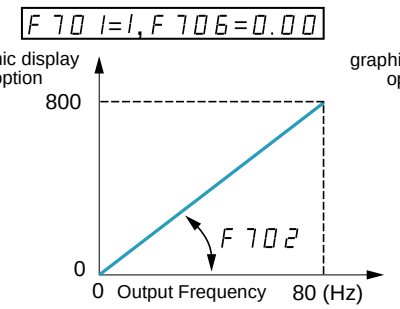
This chapter contains the following topics:

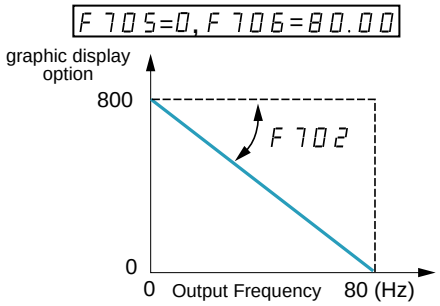
Topic	Page
Display parameters	120

Display parameters

Code	Name / Description		Adjustment range	Factory setting
F 7 10	**[Displayed param.]**	Default graphic display option operational value	0 to 10	0
0	**[Motor frequency]** Motor operating frequency (Hz or custom display), see [Customized freq val] (F 702) on page 121.			
1	**[Reference]** Speed reference (Hz or custom display), see F 702 on page 121.			
2	**[I Mot]** Motor current (% or A), see [Unit value selection] (F 701) below.			
3	**[Drive rated I]** Drive rated current (A)			
4	**[Drive therm state]** (%)			
5	**[Motor power]** Output power (kW)			
6	**[Int speed ref]** Internal speed reference (after PID function) (Hz or custom display, see F 702 on page 121.			
7	**[Com data]** Serial communication data			
8	**[Motor speed]** Output speed (rpm, see [Motor rated speed] (F 417) on page 70)			
9	**[Com count]** Displays the total number of frames received by the communication card since the last power ON			
10	**[Com count norm st.]** Displays the total number of valid frames received by the communication card since the last power ON			
	The setting of parameter [Displayed param.] (F 710) determines the default display on the drive's embedded display terminal upon power up.			
	Status alarms C, P, L, and H can only be displayed on the graphic display option if [Displayed param.] (F 710) is set to 0. See "Run Mode" on page 23 for more information.			
F 701	**[Unit value selection]**	Unit value selection	-	1
0	**[%]**			
1	**[Amp or Volt]**			
	The setting of parameter F 701 determines how certain values will be displayed on the drive embedded display terminal, either as a percentage of the drive rating or as a value of amperes or volts as appropriate.			
	The setting of F 701 will only affect parameters and display values that can be represented in amperes or volts. This includes the following parameters:			
	[Motor thermal prot.] (tHr) and F 173: motor rated current			
	F 251: DC braking current level			
	F 185 and F 601: motor current limit			
	F 611: underload detection level			
	Motor rated voltage (parameters uLu and F 171) are displayed in volts.			
F 708	**[Display ref. resol.]**	graphic display option Frequency Resolution	-	0
0	Disabled - 0.1 Hz steps			
1 **to** 255	See the formula below			
	Parameter F 708 works along with parameter [Loc. speed ref. step] (F 707) (see page 77) to adjust the incremental steps of the drive embedded display terminal frequency display.			
	At its factory setting, parameter F 708 is disabled and the embedded display terminal increments or decrements frequency displays in 0.1 Hz steps.			
	If parameter F 708 is set to a value other than 0, then the embedded display terminal frequency display is determined as follows: embedded display terminal frequency display = Internal speed reference (after PID function) x F 708 / F 707			
	For example, if both F 707 and F 708 are equal to 1, the embedded display terminal frequency display will increase only in 1 Hz steps.			
F 621	**[Run time alarm]**		0.0 to 999.9	610.0 (6100 hours)
	Parameter F 621 is used in conjunction with a relay output set to functions 42 or 43 (see page 102) to signal that the run time specified by the setting of F 621 has accumulated.			
	0.1 = 1 hour, 100 = 1000 hours			
F 748	**[Power cons. memo]**	Accumulated power consumption memory	-	1
0	**[Disable]**			
1	**[Enable]**			
	The setting of parameter F 748 determines whether the drive's accumulated power consumption memory, displayed in kilowatt-hours (kWh), is cleared when the line power is cycled. If F 748 is set to 0, the memory is cleared. If set to 1, the kWh memory is retained.			

Code	Name / Description		Adjustment range	Factory setting
F 749	**[Power cons. unit]**		-	According to drive rating (1)
0	**[1 kWh]**			
1	**[0.1 = 1 kWh]**			
2	**[0.01 = 1 kWh]**			
3	**[0.001 = 1 kWh]**			
	The setting of parameter F 749 determines the scaling of the kWh display on the embedded display terminal.			
F 702	**[Customized freq val]**	Customized freq val	0.00 to 200.00	0.00
	Parameters F 702, F 705, and F 706 can be used to customize a speed display on the drive embedded display terminal to match the application's operational speed, for example, feet per minute or units per hour. 0.00: Frequency displayed in Hz 0.0 If parameter F 702 is set to a value other than 0.00, the frequency value displayed will be calculated as follows: Value displayed = display or parameter frequency x F 702. See example below. 1 to 200.0: Conversion factor			
F 703	**[Frequency convert.]**	Frequency free unit conversion selection]		0
0	**[All]** Frequencies display free unit			
1	**[PID only]** PID frequencies free unit conversion			
F 705	**[Custom freq. slope]**	Custom Frequency Display Conversion Slope]	-	1
0	**[Negative slope]**			
1	**[Positive slope]**			
	Parameter F 705 sets the slope of the custom frequency display conversion. See the diagrams below for examples of the operation of this function.			
F 706	**[Customize unit bias]**	Custom Frequency Display Conversion Bias	0.00 to F H Hz	0.00 Hz
	Parameter F 706 adds a bias to the custom frequency display conversion process.			





(1) See table page 167.

Detected Fault Management Parameters

10

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Time delay	125
Catch On The Fly (F301)	126
Overtorque Detection	132
Nuisance Overvoltage And Input Phase Detected Fault Avoidance	133
Motor Overload Characteristics	134

Code	Name / Description	Factory setting
F 3 0 3	**[Number auto reset]**	0

⚠ DANGER

UNINTENDED EQUIPMENT OPERATION
- The automatic restart can only be used on machines or installations which do not pose any danger to either personnel or equipment.
- If the automatic restart is activated, the fault relay will only indicate a fault has been detected once the time-out period for the restart sequence has expired.
- The equipment must be used in compliance with national and regional safety regulations

Failure to follow these instructions will result in death or serious injury.

0	Disabled.
1 to 10	Number of clear attempts.

Description

The table below lists the detected faults that can be cleared with Auto clear. If parameter F 3 0 3 is set to a value greater than 0 and one of these detected faults occurs, the drive will attempt to automatically clear the detected fault, allowing it to be re-started:

Fault detection codes that can be cleared with the automatic restart function after the cause has disappeared

Code	Description	Code	Description
F d 1	Damper detected fault 1 (closed damper)	0 H 2	External overheating
0 C 1	Overcurrent during acceleration	0 L 1	Drive overload
0 C 2	Overcurrent during deceleration	0 L 2	Motor overload
0 C 3	Overcurrent during constant speed	0 P 1	Overvoltage during acceleration
0 C 1 P	Short-circuit or ground detected fault during acceleration	0 P 2	Overvoltage during deceleration
0 C 2 P	Short-circuit or ground detected fault during deceleration	0 P 3	Overvoltage during constant state operation
0 C 3 P	Short-circuit or ground detected fault during constant speed operation	S 0 U t	Permanent magnet motor step-out
0 H	Drive overheating		

Auto clear attempts will continue until the number of attempts set by parameter F 3 0 3 has been exhausted.

If these attempts do not clear the detected fault condition, the drive will stop and a manual clear will be required.

If another type of detected fault occurs during the auto clear process, the drive will stop and a manual clear will be required.

A successful auto clear means that the drive accelerates the motor to the commanded speed without another detected fault occurring.

If an unspecified period of time elapses after a successful auto clear attempt without another detected fault occurring, the reset attempt counter will clear allowing another full set of reset attempts to be made during a future detected fault occurrence.

During the auto clear process, the drive embedded display terminal alternately displays r t r Y and the display value selected by parameter [Displayed param.] (F 7 1 0), page 120.

Conditions permitting auto clear

An auto clear attempt will not be made if the cause of the detected fault persists.

In the case of an 0 L 1 or 0 L 2 overload detected fault, the drive will calculate the cooling time necessary to clear the detected fault.

In the event of an 0 H detected fault, the heatsink temperature probe will indicate when the detected fault can be cleared.

DC bus voltage measurements will indicate when an 0 P 1, 0 P 2, or 0 P 3 detected fault can be cleared.

Time delay

The first clear is attempted 1 second after the detected fault occurs. Each subsequent clear attempt adds 1 second to the time interval, as illustrated in the table below.

Clear detected fault attempts

Attempt number	Time delay between detected fault reset attempt and most recent fault
1	1 second
2	2 seconds
3	3 seconds
4	4 seconds
5	5 seconds
6	6 seconds
7	7 seconds
8	8 seconds
9	9 seconds
10	10 seconds

Fault relay action

An output relay set to functions 10 and 11 (see table on page 98) will not indicate a detected fault until all clear attempts have been exhausted.

Output relay functions 28 and 29 can be used to indicate that an auto-resetable detected fault has occurred.

Output relay functions 36 and 37 can be used to signal any kind of drive detected fault, even during auto clear attempts.

Drive fault memory

If parameter [Drive fault memory] (F 6 0 2) is set to 1 and power to the drive is cycled while an auto-resetable detected fault is active, the auto clear action will be cancelled (see page 127).

Catch On The Fly (F 3 0 1)

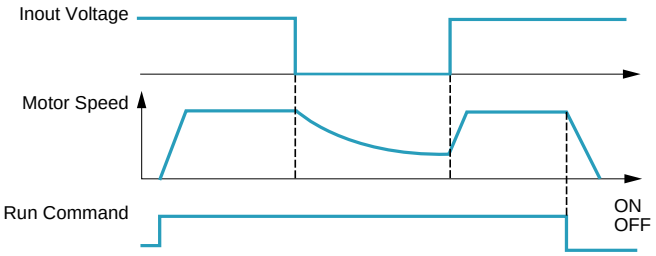
If catch-on-the-fly motor starting is enabled (parameter F 3 0 1 is not set to 0), the drive will detect the motor's rotating direction and speed before applying power. This will result in a smooth reapplication of power to a coasting motor without high current or torque pulses.

If F 3 0 1 is disabled and the drive is started into a spinning motor, it will apply a low starting frequency to the motor, operating in current limit until the motor almost stops. Then, the drive will accelerate the motor to the commanded speed.

Catch-on-the-fly motor starting will be applied if F 3 0 1 is set to 1 or 3 and:

- There is a brief power loss (the embedded display terminal does not go blank) that results in the drive removing power from the motor,
- and, there is a continuous run command to the drive (2-wire control)

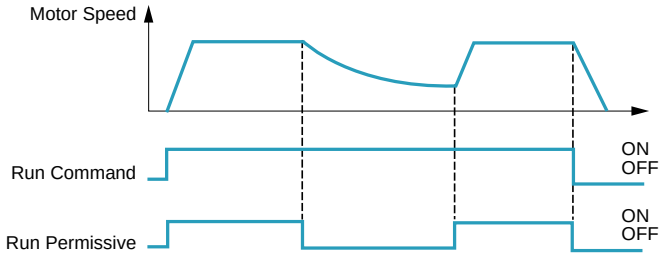
F 3 0 1 Set to 1 or 3



Catch-on-the-fly motor starting will be applied if F 3 0 1 is set to 2 or 3 and:

- The run permissive (logic input assigned to functions 1 or 54) is removed and restored,
- and, there is a continuous run command to the drive (2-wire control)

F 3 0 1 Set to 2 or 3



If F 3 0 1 is set to 4, the drive will perform a motor speed and direction search each time it receives a run command.

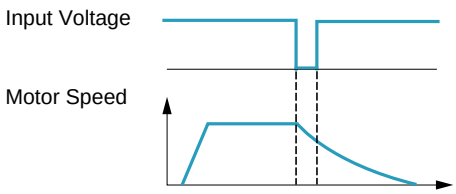
Note: Enabling catch-on-the-fly adds about 300 milliseconds to implementation of each start command to the drive.

Do not use catch-on-the-fly if there is more than one motor supplied by the drive.

Code	Name / Description	Factory setting
F 3 0 1	**[Catch on fly]**	3 (1)
0	**[Disable]**	
1	**[Brief power loss]** After brief power loss	
2	**[Run restored]** After run permissive is restored	
3	**[Power loss, run]** After brief power loss or run permissive is restored	
4	**[Each start]** During every startup	
F 6 3 2	**[Mot overload memo]** Motor Overload Memory	0
0	**[Disabled]** Cleared If parameter F 6 3 2 is set to 0, the drive's memory of the motor's thermal state (used for overload calculation) is cleared whenever the power is cycled.	
1	**[Enabled]** Retained If parameter F 6 3 2 is set to 1, the drive's memory of the motor's thermal state is retained even when power is removed. If the drive is tripped on an Motor Overload detected fault O L 2, a cooling time (as calculated by the drive) needs to expire before the motor can be restarted.	

(1) Catch-on-the-fly motor starting after a drive detected fault is active if auto clear is enabled (parameter [Number auto reset] (F 3 0 3) is not set to 0, see page 124)

Code	Name / Description	Factory setting
F 6 0 2	**[Drive fault memory]**	0
0	**[Cleared]** If parameter F 6 0 2 is set to 0 and the drive is powered after a detected fault: If the cause of the detected fault has been removed, the drive will reset and can be started. Information about the detected fault just cleared will be transferred to the detected fault history. If the cause of the detected fault has not been removed, the detected fault will be displayed again but the drive's memory of the operational information associated with the detected fault will be transferred to the detected fault history. Information about the 4th most recent detected fault will be removed from the detected fault history.	
1	**[Retained]** If parameter F 6 0 2 is set to 1 and the drive is powered after a detected fault: If the cause of the detected fault has been removed, the drive will reset and can be started. Information about the detected fault just cleared will be transferred to the detected fault history. If the cause of the detected fault has not been removed, the original detected fault and all of its operational data will be available for viewing as the current detected fault in the monitoring mode. Information about the 4th most recent detected fault will be retained in the detected fault history. Auto clear will be disabled.	
F 6 0 8	**[Input phase loss]** Input phase loss detection mode	1
0	**[Disable]**: Disabled If parameter F 6 0 8 is set to 0, input phase loss detection is disabled. Loss of one input phase will not cause the drive to trip.	
1	**[Enable]**: Enabled If parameter F 6 0 8 is set to 1, the loss of one input phase will cause an E P H 1 detected fault.	
F 3 0 2	**[Supply loss behav.]**	0
0	**[Disabled]** If parameter F 3 0 2 is set to 0 and the drive briefly loses input power, it may not trip but may instead experience a momentary reduction of motor voltage and/or current and then resume normal operation once nominal input power is restored.	
1	**[Do not use]**: DO NOT SELECT	
2	**[Freewheel]** If parameter F 3 0 2 is set to 2 and the drive briefly loses input power, the drive will remove power from the motor and allow it to coast to a stop. The embedded display terminal will flash S t O P. The drive can only be restarted by providing a new run command.	

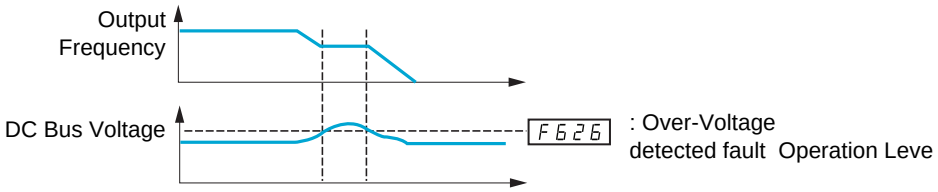


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Code	Name / Description	Adjustment range	Factory setting
F 6 2 7	**[Undervolt detect.]** Undervoltage Fault Operation Mode	-	0
0	**[Alarm (0.6U)]**: Alarm only (detection level below 60 %) If parameter F 6 2 7 is set to 0 and the supply voltage drops below 60% of its rated value, the drive will stop and indicate a detected fault code on the embedded display terminal, but it will not activate a fault relay. If the supply voltage rises above 60% of its rated value, the detected fault code on the embedded display terminal will be cleared without a clear action and the drive will be ready to operate.		
1	**[Fault (0.6U)]**: Fault (detection level below 60 %) If parameter F 6 2 7 is set to 1 and the supply voltage drops below 60% of its rated value, the drive will trip and will require a reset action to clear the detected fault before it can be restarted.		
2	**[Alarm (0.5U)]**: Alarm only (detection level below 50 %) If parameter F 6 2 7 is set to 2 and the supply voltage drops below 50% of its rated value, the drive will stop and indicate a detected fault code on the embedded display terminal, but it will not activate a fault relay. If the supply voltage rises above 50% of its rated value, the detected fault code on the embedded display terminal will be cleared without a clear action and the drive will be ready to operate.		

CAUTION

RISK OF DAMAGE TO DRIVE
When F 6 2 7 = 2 , use a line choke.
Failure to follow these instructions can result in death, serious injury, or equipment damage.

Code	Name / Description	Adjustment range	Factory setting
F 3 0 5	**[Overvoltage fault]** Overvoltage protection	-	2
0	**[Enable]** If parameter F 3 0 5 is set to 0, and the drive detects an impending DC bus overvoltage, it will automatically take one of the following actions: Increase the deceleration time Keep the motor at a steady speed Increase the motor speed  		
1	**[Disabled]** If parameter F 3 0 5 is set to 1, the drive will take no action to avoid a DC bus overvoltage.		
2	**[Quick deceleration]**: Enabled (quick deceleration mode) If parameter F 3 0 5 is set to 2, and the drive detects an impending DC bus overvoltage, it will increase the V/Hz ratio of the power applied to the motor. Motor over-excitation is used to dissipate regenerative energy into the motor instead of the drive.		
3	**[Dyn. deceleration]**: Enabled (dynamic quick deceleration mode) If parameter F 3 0 5 is set to 3, the drive will increase the V/Hz ratio of the power applied to the motor as soon as slow down begins instead of waiting for the DC bus voltage to approach the detected fault level. When motor speed is being reduced, a DC bus overvoltage can often be caused by regenerated energy being absorbed by the drive from the load and motor.		
F 6 2 6	**[Overvoltage level]**	100 to 150 % of nominal DC bus voltage	140%
	Parameter F 6 2 6 sets the DC bus voltage level at which the actions defined by parameter F 3 0 5 take place. See diagram above for more details.		

Code	Name / Description	Factory setting
F 6 0 5	**[Output phase loss]** Output phase loss detection Mode	3

⚠⚠ DANGER

HAZARD OF ELECTRIC SHOCK, EXPLOSION OR ARC FLASH

- If F 6 0 5 = 0, loss of cable is not detected
- If F 6 0 5 = 1 or 2, loss of cable is only detected at the startup of the motor
- Check this action will not endanger personnel or equipment in any way

Failure to follow these instructions will result in death or serious injury.

If output phase loss detection is enabled and an output phase loss persists for more than 1 second, the drive will trip and display the E P H 0 code.

0 **[Disabled]**
If parameter F 6 0 5 is set to 0, output phase loss detection is disabled.

1 **[First start]**: At the first start-up.
If parameter F 6 0 5 is set to 1, an output phase loss check is made only during the first motor start-up after power is applied to the drive.

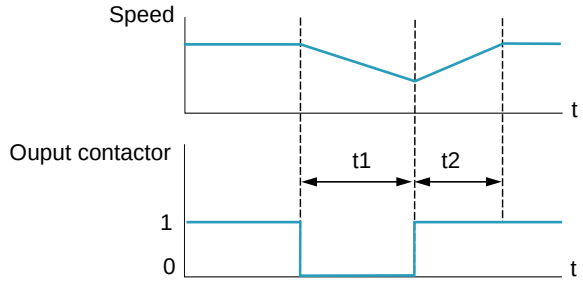
2 **[Each start]**: At every start-up.
If parameter F 6 0 5 is set to 2, an output phase loss check is made every time the motor is started.

3 **[During run]**: During operation.
If parameter F 6 0 5 is set to 3, continuous output phase loss monitoring is performed while the motor is running.

4 **[Permanent]**: At start-up and during operation.
If parameter F 6 0 5 is set to 4, monitoring for an output phase loss is performed at motor start-up and continuously during operation.

5 **[Output contactor]**: Load side disconnect mode.
Setting 5 for parameter F 6 0 5 is for applications with a load side disconnect. The drive will automatically restart the motor if the following are true:

- An all-phase loss has been detected (an output contactor or a load side disconnect has opened)
- The drive detects that a 3-phase connection has been reestablished (the output contactor or load side disconnect has closed). It is necessary to wait 1 s between disconnection and connection. See following scheme to have an example of loss of output contactor.

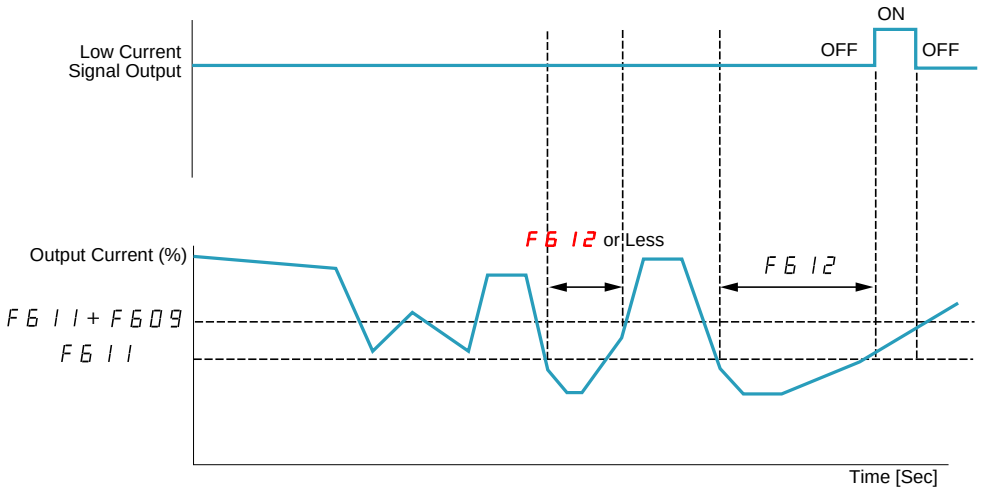


t1: deceleration without ramp (freewheel)

t2: acceleration with ramp

- A valid run command exists.

An output phase loss detection sweep is made as part of the auto-tuning process, regardless of the setting of parameter F 6 0 5. High-speed motors and other special motors may cause nuisance output phase losss.

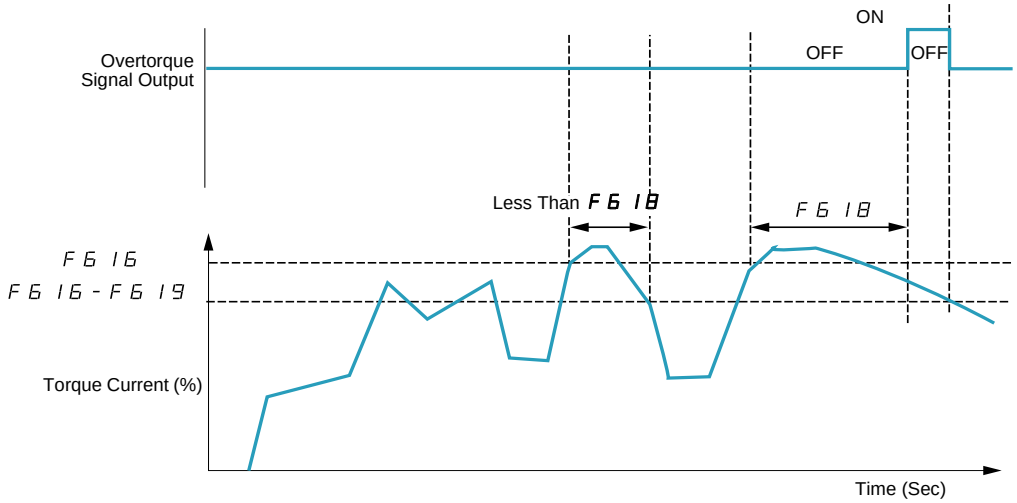
Code	Name / Description		Adjustment range	Factory setting
F 6 1 0	**[Underload det.]**	Underload / alarm selection	-	0
0	**[Alarm]** If parameter F 6 1 0 is set to 0, relay output functions 24 or 25 (see page 130) can be used to signal an underload condition without the drive faulting.			
1	**[Fault]** If parameter F 6 1 0 is set to 1 and the loading level drops below the setting of F 6 1 1 for a period of time longer than that set by F 6 1 2, the drive will trip, displaying code U C . The fault relay will be set if one has been defined (relay output functions 10 or 11, see page 98). A relay assigned to signal an underloaded condition (functions 24 or 25, see page 99) will also be set. The drive's response to an underload condition is set by parameters F 6 0 9, F 6 1 0, F 6 1 1, and F 6 1 2. The setting of parameter F 6 1 0 determines whether an underload condition signals an alarm with an output relay or faults the drive. The sum of parameters F 6 0 9 and F 6 1 1 determines the drive loading level that will clear an underload alarm/detected fault. Parameter F 6 1 2 determines how long the drive can be under load before an alarm or detected fault is signaled. See parameters F 6 0 9, F 6 1 0, F 6 1 1 and F 6 1 2 diagram below for more details. F 6 1 0 = 0 (Alarm Only)  			
F 6 1 1	**[Underload level]**	Underload Detection Level	0 to 100% (1)	0%
	Parameter F 6 1 1 sets the underload detection level.			
F 6 0 9	**[Underload band]**	Underload Detection Level Bandwidth	1 to 20% (2)	10%
F 6 1 2	**[Underload det. time]**	Underload Detection Time	0 to 255 s	0 s
F 6 3 3	**[Loss of VIA]**	Loss of VIA Analog Signal	0 to 100% (3)	0%
0	**[Disabled]** Disabled. If parameter F 6 3 3 is set to 0, the drive will not monitor for loss of signal at analog input terminal VIA			
1 to 1 0 0	**[Fault detection level]** If parameter F 6 3 3 is set to a value greater than 0 and: The signal at VIA drops below the detection level selected, and, the low signal level persists for 300 milliseconds or longer, the drive will trip and the embedded display terminal will display the code E - 1 8.			

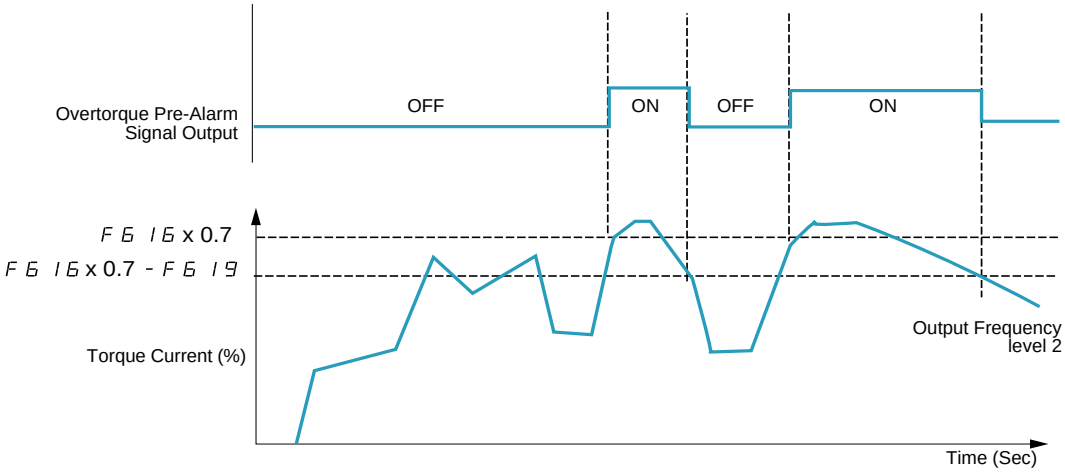
(1) Percentage of the drive's current rating. Display can also be in amperes, depending on setting of parameter [Unit value selection] (F 7 0 1) (see page 120).
(2) Percentage of [Underload level] (F 6 1 1) setting.
(3) Percentage of maximum VIA signal level

Code	Name / Description	Adjustment range	Factory setting
F 6 4 4	**[4-20 mA loss]** Drive behavior on 4-20 event		0
0	**[No]**: No		
1	**[Freewheel]** Freewheel. Freewheel stop and alarm.		
2	**[Set speed]** Fallback speed. Switch to fallback speed. Maintained as long as the trip cause is present and the run command is not disabled. See parameter [4-20mA fallback sp] (F 6 4 9) for fallback speed.		
3	**[Keep speed]** Speed maintain. The drive maintains the speed being applied when the trip occurred, as long as the trip cause is present and the run command is not disabled.		
4	**[Ramp stop]** Ramp stop.		
F 6 4 9	**[4-20mA fallback sp]** Fallback speed	0.0 to **[Max frequency]** (F H)	0.0 Hz
	See parameter [4-20 mA loss] (F 6 4 4).		
F 6 1 3	**[Short circuit det.]** Output short-circuit detection mode	-	0
0	**[Each time (std)]**: Each time a RUN command is given (standard pulse)		
1	**[One time (std)]**: Only one time after power is turned on (standard pulse)		
2	**[Each time (short)]**: Each time a RUN command is given (short-time pulse)		
3	**[One time (short)]**: Only one time after power is turned on (short-time pulse)		
	The setting of parameter F 6 1 3 determines how the drive determines an output short-circuit during start-up. Select the short-time pulse if the drive is powering a low impedance motor.		

Overtorque Detection

The drive's response to a particular motor torque level is determined by the setting of parameters F6 15 – F6 19.



Code	Name / Description	Adjustment range	Factory setting
F6 15	**[Overtorque det.]** Overtorque detected fault/Alarm Selection	-	0
0	**[Alarm]** If parameter F633 is set to 0, the drive will not monitor for loss of signal at analog input terminal VIA.		
1	**[Fault]** If parameter F6 15 is set to 1 and the drive faults, the overtorque signal output will remain latched on until the detected fault is cleared. Depending on the setting of parameter F6 15, the drive can use output relay function 12 or 13 (see table on pages 98) to signal an overtorque alarm or detected fault (0L code).		
F6 16	**[Overtorque level]** Overtorque Detection Level	0 to 250 % of nominal rated motor torque	130%
	The setting of parameter F6 16 determines the level at which the drive will act upon a motor overtorque condition (see diagrams above and below).		
			
	Output relay functions 20 or 21 can be used to signal a overtorque pre-alarm when the calculated motor torque reaches 70% of the value set by parameter F6 16.		
F6 18	**[OvTorque det time]** Overtorque Detection Time	0.0 to 10 s	0.5 s
	The setting of parameter F6 18 determines how long the drive needs to detect a motor overtorque condition before it signals an alarm or detected fault (see above diagram).		
F6 19	**[Overtorque band]** Overtorque Detection Level Bandwidth	0 to 100 % of F6 16 level	10%
	While the setting of parameter F6 16 determines the level at which a motor overtorque alarm or detected fault will be signaled, the setting of parameter F6 19 determines how far the calculated motor torque needs to drop before the alarm or detected fault is cleared (see above diagram).		

Code	Name / Description	Factory setting
F 6 3 4	**[Amb. temp. alarm]** Ambient Temperature For drive Service Alarm	3
1	**[- 10 to 10 °C]**	
2	**[11 to 20 °C]**	
3	**[21 to 30 °C]**	
4	**[31 to 40 °C]**	
5	**[41 to 50 °C]**	
6	**[51 to 60 °C]**	
	The drive can be programmed to signal a service alarm using output relay functions 44 or 45 (see page 102). The status of the service alarm can be displayed on the embedded display terminal (see page 21). At initial start-up, set parameter F 6 3 4 to the drive's average ambient operating temperature. Setting F 6 3 4 to the highest annual temperature or changing the value after drive operation has begun may result in an early drive service alarm.	

Nuisance Overvoltage And Input Phase Detected Fault Avoidance

Parameters F 4 8 1 to F 4 8 3 can be used to avoid nuisance overvoltage and input phase faults caused by:

- High input impedance: line reactor
- Low input impedance: high kVA distribution network
- Voltage instability: generator power source

If nuisance faults occur, increase the value of parameter F 4 8 1. If increasing the value of F 4 8 1 over 1000 does not remove nuisance faults, increase the values of parameters F 4 8 2 and F 4 8 3 as needed.

Code	Name / Description	Adjustment range	Factory setting
F 4 8 1	**[In noise comp. filter]** Line noise compensation filter	0 to 9999 µs	0 µs
F 4 8 2	**[In noise Inhibit filter]** Line noise Inhibitor filter	0 to 9999 µs	442 µs
F 4 8 3	**[In noise inhibit gain]** Line noise Inhibitor gain	0 to 300 %	100%
F 4 8 4	**[Pwr supply adj. gain]** Power supply adjustment gain	0.0 to 2.0 s	0.0

When the using machine has specific resonance, the following phenomena are happened:

- the machine occurs vibration,
- unusual noise of machine or peripheral.

If these phenomena are occurred, the following parameters should be adjusted:

- at first, set [Pwr supply adj. gain] (F 4 8 4) to 0.5,
- next, set F 4 8 4 as another value when no effect by setting F 4 8 4 to 0.5,
- if [Motor rated freq.] (u L) = 50 Hz, set F 4 8 1 to the following value 531,
- if u L = 60 Hz, set F 4 8 1 to the following value 442.

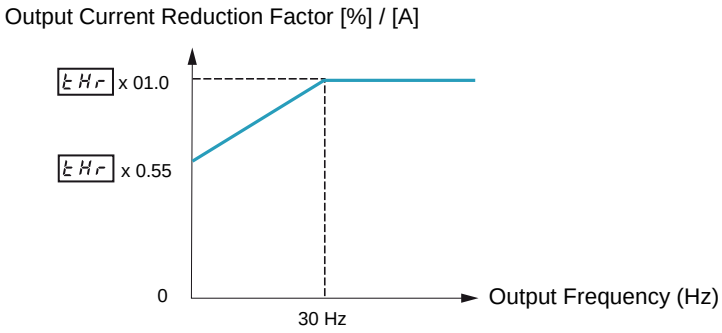
Note: F 4 8 1 and F 4 8 3 are invalid when F 4 8 4 has a value excluding 0.0.

Motor Overload Characteristics

Motor Type

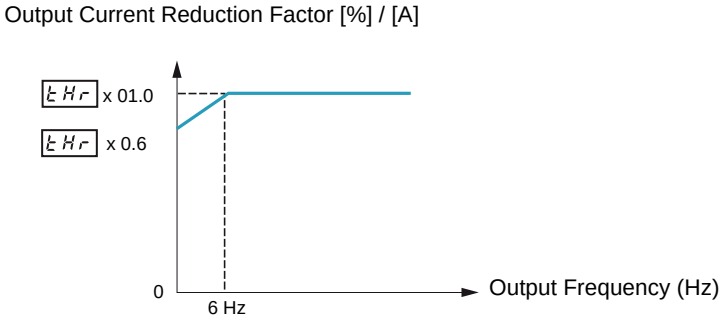
Set OLN to 0, 1, 2, or 3 if a self-cooled motor is being powered by the drive. The diagram below illustrates the overload protection level for the self-cooled motor as a function of motor frequency.

Overload Protection for a Self-Cooled Motor



Set OLN to 4, 5, 6, or 7 if a forced-cooled motor is being powered by the drive. The diagram below illustrates the overload protection level for the forced-cooled motor as a function of motor frequency.

Overload Protection for a Forced-Cooled Motor



Overload Protection

To enable motor overload protection, set OLN to 0, 1, 4, or 5.

CAUTION
RISK OF DAMAGE TO THE MOTOR When OLN is set to 2, 3, 6 or 7 motor thermal protection is no longuer provided by the drive. Provide an alternative means of thermal protection. **Failure to follow these instructions can result in equipment damage.**

To disable motor overload protection, set OLN to 2, 3, 6, or 7. In this case, a separate overload protective device, external to the ATV212 drive, needs to be wired between the drive and the motor.

Overload Stall

The overload stall function is only compatible with variable torque loads where the load on the motor and drive is dependent on the operating frequency and where the load can be reduced by slowing the motor.

If overload stall is enabled, the drive will reduce its output frequency if it detects an impending overload. As the overload condition of the motor is dissipated, the drive will return its output frequency to the commanded value.

To enable overload stall, set OLN to 1, 3, 5, or 7.

To disable overload stall, set OLN to 0, 2, 4, or 6.

Code	Name / Description	Factory setting
OLN	**[Motor overload prot]** Motor Overload Characteristics	0

CAUTION

RISK OF DAMAGE TO THE MOTOR
When OLN is set to 2, 3, 6?or 7 motor thermal protection is no longuer provided by the drive. Provide an alternative means of thermal protection.
Failure to follow these instructions can result in equipment damage.

This parameter value depends on:

- the motor type (self cool or forced cooled),
- and the protection.

Motor type	Protection		OLN value	Description	Behavior
	Overload protection	Overload stall			
Self cooled	enabled	disabled	0	**[Std mot. protect.]**	In case of overload defined by [Motor thermal prot.] (tHr) parameter, the drive trips in OL2 and the letter L is flashing.
	enabled	enabled	1	**[Std & stall mot. prot]**	In case of overload defined by [Motor thermal prot.] (tHr) parameter, the drive reduces automatically the speed and follows a fallback speed (80 % of Motor rated frequency uL) (1). If the overload remains during the fallback speed, the drive trips in OL2 and the letter L is flashing.
	disabled	disabled	2	**[Self cool]**	-
	disabled	enabled	3	**[Slf cool stall ov.load]**	In case of overload defined by [Motor thermal prot.] (tHr) parameter, the drive reduces automatically the speed and follows a fallback speed (80 % of Motor rated frequency uL) (1). The drive will not trip in OL2.
Forced cooled	enabled	disabled	4	**[Forced cool prot]**	In case of overload defined by [Motor thermal prot.] (tHr) parameter, the drive trips in OL2 and the letter L is flashing.
	enabled	enabled	5	**[Forc cool stall prot]**	In case of overload defined by [Motor thermal prot.] (tHr) parameter, the drive reduces automatically the speed and follows a fallback speed (80 % of Motor rated frequency uL) (1). If the overload remains during the fallback speed, the drive trips in OL2 and the letter L is flashing.
	disabled	disabled	6	**[Forced cool]**	-
	disabled	enabled	7	**[F cool & stall ov load]**	In case of overload defined by [Motor thermal prot.] (tHr) parameter, the drive reduces automatically the speed and follows a fallback speed (80 % of Motor rated frequency uL) (1). The drive will not trip in OL2.

(1) If the speed is lower than the fallback speed, the drive will keep the same speed.

Serial Communication Parameters

11

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Network communication between the ATV212 drive and a master controller	138
Data structure parameters	140

Network communication between the ATV212 drive and a master controller

⚠WARNING

LOSS OF CONTROL

- The designer of any control scheme must consider the potential failure modes of control paths and, for certain critical control functions, provide a means to achieve a safe state during and after a path failure. Examples of critical control functions are emergency stop and overtravel stop.
- Separate or redundant control paths must be provided for critical control functions.
- System control paths may include communication links. Consideration must be given to the implications of unanticipated transmission delays or failures of the link (1).

Failure to follow these instructions can result in death, serious injury, or equipment damage.

(1) For additional information, refer to NEMA ICS 1.1 (latest edition), “Safety Guidelines for the Application, Installation, and Maintenance of Solid State Control” and to NEMA ICS 7.1 (latest edition), “Safety Standards for Construction and Guide for Selection, Installation and Operation of Adjustable-Speed Drive Systems.”

Network communication between the ATV212 drive and a master controller is possible through five protocols selectable through the embedded display terminal:

- Modbus® RTU
- Metasys® N2
- Apogee® P1 FLN
- BACnet
- LonWorks®

Three types of data exchange are possible:

- Monitoring: monitoring values such as output frequency, voltage, and current
- Programming: reading, editing, and writing drive parameters
- Control: starting and stopping the drive and controlling the frequency reference

For operation on a network containing multiple drives, each ATV212 drive needs to be assigned a unique address using parameter F802.

For operation on a network where all drives are slaves responding to a central control system:

- Parameters [Command mode sel] (CMOd) (see page 77) and [Frequency mode sel] (FMOd) (see page 77) needs to be set correctly:
  - Setting CMOd to 2 enables start/stop control of the drive via network communication
  - Setting FMOd to 4 enables the frequency reference to be controlled by network communication
  - Setting either CMOd to 2 or FMOd to 4 enables serial communication error detection. The setting of parameter F851 determines the drive’s response in case of a loss of communication.

Control of the ATV212 drive can be established by a master controller over a serial communication network regardless of the setting of CMOd or FMOd (see diagram on page 46). Control can be restored to the source defined by CMOd and FMOd if the serial communication network relinquishes control or a logic input assigned to function 48 (forced local) is enabled.

Code	Name / Description		Adjustment range	Factory setting
F800	**[Mdb RJ45 baud]**	Modbus RJ45 baud rate	-	1
0	**[9600 bps]**			
1	**[19200 bps]**			
F801	**[Mdb RJ45 parity]**	Modbus RJ45 parity	-	1
0	**[No]**: No parity			
1	**[Even]**: Even parity			
2	**[Odd]**: Odd parity			
F802	**[Modbus address]**		0 to 247	1
	This address is used whatever the port used.			

Code	Name / Description	Adjustment range	Factory setting
F803	**[Com. time out]**	-	3

⚠ WARNING

LOSS OF CONTROL
- If F803 is set to 0, communication control will be inhibited.
- For safety reasons, inhibiting the communication interruption detection should be restricted to the debug phase or to special applications.

Failure to follow these instructions can result in death, serious injury, or equipment damage.

0 Communication error detection disabled
1 **to** 100 1 to 100 seconds

F820	**[Mdb network baud]** Modbus network baud rate	-	1

0 **[9600]**
1 **[19200]**

F821	**[Mdb network parity]** Modbus network parity	-	1

0 **[No]**: No parity
1 **[Even]**: Even parity
2 **[Odd]**: Odd parity

F829	**[Network protocol]** Network protocol selection	-	1

1 **[Mdb RTU]**
2 **[Metasys N2]**
3 **[Apogee P1]**
4 **[BACnet]**
5 **[LonWorks]**

F829 is enable if F807 is set to 1 previously.

Note: On the ATV21, Lonworks configuration corresponded to value 1.

F851	**[Com. fault setting]** Communication fault setting	-	4

⚠ WARNING

LOSS OF CONTROL
If F851 is set to 1, communication control will be inhibited.
For safety reasons, inhibiting the communication interruption detection should be restricted to the debug phase or to special application.
Failure to follow these instructions can result in death, serious injury, or equipment damage.

⚠ WARNING

LOSS OF CONTROL
Know and understand the setting of parameter F851. This parameter controls the behavior of the drive in the event of a network communication loss. If the value of F851 is 0, 1, 2, or 3, the drive will not trip on an Err8.
Failure to follow these instructions can result in death, serious injury, or equipment damage.

0 **Ramp stp (F/Cmod):** Drive ramps to a stop. Serial control is relinquished to the sources defined by [Frequency mode sel] (FMod) and [Command mode sel] (CMod). This function is only used with the Lonworks terminal board.

1 **[No active]**: Last commanded operation continues.
2 **[Ramp stop]**: Drive ramps to a stop. Serial control is maintained.
3 **[Freewheel]**: Drive removes power from the motor which coasts to a stop. Serial control is maintained.
4 **[Err5 or Err8]**: Drive faults with either a communication detected fault Err5 or a network detected fault Err8.

Note: For Modbus connection, only the function 1 is taken into account. The other function make drive trip in Err8 or Err5.

F807	**[Com channel choice]** Communication channel choice	-	1

0 **[RJ45]**: command Modbus via RJ45 port.
1 **[Open style]**: Modbus, BACnet, Apogee P1, Metasys N2 and Lonworks defined by [Network protocol] F829 via open style port.
F807 can only be adjusted while the drive is stopped.

Data structure parameters

Parameters F856– F880 define the structure of data transmitted between the drive and the data communication network

Code	Name / Description	Factory setting
F856	**[Mot. poles (comm.)]** Number of motor poles for communication	2
1	**[2 poles]**	
2	**[4 poles]**	
3	**[6 poles]**	
4	**[8 poles]**	
5	**[10 poles]**	
6	**[12 poles]**	
7	**[14 poles]**	
8	**[16 poles]**	
F870	**[Block write data 1]**	0
0	**[No select]**: No selection	
1	**[Command word 1]**	
2	**[Command word 2]**	
3	**[Frequency Setpoint]**	
4	**[Relay command]**: Ouput data on the terminal board	
5	**[FM command]**: Analog output for communication	
6	**[Speed Setpoint]**	
F871	**[Block write data 2]**	0
0	**[No select]**: No selection	
1	**[Command word 1]**	
2	**[Command word 2]**	
3	**[Frequency Setpoint]**	
4	**[Relay command]**: Ouput data on the terminal board	
5	**[FM command]**: Analog output for communication	
6	**[Speed Setpoint]**	
F875	**[Block read data 1]**	0
0	**[No select]**: No selection	
1	**[Status info]**	
2	**[Freq. out]**: Output frequency	
3	**[Motor current]**: Ouput current	
4	**[Ouput volt]**: Ouput voltage	
5	**[Alarm info]**: Alarm information	
6	**[PID feedback value]**	
7	**[Input term. mon]**: Input terminal board monitor	
8	**[Out term. mon]**: Output terminal board monitor	
9	**[VIA monitor]**: VIA terminal board monitor	
10	**[VIB monitor]**: VIB terminal board monitor	
11	**[Mot speed mon.]**: Ouput motor speed monitor	
F876	**[Block read data 2]**	0
0	**[No select]**: No selection	
1	**[Status info]**	
2	**[Freq. out]**: Output frequency	
3	**[Motor current]**: Ouput current	
4	**[Ouput volt]**: Ouput voltage	
5	**[Alarm info]**: Alarm information	
6	**[PID feedback value]**	
7	**[Input term. mon]**: Input terminal board monitor	
8	**[Out term. mon]**: Output terminal board monitor	
9	**[VIA monitor]**: VIA terminal board monitor	
10	**[VIB monitor]**: VIB terminal board monitor	
11	**[Mot speed mon.]**: Ouput motor speed monitor	

Code	Name / Description	Factory setting
F877	**[Block read data 3]**	0
0	**[No select]**: No selection	
1	**[Status info]**	
2	**[Freq. out]**: Output frequency	
3	**[Motor current]**: Ouput current	
4	**[Ouput volt]**: Ouput voltage	
5	**[Alarm info]**: Alarm information	
6	**[PID feedback value]**	
7	**[Input term. mon]**: Input terminal board monitor	
8	**[Out term. mon]**: Output terminal board monitor	
9	**[VIA monitor]**: VIA terminal board monitor	
10	**[VIB monitor]**: VIB terminal board monitor	
11	**[Mot speed mon.]**: Ouput motor speed monitor	
F878	**[Block read data 4]**	0
0	**[No select]**: No selection	
1	**[Status info]**	
2	**[Freq. out]**: Output frequency	
3	**[Motor current]**: Ouput current	
4	**[Ouput volt]**: Ouput voltage	
5	**[Alarm info]**: Alarm information	
6	**[PID feedback value]**	
7	**[Input term. mon]**: Input terminal board monitor	
8	**[Out term. mon]**: Output terminal board monitor	
9	**[VIA monitor]**: VIA terminal board monitor	
10	**[VIB monitor]**: VIB terminal board monitor	
11	**[Mot speed mon.]**: Ouput motor speed monitor	
F879	**[Block read data 5]**	0
0	**[No select]**: No selection	
1	**[Status info]**	
2	**[Freq. out]**: Output frequency	
3	**[Motor current]**: Ouput current	
4	**[Ouput volt]**: Ouput voltage	
5	**[Alarm info]**: Alarm information	
6	**[PID feedback value]**	
7	**[Input term. mon]**: Input terminal board monitor	
8	**[Out term. mon]**: Output terminal board monitor	
9	**[VIA monitor]**: VIA terminal board monitor	
10	**[VIB monitor]**: VIB terminal board monitor	
11	**[Mot speed mon.]**: Ouput motor speed monitor	

Code	Name / Description	Adjustment range	Factory setting
F880	**[Free ID parameter]** Free Notes	0 to 65535	0
	The free notes parameter can be used to set a unique value to identify the drive on a network.		

Parameters F890 – F896 should be adjusted only if the corresponding optional equipment has been installed. See the ATV212 catalog for more detail.

Code	Name / Description
F890	**[Network adress]**
F891	**[Network baud rate]**
F892	**[Network time out]**
F893	**[Instance number H]**
F894	**[Instance number L]**
F895	**[Max master]**
F896	**[Max info frames]**

When the value of F829 parameter is changed, the adjustment range and factory setting of F890 to F896 are automatically setted.

	Modbus		APOGEE FLN P1		METASYS N2		BACNET	
	Setting Range	Factory setting	Setting Range	Factory setting	Setting Range	Factory set-ting	Setting Range	Factory setting
F829	-	1	3	3	2	2	4	4
F890	0 to 65535	0	1 to 99	99	1 to 255	1	0 to 127	0
F891			0 to 6	0	1 to 5	5	1 to 5	5
F892			20 to 600	100	20 to 600	100	20 to 600	100
F893			0 to 4194	0	0 to 4194	0	0 to 4194	0
F894			0 to 999	0	0 to 999	0	0 to 999	0
F895			0 to 127	0	0 to 127	0	0 to 127	127
F896			0 to 100	0	0 to 100	0	1 to 100	1

There are 2 connection port witch support different communication protocol, embedded or using option board.

The two channels could communicate simultaneously with the product, but only one could send the logical or frequency command to the drive:

- The two channel used for monitoring
- One channel used for command (run order and speed) and the second for monitoring.

The configuration parameters of communication are taking account at next power up of the product.

	Description	RJ45 Modbus	Network Modbus	Network Apogee P1	Network Metasys N2	Network BACnet	Network LonWorks
F829	Network selection	-	●	●	●	●	●
F800	Modbus RJ45 Baud rate	●	-	-	-	-	-
F801	Modbus RJ45 Parity	●	-	-	-	-	-
F802	Modbus address	●	●	-	-	-	-
F803	Modbus time out	●	●	-	-	-	(1)
F851	Com fault behavior	●	●	●	●	●	●
F820	Modbus Net Baud rate	-	●	-	-	-	-
F821	Modbus Net Parity	-	●	-	-	-	-
F890	Network parameter	-	-	●	●	●	-
F891	Network parameter	-	-	●	-	●	-
F892	Network parameter	-	-	●	●	●	-
F893	Network parameter	-	-	-	-	●	-
F894	Network parameter	-	-	-	-	●	-
F895	Network parameter	-	-	-	-	●	-
F896	Network parameter	-	-	-	-	●	-

(1) Time out disconnection board, internal default value (3s)

Start/Stop Control By Speed Reference Level

12

What's in this Chapter?

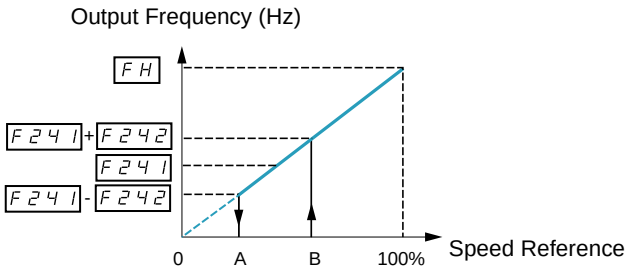
This chapter contains the following topics:

Topic	Page
Overview	144

Overview

Use parameters [Freq. pedestal] (F 2 4 1) and [Freq. pedestal hyst.] (F 2 4 2) to enable start/stop control of the drive based on the speed reference level.

If the drive operates normally and has a run permissive signal, it will start powering the motor as soon as the speed reference level exceeds the frequency set by F 2 4 1 + F 2 4 2 (point B in diagram below). It will remove power from the motor as soon as the output frequency drops below the level set by F 2 4 1 – F 2 4 2 (point A in diagram below).



Code	Name / Description		Adjustment range	Factory setting
F 2 4 1	**[Freq. pedestal]**	Operating starting frequency]	0.0 to **[Max frequency]** (F H) Hz	0.0 Hz
F 2 4 2	**[Freq. pedestal hyst.]**	Operating starting frequency hysteresis	0.0 to **[Max frequency]** (F H) Hz	0.0 Hz

Droop Control

13

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Droop Control	145

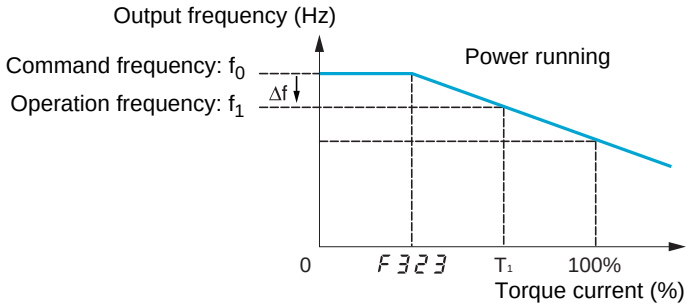
Droop control principle

The use of droop control (or negative slip compensation) can help balance the load between multiple motors in a load sharing application. The amount of slip or speed droop allowed in the motor powering the load is determined by the load current level and the setting of parameters F320 and F323.

During motoring, droop control decreases the drive output frequency. During regenerative braking, droop control increases the drive output frequency.

When enabled, droop control is active when:

- The load current exceeds the level set by parameter F323.
- The drive output frequency is between the [Mot start freq.] F240 (see page 82) and [Max frequency] (FH) (see page 82).



The amount of speed droop allowed (f) can be calculated by this equation:
f = uL (1) x F320 x (load current – F323)(2)

Example:
uL = 60 Hz
F320 = 10%
F323 = 30% (of drive's rated current)
Load current = 100% of drive's rating

f = 60 x 0.1 x (1 – 0.3)
f = 60 x 0.07
f = 4.2

Assuming the speed reference is set to 60 Hz, the output frequency will be: f1 = f0 – f = 60 – 4.2 = 55.8 (Hz).

Code	Name / Description	Adjustment range	Factory setting
F320	**[Load gain]**	0 to 100%	0%
F323	**[Load gain offset]**	0 to 100% (3)	10%

(1) Parameter [Motor Rated freq] (uL) (see page 70). The value entered for uL in this formula should not exceed 100, regardless of the actual setting of parameter uL.
(2) Speed droop is zero if (load current – F323 = 0).
(3) Percent of the drive's rated current.

Diagnostics and troubleshooting

III

What's in this Part?

This part contains the following chapters:

Chapter	Chapter Name	Page
14	Diagnostics and troubleshooting	149

Diagnostics and troubleshooting

14

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Detected fault conditions	150
Alarm Conditions	153
Pre-alarm Conditions	154
Clearing the detected fault	155

Detected fault conditions

Refer to tables on pages hereafter to diagnose and solve troubles when there is a fault detection, or when an alarm, or pre-alarm condition occurs.

If the trouble cannot be solved by the actions described in the tables, contact your Schneider Electric representative.

⚠ ⚠DANGER

HAZARD OF ELECTRIC SHOCK, EXPLOSION OR ARC FLASH

- Read and understand the instructions in «Before you begin» chapter, before performing the procedure in this section.

Failure to follow these instructions will result in death or serious injury.

Alarm Codes

Code	Name	Possible causes	Remedies
CF12	[Download transfer fault]	• Invalid configuration. The configuration loaded in the drive via the bus or communication network is inconsistent. • Transfer using PC soft has not been successful due to rating differences (for example upload of an ATV212●●●N4 configuration to an ATV212●●●M3)	• Check the configuration loaded previously. • Load a compatible configuration. • To perform download, uncheck "Display communication error" (in Tool / Environnement option / Startup/Comm.)
E-18	[VIA signal fault]	• The VIA analog signal is below the level set by parameter F633.	• Check the signal at VIA and rectify the cause of the signal loss. • Verify that parameter F633 is set correctly.
E-19	[CPU communications err.]	• Communication error between control CPUs	• Contact Schneider Electric to repair the drive.
E-20	[Excess torque boost flt]	• Torque boost parameter [Auto Torque Boost] (F402) is set too high. • The motor impedance is too low.	• Repeat the drive auto-tune and then adjust down parameter [Auto Torque Boost] (F402).
		During deceleration when [Mot cont. mode sel.] (Pt) = (1) [Quadr. U/F] with 3 conditions: - Processing for stop - Load current value > 88% x [Motor Current Limitation] (F601) - Too slow deceleration, [Max frequency] (FH) /[Deceleration time 1] (dEC) x 2 msec < 0.01Hz	• Set [Auto ramp] (AU1) = (0) [Disabled] • Decrease the deceleration ramp with [Deceleration time 2] (F501) and [Commut. ramp freq.] (F505).
E-21	[CPU error 2 fault]	• The control board CPU is inoperable.	• Contact Schneider Electric to repair the drive.
E38	[EEprom pwr incompat.]	• Eeprom power incompatible. • Product hardware detected fault.	• Contact Schneider Electric to repair the drive.
EEP1	[EEPROM error 1 fault]	• A data writing error has occurred.	• Cycle power to clear the detected fault.
EEP2	[EEPROM error 2 fault]	• Power was removed from the drive during a parameter reset operation resulting in a data writing error.	• Cycle power to clear the detected fault and try the parameter reset operation again. • If the detected fault does not clear, contact Schneider Electric to repair the drive.
EEP3	[EEPROM error 3 fault]	• A data reading error has occurred.	• Cycle power to clear the detected fault.
EF2	[Ground fault]	• Ground fault in motor or motor cables	• Check the motor and motor cables for ground faults.
EPHO	[Output phase loss fault]	• Loss of one or more output phases	• Determine the cause of the missing output phase (such as a bad connection, an output disconnect, or an open winding in the motor) and rectify the trouble. • Check parameter F605.
EPH1	[Input phase loss fault]	• Loss of one input phase	• Determine the cause of the missing input phase and rectify. • Check parameter F608.
Err1	[Speed ref. error fault]	• Parameters F202, F203, F210, or F212 are set improperly.	• Set the parameters to the correct settings.

Code	Name	Possible causes	Remedies
Err2	[RAM fault]	• The control board RAM is inoperable.	• Contact Schneider Electric to repair the drive.
Err3	[ROM fault]	• The control board ROM is inoperable.	• Contact Schneider Electric to repair the drive.
Err4	[CPU fault 1]	• The control board CPU is inoperable.	• Contact Schneider Electric to repair the drive.
Err5	[Com RJ45 fault]	• Serial communication error	• Check network control devices and cables. • Check the setting of the communication timeout parameter, F803. • Check the remote graphic display option cable. • Check the setting of F829 parameters.
Err7	[Current sensor fault]	• A motor current sensor is inoperable.	• Replace the drive.
Err8	[Network error fault]	• Network communication error	• Check the network control devices and cables.
Err9	[Remote keypad fault]	• Graphic display option cable disconnected	• Check the RJ45 cable.
EtnI	[Auto-tuning fault]	• Parameters F401 to F494 are incorrectly set. • The motor is too large for the drive. • The motor cable gauge is too small. • The motor is still rotating at the start of the auto-tune. • The drive is not powering a 3-phase induction motor.	• Set parameters F401–F494 correctly. • Use a larger drive. • Use a larger gauge motor cable. • Verify that the motor is stopped before starting an auto-tune. • Use the drive to power only a 3-phase induction motor.
EtyP	[Drive fault]	• The main control board is inoperable.	• Set parameter [Parameter reset] (tyP) to 6. • If this does not clear the detected error, replace the drive.
Fd1	[Closed damper 1 fault]	• Damper is locked in closed position.	• Set [Damper flt behavior] (F583) to 0. • Check the FL relay connection (FLA/FLB). • Check the relay configuration (F130/F132).
Fd2	[Closed damper 2 fault]	• Damper blocked open or soldered.	• Set [Damper fdb type] (F580) to 0 or 1.Check the FL relay connection (FLA/FLB). • Check the relay configuration (F130/F132).
nO2O	[Total input power]	• The accumulated input power value is more than 999.999 kWh.	• Clear the accumulated input power value using logic input function 51, or parameter F748.
OCI	[Overcurrent acceleration]	• The acceleration time is too short. • The setting of parameter [Mot cont. mode sel.] (Pt) is incorrect. • The drive is starting into a rotating load. • The drive is powering a low impedance motor. • Ground fault	• Increase the acceleration time parameters (ACC or F500). • Select the correct setting for parameter [Mot cont. mode sel.] (Pt). • Enable catch on the fly, parameter F301. • Adjust the switching frequency parameter F300. • Set parameter F316 to 1 or 3.
OCIP	[SC or ground fault acc.]	• Short circuit or ground fault during acceleration	• Using a 1000 V testing tool megger, check the motor and motor cables for ground faults.
OC2	[Overcurrent deceleration]	• The deceleration time is too short. • Ground fault	• Increase the deceleration time parameters (dEC or F501). • Set parameter F316 to 1 or 3.
OC2P	[SC or ground fault dec.]	• Short circuit or ground fault during deceleration	• Using a 1000 V megger, check the motor and motor cables for ground faults.
OC3	[Overcurrent cont. speed]	• Abrupt fluctuations in load • Abnormal load condition	• Reduce the load fluctuations. • Check the load. • Set parameter F316 to 1 or 3.
OC3P	[SC/ground flt cont. spd]	• Short circuit or ground fault during constant speed operation	• Using a 1000 V megger, check the motor and motor cables for ground faults.
OCA	[SC inverter at start]	• Ground fault	• Using a 1000 V megger, check the motor and motor cables for ground faults.
OCL	[SC mot. cable at start]	• Phase to phase output short circuit • The motor impedance is too low.	• Using a 1000 V megger, check the motor and motor cables for ground faults.

Code	Name	Possible causes	Remedies
OH	[Drive overtemperature]	• The drive cooling fan is not working. • The ambient temperature is too high. • An enclosure air vent is blocked. • A heat source is too close to the drive. • The drive heatsink temperature sensor is malfunctioning.	• Restart operation by resetting the drive detected fault after cool-off. • Decrease the ambient temperature by increasing the free space around the drive and removing any heat generating source from the proximity of the drive. • Check the fan operation
OH2	[PTC overheating]	• The external PTC embedded in the motor windings indicates a motor overtemperature condition.	• Correct the motor overload condition. • Check the PTC for correct operation.
OL1	[Drive overload]	• The acceleration time is too short. • The DC injection current level is too high. • The setting of parameter [Mot cont. mode sel.] (PtC) is incorrect. • The drive is starting into a rotating load. • The load is too large.	• Increase the acceleration time parameters (ACC or F500). • Reduce the setting of parameters F251 and/or F252. • Select the correct setting for parameter [Mot cont. mode sel.] (PtC). • Enable catch on the fly, parameter F301. • Set parameter F302 to 2. • Use a drive with a higher power rating.
OL2	[Motor overload]	• The setting of parameter [Mot cont. mode sel.] (PtC) is incorrect. • The motor is jammed. • Low-speed operation is performed continuously • Excessive load is applied to the motor.	• Select the correct setting for parameter [Mot cont. mode sel.] (PtC). • Check the load. • Adjust parameter OLN to the overload level that the motor can withstand during low speed operation.
OP1	[Overvoltage acceleration]	• The input voltage is fluctuating abnormally. • Power network is greater than 200 kVA. • Power factor capacitor switching • SCR switching on power network • The drive is starting into a rotating load. • Intermittent output phase fault	• Install a line reactor. • Enable catch on the fly, parameter F301. • Set parameter F302 to 2. • Determine the cause of the missing output phase (such as a bad connection, an output disconnect, or an open winding in the motor) and rectify the trouble.
OP2	[Overvolt. deceleration]	• The deceleration time is too short. • Overhauling load • The input voltage is fluctuating abnormally. • Power network is greater than 200 kVA • Power factor capacitor switching • SCR switching on power network • The drive is starting into a rotating load. • Intermittent output phase fault	• Increase the deceleration time parameters (DEC or F501). • Enable parameter F305. • Install a line reactor. • Check the input and output circuits for phase loss detection and rectify. • Enable catch on the fly, parameter F301.
OP3	[Overvoltage cont. speed]	• The input voltage is fluctuating abnormally. • Power network is greater than 200 kVA • Power factor capacitor switching • SCR switching on power network • The drive is regenerating - the load causes the motor to run at a frequency higher than drive output frequency. • Intermittent output phase fault	• Install a line reactor. • Check the input and output circuits for phase loss detection and rectify.
Ot	[Overtorque]	• The calculated motor torque has reached the level set by parameter F616.	• Adjust the settings of parameters F615 and F616 as needed. • Verify machine operation.
SOUt	[PM motor step-out] (permanent magnet motor pulls out of synchronism)	• The motor is jammed. • Output phase loss • Impact load	• Check the load and correct the jammed condition. • Check the condition of the motor and load wiring.
UC	[Underload]	• The measured motor current has dropped below the level set by parameter F611.	• Check parameters F610–612 for the correct settings.
UP1	[Undervoltage]	• The input voltage is too low.	• Check the input voltage and rectify the trouble. • Select the correct setting for parameter F627. • Enable catch on the fly, parameter F301. • Set parameter F302 to 2.

Alarm Conditions

Alarms do not cause the drive to enter a fault condition.

Alarm Codes

Code	Description	Possible causes	Remedies
AtnI	[Auto tune]	• Auto-tuning in process	• Normal if it the message disappears after a few seconds.
CLr	[Reset active]	• This message is displayed after the STOP key is pressed while an detected fault is displayed.	• Press the STOP key again to clear the detected fault.
db	[DC braking]	• DC braking in process	• The alarm code goes off in several seconds if no trouble occurs.
dbOn	[dbOn]	• Motor shaft fixing control	•
E-17	[HMI error]	• A graphic display option key has been held down for more than 20 seconds. • A graphic display option key may not be operating properly.	• Release the graphic display option key. • If this does not clear the error, replace the drive.
E1	[Excess value] The number of digits that can be displayed has been exceeded	• The number of digits entered for values such as frequencies is more than 4 (the upper digits have priority).	• Lower the frequency free-unit magnification [Customized freq val] (F702).
EOFF	[Loc. Stop en.]	• The operation panel is used to stop the operation in automatic control or remote control mode.	• Press the STOP key for an emergency stop. To cancel the emergency stop, press any other key.
Err1	[Speed ref alarm]	• The frequency setting signals at points 1 and 2 are set too close to each other.	• Set the frequency setting signals at points 1 and 2 apart from each other.
h999	[Pin&1MWh] Integral input power	• Integral input power is more than 999.99 kWh.	• Press and hold down the ENT key for 3 s or more when power is off or when the input terminal function CKWH is turned on or displayed.
H999	[Pout&1MWh] Integral output power	• Integral output power is more than 999.99 kWh.	• Press and hold down the ENT key for 3 s or more when power is off or when the input terminal function CKWH is turned on or displayed.
HEAd End	[Head] [End] Display of first/last data items	• The first and last data item in the auh data group is displayed.	• Press MODE key to exit the data group.
HI LO	[High] [Low] Parameter adjustment error	• During programming, a value was entered that exceeds the maximum or minimum value of the parameter.	• Enter a value within the bounds of the parameter
InIt	[Initialization]	• Parameters are being initialized to default values.	• Normal if the message disappears after several seconds.
LSTP	[Low speed stop] Auto-stop because of continuous operation at the lower-limit frequency	• The automatic stop function selected with F256 was activated.	• To deactivate the automatic stop function, increase the frequency command above the lower-limit frequency LL+F391 or turn off the operation command.
NOFF	[Line undervolt flt]	• The phase-to-phase input voltage is too low.	• Measure the main circuit supply voltage. If the voltage is at a normal level, the drive requires repair.
OFF	[Drive stop]	• The ST-CC (run permissive) circuit is open.	• Close the ST-CC circuit.
nSt	[Lock State]	• The Li is already active when the function is validated. • The Li is already active when a configuration transfer is done with the function is validated.	• Deactivate the active Li configured.
rtry	[Auto reset]	• The drive is in the process of restart. • A momentary stop occurred.	• The drive is operating normally if it restarts after several seconds.
STOP	[Stop supply] Momentary power loss slowdown stop prohibition function activated.	• The slowdown stop prohibition function set with F302 (momentary power loss ride-through operation) is activated.	• To restart operation, reset the drive or input an operation signal again.

Pre-alarm Conditions

Pre-alarm Codes

Code	Pre-alarm	Description
C	[Current alarm]	• The drive is at current limit. • For more information, refer to parameter F60 1 (see page 69) and F 185 (see page 74).
P	[DC bus alarm]	• The drive is approaching an overvoltage detected fault due to a high supply line, regenerative motor braking, or a combination of these. For more information, refer to parameters F305 (see page 128) and F626 (see page 128).
L	[Motor overload al]	• The motor overload timer has reached or exceeded 50% of its detected fault level.
H	[Drv overheat alrm]	• The drive is approaching an overheating fault detection.

The pre-alarm codes are displayed, flashing on the embedded HMI, in the following order from left to right: C, P, L, H.

If two or more troubles arise simultaneously, one of the following pre-alarm codes appears and flashes: CP, PL, CPL.

Clearing the detected fault

In the event of a non resettable detected fault:

1. Disconnect all power, including external control power that may be present.
2. Lock all power disconnects in the open position.
3. Wait 15 minutes to allow the DC bus capacitors to discharge (the drive LEDs are not indicators of the absence of DC bus voltage).
4. Measure the voltage of the DC bus between the PA/+ and PC/– terminals to ensure that the voltage is less than 42 Vdc.
5. If the DC bus capacitors do not discharge completely, contact your local Schneider Electric representative. Do not repair or operate the drive.
   - Find and correct the detected fault.
   - Restore power to the drive to confirm the detected fault has been rectified.

When any overload function (OL 1 or OL 2) is active, the drive cannot be reset by inputting a reset signal from an external device or with the Stop key on the display terminal if the calculated cooling time has not expired. Calculated cooling time:

- OL 1: 30 seconds after the detected fault has occurred
- OL 2: 120 seconds after the detected fault has occurred

CAUTION

RISK OF DAMAGE TO THE MOTOR

- Repeated reset of the thermal state after a thermal overload can result in thermal stress to the motor.
- When trips occur, promptly inspect the motor and driven equipment for problems (such as a locked shaft or mechanical overload) before restarting. Also check the power supplied to the motor for abnormal conditions (such as a phase loss or phase imbalance).

Failure to follow these instructions can result in equipment damage.

Annex

IV

What's in this Part?

This part contains the following chapters:

Chapter	Chapter Name	Page
15	Migration	159
17	Parameters Reset Tables	161
18	User Settings Tables	171

Migration

15

What's in this Chapter?

This chapter contains the following topics:

Topic	Page
Migration ATV21 - ATV212	160

Migration ATV21 - ATV212

General

The ATV212 is compatible with the ATV21

Migration Modbus ATV21 to ATV212: When controlling ATV21 using Modbus RJ45, parameter [Network protocol] (F B 2 9) should be set to 1.

With ATV212, parameter F B 2 9 should also be set to 1 and parameter [Com channel choice] (F B 0 7) set to [RJ45] (0). Factory setting is [Open style] (1).

Settings of other communication parameters described from page 138 remain the same as on ATV21.

Note: For LonWorks, parameter F B 2 9 needs to be set to 1 for ATV21 and needs to be set to 5 for ATV212.

A configuration transfer from ATV21 to ATV212 is possible.

For example:

You can upload a configuration from an ATV21 via PC Soft (and selected the inverter Type : ATV21) and download it into ATV212.

After a transfer from ATV21 to ATV212, the new parameters stay at their factory setting:

[Damper fdb type] (F 5 8 0), [Time open Damper] (F 5 8 1), [Time close Damper] (F 5 8 2) ,[Damper flt behavior] (F 5 8 3),[Forced fire control] (F 6 5 0), [Forced fire function] (F 6 5 9), [Com channel choice] (F B 0 7), [Mdb network baud] (F B 2 0), [Mdb network parity] (F B 2 1) and [LL for ov.cur. prev.] (F 3 9 0).

The download configuration is not allowed if the drive is running.

In case of an interruption of download configuration transfer to the drive and detected fault, the C F 1 2 is set. This detected fault code keeps also present even after power off of the drive.

To reset the download transfer detected fault code C F 1 2:

- Make a new successful transfer
- Make a factory setting on the drive (using t y P parameter)

At the end of download transfer, the drive cannot run if a logic input configured to a function is active. To use the function and run the motor, it's necessary to disable and enable the logic input.

Commissioning

Compatible loader tool with ATV21

- PC Soft V1.0 and higher

Compatible loader tools with ATV212:

- PC Soft V1.06 and higher,
- Multi-Loader V3.11 and higher,
- SoMoveMobile V2.2 and higher,

Parameters Reset Tables

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Parameter Reset

Refer to Menu navigation diagram page 62 to know how to reach [Parameter reset] (tyP) parameter.

The Altivar 212 drive offers three parameter reset options:

- Factory reset: [Parameter reset] (tyP) = 3
- 50 Hz reset: [Parameter reset] (tyP) = 1
- 60 Hz reset: [Parameter reset] (tyP) = 2

This appendix describes parameter values after these reset operations.

The following tables identify:

- Parameters whose values after a reset do not vary by reset type, see page 162.
- Parameters whose values after a reset vary by reset type, see page 166.
- Parameters whose values after a reset are drive model dependant but do not vary by reset type, see page 167.
- Parameters whose values after a reset are drive model and reset type dependant, see page 168.
- Parameters whose values do not change if a reset is performed, see page 169.

Parameter values that do not vary by reset type

The table below lists the parameters whose values, after a reset, do not vary by the reset type.

To determine the value of a parameter after a reset, locate the parameter in the first column and read across the row to the default value column. The number that appears at the intersection of the parameter and the default value is the parameter's value after a reset of any type ([Parameter reset] (tYP) = 1, [Parameter reset] (tYP) = 2, or [Parameter reset] (tYP) = 3).

Parameters whose values after a reset do not vary by reset type

Parameter	Description	Unit	Default Value
AU1	[Auto ramp]	–	1
AU4	[Auto set function]	–	0
FMSL	[AO funct. selection]	–	0
FM	[AO scaling]	–	–
tYP	[Parameter reset]	–	0
Fr	[Local mot. direction]	–	0
FC	[Local speed ref.]	Hz	0.0
LL	[Low limit frequency]	Hz	0.0
Pt	[Mot cont. mode sel.]	–	1
OLM	[Motor overload prot]	–	0
Sr1	[Preset speed 1]	Hz	15
Sr2	[Preset speed 2]	Hz	20
Sr3	[Preset speed 3]	Hz	25
Sr4	[Preset speed 4]	Hz	30
Sr5	[Preset speed 5]	Hz	35
Sr6	[Preset speed 6]	Hz	40
Sr7	[Preset speed 7]	Hz	45
F100	[Freq. 1 reached]	Hz	0.0
F101	[Freq. 2 reached]	Hz	0.0
F102	[Freq.2 bandw.]	Hz	2.5
F108	[Logic Funct 1 active]	–	0
F109	[VIA selection]	–	0
F110	[Logic Funct 2 active]	–	1
F111	[LI F selection]	–	2
F112	[LI R selection]	–	6
F113	[LI RES selection]	–	10
F118	[VIA LI selection]	–	7
F130	[RY Relay Function 1]	–	4
F132	[FL Relay Function]	–	11
F137	[RY Relay Function 2]	–	255
F139	[RY logic select.]	–	0
F167	[Freq band det range]	Hz	2.5
F200	[Auto/man speed ref]f	–	0
F201	[VIB ref. point 1]	%	0
F202	[VIA freq. point 1]	Hz	0.0
F203	[VIA freq. point 2]	%	100
F207	[Remote spd ref 2]	–	2
F210	[VIB ref. point 1]	%	0

Parameter	Description	Unit	Default Value
F211	[VIB freq. point 1]	Hz	0.0
F212	[VIB ref. point 2]	%	100
F240	[Mot start freq.]	Hz	0.5
F241	[Freq. pedestal]	Hz	0.0
F242	[Freq. pedestal hyst.]	Hz	0.0
F250	[DC brake start freq.]	Hz	0.0
F251	[DC braking current]	A	50
F252	[DC braking time]	s	1.0
F256	[Time limit low spd]	s	0.0
F264	[+speed LI resp time]	s	0.1
F265	[+speed freq. step]	Hz	0.1
F266	[- speed LI resp time]	s	0.1
F267	[- speed freq. step]	Hz	0.1
F268	[Init +/- Speed]	Hz	0.0
F269	[Init +/- Speed memo]	–	1
F270	[Jump frequency 1]	Hz	0.0
F271	[Jump bandwidth 1]	Hz	0.0
F272	[Jump frequency 2]	Hz	0.0
F273	[Jump bandwidth 2]	Hz	0.0
F274	[Jump frequency 3]	Hz	0.0
F275	[Jump bandwidth 3]	Hz	0.0
F294	[Forced speed freq.]	Hz	50
F295	[Switch rem/Local]	–	1
F301	[Catch on fly]	–	3
F302	[Supply loss behav.]	–	0
F305	[Overvoltage fault]	–	2
F307	[Mot volt limitation]	–	3
F311	[Motor direction]	–	1
F312	[Noise reduction]	–	0
F316	[Switch. freq. mode]	–	1
F320	[Load gain]	%	0
F323	[Load gain offset]	%	10
F359	[PID ctrl wait time]	s	0
F360	[PID control enable]	–	0
F362	[PID Prop Gain]	–	0.30
F363	[PID Integral Gain]	–	0.20
F366	[PID Derivative Gain]	–	0.00
F400	[Auto-tuning drive]	–	0
F401	[Slip Compensation]	%	50
F418	[Frequency loop gain]	–	40
F419	[Freq. loop stability]	–	20
F470	[VIA bias]	–	128
F471	[VIA gain]	–	148
F472	[VIB bias]	–	128
F473	[VIB gain]	–	148
F482	[In noise Inhibit filter]	µs	442

Parameter	Description	Unit	Default Value
F483	[In noise inhibit gain]	–	100
F484	[Pwr supply adj. gain]	–	0.0
F485	[Stall control coef. 1]	–	100
F492	[Stall control coef. 2]	–	100
F495	[Motor voltage coef.]	%	104
F496	[PWM adj. coef.]	kHz	14.0
F502	[Acc/dec 1 pattern]	–	0
F503	[Acc/dec 2 pattern]	–	0
F504	[Ramp switching]	–	1
F505	[Commut. ramp freq.]	Hz	0.0
F506	[Acc/Dec S-pat start]	%	10
F507	[Acc/Dec S-pat end]	%	10
F602	[Drive fault memory]	–	0
F603	[Ext. fault stop Mode]	–	0
F604	[DC brk time ext flt]	s	1.0
F605	[Output phase loss]	–	3
F607	[Mot overload time]	s	300
F608	[Input phase loss]	–	1
F609	[Underload band]	%	10
F610	[Underload det.]	–	0
F611	[Underload level]	% / A	0
F612	[Underload det. time]	s	0
F613	[Short circuit det.]	–	0
F615	[Overtorque det.]	–	0
F616	[Overtorque level]	%	130
F618	[OvTorque det time]	s	0.5
F619	[Overtorque band]	%	10
F621	[Run time alarm]	h	610.0 (6100 h)
F627	[Undervolt detect.]	–	0
F632	[Mot overload memo]	–	0
F633	[Loss of VIA]	%	0
F634	[Amb. temp. alarm]	–	3
F645	[Mot PTC selection]	–	0
F646	[PTC resistor value]	Ω	3000
F650	[Forced fire control]	–	0
F691	[AO slope]	–	1
F692	[Analog output bias]	%	0
F700	[Parameter lock]	–	0
F701	[Unit value selection]	–	1
F702	[Customized freq val]	–	0
F703	[Frequency convert.]	–	0
F706	[Customize unit bias]	Hz	0.0
F707	[Loc. speed ref. step]	Hz	0.0
F708	[Display ref. resol.]	–	0
F710	[Displayed param.]	–	0
F721	[Loc. mot stop mode]	–	0

Parameter	Description	Unit	Default Value
F730	[Up/down key ref]	–	0
F732	[Loc/rem key]	–	0
F733	[Run/stop key]	–	0
F734	[Priority stop]	–	0
F735	[HMI reset button]	–	1
F738	[Quick menu AUF]	–	0
F748	[Power cons. memo]	–	1
F800	[Mdb RJ45 baud]	–	1
F801	[Mdb RJ45 parity]	–	1
F802	[Modbus address]	–	1
F803	[Com. time out]	s	3
F829	[Network protocol]	–	1
F851	[Com. fault setting]	–	4
F856	[Mot. poles (comm.)]	–	2
F870	[Block write data 1]	–	0
F871	[Block write data 2]	–	0
F875	[Block read data 1]	–	0
F876	[Block read data 2]	–	0
F877	[Block read data 3]	–	0
F878	[Block read data 4]	–	0
F879	[Block read data 5]	–	0
F880	[Free ID parameter]	–	0
F890	[Network adress]	–	(1)
F891	[Network baud rate]	–	(1)
F892	[Network time out]	–	(1)
F893	[Instance number H]	–	(1)
F894	[Instance number L]	–	(1)
F895	[Max master]	–	(1)
F896	[Max info frames]	–	(1)

(1) See table page 167.

Parameter values that vary according to reset type

The table below lists the parameters whose values, after a reset, depend on the reset type ([Parameter reset] (tYP) = 1, [Parameter reset] (tYP) = 2, or [Parameter reset] (tYP) = 3).

To determine the value of a parameter after a reset, locate the parameter in the first column and read across the row to the column that corresponds to the reset type. The number that appears at the intersection of the parameter and the reset type is the parameter's value after a reset of the corresponding type.

Parameters whose values after a reset vary by reset type

Parameter	Description	Unit	Factory Reset tYP = 3	50 Hz Reset tYP = 1	60 Hz Reset tYP = 2
CMOd	[Command mode sel]	–	0	0	0
FMOd	[Frequency mode sel]	–	1	1	1
FH	[Max frequency]	Hz	50	50	60
uL	[Upper limit freq]	Hz	50	50	60
uL	[Motor rated freq.]	Hz	50	50	60
F170	[Mot 2 rated Freq.]	Hz	50	50	60
F204	[VIA freq. point 2]	Hz	50	50	60
F213	[VIB freq. point 2]	Hz	50	50	60
F303	[Number auto reset]	–	0	0	0
F480	[No load cur. coef]	%	100	0	100
F481	[In noise comp. filter]	micro-seconds	0	100	0

Parameter values that vary According to drive rating, but not reset type

The table below lists the parameters whose values, after a reset, depend on the drive model.

To determine the value of a parameter after a reset, locate the drive model number in first column and read across the row to the column that corresponds to the parameter code. The number that appears at the intersection of the model number and the parameter code is the parameter's value after a reset. These values are the same for every reset types ([Parameter reset] (tYP) = 1, [Parameter reset] (tYP) = 2, or [Parameter reset] (tYP) = 3).

Parameters whose values after a reset are drive model dependant but do not vary by reset type

Reference	Parameter										
	ACC	dEC	vLv	ub	F171	F172	F300	F402	F494	F626	F749
	s	s	V	%	V	%	kHz	%	-	%	-
ATV212H075M3X	10	10	200	6	200	6	12	5.8	80	140	0
ATV212HU15M3X	10	10	200	6	200	6	12	4.3	70	140	0
ATV212HU22M3X	10	10	200	5	200	5	12	4.1	70	140	0
ATV212HU30M3X	10	10	200	5	200	5	12	3.7	70	140	0
ATV212HU40M3X	10	10	200	5	200	5	12	3.4	70	140	1
ATV212HU55M3X	10	10	200	4	200	4	12	3.0	70	140	1
ATV212HU75M3X	10	10	200	3	200	3	12	2.5	70	140	1
ATV212HD11M3X	10	10	200	2	200	2	12	2.3	60	140	1
ATV212HD15M3X	10	10	200	2	200	2	12	2.0	50	140	1
ATV212HD18M3X	30	30	200	2	200	2	8	2.0	50	140	1
ATV212HD22M3X	30	30	200	2	200	2	8	1.8	50	140	1
ATV212HD30M3X	30	30	200	2	200	2	8	1.8	50	140	1
ATV212H075N4	10	10	400	6	400	6	12	5.8	80	140	0
ATV212HU15N4	10	10	400	6	400	6	12	4.3	70	140	0
ATV212HU22N4	10	10	400	5	400	5	12	4.1	70	140	0
ATV212HU30N4	10	10	400	5	400	5	12	3.7	70	140	0
ATV212HU40N4	10	10	400	5	400	5	12	3.4	70	140	1
ATV212HU55N4	10	10	400	4	400	4	12	2.6	70	140	1
ATV212HU75N4	10	10	400	3	400	3	12	2.3	70	140	1
ATV212HD11N4	10	10	400	2	400	2	12	2.2	60	140	1
ATV212HD15N4	10	10	400	2	400	2	12	1.9	50	140	1
ATV212HD18N4	30	30	400	2	400	2	8	1.9	50	140	1
ATV212HD22N4S	30	30	400	2	400	2	6	1.8	50	140	1
ATV212HD22N4	30	30	400	2	400	2	8	1.8	50	140	1
ATV212HD30N4	30	30	400	2	400	2	8	1.8	50	140	1
ATV212HD37N4	30	30	400	2	400	2	8	1.8	50	140	2
ATV212HD45N4	30	30	400	2	400	2	8	1.7	50	140	2
ATV212HD55N4	30	30	400	2	400	2	8	1.6	40	140	2
ATV212HD75N4	30	30	400	2	400	2	8	1.5	40	140	2

Parameter values that vary According to drive rating and reset type

The table below lists lists the parameters whose values, after a reset, depend on the drive model and the reset type ([Parameter reset] (tYP) = 1, [Parameter reset] (tYP) = 2, or [Parameter reset] (tYP) = 3). To determine the value of a parameter after a reset:

1. Locate the drive model number in the first column.
2. Read across the row to the group of columns that corresponds to the reset type ([Parameter reset] (tYP) = 1, [Parameter reset] (tYP) = 2, or [Parameter reset] (tYP) = 3).
3. Locate the parameter code in the columns corresponding to the reset type.

The number that appears at the intersection of the drive model number and the parameter code is the parameter's value after a reset of the specified type.

Parameters whose values after a reset are drive model and reset type dependant

Reference	Factory reset tYP = 3				50 Hz reset tYP = 1							60 Hz reset tYP = 2						
	tHr	F173	F185	F601	tHr	F173	F185	F415	F416	F417	F601	tHr	F173	F185	F415	F416	F417	F601
	%	%	%	%	%	%	%	A	%	rpm	%	%	%	%	A	%	rpm	%
ATV212H075M3X	100	100	110	110	100	100	110	3.5	64	1400	110	100	100	110	3.0	60	1700	110
ATV212HU15M3X	100	100	110	110	100	100	110	6.1	61	1420	110	100	100	110	5.8	59	1715	110
ATV212HU22M3X	100	100	110	110	100	100	110	8.8	59	1430	110	100	100	110	8.0	61	1715	110
ATV212HU30M3X	100	100	110	110	100	100	110	12.5	63	1420	110	100	100	110	12.4	48	1760	110
ATV212HU40M3X	100	100	110	110	100	100	110	15.8	61	1425	110	100	100	110	15.2	51	1769	110
ATV212HU55M3X	100	100	110	110	100	100	110	20.6	57	1430	110	100	100	110	22.0	53	1780	110
ATV212HU75M3X	100	100	110	110	100	100	110	26.3	54	1450	110	100	100	110	28.0	42	1780	110
ATV212HD11M3X	100	100	110	110	100	100	110	36.9	53	1450	110	100	100	110	36.0	39	1766	110
ATV212HD15M3X	100	100	110	110	100	100	110	49.5	53	1455	110	100	100	110	48.0	36	1771	110
ATV212HD18M3X	100	100	110	110	100	100	110	61.0	53	1455	110	100	100	110	61.0	39	1771	110
ATV212HD22M3X	100	100	110	110	100	100	110	68.0	53	1460	110	100	100	110	68.0	36	1771	110
ATV212HD30M3X	100	100	110	110	100	100	110	93.0	50	1460	110	100	100	110	93.0	33	1771	110
ATV212H075N4	100	100	110	110	100	100	110	2.0	64	1400	110	100	100	110	1.5	60	1720	110
ATV212HU15N4	100	100	110	110	100	100	110	3.5	61	1420	110	100	100	110	2.9	59	1700	110
ATV212HU22N4	100	100	110	110	100	100	110	5.1	59	1430	110	100	100	110	4.0	61	1715	110
ATV212HU30N4	100	100	110	110	100	100	110	7.2	63	1420	110	100	100	110	6.2	48	1715	110
ATV212HU40N4	100	100	110	110	100	100	110	9.1	61	1425	110	100	100	110	7.6	51	1760	110
ATV212HU55N4	100	100	110	110	100	100	110	11.9	57	1430	110	100	100	110	11.0	53	1769	110
ATV212HU75N4	100	100	110	110	100	100	110	15.2	54	1450	110	100	100	110	14.0	42	1780	110
ATV212HD11N4	100	100	110	110	100	100	110	21.3	53	1450	110	100	100	110	21.0	39	1780	110
ATV212HD15N4	100	100	110	110	100	100	110	28.6	53	1455	110	100	100	110	27.0	36	1766	110
ATV212HD18N4	100	100	110	110	100	100	110	35.1	53	1455	110	100	100	110	35.1	39	1771	110
ATV212HD22N4S	100	100	110	110	100	100	110	41.7	53	1460	110	100	100	110	41.7	36	1780	110
ATV212HD22N4	100	100	110	110	100	100	110	41.7	53	1460	110	100	100	110	41.7	36	1771	110
ATV212HD30N4	100	100	110	110	100	100	110	55.0	50	1460	110	100	100	110	55.0	33	1771	110
ATV212HD37N4	100	100	110	110	100	100	110	67	51	1475	110	100	100	110	67	31	1771	110
ATV212HD45N4	100	100	110	110	100	100	110	81	51	1475	110	100	100	110	71	34	1771	110
ATV212HD55N4	100	100	110	110	100	100	110	99	53	1480	110	100	100	110	86	31	1771	110
ATV212HD75N4	100	100	110	110	100	100	110	135	53	1480	110	100	100	110	114	31	1771	110

Parameter values that do not change if reset

The parameters listed in the table below cannot be reset. The table lists the default settings of these parameters.

Parameters whose values do not change if a reset is performed

Parameter	Description	Default Value
FN	[AO scaling]	–
FNSL	[AO funct. selection]	0
F109	[VIA selection]	0
F470	[VIA bias]	128
F471	[VIA gain]	148
F472	[VIB bias]	128
F473	[VIB gain]	148
F880	[Free ID parameter]	0

User Settings Tables

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Use the Configuration Setting Table to look up parameter default settings, to record customized parameter settings, and to look up sections of the manual, by page number, that contain detailed parameter descriptions.

Configuration Setting Table

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
FC	77	[Local speed ref.]	Hz	–	[Low limit frequency] (LL) to [Upper limit freq] (UL)	0.0	
AUI	85	[Auto ramp]	-	0	[Disabled]	1	
				1	[Enable]		
				2	[ACC only]		
AU4	63	[Auto set function]	-	0	[Factory set]	0	
				1	[Run permissive]		
				2	[3-wire]		
				3	[+/- Speed]		
				4	[4-20mA speed ref]		
CMOd	77	[Command mode sel]	-	0	[Logic inputs]	0	
				1	[HMI]		
				2	[Communication]		
FMOd	77	[Frequency mode sel]	-	1	[Ref source VIA]	1	
				2	[Ref source VIB]		
				3	[HMI reference]		
				4	[Serial com ref.]		
				5	[+/- Speed]		
FMSL	108	[AO funct. selection]	-	0	[Motor frequency]	0	
				1	[Motor current]		
				2	[Speed ref]		
				3	[DC bus U]		
				4	[Motor U]		
				5	[Input power]		
				6	[Output power]		
				7	[motor torque]		
				8	[Torque I]		
				9	[Motor thermal]		
				10	[Drive thermal]		
				11	[Do not use]		
				12	[Internal reference]		
				13	[VIA]		
				14	[VIB]		
				15	[Fixed 100%]		
				16	[Fixed 50%]		
				17	[Fixed 100%]		
				18	[Com data]		
				19	[Do not use]		
FM	108	[AO scaling]	-	–	–	–	

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
tYP	62	[Parameter reset]	-	0	[No action]	0	–
				1	[50 Hz reset]		
				2	[60 Hz reset]		
				3	[Factory set]		
				4	[Trip cleared]		
				5	[Cumul time clear]		
				6	[EtYP fault reset]		
				7	[Save parameters]		
				8	[Recall parameters]		
				9	[Elapse time reset]		
Fr	77	[Local mot. direction]	-	0	[Run FW]	0	
				1	[Run rev.]		
				2	[Run FW+rev]		
				3	[Run rev+FW]		
ACC	83	[Acceleration time 1]	s	–	0.0 – 3200	Model depen-dent	
dEC	83	[Deceleration time 1]	s	–	0.0 – 3200	Model depen-dent	
FH	82	[Max frequency]	Hz	–	30.0 – 200.0	80.0	
UL	82	[Upper limit freq]	Hz	–	0.5 – [Max frequency] (FH)	50.0	
LL	82	[Low limit frequency]	Hz	–	0.0 – [Upper limit freq] (UL)	0.0	
uL	70	[Motor rated freq.]	Hz	–	25.0 – 200.00	50.0	
uLu	70	[Motor Rated Voltage]	V	230 V models	50 – 330	230	
				460 V models	50 – 660	400	
Pt	67	[Mot cont. mode sel.]	-	0	[Constant V/Hz]	1	
				1	[Variable Torque]		
				2	[Cst V/Hz+Boost]		
				3	[SVC]		
				4	[Economy]		
				5	[Do not use]		
				6	[Do not use]		
ub	68	[Motor Voltage Boost]	%	–	0.0 – 30.0	Model depen-dent	
tHr	70	[Motor thermal prot.]	%/A	–	10 – 100% of drive's output current rating	100%	
OLn	135	[Motor overload prot]	-	0	[Std mot. protect.]	0	
				1	[Std & stall mot. prot]		
				2	[Self cool]		
				3	[Slf cool stall ov.load]		
				4	[Forced cool prot]		
				5	[Forc cool stall prot]		
				6	[Forced cool]		
				7	[F cool & stall ov load]		
Sr1	112	[Preset speed 1]	Hz	1	[Low limit frequency] (LL) to [Upper limit freq] (UL)	15	
Sr2	112	[Preset speed 2]	Hz	1	[Low limit frequency] (LL) to [Upper limit freq] (UL)	20	
Sr3	112	[Preset speed 3]	Hz	1	[Low limit frequency] (LL) to [Upper limit freq] (UL)	25	
Sr4	112	[Preset speed 4]	Hz	1	[Low limit frequency] (LL) to [Upper limit freq] (UL)	30	
Sr5	112	[Preset speed 5]	Hz	1	[Low limit frequency] (LL) to [Upper limit freq] (UL)	35	
Sr6	112	[Preset speed 6]	Hz	1	[Low limit frequency] (LL) to [Upper limit freq] (UL)	40	
Sr7	112	[Preset speed 7]	Hz	1	[Low limit frequency] (LL) to [Upper limit freq] (UL)	45	
F100	114	[Freq. 1 reached]	Hz	-	0.0 to [Max frequency] (FH)	0.0	
F101	114	[Freq. 2 reached]	Hz	-	0.0 to [Max frequency] (FH)	0.0	
F102	114	[Freq.2 bandw.]	Hz	-	0.0 to [Max frequency] (FH)	2.5	
F108	112	[Logic Funct 1 active]	-	0 – 73	See table on page 91	0	

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
F109	90	[VIA selection]	-	0	AI	0	
				1	LI sink		
				2	LI source		
F110	112	[Logic Funct 2 active]	-	0 – 73	See table page 162	1	
F111	90	[LI F selection]	-	0 – 72	See table page 162	2	
F112	90	[LI R selection]	-	0 – 72	See table page 162	6	
F113	90	[LI RES selection]	-	0 – 72	See table page 162	10	
F118	90	[VIA LI selection]	-	0 – 73	See table page 162	7	
F130	109	[RY Relay Function 1]	-	0 – 61, 254, 255	See table page 162	4	
F132	109	[FL Relay Function]	-	0 – 61, 254, 255	See table page 162	11	
F137	113	[RY Relay Function 2]	-	0 – 61, 254, 255	See table page 162	255	
F139	113	[RY logic select.]	-	0	Function 1and 2	0	
				1	Function 1 or 2		
F146	109	[RY delay]	s	-	0.0 – 60.0 s	0.0	
F147	110	[FL Relay delay]	s	-	0.0 – 60.0 s	0.0	
F160	106	[VIA rel thresh. logic]	%	-	0 – 100	0	
F161	106	[VIA threshold hyst.]	%	-	0 – 20	3	
F162	106	[VIB rel thresh. logic]	%	-	0 – 100	0	
F163	106	[VIB threshold hyst.]	%	-	0 – 20	3	
F167	115	[Freq band det range]	Hz	-	0.0 to [Max frequency] (FH)	2.5	
F170	74	[Mot 2 rated Freq.]	Hz	-	25.0 to 200.0	50.0	
F171	74	[Motor 2 rated Volt]	V	230V model	50 to 330	230	
				460V model	50 to 660	400	
F172	74	[Motor 2 Volt Boost]	%	-	0 – 30	Model depen-dant	
F173	74	[Motor 2 Overload]	%/A	-	10 – 100% of drive rating	100	
F185	74	[Mot. 2 current limit]	%/A	-	10 – 110%	110	
F200	108	[Auto/man speed ref]	-	0	[Enable]	0	
				1	[Disable]		
F201	106	[VIA ref point 1]	%	-	0 – 100	0	
F202	106	[VIA freq. point 1]	Hz	-	0.0 – 200.0	0.0	
F203	106	[VIA freq. point 2]	%		0 – 100	100	
F204	106	[VIA freq. point 2]	Hz		0.0 – 200.0	50.0	
F207	78	[Remote spd ref 2]	-	1	[VIA]	2	
				2	[VIB]		
				3	[HMI]		
				4	[Communication]		
				5	[+/– Speed]		
F210	106	[VIB ref. point 1]	%		0 – 100	0	
F211	106	[VIB freq. point 1]	Hz		0.0 – 200.0	0.0	
F212	106	[VIB ref. point 2]	%		0 – 100	100	
F213	106	[VIB freq. point 2]	Hz		0.0 – 200.0	50.0	
F240	82	[Mot start freq.]	Hz	-	0.5 – 10.0	0.5	
F241	144	[Freq. pedestal]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F242	144	[Freq. pedestal hyst.]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F250	88	[DC brake start freq.]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F251	88	[DC braking current]	%/A	-	0 – 100%	50	

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
F252	88	[DC braking time]	s	-	0.0 – 20.0	1.0	
F256	78	[Time limit low spd]	s	0	[Disable]	0.0	
				1	[Enable]		
F264	113	[+speed LI resp time]	s	-	0.0 – 10.0	0.1	
F265	113	[+speed freq. step]	Hz	-	0.0 – [Max frequency] (FH)	0.1	
F266	113	[- speed LI resp time]	s	-	0.0 – 10.0	0.1	
F267	113	[- speed freq. step]	Hz	-	0.0 – [Max frequency] (FH)	0.1	
F268	113	[Init +/- Speed]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F269	113	[Init +/- Speed memo]	-	0	[Disable]	1	
				1	[Enable]		
F270	87	[Jump frequency 1]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F271	87	[Jump bandwidth 1]	Hz	-	0.0 – 30.0	0.0	
F272	87	[Jump frequency 2]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F273	87	[Jump bandwidth 2]	Hz	-	0.0 – 30.0	0.0	
F274	87	[Jump frequency 3]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F275	87	[Jump bandwidth 3]	Hz	-	0.0 – 30.0	0.0	
F294	79	[Forced speed freq.]	Hz	-	[Low limit frequency] (LL) – [Upper limit freq] (UL)	50.0	
F295	78	[Switch rem/Local]	-	0	[No bumpless]	1	
				1	[Bumpless]		
F300	85	[Switch. freq. level]	kHz	-	6.0 – 16.0	Model depen-dent	
F301	126	[Catch on fly]	-	0	[Disable]	3	
				1	[Brief power loss]		
				2	[Run restored]		
				3	[Power loss, run]		
				4	[Each start]		
F302	127	[Supply loss behav.]	-	0	[Disabled]	0	
				1	[Do not use]		
				2	[Freewheel]		
F303	124	[Number auto reset]	-	0	[Disabled]	3	
				1 - 10	[Number of fault reset attempts]		
F305	128	[Overvoltage fault]	-	0	[Enable]	2	
				1	[Disabled]		
				2	[Quick deceleration]		
				3	[Dyn. deceleration]		
F307	73	[Mot volt limitation]	-	0	[Motor volt limit]	3	
				1	[Line & mot correct.]		
				2	[No action]		
				3	[U Line correction]		
F311	86	[Motor direction]	-	0	[Fw & Rev.]	1	
				1	[Fw only]		
				2	[Rev. only]		
F312	86	[Noise reduction]	-	0	[Disable]	0	
				1	[Enable]		
F316	86	[Switch. freq. mode]	-	0	[Fixed]	1	
				1	[Auto]		
				2	[460 V fixed]		
				3	[460 V Auto]		
F320	146	[Load gain]	%	-	0 – 100%	0	
F323	146	[Load gain offset]	%	-	0 – 100%	10	
F359	111	[PID ctrl wait time]	s	-	0 – 2400	0	
F360	110	[PID control enable]	-	0	[No PID]	0	
				1	[PID by VIA]		
				2	[PID by VIB]		
F362	110	[PID Prop Gain]	-	-	0.01 – 100.0	0.30	
F363	110	[PID Integral Gain]	-	-	0.01 – 100.0	0.20	

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
F366	111	[PID Derivative Gain]	-	-	0.00 – 2.55	0.00	
F380	111	[PID reverse error]	-	0	[No]	0	
				1	[Yes]		
F391	111	[Stop on LL hyst]	Hz	-	0.0 – [Max frequency] (FH)	0.2	
F392	111	[PID wake up (thres)]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F393	111	[PID wake up, feedb]	Hz	-	0.0 – [Max frequency] (FH)	0.0	
F400	71	[Auto-tuning drive]	-	0	[Disabled]	0	
				1	[Initialize constant]		
				2	[Complete tune]		
F401	74	[Slip Compensation]	%	-	0 – 150	50	
F402	74	[Auto Torque Boost]	%	-	0.0 – 30.0	Model depen-dent	
F415	70	[Motor rated current]	A	-	0.1 – 200.0	Model depen-dent	
F416	70	[Mot no-load current]	%	-	10.0 – 100.0	Model depen-dent	
F417	70	[Motor rated speed]	rpm	-	100 – 15000	Model depen-dent	
F418	75	[Frequency loop gain]	-	-	1 – 150	40	
F419	75	[Freq. loop stability]	-	-	1 – 100	20	
F470	107	[VIA bias]	-	-	0 – 255	128	
F471	107	[VIA gain]	-	-	0 – 255	148	
F472	107	[VIB bias]	-	-	0 – 255	128	
F473	107	[VIB gain]	-	-	0 – 255	148	
F480	72	[No load cur. coef]	-	-	100 – 130	100	
F481	133	[In noise comp. filter]	µs	-	0 – 9999	0	
F482	133	[In noise Inhibit filter]	µs	-	0 – 9999	442	
F483	133	[In noise inhibit gain]	-	-	0.0 – 300.0	100.0	
F484	133	[Pwr supply adj. gain]	-	-	0.0 to 2.0	0.0	
F485	72	[Stall control coef. 1]	-	-	10 – 250	100	
F492	72	[Stall control coef. 2]	-	-	50 – 150	100	
F494	72	[Mot. adj coefficient]	-	-	DO NOT ADJUST	Model depen-dant	
F495	72	[Motor voltage coef.]	%	-	90 – 120	104	
F496	72	[PWM adj. coef.]	kHz	-	0.1 – 14.0	14.0	
F500	83	[Acceleration time 2]	s	1	0.0 – 3200	20.0	
F501	83	[Deceleration time 2]	s	1	0.0 – 3200	20.0	
F502	84	[Acc/dec 1 pattern]	-	0	[Linear]	0	
				1	[S-ramp 1]		
				2	[S-ramp 2]		
F503	84	[Acc/dec 2 pattern]	-	0	[Linear]	0	
				1	[S-pattern 1]		
				2	[S-pattern 2]		
F504	85	[Ramp switching]	-	1	[Ramp 1]	1	
				2	[Ramp 2]		
F505	85	[Commut. ramp freq.]	Hz	-	0.0 – [Upper limit freq] (UL)	0.0	
F506	84	[Acc/Dec S-pat start]	%	-	0 – 50	10	
F507	84	[Acc/Dec S-pat end]	-	-	0 – 50	10	

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
F580	117	[Damper fdb type]	-	0	[No feedback]	0	
				1	[LIH set]		
				2	[LIL set]		
				3	[Com. LIH set]		
				4	[Com. LIL set]		
F581	117	[Time open Damper]	-	-	0.05 to 300.00 s	60.00	
F582	117	[Time close Damper]	-	-	0.05 to 300.00 s	60.00	
F583	117	[Damper flt behavior]	-	0	[No fault]	1	
				1	[Freewheel stop]		
				2	[Ramp stop]		
F601	69	[Motor Current Limit]	%/A	-	10 – 110%	110%	
F602	127	[Drive fault memory]	-	0	[Cleared]	0	
				1	[Retained]		
F603	115	[Ext. fault stop Mode]	-	0	[Freewheel]	0	
				1	[Ramp stop]		
				2	[DC braking]		
F604	115	[DC brk time ext flt]	s	-	0.0 – 20.0	1.0	
F605	129	[Output phase loss]	-	0	[Disabled]	3	
				1	[First start]		
				2	[Each start]		
				3	[During run]		
				4	[Permanent]		
				5	[Catch on fly]		
F607	70	[Mot overload time]	s	-	10 – 2400	300	
F608	127	[Input phase loss]	-	0	[Disable]	1	
				1	[Enable]		
F609	130	[Underload band]	%	-	1 – 20	10	
F610	130	[Underload det.]	-	0	[Alarm]	0	
				1	[Fault]		
F611	130	[Underload level]	%/A	-	0 – 100%	0	
F612	130	[Underload det. time]	s	-	0 – 255	0	
F613	131	[Short circuit det.]	-	0	[Each time (std)]	0	
				1	[One time (std)]		
				2	[Each time (short)]		
				3	[One time (short)]		
F615	132	[Overtorque det.]	-	0	[Alarm]	0	
				1	[Fault]		
F616	132	[Overtorque level]	%	-	0 – 250	130	
F618	132	[OvTorque det time]	s	-	0.0 – 10.0	0.5	
F619	132	[Overtorque band]	%	-	0 – 100%	10	
F621	120	[Run time alarm]	h	-	0.0 – 999.9 (0.1 = 1 hour, 100 = 1000 hours)	610.0	
F626	128	[Overvoltage level]	%	1	[100 – 150% of nominal DC bus voltage]	140	
F627	127	[Undervolt detect.]	-	0	[Alarm (0.6U)]	0	
				1	[Fault (0.6U)]		
				2	[Alarm (0.5U)]		
F632	126	[Mot overload memo]	-	0	[Disabled]	0	
				1	[Enabled]		
F633	130	[Loss of VIA]	%	0	[Disabled]	0	
				1??? 100	[Fault detection level]		
F634	133	[Amb. temp. alarm]	-	1	[-10 to 10°C]	3	
				2	[11 to 20°C]		
				3	[21 to 30°C]		
				4	[31 to 40°C]		
				5	[41 to 50°C]		
				6	[51 to 60°C]		

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
F644	131	[4-20 mA loss]	-	0	[No]	0	
				1	[Freewheel]		
				2	[Set speed]		
				3	[Keep speed]		
				4	[Ramp stop]		
F645	111	[Mot PTC selection]	-	0	[Disabled]	0	
				1	[Enabled fault]		
				2	[Enabled alarm]		
F646	112	[PTC resistor value]	W	-	100 – 9999	3000	
F649	131	[4-20mA fallback sp]	Hz	-	0 – [Max frequency] (F H) Hz	0	
F650	79	[Forced fire control]	-	0	[Disable]	0	
				1	[Enable forward]		
				2	[Enable Reverse]		
F659	79	[Forced fire function]	-	0	[Enable transition ''0->1'']	0	
				1	[Enable level 1]		
				2	[Enable level 0]		
F691	109	[AO slope]	-	0	[Negative slope]	1	
				1	[Positive slope]		
F692	109	[Analog output bias]	%	-	0 – 100%	0	
F694	109	[Freq. for AO = 0V]	Hz	-	0 – [Max frequency] (F H) Hz	0	
F695	109	[Freq. for AO = 10V]	Hz	-	0 – [Max frequency] (F H) Hz	0	
F700	64	[Parameter lock]	-	0	[Unlocked]	0	
				1	[Locked]		
F701	120	[Unit value selection]	-	0	[%]	1	
				1	[Amp or Volt]		
F702	121	[Customized freq val]	-	0	Frequency displayed in Hz	0	
				0.01 – 200.0	Conversion factor		
F703	121	[Frequency convert.]	-	0	[All]	0	
				1	[PID only]		
F705	121	[Custom freq. slope]	-	0	[Negative slope]	1	
				1	[Positive slope]		
F706	121	[Customize unit bias]	Hz	-	0.00 – [Max frequency] (F H)	0.00	
F707	77	[Loc. speed ref. step]	Hz	0	[Disable]	0.00	
				1	[Enable]		
F708	120	[Display ref. resol.]	-	0	Disabled – 0.1 Hz steps	0	
				1 – 255	See formula on page 120		
F710	120	[Displayed param.]	-	0	[Motor frequency]	0	
				1	[Reference]		
				2	[I Mot]		
				3	[Drive rated I]		
				4	[Drive therm state]		
				5	[Motor power]		
				6	[Int speed ref]		
				7	[Com data]		
				8	[Motor speed]		
				9	[Com count]		
				10	[Com count norm st.]		
F721	78	[Loc. mot stop mode]	-	0	[Ramp stop]	0	
				1	[Freewheel]		
F730	80	[Up/down key ref]	-	0	[Enable]	0	
				1	[Disable]		
F732	80	[Loc/rem key]	-	0	[Permitted memo]	0	
				1	[Prohibited]		
				2	[Permitted no memo]		
F733	80	[Run/stop key]	-	0	[Enable]	0	
				1	[Disable]		
F734	80	[Priority stop]	-	0	[Enable]	0	
				1	[Disable]		
F735	80	[HMI reset button]	-	0	[Disable]	1	
				1	[Enable]		

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
F738	64	[Quick menu AUF]	-	0	[AUF displayed]	0	
				1	[AUF hidden]		
F748	120	[Power cons. memo]	-	0	[Disable]	Model depen-dant	
				1	[Enable]		
F749	121	[Power cons. unit]	kWh	0	[1 kWh]	Model depen-dant	
				1	[0.1 kWh]		
				2	[0.01 kWh]		
				3	[0.001 kWh]		
F800	138	[Mdb RJ45 baud]	-	0	[9600 bps]	1	
				1	[19200 bps]		
F801	138	[Mdb RJ45 parity]	-	0	[No]	1	
				1	[Even]		
				2	[Odd]		
F802	138	[Modbus address]	-	-	0 – 247	1	
F803	139	[Com. time out]	s	0	Communication error detection disabled	3	
				1-100	1 to 100 seconds		
F807	139	[Com channel choice]	-	0	[RJ45]	1	
				1	[Open style]		
F820	139	[Mdb network baud]	-	0	[9600]	1	
				1	[19200]		
F821	139	[Mdb network parity]	s	0	[No]	1	
				1	[Even]		
				2	[Odd]		
F829	139	[Network protocol]	-	1	[Mdb RTU]		
				2	[Metasys N2]		
				3	[Apogee P1]		
				4	[BACnet]		
				5	[LonWorks]		
F851	139	[Com. fault setting]	-	0	[Ramp stp (F/Cmod)]	4	
				1	[No active]		
				2	[Ramp stop]		
				3	[Freewheel]		
				4	[Err5 or Err8]		
F856	140	[Mot. poles (comm.)]	-	1	[2 poles]	2	
				2	[4 poles]		
				3	[6 poles]		
				4	[8 poles]		
				5	[10 poles]		
				6	[12 poles]		
				7	[14 poles]		
				8	[16 poles]		
F870	140	[Block write data 1]	-	0	[No select]	0	
				1	[Command word 1]		
				2	[Command word 2]		
				3	[Frequency Setpoint]		
				4	[Relay command]		
				5	[FM command]		
				6	[Speed Setpoint]		
F871	140	[Block write data 2]	-	0	[No select]	0	
				1	[Command word 1]		
				2	[Command word 2]		
				3	[Frequency Setpoint]		
				4	[Relay command]		
				5	[FM command]		
				6	[Speed Setpoint]		

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
F875	140	[Block read data 1]	-	0	[No select]	0	
				1	[Command 1]		
				2	[Freq. out]		
				3	[Motor current]		
				4	[Output volt]		
				5	[Alarm info]		
				6	[PID feedback value]		
				7	[Input term. mon]		
				8	[Out term. mon]		
				9	[VIA monitor]		
				10	[VIB monitor]		
				11	[Mot speed mon.]		
F876	140	[Block read data 2]	-	0	[No select]	0	
				1	[Command 1]		
				2	[Freq. out]		
				3	[Motor current]		
				4	[Output volt]		
				5	[Alarm info]		
				6	[PID feedback value]		
				7	[Input term. mon]		
				8	[Out term. mon]		
				9	[VIA monitor]		
				10	[VIB monitor]		
				11	[Mot speed mon.]		
F877	141	[Block read data 3]	-	0	[No select]	0	
				1	[Status info]		
				2	[Freq. out]		
				3	[Motor current]		
				4	[Output volt]		
				5	[Alarm info]		
				6	[PID feedback value]		
				7	[Input term. mon]		
				8	[Out term. mon]		
				9	[VIA monitor]		
				10	[VIB monitor]		
				11	[Mot speed mon.]		
F878	141	[Block read data 4]	-	0	[No select]	0	
				1	[Status info]		
				2	[Freq. out]		
				3	[Motor current]		
				4	[Output volt]		
				5	[Alarm info]		
				6	[PID feedback value]		
				7	[Input term. mon]		
				8	[Out term. mon]		
				9	[VIA monitor]		
				10	[VIB monitor]		
				11	[Mot speed mon.]		
F879	141	[Block read data 5]	-	0	[No select]	0	
				1	[Status info]		
				2	[Freq. out]		
				3	[Motor current]		
				4	[Output volt]		
				5	[Alarm info]		
				6	[PID feedback value]		
				7	[Input term. mon]		
				8	[Out term. mon]		
				9	[VIA monitor]		
				10	[VIB monitor]		
				11	Mot speed mon.		
F880	141	[Free ID parameter]	-	-	0 – 65535	0	
F890	142	[Network adress]	-	-	0 – 65535	(1)	
F891	142	[Network baud rate]	-	-	0 – 65535	(1)	

Code	Page	Name	Unit	Adjustment Range / Function		Factory Setting	User Setting
F892	142	[Network time out]	-	-	20 - 600	(1)	
F893	142	[Instance number H]	-	-	0 – 4194	(1)	
F894	142	[Instance number L]	-	-	0 – 999	(1)	
F895	142	[Max master]	-	-	0 – 127	(1)	
F896	142	[Max info frames]	-	-	0 – 100	(1)	

(1) See table page 142.