HIWIN MIKROSYSTEM

E Series Servo Drive

MECHATROLINK-III Communication Command Manual

www.hiwinmikro.tw
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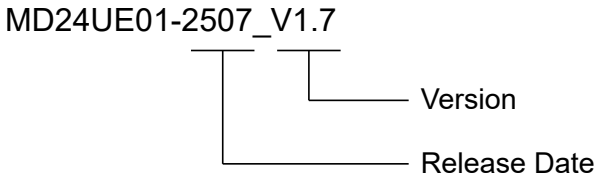
Revision History

The version of the manual is also indicated on the bottom of the front cover.



Release Date	Version	Applicable Product	Revision Contents
Jul. 31st, 2025	1.7	E1 series servo drive E2 series servo drive	1. Update section 7.3.1 **Device parameters**. 2. Update section 7.3.2 **Monitoring parameters (Ut parameters)**.
Dec. 31st, 2024	1.6	E1 series servo drive E2 series servo drive	1. Update section 3.2.13 **Velocity control (VELCTRL: 3Ch)**. 2. Update section 3.2.14 **Torque control (TRQCTRL: 3Dh)**. 3. Update section 7.3.1 **Device parameters**. 4. Update section 8.3 **Command alarm / warning codes**.
Aug. 31st, 2024	1.5	E1 series servo drive E2 series servo drive	1. Modify the title and cover of this manual. 2. Support E1 and E2 series drives. Modify the term of E1 to E series. 3. Add section 2.3.2 **Panel configuration for ED2F drive**. 4. Add section 2.4.2 **Panel configuration for ED2F drive**. 5. Update section 3.1.2 **Read ID (ID_RD: 03h)**. 6. Update the alarm description in section 3.2.9 ~ 3.2.13. 7. Update section 3.2.17 **Setting motion command data**. 8. Update section 7.3.1 **Device parameters**. 9. Update section 8.2 **Communication alarm / warning codes**.
Oct. 31st, 2023	1.4	E1 series servo drive	1. Update section 3.2.12 **Zero point return command (ZRET: 3Ah)**. 2. Update section 8.2 **Communication alarm / warning codes**.
May. 31st, 2023	1.3	E1 series servo drive	1. Update section 2.11.1 **Servo command control (SVCMD_CTRL)**. 2. Update section 2.12.2 **Bit allocation of servo command input signal monitoring**. 3. Update section 3.2.12 **Zero point return command (ZRET: 3Ah)**. 4. Update section 3.2.15 **Read servo parameter (SVPRM_RD: 40h)**. 5. Update section 7.1.2 **Parameters related to machine specification**. 6. Update section 7.3 **Drive parameters (Pt parameters)**. 7. Update section 7.3.1 **Manufacturer specific profile area**. 8. Update section 7.3.2 **Monitoring parameter**.

Release Date	Version	Applicable Product	Revision Contents
Jan. 31st, 2023	1.2	E1 series servo drive	1. Update section 2.11.1 **Servo command control (SVCMD_CTRL)**. 2. Update section 2.11.2 **Servo command status (SVCMD_STAT)**. 3. Update section 2.12.1 **Bit allocation of servo command output signal monitoring**. 4. Update section 2.12.2 **Bit allocation of servo command input signal monitoring**. 5. Update section 3.2.1 **Apply brake (BRK_ON: 21h)**. 6. Update section 3.2.15 **Read servo parameter (SVPRM_RD: 40h)**. 7. Update section 3.2.16 **Write servo parameter (SVPRM_WR: 41h)**. 8. Update section 4.1.6 **Read servo parameter (SVPRM_RD: 40h)**. 9. Update section 4.1.7 **Write servo parameter (SVPRM_WR: 41h)**. 10. Update section 7.1.3 **Parameters related to system unit**. 11. Update section 7.1.4 **Parameters for adjustment**. 12. Add section 7.2 **Drive parameters (Pt parameters)**.
Feb. 26th, 2021	1.1	E1 series servo drive	1. Update section 2.2 **Connecting to E1 servo drive (CN9).** 2. Update section 2.8.1 **Command code (CMD/RCMD).** 3. Update section 2.9.2 **Subcommand control (SUB_CTRL).** 4. Update section 3.1.2 **Read ID (ID_RD: 03h).** 5. Update section 3.2.13 **Velocity control (VELCTRL: 3Ch).** 6. Update section 4.1.1 **Combinations of main commands and subcommands.** 7. Update section 7.1.2 **Parameters related to machine specification.** 8. Update section 7.1.4 **Parameters for adjustment.** 9. Update section 7.1.5 **Parameters related to command.** 10. Update section 7.1.6 **Common Parameters and Corresponding Drive Parameters.** 11. Update section 8.1 **Drive alarm / warning codes.** 12. Update section 8.2 **Communication alarm / warning codes.** 13. Update section 8.3 **Command alarm / warning codes.**
Jan. 22nd, 2020	1.0	E1 series servo drive	First edition.

Related Documents

Through related documents, users can quickly understand the positioning of this manual and the correlation between manuals and products. Go to HIWIN MIKROSYSTEM's official website → Download → Manual Overview for details (https://www.hiwinmikro.tw/Downloads/ManualOverview_EN.htm).

Table of Contents

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1. About this manual

1.1 Preface

This manual provides information necessary to operate HIWIN E series servo drive via MECHATROLINK-III communication. For further understanding of E series servo drive, please refer to related user manuals.

1.2 Trademarks

MECHATROLINK is a trademark of MECHATROLINK Members Association.

2. MECHATROLINK-III communication

2.1 Communication specification

Table 2.1.1

MECHATROLINK-III Specification	
Communication Protocol	MECHATROLINK-III
Station Address Setup	03 to EF hex
Baud Rate	100 Mbps
Transmission Cycle	250 μs, 500 μs, 750μs, 1.0 ms to 4.0 ms (0.5 ms increment)
Transmission Bytes	32 or 48 bytes
Control Method	Position control, Speed control or Torque control
Profile	MECHATROLINK-III standard servo profile

Note: For the detailed information of drive setup, refer to section 2.3.

2.2 Connecting to E series servo drive (CN9)

Use Ethernet crossover cable to connect servo drive to MECHATROLINK-III compatible master or device. For the pin assignment of the crossover cable, please refer to figure 2.2.1.

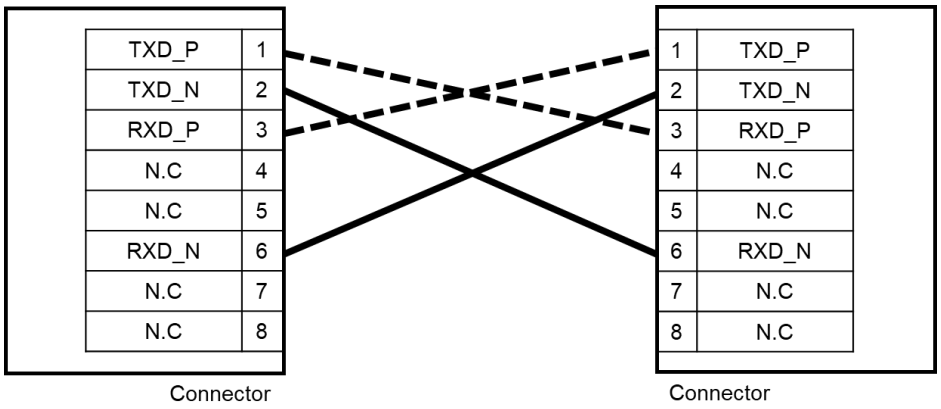

Figure 2.2.1

2.3 MECHATROLINK-III communication setup

2.3.1 Panel configuration for ED1F drive

The rotary switches (SW1 and SW2) and DIP switch (SW3) shown in figure 2.3.1 are used to set MECHATROLINK-III communication specification.

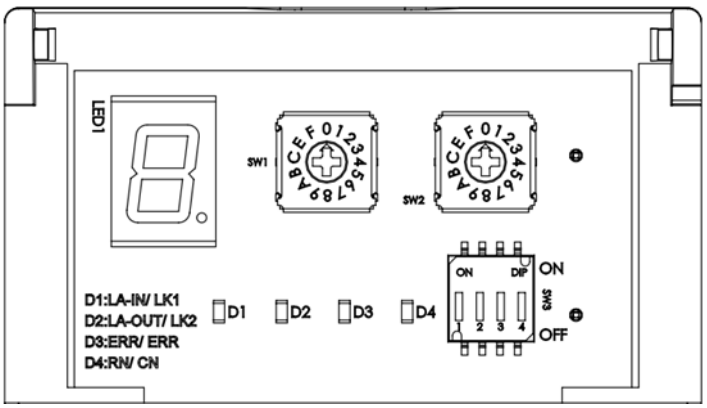

Figure 2.3.1

- Communication specification (SW3)

Table 2.3.1

SW3	Function	Setting		
		1	2	Transmission Bytes
Pin 1 and 2	Sets transmission bytes.	OFF	OFF	Reserved
		ON	OFF	32 bytes
		OFF	ON	48 bytes
		ON	ON	Reserved
Pin 3	Reserved			
Pin 4	Reserved			

- Station address (SW1 and SW2)

Set station number by using the rotary switches (SW1 and SW2). While connecting two or more MECHATROLINK-III compatible products, please set different station number for each product.

Table 2.3.2

SW1	SW2	Station Address
0	0 to 2	Reserved
0	3	03h
⋮	⋮	⋮

SW1	SW2	Station Address
E	F	EFh
F	0 to F	Reserved

Note: If the settings of the communications switches (SW1, SW2, and SW3) are changed, please reset power for the new settings to take effect.

2.3.2 Panel configuration for ED2F drive

The rotary switches (SW1 and SW2) shown in figure 2.3.2 are used to set MECHATROLINK-III communication specification.

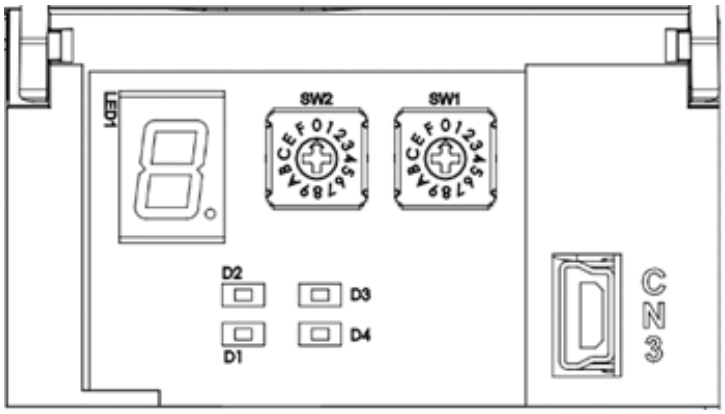

Figure 2.3.2

- Station address (SW1 and SW2)

  Set station number by using the rotary switches (SW1 and SW2). While connecting two or more MECHATROLINK-III compatible products, please set different station number for each product.

Table 2.3.2

SW2	SW1	Station Address
0	0 to 2	Reserved
0	3	03h
⋮	⋮	⋮
E	F	EFh
F	0 to F	Reserved

Note: If the settings of the communications switches (SW1 and SW2) are changed, please reset power for the new settings to take effect.

2.4 Communication status LED

2.4.1 Panel configuration for ED1F drive

LK1 LED (D1), LK2 LED (D2), ERR LED (D3) and CN LED (D4) shown in figure 2.4.1 are used to indicate MECHATROLINK-III communication status.

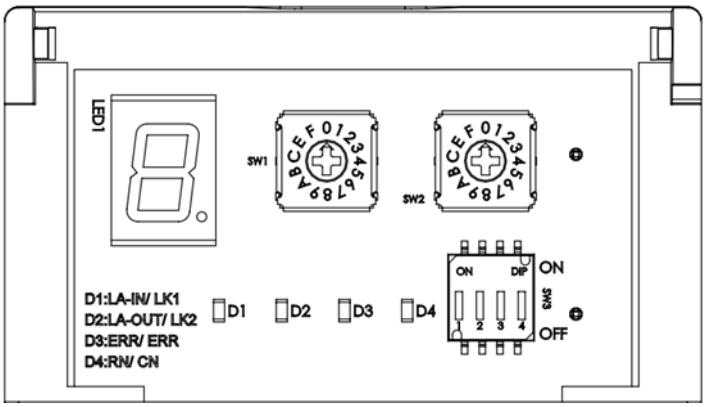

Figure 2.4.1

Table 2.4.1

Name	Description
LINK (LK1 and LK2)	This LED lights up when the power is turned on and a hardware connection is established.
Error (ERR)	This LED lights up when MECHATROLINK-III communication error occurs.
Connection (CN)	This LED lights up when a connection is established.

2.4.2 Panel configuration for ED2F drive

D1, D2, D3 and D4 shown in figure 2.4.2 are used to indicate MECHATROLINK-III communication status.

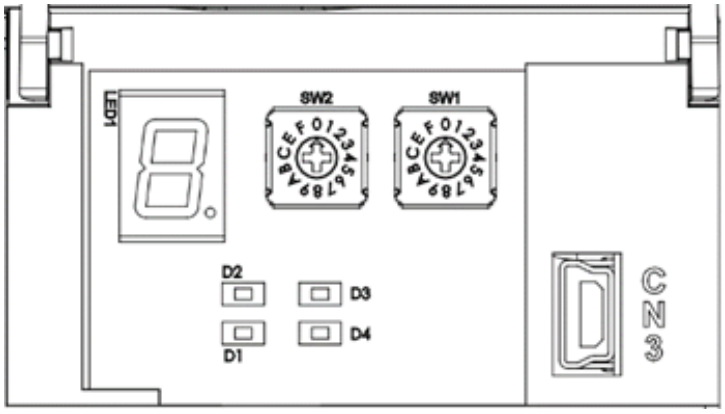

Figure 2.4.2

Table 2.4.2

Name	Description
LINK (D1 and D2)	This LED lights up when the power is turned on and a hardware connection is established.
Error (D3)	This LED lights up when MECHATROLINK-III communication error occurs.
Connection (D4)	This LED lights up when a connection is established.

2.5 Data format

A standard command format is composed of a main command and a subcommand. The data format is shown in table 2.5.1.

Table 2.5.1

	Byte	Command	Response
Main Command Area	0	CMD	RCMD
	1	WDT	RWDT
	2	CMD_CTRL	CMD_STAT
	3		
	4 – 31	CMD_DATA	RSP_DATA
Subcommand Area	32	SUBCMD	RSUBCMD
	33	SUB_CTRL	SUB_STAT
	34		
	35		
	36 – 47	SUB_CMD_DATA	SUB_RSP_DATA

2.6 Communication phase

The communication phases of MECHATROLINK-III are listed in table 2.6.1.

Table 2.6.1

Phase	Operating State	Description
0	Power on	When the slave is turned on, communication phase changes to phase 1.
1	Communication initialization	The slave completes internal initialization and is waiting for CONNECT command.
2	Normal operation	Asynchronous communication is enabled. Only asynchronous command can be used.
3		Synchronous communication is enabled. Both synchronous command and asynchronous command can be used.
4		When the slave receives DISCONNECT command from C1 master, the slave re-initializes and shifts to connection-wait state (phase 1).
5	Power off	The master and the slave are turned off.

2.7 Common command format

Standard servo profile commands are classified into two categories: common command and servo command. Common commands are used for MECHATROLINK-III communication. Servo commands are used for standard servo profile. This section will describe the related information of common command. The data format of common command is shown in table 2.7.1. Bytes 0 to 31 are used by main command; bytes 32 to 47 are used by subcommand to supplement main command.

Table 2.7.1

	Byte	Command	Response
Main Command Area	0	CMD	RCMD
	1	WDT	RWDT
	2	CMD_CTRL	CMD_STAT
	3		
	4 – 31	CMD_DATA	RSP_DATA
Subcommand Area	32	SUBCMD	RSUBCMD
	33	SUB_CTRL	SUB_STAT
	34		
	35		
	36 – 47	SUB_CMD_DATA	SUB_RSP_DATA

2.8 Command header of main command

2.8.1 Command code (CMD/RCMD)

Byte 0 of command field and response field are defined as CMD field and RCMD field. The data in RCMD field is the copy of the data in CMD field. Table 2.8.1.1 shows the command codes used by common command and servo command.

Table 2.8.1.1

Profile	Command Code (Hex.)	Command	Operation
Common Command	00	NOP	No operation
	03	ID_RD	Reads drive ID information.
	04	CONFIG	Enable parameter setup.
	05	ALM_RD	Reads alarm/warning.
	06	ALM_CLR	Clears alarm/warning state.
	0D	SYNC_SET	Requests for synchronous communication.
	0E	CONNECT	Requests for connection.
	0F	DISCONNECT	Requests for disconnection.
Servo Command	21	BRK_ON	Requests to apply brake.
	22	BRK_OFF	Requests to release brake.
	23	SENS_ON	Requests to turn sensor on.
	24	SENS_OFF	Requests to turn sensor off.
	30	SMON	Monitors drive status.
	31	SV_ON	Servo on
	32	SV_OFF	Servo off
	34	INTERPOLATE	Interpolation
	35	POSING	Positioning
	36	FEED	Constant-speed feed
	39	EX_POSING	Positioning by external input position
	3A	ZRET	Zero point return command
	3C	VELCTRL	Velocity control
	3D	TRQCTRL	Torque control
	40	SVPRM_RD	Reads servo parameters.
	41	SVPRM_WR	Writes servo parameters.

2.8.2 Watchdog data (WDT/RWDT)

Byte 1 of command field and response field are defined as WDT field and RWDT field. The format is shown in figure 2.8.2.1.

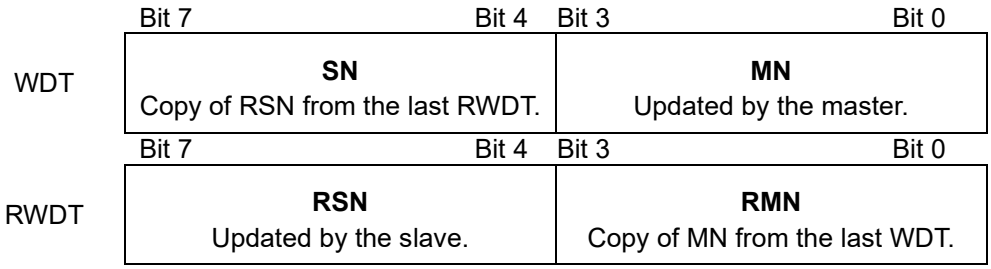

Figure 2.8.2.1

The watchdog data (WDT) is checked after synchronous communication (phase 3) is established. E series servo drive starts to refresh watchdog data (RWDT) before the master sends CONNECT command.

2.8.3 Command control (CMD_CTRL)

Bytes 2 and 3 of command field are defined as CMD_CTRL fields. Table 2.8.3.1 describes the command control data in CMD_CTRL fields. The data in CMD_CTRL fields will still be valid even when an alarm specified by CMD_ALM occurs.

Table 2.8.3.1

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
CMD_ID		Reserved		ALM_CLR	Reserved		
Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8
Reserved							

- ALM_CLR: Clears alarm or warning state.
  (1) Definition
  0: Disabled; 1: Enabled

  (2) Description
  ALM_CLR clears alarm or warning state at the rising edge. The processing is the same as when ALM_CLR_MODE of ALM_CLR command is set to 0 (Clears current alarm or warning state).

- CMD_ID: Command ID

  (1) Definition

  The master uses command ID to have the slave acknowledge that a command is a new command when the master sends the same command repeatedly. The slave uses command ID to inform the master to which command it is responding. A value from 0 to 3 is used.

  (2) Description

  Since the slave returns the CMD_ID of the command being executed, the master can clearly identify the slave is sending the response of which command. When CMD_RDY = 0, the slave disregards command that has a different CMD_ID and continues executing current command. Commands that can be regarded as new commands by the change in CMD_ID are EX_POSING and ZRET.

2.8.4 Command status (CMD_STAT)

Bytes 2 and 3 of response field are defined as CMD_STAT fields. The data in CMD_STAT fields will still be valid even when an alarm specified by CMD_ALM occurs. CMD_STAT fields are shown in table 2.8.4.1.

Table 2.8.4.1

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
RCMD_ID		Reserved		ALM_CLR_CMP	CMDRDY	D_WAR	D_ALM
Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8
COMM_ALM				CMD_ALM			

- D_ALM

  (1) Definition

  1: The slave is in alarm state.

  0: Other (Normal state, or alarm states specified by COMM_ALM and CMD_ALM)

  (2) Description

  When a device-specific alarm other than alarm specified by COMM_ALM and CMD_ALM has occurred, D_ALM is set to 1. D_ALM is independent from COMM_ALM and CMD_ALM. When D_ALM = 1 in servo-on state, the slave will become servo-off. When the slave changes from alarm state to normal state after ALM_CLR command and SVCMD_IO.ALM_CLR are executed, D_ALM is set to 0.

- D_WAR

  (1) Definition

  1: The slave is in warning state.

  0: Other (Normal state, or warning states specified by COMM_ALM and CMD_ALM)

  (2) Description

  When a device-specific warning other than warning specified by COMM_ALM and CMD_ALM has occurred, D_WAR is set to 1. D_WAR is independent from COMM_ALM and CMD_ALM. When D_WAR = 1 in servo-on state, the slave will remain servo-on. When the slave changes from warning state to normal state after ALM_CLR command and CMD_CTRL.ALM_CLR are executed, D_WAR is set to 0.

- CMDRDY

  (1) Definition

  1: Command reception is ready.

  0: Command reception is not ready.

  (2) Description

  CMDRDY = 0 means that command processing is still in progress. When CMDRDY = 0, the slave continues executing current command, and new command sent from the master will be disregarded. Completion of command execution is confirmed by the confirmation method specified by each command. If command execution is possible despite alarm or warning state, CMDRDY is set to 1.

- ALM_CLR_CMP

  (1) Definition

  1: Execution of ALM_CLR command is completed.

  0: Other

  (2) Description

  ALM_CLR_CMP = 1 means that CMD_CTRL.ALM_CLR = 1 has been received and alarm state has been cleared. ALM_CLR_CMP command can be canceled by setting CMD_CTRL.ALM_CLR to 0.

- RCMD_ID

  (1) Definition

  Echo back of the CMD_ID in the command field

(2) Description

Returns the CMD_ID in the command field.

■ CMD_ALM

(1) Definition

Notifies command alarm.

(2) Description

CMD_ALM is used to indicate command alarm. CMD_ALM is independent from COMM_ALM, D_ALM and D_WAR. If a normal command is received after a command alarm occurs, CMD_ALM is automatically cleared. The communication phase and servo status will not change even when CMD_ALM is not 0.

Table 2.8.4.2

Code		Contents	Remark
Normal	0	Normal	-
Warning	1	Invalid data	The slave notifies a warning state. The command is executed by the specified value or by the maximum or minimum allowable value.
	2	-	
	3	-	
	4	-	
	5	-	
	6	-	
	7	-	
Alarm	8	Unsupported command	The slave notifies an alarm state and the command is not executed.
	9	Invalid data	
	A	Command execution condition error	
	B	Subcommand combination error	
	C	Phase error	
	D	-	
	E	-	
	F	-	

■ COMM_ALM

(1) Definition

Notifies communication alarm.

(2) Description

COMM_ALM is used to indicate alarm in MECHATROLINK communication. COMM_ALM is independent from CMD_ALM, D_ALM and D_WAR. COMM_ALM is cleared at the rising edge of CMD_CTRL.ALM_CLR or by ALM_CLR command.

Table 2.8.4.3

Code		Contents	Remark
Normal	0	Normal	-
Warning	1	FCS error	Warning occurs when an error has been detected for the first time. The servo state will be remained. ➢ Error detection method 1: FCS error An error has been detected in frame check sequence. 2: Command data is not received. The command data sent to the slave is not received. 3: Synchronous frame is not received. The synchronous frame is not received.
	2	Command data is not received.	
	3	Synchronous frame is not received.	
	4	-	
	5	-	
	6	-	
	7	-	
Alarm	8	FCS error	Alarm occurs when an error has been detected continuously for specific times. If the system is in communication phase 3 when an alarm occurs, it will shift to phase 2. The servo state will be changed to servo-off. ➢ Error detection method 8, 9, A: Sets if an error has been detected twice. B, C: Sets immediately if an error has been detected.
	9	Command data is not received.	
	A	Synchronous frame is not received.	
	B	Synchronization interval error	
	C	WDT error	
	D	-	
	E	-	
	F	-	

2.9 Command header of subcommand

2.9.1 Subcommand code (SUB_CMD/SUB_RCMD)

Byte 32 of command field and response field are defined as SUB_CMD field and SUB_RCMD field. The standard subcommands used by E series servo drive are listed in table 2.9.1.1.

Table 2.9.1.1

Profile	Command Code (Hex.)	Command	Operation
Servo Command	00	NOP	No operation.
	05	ALM_RD	Reads alarm/warning.
	06	ALM_CLR	Clears alarm/warning.
	30	SMON	Monitors drive status.
	40	SVPRM_RD	Reads servo parameters.
	41	SVPRM_WR	Writes servo parameters.

2.9.2 Subcommand control (SUB_CTRL)

Bytes 33 to 35 of command field are defined as SUB_CTRL fields. SUB_CTRL fields are defined in table 2.9.2.1.

Table 2.9.2.1

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

The details of the control bits are shown in table 2.9.2.2.

Table 2.9.2.2

Bit	Name	Contents	Value (Hex.)	Setting
12 – 15	SEL_MON4	Monitoring selection 4	0 to F	Monitoring selection
16 – 19	SEL_MON5	Monitoring selection 5	0 to F	Monitoring selection
20 – 23	SEL_MON6	Monitoring selection 6	0 to F	Monitoring selection

2.9.3 Subcommand status (SUB_STAT)

Bytes 33 to 35 of response field are defined as SUB_STAT fields. SUB_STAT fields are defined in table 2.9.3.1.

Table 2.9.3.1

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

The details of the status bits are shown in table 2.9.3.2.

Table 2.9.3.2

Bit	Name	Contents	Value (Hex.)	Setting
2	SUBCMDRDY	Subcommand reception is ready.	1	Command reception is ready.
			0	Command reception is not ready.
8 – 11	SUBCMD_ALM	Subcommand alarm	0 to F	Refer to section 2.8.4 for CMD_ALM.
12 – 15	SEL_MON4	Monitoring selection 4	0 to F	Monitoring selection
16 – 19	SEL_MON5	Monitoring selection 5	0 to F	Monitoring selection
20 – 23	SEL_MON6	Monitoring selection 6	0 to F	Monitoring selection

2.10 Servo command format

The data format of servo command is shown in table 2.10.1. Bytes 0 to 31 are main command area. Servo commands can be expanded to 48 bytes by using subcommands.

Table 2.10.1

	Byte	Command	Response
Main Command Area	0	CMD	RCMD
	1	WDT	RWDT
	2	CMD_CTRL	CMD_STAT
	3		
	4	SVCMD_CTRL	SVCMD_STAT
	5		
	6		
	7		
	8	SVCMD_IO	SVCMD_IO
	9		
	10		
	11		
	12 – 31	CMD_DATA	RSP_DATA

2.11 Command header section

2.11.1 Servo command control (SVCMD_CTRL)

Bytes 4 to 7 of command field are defined as SVCMD_CTRL fields. The control bits are used to specify the operation of the slave. The data in SVCMD_CTRL fields will still be valid even when an alarm specified by CMD_ALM occurs.

Table 2.11.1.1 shows the allocation of the control bits.

Table 2.11.1.1

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

Note: *1 Not supported.

Table 2.11.1.2 shows the details of the control bits.

Table 2.11.1.2

Bit	Name	Contents	Value (Hex.)	Setting	Enabling Time
0	CMD_PAUSE	Pauses move command.	0	None	Level
			1	Pauses move command.	
	Pauses the execution of move command: POSING, FEED, EX_POSING, ZRET and VELCTRL. Movement is stopped according to the setting of STOP_MODE.				
1	CMD_CANCEL	Cancels move command.	0	None	Level
			1	Cancels move command.	
	Cancels the execution of move command: POSING, FEED, EX_POSING, ZRET and VELCTRL. Movement is stopped according to the setting of STOP_MODE.				
2 – 3	STOP_MODE	Selection of stop mode	0	Decelerates to stop.	Level
			1	Immediate stop	
			2 – 3	Reserved	
	Selects stop mode for CMD_PAUSE and CMD_CANCEL.				

Bit	Name	Contents	Value (Hex.)	Setting	Enabling Time
8	LT_REQ1	Latch request 1	0	None	Rising edge
			1	Requests for latch.	
	Requests to latch by Z phase signal or EXT1.				
9	LT_REQ2	Latch request 2	0	None	Rising edge
			1	Requests for latch.	
	Requests to latch by Z phase signal.				
10 – 11	LT_SEL1	Selection of latch signal 1	0	Z phase signal	Rising edge of LT_REQ1
			1	EXT1	
			2 – 3	Reserved	
	Z phase signal and EXT1 are supported. Note: The corresponding signal for EXT1 is EXT_PROBE1 in servo drive input function list.				
12 – 13	LT_SEL2	Selection of latch signal 2	0	Z phase signal	Rising edge of LT_REQ2
			1 – 3	Reserved	
	Only Z phase signal is supported.				
16 – 18	SEL_MON1	Monitoring selection 1	0 – F	Monitoring selection	Level
	Sets monitoring information, please refer to section 5.3.				
19 – 22	SEL_MON2	Monitoring selection 2	0 – F	Monitoring selection	Level
	Sets monitoring information, please refer to section 5.3.				
23 – 26	SEL_MON3	Monitoring selection 3	0 – F	Monitoring selection	Level
	Sets monitoring information, please refer to section 5.3.				

Note: If LT_REQ1 and LT_REQ2 are enabled at the same time, LT_REQ1 command will be executed, and LT_REQ2 will be ignored.

Latch operation starts at the rising edge of LT_REQ. The operations to be performed when commands are changed during latch operations are listed in table 2.11.1.3. (The value of LT_SEL is an example.)

Table 2.11.1.3

Command before switching	Command after switching	Latch operation
Command without latch function LT_SEL = 1 LT_REQ = 1	Common command	The latch request before switching is continued.
Command with latch function LT_SEL = 1 LT_REQ = 1	Common command	Operation of the command with latch function is interrupted.
Command without latch function LT_SEL = 1 LT_REQ = 1	Command without latch function LT_SEL = 1 LT_REQ = 1	The latch request before switching is continued.
Command without latch function LT_SEL = 1 LT_REQ = 1	Command without latch function LT_SEL = 2 LT_REQ = 1	The latch request before switching is continued.
Command without latch function LT_SEL = 1 LT_REQ = 1	Command with latch function LT_SEL = 1 LT_REQ = 1	Switches to the latch request of the command after switching. The servo drive executes its latch request. (internal processing) If the status “L_CMP = 1” is established before command switching, “L_CMP = 0” is set when command switches.
Command with latch function LT_SEL = 1 LT_REQ = 1	Command without latch function LT_SEL = 1 LT_REQ = 1	Switches to the latch request of the command after switching. The servo drive executes its latch request. (internal processing) If the status “L_CMP = 1” is established before command switching, “L_CMP = 0” is set when command switches.
Command with latch function LT_SEL = 1 LT_REQ = 1	Command with latch function LT_SEL = 1 LT_REQ = 1	Switches to the latch request of the command after switching. The servo drive executes its latch request. (internal processing) If the status “L_CMP = 1” is established before command switching, “L_CMP = 0” is set when command switches.

Note:

(1) Command with latch function:

EX_POSING and ZRET

Command without latch function:

BRK_ON, BRK_OFF, SENS_ON, SENS_OFF, SMON, SV_ON, SV_OFF, INTERPOLATE, POSING, FEED, VELCTRL, TRQCTRL, SVPRM_RD and SVPRM_WR

Common command:

NOP, ID_RD, CONFIG, ALM_RD, ALM_CLR, SYNC_SET, CONNECT and DISCONNECT

(2) LT_SEL: LT_SEL1 or LT_SEL2
LT_REQ: LT_REQ1 or LT_REQ2

2.11.2 Servo command status (SVCMD_STAT)

Bytes 4 to 7 of response field are specified as SVCMD_STAT fields. The status bits indicate the status of the slave. The data in SVCMD_STAT fields will still be valid even when an alarm specified by CMD_ALM occurs.

Table 2.11.2.1 shows the allocation of the status bits.

Table 2.11.2.1

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Reserved		ACCFIL[*1]		Reserved		CMD_ CANCEL_ CMP	CMD_ PAUSE_ CMP
Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8
Reserved		SV_ON	M_RDY	PON	POS_RDY	L_CMP2	L_CMP1
Bit 23	Bit 22	Bit 21	Bit 20	Bit 19	Bit 18	Bit 17	Bit 16
SEL_MON2				SEL_MON1			
Bit 31	Bit 30	Bit 29	Bit 28	Bit 27	Bit 26	Bit 25	Bit 24
Reserved				SEL_MON3			

Note: [*1] Not supported.

Table 2.11.2.2 shows the details of the status bits.

Table 2.11.2.2

Bit	Name	Contents	Value (Hex.)	Setting
0	CMD_PAUSE_CMP	Indicates if move command is paused.	0	Incomplete
			1	Move command is paused.
	This bit is used to indicate if POSING, FEED, EX_POSING, ZRET and VELCTRL commands are paused or not.			
1	CMD_CANCEL_CMP	Indicates if move command is canceled.	0	Incomplete
			1	Move command is canceled.
	This bit is used to indicate if POSING, FEED, EX_POSING, ZRET and VELCTRL commands are canceled or not.			
8	L_CMP1	Latch completion 1	0	Incomplete
			1	Latch is completed.
	This bit is used to indicate if the latch request of LT_REQ1 completes or not. L_CMP1 will remain at 1 until LT_REQ1 is set to 0.			
9	L_CMP2	Latch completion 2	0	Incomplete
			1	Latch is completed.
	This bit is used to indicate if the latch request of LT_REQ2 completes or not. L_CMP2 will remain at 1 until LT_REQ2 is set to 0.			
10	POS_RDY	Position data is ready.	0	Not ready
			1	Ready
	This bit is used to indicate if position data being monitored is valid or not. (1) When an absolute encoder is used: POS_RDY = 1 means SENS_ON command completes. POS_RDY = 0 means SENS_OFF command completes. (2) When an incremental encoder is used: POS_RDY=1 means CONNECT command completes.			
11	PON	Power on	0	Power off
			1	Power on
	This bit is used to indicate if the power is turned on or not.			
12	M_RDY	Motor energization is ready.	0	Not ready
			1	Ready
	This bit is used to indicate if the motor is ready for servo on or not.			
13	SVON	Servo on	0	Servo off
			1	Servo on
	This bit is used to indicate if the motor is energized or not.			
16 – 19	SEL_MON1	Monitoring selection 1: Returns what data is being monitored.	0 to F	Monitoring selection
	This bit is used to indicate what data is being monitored.			
20 – 23	SEL_MON2	Monitoring selection 2: Returns what data is being monitored.	0 to F	Monitoring selection
	This bit is used to indicate what data is being monitored.			
24 – 27	SEL_MON3	Monitoring selection 3:	0 to F	Monitoring selection

Bit	Name	Contents	Value (Hex.)	Setting
		Returns what data is being monitored.		
	This bit is used to indicate what data is being monitored.			

2.11.3 Supplementary information on CMD_PAUSE and CMD_CANCEL

- CMD_PAUSE
  1. CMD_PAUSE is used to pause move command. Move command processing can be continued by clearing CMD_PAUSE.
  2. CMD_PAUSE is only valid for POSING, FEED, EX_POSING, ZRET and VELCTRL commands.
  3. Movement stops according to the setting of STOP_MODE.
  4. CMD_PAUSE is disregarded when it is used for commands other than POSING, FEED, EX_POSING, ZRET and VELCTRL. CMD_PAUSE_CMP remains at 0.
  5. When CMD_PAUSE_CMP changes to 1, DEN remains at 0 (position mode).
  6. When CMD_PAUSE_CMP changes to 1, the previous control mode retains.

  Note: CMD_PAUSE_CMP is set to 1 as both CMD_PAUSE and ZSPD are 1.

  Example of pausing POSING command is shown in figure 2.11.3.1.

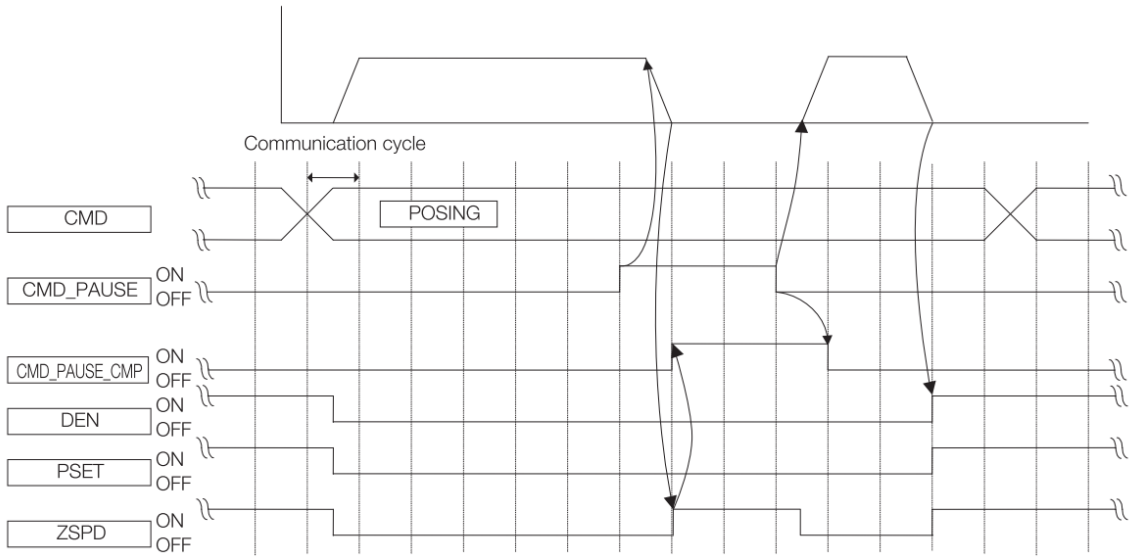

Figure 2.11.3.1

Example of pausing VELCTRL command is shown in figure 2.11.3.2.

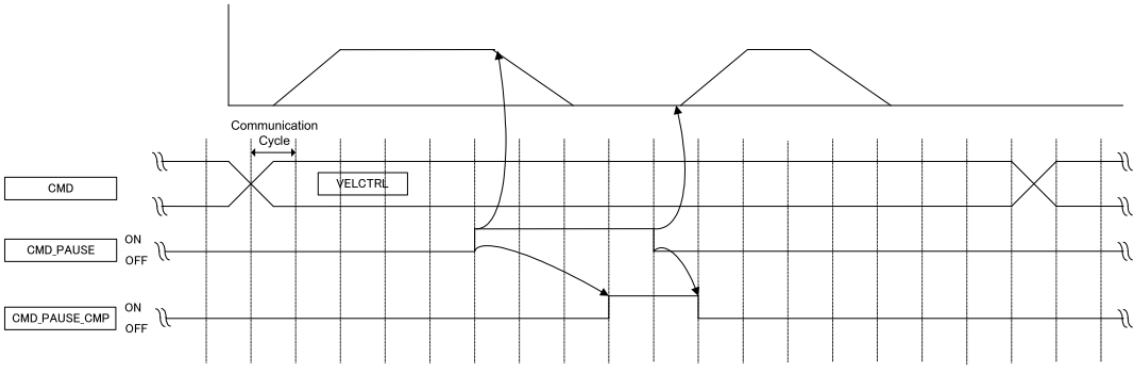

Figure 2.11.3.2

- CMD_CANCEL
  1. CMD_CANCEL is used to interrupt move command. Move command processing is cleared.
  2. CMD_CANCEL is only valid for POSING, FEED, EX_POSING, ZRET and VELCTRL commands.
  3. Movement stops according to the setting of STOP_MODE.
  4. CMD_CANCEL is disregarded when it is used for commands other than POSING, FEED, EX_POSING, ZRET and VELCTRL. CMD_CANCEL_CMP remains at 0.
  5. In position mode, when DEN=1, CMD_CANCEL_CMP will become 1. In velocity mode, when ZSPD=1, CMD_CANCEL_CMP will become 1.
  6. When CMD_CANCEL_CMP changes to 1, the previous control mode retains.
  7. When CMD_PAUSE and CMD_CANCEL are used at the same time or when CMD_CANCEL is used after CMD_PAUSE, CMD_CANCEL takes priority over CMD_PAUSE.

Note: If 0 is set for CMD_CANCEL during deceleration, the next command (POSING, FEED, EX_POSING, ZRET and VELCTRL) can be restarted before 1 is set for CMD_CANCEL_CMP. However, EX_POSING and ZRET require alternation of CMD_ID.

Example of canceling POSING command is shown in figure 2.11.3.3.

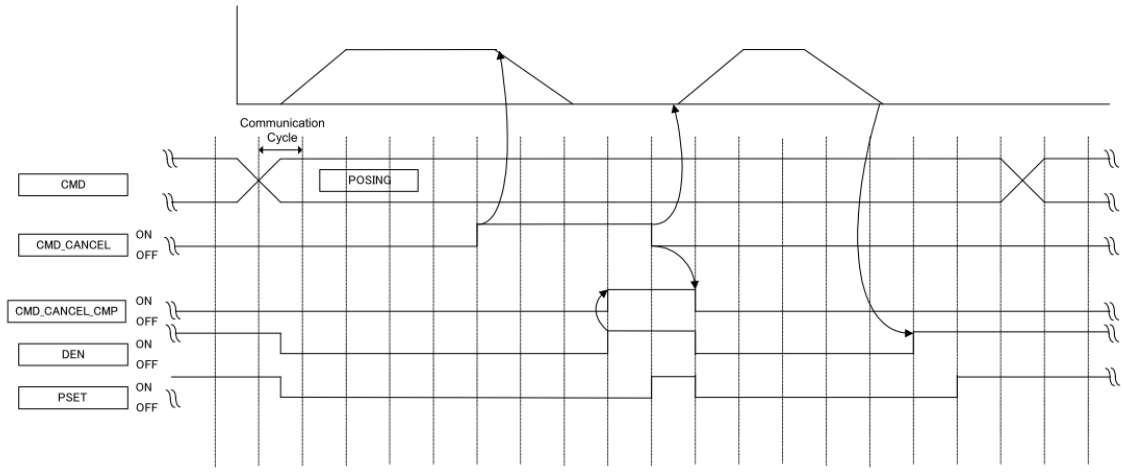

Figure 2.11.3.3

Example of canceling VELCTRL command is shown in figure 2.11.3.4.

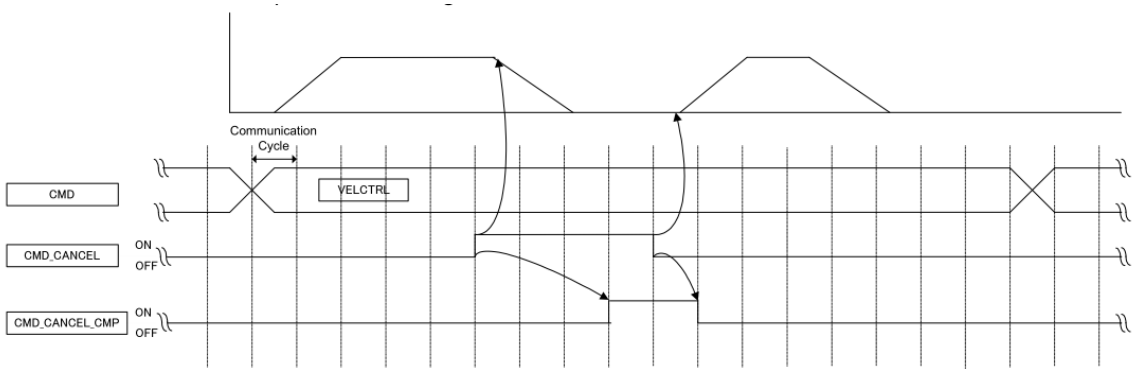

Figure 2.11.3.4

2.12 Servo command I/O signal (SVCMD_IO)

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

2.12.1 Bit allocation of servo command output signal monitoring

Bytes 8 to 11 of command field are defined as I/O signal fields for servo command output signals. Servo command output signals are signals outputted to the slave. Table 2.12.1.1 shows the bit allocation of output signal. The data in SVCMD_IO fields will still be valid even when an alarm specified by CMD_ALM occurs.

Table 2.12.1.1

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
N_CL	P_CL	P_PPI*1	V_PPI*1	Reserved			
Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8
Reserved							
Bit 23	Bit 22	Bit 21	Bit 20	Bit 19	Bit 18	Bit 17	Bit 16
O4	O3	O2	O1	Reserved			
Bit 31	Bit 30	Bit 29	Bit 28	Bit 27	Bit 26	Bit 25	Bit 24
Reserved							

Note: *1 Not supported.

Table 2.12.1.2 shows the details of output signals.

Table 2.12.1.2

Bit	Name	Contents	Value	Setting
6	P_CL	Forward Torque Limit	0	Torque not clamped
			1	Torque clamped
	Used to select whether the forward torque is clamped or not. Common parameter 8C (forward torque limit) becomes effective. Note: The value of common parameter 8C and the values specified by TLIM and Pt402 (Pt483) are compared. The smallest value becomes effective.			
7	N_CL	Reverse Torque Limit	0	Torque not clamped
			1	Torque clamped
	Used to select whether the reverse torque is clamped or not. Common parameter 8D (reverse torque limit) becomes effective. Note: The value of common parameter 8D and the values specified by TLIM and the Pt403 (Pt484) are compared. The smallest value becomes effective.			
20 - 23	O1 to O4	Output signal control	0	OFF
			1	ON
	Sets output signal to ON/OFF.			

2.12.2 Bit allocation of servo command input signal monitoring

Bytes 8 to 11 of response field are defined as I/O signal fields for servo command input signals. Servo command input signals are used to indicate the states of slave signals. The data in SVCMD_IO fields will still be valid even when an alarm specified by CMD_ALM occurs.

Table 2.12.2.1 shows the bit allocation of input signal.

Table 2.12.2.1

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
ESTP	EXT3*1	EXT2*1	EXT1	N-OT	P-OT	DEC	Reserved
Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8
ZPOINT	PSET	NEAR	DEN	N-SOT	P-SOT	BRK_ON	Reserved
Bit 23	Bit 22	Bit 21	Bit 20	Bit 19	Bit 18	Bit 17	Bit 16
Reserved				ZSPD	V_CMP	V_LIM	T_LIM
Bit 31	Bit 30	Bit 29	Bit 28	Bit 27	Bit 26	Bit 25	Bit 24
I8	I7	I6	I5	I4	I3	I2	I1

Note: *1 Not supported.

Table 2.12.2.2 shows the details of the input signals.

Table 2.12.2.2

Bit	Name	Contents	Value	Setting
1	DEC	Limit switch for deceleration during zero point return operation	0	OFF
			1	ON
	This bit is used to indicate the state of limit switch for deceleration during zero point return operation.			
2	P_OT	Forward hardware limit	0	OFF
			1	ON
	Overtravel (OT) is a function that forcibly stops a movable machine unit if it moves beyond its allowable range of movement. P_OT is used to indicate if the movement of a movable machine unit is in prohibited state in forward direction or not. The OT stop judgment is made based on ZSPD.			
3	N_OT	Reverse hardware limit	0	OFF
			1	ON
	Overtravel (OT) is a function that forcibly stops a movable machine unit if it moves beyond its allowable range of movement. N_OT is used to indicate if the movement of a movable machine unit is in prohibited state in reverse direction or not. The OT stop judgment is made based on ZSPD.			
4	EXT1	External latch 1 input signal	0	OFF
			1	ON
	The status used to judge the state of the external latch 1 input signal.			

Bit	Name	Contents	Value	Setting
7	ESTP	Emergency stop	0	OFF
			1	ON
	This bit is used to indicate the state of STO. When SF1 or SF2 of STO is triggered, the value of this bit is 1.			
9	BRK_ON	Brake application	0	Brake is released.
			1	Brake is applied.
	The holding brake is used in application where servo drive controls the vertical axis. This bit is used to indicate the state of holding brake.			
10	P_SOT	Forward software limit	0	Normal status
			1	Software limit is activated.
	Software limit forcibly stops a movable machine unit if it moves beyond the software limit range. The function is the same as overtravel function. Software limit can be used with or without P_OT or N_OT (overtravel signal). This bit is used to indicate if a movable machine unit reaches forward software limit (common parameter 26).			
11	N_SOT	Reverse software limit	0	Normal status
			1	Software limit is activated.
	Software limit forcibly stops a movable machine unit if it moves beyond the software limit range. The function is the same as overtravel function. Software limit can be used with or without P_OT or N_OT (overtravel signal). This bit is used to indicate if a movable machine unit reaches reverse software limit (common parameter 28).			
12	DEN	Distribution completed (position mode)	0	During distribution
			1	Distribution is completed.
	This bit is used to indicate if the reference position sent from the servo drive is completed. This input signal is only valid in position mode.			
13	NEAR	Near position (position mode)	0	Outside the near-position range
			1	Within the near-position range
	This bit is used to indicate if the current position is within the near-position range (common parameter 67). This input signal is only valid in position mode.			
14	PSET	Positioning completed (position mode)	0	Outside the positioning completion range
			1	Within the positioning completion range
	This bit is used to indicate if the current position is within the in-position range (common parameter 66). This input signal is only valid in position mode.			
15	ZPOINT	Zero point	0	Outside the zero point range
			1	Within the zero point range
	This bit is used to indicate if the current position is within the zero point detection range (common parameter 8B).			
16	T_LIM	Torque limit	0	Not in the torque limited state
			1	In the torque limited state
	This bit is used to indicate if the torque is clamped at the forward toque limit or the reverse toque limit.			
17	V_LIM	Speed limit (torque mode)	0	Speed limit is not detected.
			1	Speed limit is detected.
	This bit is used to indicate if the speed is clamped at the limit value specified in the command. This input signal is only valid in torque mode.			
18	V_CMP	Speed match (velocity mode)	0	Speed not matched
			1	Speed matched

Bit	Name	Contents	Value	Setting
	This bit is used to indicate if the speed is within the speed match signal detection range.			
19	ZSPD	Zero speed (velocity mode)	0	Zero speed is not detected.
			1	Zero speed is detected.
	This bit is used to indicate if the current speed is within the zero speed detection range (common parameter 8E).			
24 - 31	I1 to I8	Input signal monitoring	0	OFF
			1	ON
	Monitoring input signal I1 to I8.			

3. Details of commands

3.1 Common commands

3.1.1 No operation (NOP: 00h)

The current state is returned to response field.

- Data format

Table 3.1.1.1

Byte	Command	Response
0	NOP (00h)	NOP (00h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 31	Reserved	Reserved

- Command description

Table 3.1.1.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = NOP (00h) and CMD_STAT.CMDRDY = 1.
Alarm Description	N/A

3.1.2 Read ID (ID_RD: 03h)

ID_RD command is used to read the information of the slave. The slave information to be read can be specified by ID_CODE.

■ Data format

Table 3.1.2.1

Byte	Command	Response
0	ID_RD (03h)	ID_RD (03h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4	ID_CODE	ID_CODE
5	OFFSET	OFFSET
6 – 7	SIZE	SIZE
8 – 31	Reserved	ID

■ Command description

Table 3.1.2.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = ID_RD (03h), CMD_STAT.CMDRDY = 1, and ID_CODE, OFFSET and SIZE in response field.
Command Parameter	● ID_CODE Selection code of ID data ● OFFSET Offset of ID reading ● SIZE Data size (bytes)
Alarm Description	● When ID_CODE data is invalid, CMD_ALM = 9 hex. ● When OFFSET data is invalid or SIZE data does not match, CMD_ALM = 9 hex.

■ Details of ID_CODE

Details of ID_CODE are given in table 3.1.2.3.

Table 3.1.2.3

<table>
<tr><th>ID_CODE</th><th>Contents</th><th>Data Size</th><th>Data Type</th></tr>
<tr><td rowspan="2">01h</td><td>Vendor ID code</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 00000A8Dh
An ID code used to indicate the vendor</td></tr>
<tr><td rowspan="2">02h</td><td>Device code</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 151A0005h (E1 series servo drive)
Value: 151A0006h (E2 series servo drive)
Code used to indicate each device</td></tr>
<tr><td rowspan="2">03h</td><td>Device version</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Return the firmware version of this product. Example: 00020b06h
Version information of device</td></tr>
<tr><td rowspan="2">04h</td><td>Device information file version</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Set MDI version.
<table>
<tr><td>Bit 7</td><td>Bit 6</td><td>Bit 5</td><td>Bit 4</td><td>Bit 3</td><td>Bit 2</td><td>Bit 1</td><td>Bit 0</td></tr>
<tr><td colspan="8">Revision No.</td></tr>
<tr><td>Bit 15</td><td>Bit 14</td><td>Bit 13</td><td>Bit 12</td><td>Bit 11</td><td>Bit 10</td><td>Bit 9</td><td>Bit 8</td></tr>
<tr><td colspan="4">Major version</td><td colspan="4">Minor version</td></tr>
</table>

Major version: When there are major changes to the MDI associated with function additions and function changes, such as addition of profile
Minor version: When there are changes to the MDI associated with minor function additions and function changes
Revision No.: The returned value will normally be 0.

Bit 16 to 31 are reserved.</td></tr>
<tr><td rowspan="2">05h</td><td>Extended address setting</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">The value is always 1 in E series servo drive.
The number of extended addresses</td></tr>
<tr><td rowspan="2">10h</td><td>Profile type 1 (primary)</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 00000010h
Profile type (primary) that the device supports</td></tr>
<tr><td rowspan="2">11h</td><td>Profile version 1 (primary)</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 00000100h
Profile version (primary) that the device supports</td></tr>
<tr><td rowspan="2">12h</td><td>Profile type 2</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 000000FFh (This code means the function is not supported.)
E series servo drive only supports one profile.</td></tr>
<tr><td rowspan="2">13h</td><td>Profile version 2</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 00000000h</td></tr>
<tr><td>14h</td><td>Profile type 3</td><td>4 bytes</td><td>Binary data</td></tr>
</table>

<table>
<tr><th>ID_CODE</th><th>Contents</th><th>Data Size</th><th>Data Type</th></tr>
<tr><td></td><td colspan="3">Value: 000000FFh (This code means the function is not supported.)
E series servo drive only supports one profile.</td></tr>
<tr><td rowspan="2">15h</td><td>Profile version 3</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 00000000h</td></tr>
<tr><td rowspan="2">16h</td><td>Minimum value of transmission cycle</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 25000 [unit: 0.01 μs] (0.25 ms)
The minimum value of transmission cycle that the device supports</td></tr>
<tr><td rowspan="2">17h</td><td>Maximum value of transmission cycle</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 400000 [unit: 0.01 μs] (4 ms)
The maximum value of transmission cycle that the device supports</td></tr>
<tr><td rowspan="2">18h</td><td>Transmission cycle increment (granularity)</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 00000003h
The increment of transmission cycle that E series servo drive supports
Four levels of transmission cycle increments are provided.
00h: 31.25, 62.5, 125, 250, 500 (μs), and 2 to 64 (ms)
(2 ms increment)
01h: 31.25, 62.5, 125, 250, 500 (μs), and 1 to 64 (ms)
(1 ms increment)
02h: 31.25, 62.5, 125, 250, 500 (μs), and 1 to 64 (ms)
(0.5 ms increment)
03h: 31.25, 62.5, 125, 250, 500, 750 (μs), and 1 to 64 (ms)
(0.5 ms increment)</td></tr>
<tr><td rowspan="2">19h</td><td>Minimum value of communication cycle</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 25000 [unit: 0.01 μs] (0.25 ms)
The minimum value of communication cycle that the device supports</td></tr>
<tr><td rowspan="2">1Ah</td><td>Maximum value of communication cycle</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 3200000 [unit: 0.01 μs] (32 ms)
The maximum value of communication cycle that the device supports</td></tr>
<tr><td rowspan="2">1Bh</td><td>Number of transmission bytes</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">The number of transmission bytes that the device supports
Bytes which can be transmitted are indicated by the following bits. (0: Not supported, 1: Supported)
<table>
<tr><th>Bit 7</th><th>Bit 6</th><th>Bit 5</th><th>Bit 4</th><th>Bit 3</th><th>Bit 2</th><th>Bit 1</th><th>Bit 0</th></tr>
<tr><td colspan="3">Reserved</td><td>64 bytes</td><td>48 bytes</td><td>32 bytes</td><td>16 bytes</td><td>8 bytes</td></tr>
<tr><td colspan="3">0</td><td>0</td><td>1</td><td>1</td><td>0</td><td>0</td></tr>
</table>
Bit 8 to 31 are reserved.</td></tr>
<tr><td rowspan="2">1Ch</td><td>Number of transmission bytes (current setting)</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">The number of transmission bytes for cyclic communication
The mark “*“ will be set to 1 to show current setting. Bytes which can be transmitted are indicated by the following bits.
<table>
<tr><th>Bit 7</th><th>Bit 6</th><th>Bit 5</th><th>Bit 4</th><th>Bit 3</th><th>Bit 2</th><th>Bit 1</th><th>Bit 0</th></tr>
<tr><td colspan="3">Reserved</td><td>64 bytes</td><td>48 bytes</td><td>32 bytes</td><td>16 bytes</td><td>8 bytes</td></tr>
<tr><td colspan="3">0</td><td>0</td><td>*</td><td>*</td><td>0</td><td>0</td></tr>
</table>
Bit 8 to 31 are reserved.</td></tr>
<tr><td>1Dh</td><td>Profile type (current setting)</td><td>4 bytes</td><td>Binary data</td></tr>
</table>

<table>
<tr><th>ID_CODE</th><th>Contents</th><th>Data Size</th><th>Data Type</th></tr>
<tr><td></td><td colspan="3">This is the profile selected by CONNECT command.</td></tr>
<tr><td rowspan="2">20h</td><td>Supported communication mode</td><td>4 bytes</td><td>Binary data</td></tr>
<tr><td colspan="3">Value: 00000003h (cyclic communication and event-driven communication)
The communication modes that the device supports</td></tr>
<tr><td rowspan="2">30h</td><td>List of supported main commands</td><td>32 bytes</td><td>Array</td></tr>
<tr><td colspan="3">
The list of main commands that E series servo drive supports
The commands are allocated as below.
● Details of data
Bit 0 to 255: 0: The command is not supported. 1: The command is supported.
<table>
<tr><th>Bit 7</th><th>Bit 6</th><th>Bit 5</th><th>Bit 4</th><th>Bit 3</th><th>Bit 2</th><th>Bit 1</th><th>Bit 0</th></tr>
<tr><td>Reserved</td><td>ALM_CLR</td><td>ALR_RD</td><td>CONFIG</td><td>ID_RD</td><td>PRM_WR</td><td>PRM_RD</td><td>NOP</td></tr>
<tr><td>0</td><td>1</td><td>1</td><td>1</td><td>1</td><td>0</td><td>0</td><td>1</td></tr>
</table>
<table>
<tr><th>Bit 15</th><th>Bit 14</th><th>Bit 13</th><th>Bit 12</th><th>Bit 11</th><th>Bit 10</th><th>Bit 9</th><th>Bit 8</th></tr>
<tr><td>DIS CONNECT</td><td>CONNECT</td><td>SYNC_ SET</td><td colspan="5">Reserved</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td colspan="5">0</td></tr>
</table>
Bit 16 to 23 are reserved.
<table>
<tr><th>Bit 31</th><th>Bit 30</th><th>Bit 29</th><th>Bit 28</th><th>Bit 27</th><th>Bit 26</th><th>Bit 25</th><th>Bit 24</th></tr>
<tr><td>Reserved</td><td>MEM_WR</td><td>MEM_RD</td><td>PPRM_ WR</td><td>PPRM_ RD</td><td colspan="3">Reserved</td></tr>
<tr><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td colspan="3">0</td></tr>
</table>
<table>
<tr><th>Bit 39</th><th>Bit 38</th><th>Bit 37</th><th>Bit 36</th><th>Bit 35</th><th>Bit 34</th><th>Bit 33</th><th>Bit 32</th></tr>
<tr><td colspan="3">Reserved</td><td>SENS_ OFF</td><td>SENS_ON</td><td>BRK_OFF</td><td>BRK_ON</td><td>POS_SET</td></tr>
<tr><td colspan="3">0</td><td>1</td><td>1</td><td>1</td><td>1</td><td>0</td></tr>
</table>
Bit 40 to 47 are reserved.
<table>
<tr><th>Bit 55</th><th>Bit 54</th><th>Bit 53</th><th>Bit 52</th><th>Bit 51</th><th>Bit 50</th><th>Bit 49</th><th>Bit 48</th></tr>
<tr><td>EX_FEED</td><td>FEED</td><td>POSING</td><td>INTER POLATE</td><td>Reserved</td><td>SV_OFF</td><td>SV_ON</td><td>SMON</td></tr>
<tr><td>0</td><td>1</td><td>1</td><td>1</td><td>0</td><td>1</td><td>1</td><td>1</td></tr>
</table>
<table>
<tr><th>Bit 63</th><th>Bit 62</th><th>Bit 61</th><th>Bit 60</th><th>Bit 59</th><th>Bit 58</th><th>Bit 57</th><th>Bit 56</th></tr>
<tr><td colspan="2">Reserved</td><td>TRQCTRL</td><td>VELCTRL</td><td>Reserved</td><td>ZRET</td><td>EX_ POSING</td><td>Reserved</td></tr>
<tr><td colspan="2">0</td><td>1</td><td>1</td><td>0</td><td>1</td><td>1</td><td>0</td></tr>
</table>
<table>
<tr><th>Bit 71</th><th>Bit 70</th><th>Bit 69</th><th>Bit 68</th><th>Bit 67</th><th>Bit 66</th><th>Bit 65</th><th>Bit 64</th></tr>
<tr><td colspan="6">Reserved</td><td>SVPRM_ WR</td><td>SVPRM_ RD</td></tr>
<tr><td colspan="6">0</td><td>1</td><td>1</td></tr>
</table>
Bit 72 to 255 are reserved.
</td></tr>
</table>

<table>
<tr><th>ID_CODE</th><th>Contents</th><th>Data Size</th><th>Data Type</th></tr>
<tr><td rowspan="2">38H</td><td>List of supported subcommands</td><td>32 bytes</td><td>Array</td></tr>
<tr><td colspan="3">
The list of subcommands that the device supports
The commands are allocated as below.
● Details of data
Bit 0 to 255: 0: The command is not supported. 1: The command is supported.
<table>
<tr><th>Bit 7</th><th>Bit 6</th><th>Bit 5</th><th>Bit 4</th><th>Bit 3</th><th>Bit 2</th><th>Bit 1</th><th>Bit 0</th></tr>
<tr><td>Reserved</td><td>ALM_ CLR</td><td>ALM_ RD</td><td colspan="2">Reserved</td><td>PRM_ WR</td><td>PRM_ RD</td><td>NOP</td></tr>
<tr><td>0</td><td>1</td><td>1</td><td colspan="2">0</td><td>0</td><td>0</td><td>1</td></tr>
</table>
Bit 8 to 23 are reserved.
<table>
<tr><th>Bit 31</th><th>Bit 30</th><th>Bit 29</th><th>Bit 28</th><th>Bit 27</th><th>Bit 26</th><th>Bit 25</th><th>Bit 24</th></tr>
<tr><td>Reserved</td><td>MEM_ WR</td><td>MEM_ RD</td><td>PPRM_ WR</td><td>PPRM_ RD</td><td colspan="3">Reserved</td></tr>
<tr><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td colspan="3">0</td></tr>
</table>
Bit 32 to 47 are reserved.
<table>
<tr><th>Bit 55</th><th>Bit 54</th><th>Bit 53</th><th>Bit 52</th><th>Bit 51</th><th>Bit 50</th><th>Bit 49</th><th>Bit 48</th></tr>
<tr><td colspan="7">Reserved</td><td>SMON</td></tr>
<tr><td colspan="7">0</td><td>1</td></tr>
</table>
Bit 56 to 63 are reserved.
<table>
<tr><th>Bit 71</th><th>Bit 70</th><th>Bit 69</th><th>Bit 68</th><th>Bit 67</th><th>Bit 66</th><th>Bit 65</th><th>Bit 64</th></tr>
<tr><td colspan="6">Reserved</td><td>SVPRM_ WR</td><td>SVPRM_ RD</td></tr>
<tr><td colspan="6">0</td><td>1</td><td>1</td></tr>
</table>
Bit 72 to 255 are reserved.
</td></tr>
<tr><td rowspan="2">40h</td><td>List of supported common parameters</td><td>32 bytes</td><td>Array</td></tr>
<tr><td colspan="3">
The list of common parameters that the device supports
The common parameters are allocated as below.
● Details of data
Bit 0 to 255: 0: The common parameter is not supported. 1: The common parameter is supported.
<table>
<tr><th>Bit 7</th><th>Bit 6</th><th>Bit 5</th><th>Bit 4</th><th>Bit 3</th><th>Bit 2</th><th>Bit 1</th><th>Bit 0</th></tr>
<tr><td>07</td><td>06</td><td>05</td><td>04</td><td>03</td><td>02</td><td>01</td><td>Reserved</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>0</td></tr>
</table>
<table>
<tr><th>Bit 15</th><th>Bit 14</th><th>Bit 13</th><th>Bit 12</th><th>Bit 11</th><th>Bit 10</th><th>Bit 9</th><th>Bit 8</th></tr>
<tr><td colspan="3">Reserved</td><td>0C</td><td>0B</td><td>0A</td><td>09</td><td>08</td></tr>
<tr><td colspan="3">0</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td></tr>
</table>
Bit 16 to 31 are reserved.
<table>
<tr><th>Bit 39</th><th>Bit 38</th><th>Bit 37</th><th>Bit 36</th><th>Bit 35</th><th>Bit 34</th><th>Bit 33</th><th>Bit 32</th></tr>
<tr><td>27</td><td>26</td><td>25</td><td>24</td><td>23</td><td>22</td><td>21</td><td>Reserved</td></tr>
<tr><td>0</td><td>0</td><td>0</td><td>0</td><td>0</td><td>1</td><td>1</td><td>0</td></tr>
</table>
<table>
<tr><th>Bit 47</th><th>Bit 46</th><th>Bit 45</th><th>Bit 44</th><th>Bit 43</th><th>Bit 42</th><th>Bit 41</th><th>Bit 40</th></tr>
<tr><td colspan="6">Reserved</td><td>29</td><td>28</td></tr>
<tr><td colspan="6">0</td><td>0</td><td>0</td></tr>
</table>
</td></tr>
</table>

<table>
<tr><th>ID_CODE</th><th>Contents</th><th>Data Size</th><th>Data Type</th></tr>
<tr><td>40h</td><td>
Bit 48 to 63 are reserved.
<table>
<tr><td>Bit 71</td><td>Bit 70</td><td>Bit 69</td><td>Bit 68</td><td>Bit 67</td><td>Bit 66</td><td>Bit 65</td><td>Bit 64</td></tr>
<tr><td>47</td><td>46</td><td>45</td><td>44</td><td>43</td><td>42</td><td>41</td><td>Reserved</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>0</td></tr>
</table>
<table>
<tr><td>Bit 79</td><td>Bit 78</td><td>Bit 77</td><td>Bit 76</td><td>Bit 75</td><td>Bit 74</td><td>Bit 73</td><td>Bit 72</td></tr>
<tr><td colspan="6">Reserved</td><td>49</td><td>48</td></tr>
<tr><td colspan="6">0</td><td>1</td><td>1</td></tr>
</table>
Bit 80 to 95 are reserved.
<table>
<tr><td>Bit 103</td><td>Bit 102</td><td>Bit 101</td><td>Bit 100</td><td>Bit 99</td><td>Bit 98</td><td>Bit 97</td><td>Bit 96</td></tr>
<tr><td>67</td><td>66</td><td>65</td><td>64</td><td>63</td><td>62</td><td>61</td><td>Reserved</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>0</td></tr>
</table>
Bit 104 to 127 are reserved.
<table>
<tr><td>Bit 135</td><td>Bit 134</td><td>Bit 133</td><td>Bit 132</td><td>Bit 131</td><td>Bit 130</td><td>Bit 129</td><td>Bit 128</td></tr>
<tr><td>87</td><td>86</td><td>85</td><td>84</td><td>83</td><td>82</td><td>81</td><td>Reserved</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>0</td><td>0</td><td>0</td></tr>
</table>
<table>
<tr><td>Bit 143</td><td>Bit 142</td><td>Bit 141</td><td>Bit 140</td><td>Bit 139</td><td>Bit 138</td><td>Bit 137</td><td>Bit 136</td></tr>
<tr><td>8F</td><td>8E</td><td>8D</td><td>8C</td><td>8B</td><td>8A</td><td>89</td><td>88</td></tr>
<tr><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td><td>1</td></tr>
</table>
<table>
<tr><td>Bit 151</td><td>Bit 150</td><td>Bit 149</td><td>Bit 148</td><td>Bit 147</td><td>Bit 146</td><td>Bit 145</td><td>Bit 144</td></tr>
<tr><td colspan="4">Reserved</td><td>93</td><td>92</td><td>91</td><td>90</td></tr>
<tr><td colspan="4">0</td><td>1</td><td>1</td><td>1</td><td>1</td></tr>
</table>
Bit 152 to 255 are reserved.
</td><td></td><td></td></tr>
<tr><td rowspan="2">80h</td><td>Main device name</td><td>32 bytes</td><td>ASCII Code</td></tr>
<tr><td colspan="3">The main device name
Example: ED1F-L0-0000-00
Note: To identify the device, please use device code (02h) instead of this ID_CODE.</td></tr>
<tr><td rowspan="2">90h</td><td>Sub-device name 1</td><td>32 bytes</td><td>ASCII Code</td></tr>
<tr><td colspan="3">Motor model</td></tr>
<tr><td rowspan="2">A0h</td><td>Sub-device name 2</td><td>32 bytes</td><td>ASCII Code</td></tr>
<tr><td colspan="3">Motor encoder model</td></tr>
</table>

3.1.3 Device setup (CONFIG: 04h)

This command is used to set up devices.

- Data format

Table 3.1.3.1

Byte	Command	Response
0	CONFIG (04h)	CONFIG (04h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4	CONFIG_MOD	CONFIG_MOD
5 – 31	Reserved	Reserved

- Command description

Table 3.1.3.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = CONFIG (04h), CMD_STAT.CMDRDY = 1, and CONFIG_MOD in response field.
Command Parameter	● CONFIG_MOD 0: Recalculating and setting up parameters. Other: Not supported (CMD_ALM = 9)
Alarm Description	● When CONFIG_MOD data is invalid, CMD_ALM = 9h. ● When this command is used in servo-on state, CMD_ALM = Ah.

- State of each status during CONFIG command execution

Table 3.1.3.3

Status	Before CONFIG command is executed	During command execution	After CONFIG command is executed
ALM	Current state	Current state	Current state
CMDRDY	1	0	1
Other statuses	Current state	Undefined	Current state

3.1.4 Read alarm or warning (ALM_RD: 05h)

ALM_RD command is used to read alarm or warning state. The current alarm or warning state can be read in ALM_DATA fields.

■ Data format

Table 3.1.4.1

Byte	Command	Response
0	ALM_RD (05h)	ALM_RD (05h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 5	ALM_RD_MOD	ALM_RD_MOD
6 – 7	ALM_INDEX	ALM_INDEX
8 – 31	Reserved	ALM_DATA

Note:

(1) In ALM_DATA fields, an alarm is indicated by 2 bytes.

(2) The alarm arrangement in alarm history is in the order of occurrence. The first alarm is the latest alarm.

(3) In normal state, ALM_DATA is 0.

(4) ALM_INDEX cannot be used. Settings in ALM_INDEX fields will be ignored.

■ Command description

Table 3.1.4.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = ALM_RD (05h), CMD_STAT.CMDRDY = 1, and ALM_RD_MOD and ALM_INDEX in response field.
Command Parameter	● ALM_RD_MOD 0: Reads current alarm or warning state. 1: Reads alarm history. ● ALM_DATA Stores alarm codes or warning codes.
Alarm Description	● When ALM_RD_MOD data is invalid, CMD_ALM = 9 hex.

3.1.5 Clear alarm or warning (ALM_CLR: 06h)

ALM_CLR command is used to clear alarm or warning state. It changes the state of the slave, but does not eliminate the cause of the alarm or warning. ALM_CLR command should be used to clear the alarm or warning state after the cause of the alarm or warning has been eliminated.

When a communication error (reception error) or synchronous communication error (watchdog data error) occurs during synchronous communication, after ALM_CLR command is executed, please use SYNC_SET command to recover synchronous communication.

- Data format

Table 3.1.5.1

Byte	Command	Response
0	ALM_CLR (06h)	ALM_CLR (06h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 5	ALM_CLR_MOD	ALM_CLR_MOD
6 – 31	Reserved	Reserved

- Command description

Table 3.1.5.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = ALM_CLR (06h), CMD_STAT.CMDRDY = 1, and ALM_CLR_MOD in response field.
Command Parameter	● ALM_CLR_MODE 0: Clears current alarm or warning state. 1: Clears alarm history.
Alarm Description	● When ALM_CLR_MOD data is invalid, CMD_ALM = 9 hex.

3.1.6 Start synchronous communication (SYNC_SET: 0Dh)

SYNC_SET command is used to start synchronous communication. The system will be in synchronous communication mode when the execution of this command is completed. This command can also be used to recover synchronous communication. For example, use this command to change the system from asynchronous communication mode to synchronous communication mode after communication error occurs. During the execution of this command, synchronous communication is established according to the transition of watchdog timer (WDT). The master will maintain this command until the processing has been completed. Watchdog data error detection starts after this command has been completed.

- Data format

Table 3.1.6.1

Byte	Command	Response
0	SYNC_SET (0Dh)	SYNC_SET (0Dh)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 31	Reserved	Reserved

- Command description

Table 3.1.6.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SYNC_SET (0Dh) and CMD_STAT.CMDRDY = 1.
Alarm Description	N/A

3.1.7 Establish connection (CONNECT: 0Eh)

CONNECT command is used to establish MECHATROLINK connection. After the command has been completed, slaves can be controlled via MECHATROLINK communication.

- Data format

Table 3.1.7.1

Byte	Command	Response
0	CONNECT (0Eh)	CONNECT (0Eh)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4	VER	VER
5	COM_MOD	COM_MOD
6	COM_TIM	COM_TIM
7	PROFILE_TYPE	PROFILE_TYPE
8 – 31	Reserved	Reserved

■ Command description

Table 3.1.7.2

<table>
<tr><td rowspan="2">Command Classification</td><td>Common command</td></tr>
<tr><td>Asynchronous command</td></tr>
<tr><td>Confirmation Method of Command Completion</td><td>Confirm the command is successfully executed by checking RCMD = CONNECT (0Eh), CMD_STAT.CMDRDY = 1, and VER, COM_MODE, COM_TIME, and PROFILE_TYPE in response field.</td></tr>
<tr><td>Command Parameter</td><td>● VER: Version of MECHATROLINK application layer
VER = 30h
● COM_MOD: Communication mode
<table><tr><th>Bit 7</th><th>Bit 6</th><th>Bit 5</th><th>Bit 4</th><th>Bit 3</th><th>Bit 2</th><th>Bit 1</th><th>Bit 0</th></tr><tr><td>SUBCMD</td><td colspan="3">0</td><td colspan="2">DTMODE</td><td>SYNC MODE</td><td>0</td></tr></table>● SYNCMODE: Synchronization setting
1: Perform synchronous communication.
(Watchdog data error detection is enabled. Synchronous commands can be used.)
0: Perform asynchronous communication.
(Watchdog data error detection is disabled. Synchronous commands cannot be used.)</td></tr>
<tr><td>Command Parameter</td><td>● DTMODE: Data transfer method
00: Single transmission
01: Reserved
10: Reserved
11: Reserved
● SUBCMD: Subcommand setting
0: Subcommand is disabled.
1: Subcommand is enabled.
● COM_TIM: Communication cycle setting
COM_TIM = Communication cycle/Transmission cycle
Example:
The transmission cycle is 0.5 [ms] and the communication cycle is 2 [ms].
COM_TIM = 2/0.5 = 4
● PROFILE_TYPE: Profile type setting
10h: Standard servo profile command</td></tr>
<tr><td>Alarm Description</td><td>● When VER data is invalid, CMD_ALM = 9 hex.
● When COM_TIM data is invalid, CMD_ALM = 9 hex.
● When PROFILE_TYPE data is invalid, CMD_ALM = 9 hex.
● When the number of transmission bytes is 32, but SUBCMD = 1, CMD_ALM=9 hex.</td></tr>
</table>

3.1.8 Release connection (DISCONNECT: 0Fh)

The master sends DISCONNECT command for two or more communication cycles to release a connection. At this time, the slave interrupts the processing of current command and then initializes to wait for the connection establishment request from the master.

DISCONNECT command can be sent regardless of the state of CMD_STAT.CMDRDY. If DISCONNECT command is sent when CMD_STAT.CMDRDY is 0, the processing of current command is interrupted and DISCONNECT command is executed.

- Data format

Table 3.1.8.1

Byte	Command	Response
0	DISCONNECT (0Fh)	DISCONNECT (0Fh)
1 – 31	Reserved	Reserved

- Command description

Table 3.1.8.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm DISCONNECT command has been sent for two or more communication cycles.
Alarm Description	N/A

Note:
When DISCONNECT command is received, the following operation is performed.
(1) Communication phase changes to phase 1.
(2) Slaves are servo-off.
If control power is turned off at the same time when DISCONNECT command is sent, the reliability of the data in response field is not guaranteed.

3.2 Servo commands

3.2.1 Apply brake (BRK_ON: 21h)

BRK_ON command is used to output brake operation signal. This command is only valid in servo-off state.

■ Data format

Table 3.2.1.1

Byte	Command	Response
0	BRK_ON (21h)	BRK_ON (21h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	Reserved	CPRM_SEL_MON1
16 – 19		CPRM_SEL_MON2
20 – 23		MONITOR1
24 – 27		MONITOR2
28 – 31		MONITOR3

■ Command description

Table 3.2.1.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = BRK_ON (21H) and CMD_STAT.CMDRDY = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88.
Alarm Description	● When this command is used in servo-on state, CMD_ALM = Ah.

3.2.2 Release brake (BRK_OFF: 22h)

BRK_OFF command is used to cancel brake operation signal. This command is only valid in servo-off state.

- Data format

Table 3.2.2.1

Byte	Command	Response
0	BRK_OFF (22h)	BRK_OFF (22h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	Reserved	CPRM_SEL_MON1
16 – 19		CPRM_SEL_MON2
20 – 23		MONITOR1
24 – 27		MONITOR2
28 – 31		MONITOR3

- Command description

Table 3.2.2.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SENS_ON (23H) and CMD_STAT.CMDRDY = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88.
Alarm Description	● N/A

3.2.3 Turn sensor ON (SENS_ON: 23h)

SENS_ON command is used to request for sensor initialization. After this command is executed, when an absolute encoder is used, the initial position is acquired from the encoder. The current position will be: initial position acquired from the encoder. The coordinate reference point setting, ZPOINT (zero point position) and software limit are valid. When an incremental encoder is used, only a response is returned without processing.

■ Data format

Table 3.2.3.1

Byte	Command	Response
0	SENS_ON (23h)	SENS_ON (23h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	Reserved	CPRM_SEL_MON1
16 – 19		CPRM_SEL_MON2
20 – 23		MONITOR1
24 – 27		MONITOR2
28 – 31		MONITOR3

■ Command description

Table 3.2.3.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SENS_ON (23H) and CMD_STAT.CMDRDY = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88.
Alarm Description	● N/A

3.2.4 Turn sensor OFF (SENS_OFF: 24h)

SENS_OFF command is used to turn off the power supplied to the sensor. After this command is executed, when an absolute encoder is used, the reliability of position data is not guaranteed and POS_RDY changes to 0. The coordinate reference point setting, ZPOINT (zero point position) and software limit are invalid. When an incremental encoder is used, only a response is returned without processing.

■ Data format

Table 3.2.4.1

Byte	Command	Response
0	SENS_OFF (24h)	SENS_OFF (24h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	Reserved	CPRM_SEL_MON1
16 – 19		CPRM_SEL_MON2
20 – 23		MONITOR1
24 – 27		MONITOR2
28 – 31		MONITOR3

■ Command description

Table 3.2.4.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SENS_ON (23H) and CMD_STAT.CMDRDY = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88.
Alarm Description	● N/A

3.2.5 Servo status monitor (SMON: 30H)

SMON command is used to read alarm, status, monitoring information (position, speed, torque, etc.) specified in monitoring setting, and the state of I/O signal.

- Data format

Table 3.2.5.1

Byte	Command	Response
0	SMON (30h)	SMON (30h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	Reserved	CPRM_SEL_MON1
16 – 19		CPRM_SEL_MON2
20 – 23		MONITOR1
24 – 27		MONITOR2
28 – 31		MONITOR3

- Command description

Table 3.2.5.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SMON (30H) and CMD_STAT.CMDRDY = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88.
Alarm Description	● N/A

3.2.6 Servo ON (SV_ON: 31h)

SV_ON command is used to request for servo on (motor energization).

■ Data format

Table 3.2.6.1

Byte	Command	Response
0	SV_ON (31h)	SV_ON (31h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	Reserved	CPRM_SEL_MON1
16 – 19		CPRM_SEL_MON2
20 – 23		MONITOR1
24 – 27		MONITOR2
28 – 31		MONITOR3

■ Command description

Table 3.2.6.2

Command Classification	Standard servo command
	Asynchronous command
Processing Time	Normally within 5 ms (Max. 5 s)
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SV_ON (31h), CMD_STAT.CMDRDY = 1, and SVCMD_STAT.SV_ON = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88.
Alarm Description	In the following cases, A hex will be set for CMD_ALM and the command will not be executed: ● When an alarm (COM_ALM = 8 hex or greater, or D_ALM = 1) has occurred. ● When PON = 0. ● When an absolute encoder is used, but the execution of SENS_ON command is not completed.

3.2.7 Servo OFF (SV_OFF: 32h)

SV_OFF command is used to request for servo off (stop motor energization).

■ Data format

Table 3.2.7.1

Byte	Command	Response
0	SV_OFF (32h)	SV_OFF (32h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	Reserved	CPRM_SEL_MON1
16 – 19		CPRM_SEL_MON2
20 – 23		MONITOR1
24 – 27		MONITOR2
28 – 31		MONITOR3

■ Command description

Table 3.2.7.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SV_OFF (32h), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.SV_ON = 0.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88.
Alarm Description	● N/A

3.2.8 Interpolation (INTERPOLATE: 34h)

INTERPOLATE command is used to perform interpolation feeding at the specified interpolation position every communication cycle.

- Data format

Table 3.2.8.1

Byte	Command	Response
0	INTERPOLATE (34h)	INTERPOLATE (34h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	TPOS	CPRM_SEL_MON1
16 – 19	VFF	CPRM_SEL_MON2
20 – 23	TFF	MONITOR1
24 – 27	Reserved	MONITOR2
28 – 31	TLIM	MONITOR3

■ Command description

Table 3.2.8.2

Command Classification	Standard servo command
	Synchronous command
Confirmation Method of Command Completion	(1) Confirm the command is successfully executed by checking RCMD = INTERPOLATE (34h) and CMD_STAT.CMDRDY = 1. (2) Confirm the output of reference position is completed by checking SVCMD_IO.DEN = 1, and the completion of positioning by checking SVCMD_IO.PSET = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88. ● TPOS (target position): Set with a signed value. ● VFF (velocity feedforward): Set with a signed value. This value will be cleared when another command is executed. ● TFF (torque feedforward): Set with a signed value. This value will be cleared when another command is executed. ● TLIM (torque limit): Set with an unsigned value.
Alarm Description	In the following cases, an alarm will occur and the command will not be executed: ● When the command is used in communication phase 2, CMD_ALM = C hex. ● When the command is used in servo-off state, CMD_ALM = A hex. ● When the difference to the previous TPOS exceeds the limit value, CMD_ALM = 9 hex. In the following cases, an alarm will occur and the relevant value will be clamped at the limit value: ● When VFF data is invalid, CMD_ALM = 1 hex. ● When TFF data is invalid, CMD_ALM = 1 hex.

3.2.9 Positioning (POSING: 35h)

POSING command is used to position to the target position (P1) at the positioning speed. To pause positioning, set SVCMD_CTRL.CMD_PAUSE to 1.

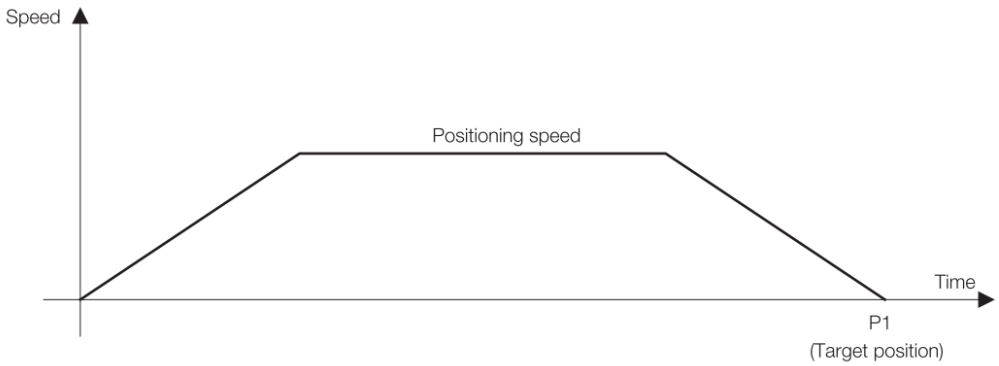

Figure 3.2.9.1

- Data format

Table 3.2.9.1

Byte	Command	Response
0	POSING (35h)	POSING (35h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	TPOS	CPRM_SEL_MON1
16 – 19	TSPD	CPRM_SEL_MON2
20 – 23	ACCR	MONITOR1
24 – 27	DECR	MONITOR2
28 – 31	TLIM	MONITOR3

■ Command description

Table 3.2.9.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	(1) Confirm the command is successfully executed by checking RCMD = POSING (= 35 hex) and CMD_STAT.CMDRDY = 1. (2) Confirm the output of reference position is completed by checking SVCMD_IO.DEN = 1, and the completion of positioning by checking SVCMD_IO.PSET = 1. (3) Confirm the completion of canceling the command by checking RCMD = POSING (= 35 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1. (4) Confirm the completion of pausing the command by checking RCMD = POSING (= 35 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_PAUSE_CMP = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88. ● TPOS (target position): Set with a signed value. ● TSPD (target speed): Set with an unsigned value. ● ACCR (acceleration): Set with an unsigned value. ● DECR (deceleration): Set with an unsigned value. ● TLIM (torque limit): Set with an unsigned value. When torque limit is not used, set the maximum allowable value. Refer to section 3.2.17 for further information of above command parameters. Refer to section 5.2 for units of above command parameters.
Alarm Description	In the following cases, an alarm will occur and the command will not be executed: ● When the command is used in servo-off state, CMD_ALM = A hex. ● When TSPD data is invalid, CMD_ALM = 9 hex. If ACCR or DECR is 0, current acceleration or deceleration will be applied, and no alarm will occur. In the following case, an alarm will occur and the relevant value will be clamped at the limit value: ● When ACCR or DECR data is invalid, CMD_ALM = 1 hex. ● When TLIM data is invalid, CMD_ALM = 1 hex.

■ Operation for smooth acceleration and deceleration

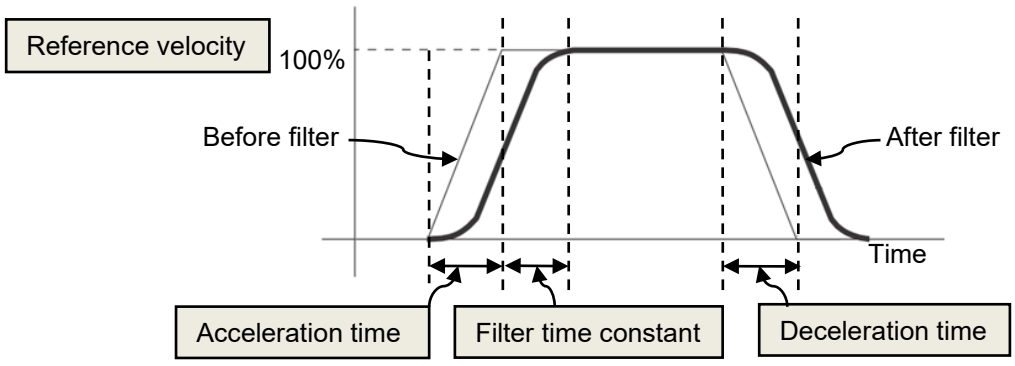

Figure 3.2.9.2

3.2.10 Feed (FEED: 36h)

FEED command is used to perform constant-speed feed at the specified feed speed. The speed and direction of feed can be changed by the setting of feed speed. To cancel constant-speed feed, set SVCMD_CTRL.CMD_CANCEL to 1, and to pause constant-speed feed, set SVCMD_CTRL.CMD_PAUSE to 1.

- Data format

Table 3.2.10.1

Byte	Command	Response
0	FEED (36h)	FEED (36h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	Reserved	CPRM_SEL_MON1
16 – 19	TSPD	CPRM_SEL_MON2
20 – 23	ACCR	MONITOR1
24 – 27	DECR	MONITOR2
28 – 31	TLIM	MONITOR3

■ Command description

Table 3.2.10.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	(1) Confirm the completion of canceling the command by checking RCMD = FEED (= 36 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1. (2) Confirm the output of reference position is completed by checking SVCMD_IO.DEN = 1, and the completion of positioning by checking SVCMD_IO.PSET = 1. (3) Confirm the completion of pausing the command by checking RCMD = FEED (= 36 hex), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_PAUSE_CMP = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88. ● TSPD (target speed): Set with a signed value. ● ACCR (acceleration): Set with an unsigned value. ● DECR (deceleration): Set with an unsigned value. ● TLIM (torque limit): Set with an unsigned value. When torque limit is not used, set the maximum allowable value. Refer to section 3.2.17 for further information of above command parameters. Refer to section 5.2 for units of above command parameters.
Alarm Description	In the following cases, an alarm will occur and the command will not be executed: ● When the command is used in servo-off state, CMD_ALM = A hex. ● When TSPD data is invalid, CMD_ALM = 9 hex. ● If ACCR or DECR is 0, current acceleration or deceleration will be applied, and no alarm will occur. In the following case, an alarm will occur and the relevant value will be clamped at the limit value: ● When ACCR or DECR data is invalid, CMD_ALM = 1 hex. ● When TLIM data is invalid, CMD_ALM = 1 hex.

■ Operation example of FEED command

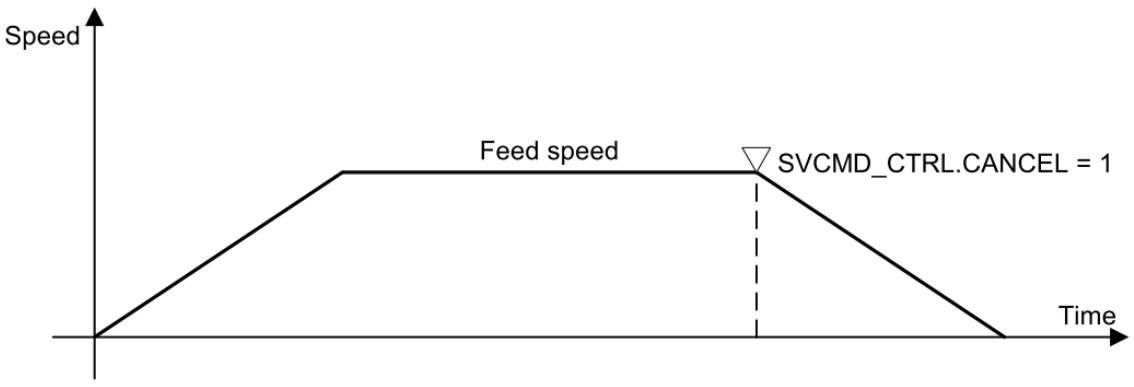

Figure 3.2.10.1

3.2.11 External input positioning (EX_POSING: 39h)

EX_POSING command performs positioning in response to the external positioning signal. To pause EX_POSING command, set SVCMD_CTRL.CMD_PAUSE to 1.

- Data format

Table 3.2.11.1

Byte	Command	Response
0	EX_POSING (39h)	EX_POSING (39h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	TPOS	CPRM_SEL_MON1
16 – 19	TSPD	CPRM_SEL_MON2
20 – 23	ACCR	MONITOR1
24 – 27	DECR	MONITOR2
28 – 31	TLIM	MONITOR3

■ Command description

Table 3.2.11.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	(1) Confirm the command is successfully executed by checking RCMD = EX_POSING (39h) and CMD_STAT.CMDRDY = 1. (2) Confirm the completion of latch by checking SVCMD_IO.L_CMP1 = 1. (3) Confirm the output of reference position is completed by checking SVCMD_IO.DEN = 1, and the completion of positioning by checking SVCMD_IO.PSET = 1. (4) Confirm the completion of canceling the command by checking RCMD = EX_POSING (39h), CMD_STAT.CMDRDY = 1, and SVCMD_STAT.CMD_CANCEL_CMP = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88. ● TPOS (target position): Set with a signed value. ● TSPD (target speed): Set with an unsigned value. ● ACCR (acceleration): Set with an unsigned value. ● DECR (deceleration): Set with an unsigned value. ● TLIM (torque limit): Set with an unsigned value. When torque limit is not used, set the maximum allowable value. Refer to 3.2.17 for further information of above command parameters. Refer to section 5.2 for units of above command parameters.
Alarm Description	In the following cases, an alarm will occur and the command will not be executed: ● When the command is used in servo-off state, CMD_ALM = A hex. ● When TSPD data is invalid, CMD_ALM = 9 hex. If ACCR or DECR is 0, current acceleration or deceleration will be applied, and no alarm will occur. In the following case, an alarm will occur and the relevant value will be clamped at the limit value: ● When ACCR or DECR data is invalid, CMD_ALM = 1 hex. ● When TLIM data is invalid, CMD_ALM = 1 hex.

■ Operating sequence

The following describes the operating sequence while using EX_POSING command.

1. The master sends EX_POSING command. Target position P1 is set in the target position field to be used as the positioning target if external positioning signal is not inputted. Select latch signal by LT_SEL1 of SVCMD_CTRL and send latch request by setting LT_REQ1 to 1.
2. The motor starts to move toward target position P1 at the specified speed when the slave receives EX_POSING command. At the same time, the slave enters external input positioning mode.
3. When external positioning signal is inputted, the slave sets latch completion status L_CMP1 to 1 to notify the master that latch has completed.
4. The slave calculates external input positioning target position P3 and the motor moves to

external input positioning target P3.

External input positioning target position P3 = Latched position P2 by external positioning signal + Final travel distance for external input positioning

5. After the motor moves to target position P3, the slave sets DEN (distribution completed) to 1 to notify the master the completion of reference position output.

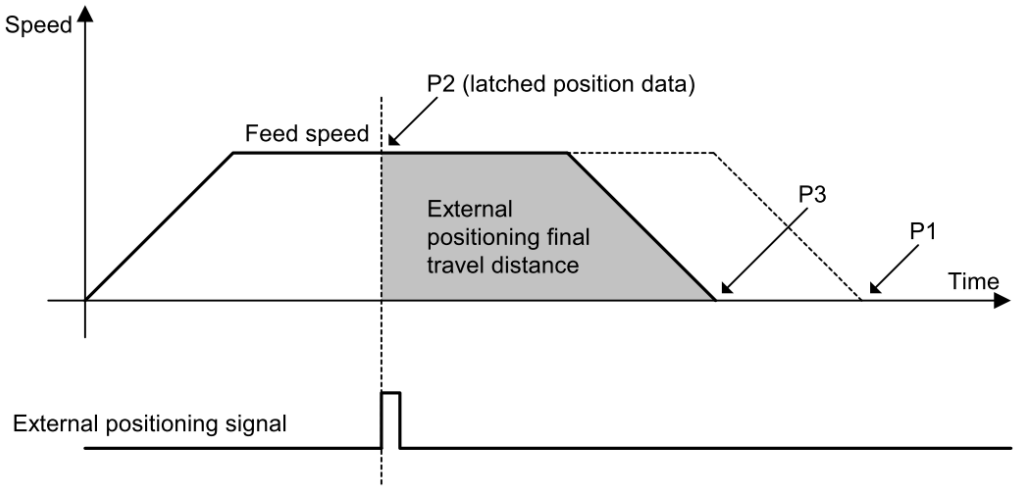

Figure 3.2.11.1

- Supplementary information

Set SVCMD_CTRL.CMD_CANCEL to 1 to cancel EX_POSING command. The moving direction after latch is determined by the value set for final travel distance for external input positioning.

1. If the value set for final travel distance for external input positioning is positive:
   If the motor moves in positive direction when latch occurs, the motor will still move in positive direction (the same direction) for positioning after latch. If the motor moves in negative direction when latch occurs, the motor will move in positive direction (the reverse direction) for positioning after latch.

2. If the value set for final travel distance for external input positioning is negative:
   If the motor moves in positive direction when latch occurs, the motor will move in negative direction (the reverse direction) for positioning after latch. If the motor moves in negative direction when latch occurs, the motor will still move in negative direction (the same direction) for positioning after latch.

3.2.12 Zero point return command (ZRET: 3Ah)

ZRET command is used to perform zero point return operation by using zero point limit switch and position latch signal. The signal used to latch position is specified by latch signal selection. To pause zero point return operation, set SVCMD_CTRL.CMD_PAUSE to 1.

- Data format

Table 3.2.12.1

Byte	Command	Response
0	ZRET (3Ah)	ZRET (3Ah)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	MODE	CPRM_SEL_MON1
16 – 19	TSPD	CPRM_SEL_MON2
20 – 23	ACCR	MONITOR1
24 – 27	DECR	MONITOR2
28 – 31	TLIM	MONITOR3

■ Command description

Table 3.2.12.2

<table>
<tr><td rowspan="2">Command Classification</td><td>Standard servo command</td></tr>
<tr><td>Asynchronous command</td></tr>
<tr><td>Confirmation Method of Command Completion</td><td>(1) Confirm the command is successfully executed by checking RCMD = ZRET (3Ah) and CMD_STAT.CMDRDY = 1.
(2) Confirm the completion of motion reference output by checking SVCMD_IO.DEN = 1, and the completion of positioning at the zero point by checking SVCMD_IO.ZPOINT (zero point position) = 1 and SVCMD_IO.PSET = 1.
(3) Confirm the completion of canceling the command by checking RCMD = ZRET (3Ah), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1.
(4) Confirm the completion of pausing the command by checking RCMD = ZRET (3Ah), CMD_STAT.CMDRDY = 1, and SVCMD_STAT.CMD_PAUSE_CMP = 1.</td></tr>
<tr><td>Command Parameter</td><td>● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88.
● MODE: (Lower 1 byte)<table><tr><td>Bit 7</td><td>Bit 6</td><td>Bit 5</td><td>Bit 4</td><td>Bit 3</td><td>Bit 2</td><td>Bit 1</td><td>Bit 0</td></tr><tr><td>HOME_DIR</td><td colspan="3">Reserved</td><td colspan="4">TYPE</td></tr></table>(1) MODE.HOME_DIR (zero point return direction): Select zero point return direction.
MODE.HOME_DIR = 0: Positive direction
MODE.HOME_DIR = 1: Negative direction
(2) MODE.TYPE (zero point return type): Set zero point return type from the following patterns.
MODE.TYPE = 0: Latch signal
MODE.TYPE = 1: Deceleration limit switch + latch signal
● TSPD (target speed): Set with an unsigned value.
● ACCR (acceleration): Set with an unsigned value.
● DECR (deceleration): Set with an unsigned value.
● TLIM (torque limit): Set with an unsigned value.
When torque limit is not used, set the maximum allowable value.
Refer to 3.2.17 for further information of above command parameters.
Refer to section 5.2 for units of above command parameters.</td></tr>
<tr><td>Alarm Description</td><td>In the following cases, an alarm will occur and the command will not be executed:
● When the command is used in servo-off state, CMD_ALM = A hex.
● When TSPD data is invalid, CMD_ALM = 9 hex.
If ACCR or DECR is 0, current acceleration or deceleration will be applied, and no alarm will occur.
In the following case, an alarm will occur and the relevant value will be clamped at the limit value:
● When ACCR or DECR data is invalid, CMD_ALM = 1 hex.
● When TLIM data is invalid, CMD_ALM = 1 hex.</td></tr>
</table>

■ Operation sequence

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

1. MODE = 0 (Latch signal)

(1) The C1 master sends ZRET command. Select latch signal[*1] with LT_SEL1 of SVCMD_CTRL and output latch request by setting LT_REQ1 = 1.

(2) The slave starts feeding in the direction specified by MODE.HOME_DIR at the speed set by the parameter of “Approach Speed of Zero Point Return” (common parameter 84).

(3) When the latch signal specified by LT_SEL1 of SVCMD_CTRL is input, the slave executes positioning by using the parameters of “Final Travel Distance for Zero Point Return” (common parameter 86) and “Creep Speed of Zero Point Return” (common parameter 85). After positioning completes, the slave sets current position as the zero point of the coordinates.

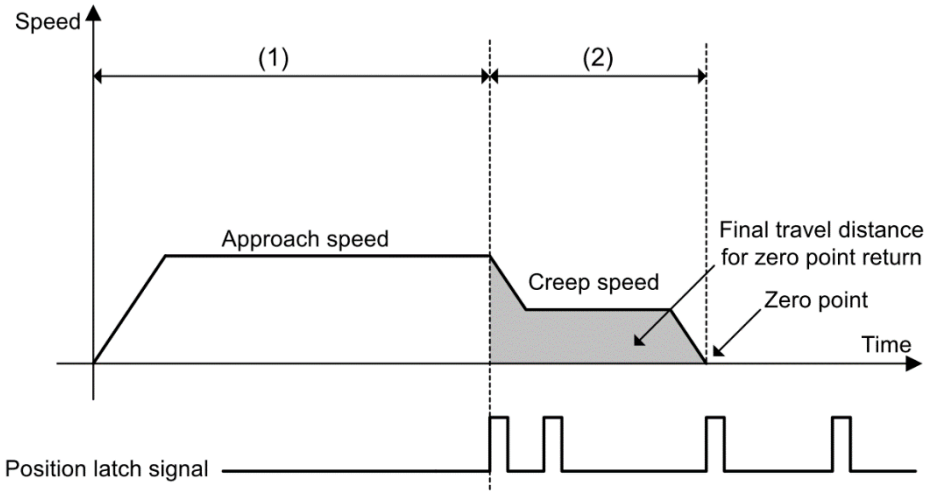

Figure 3.2.12.1 Zero point return sequence (MODE = 0)

2. MODE = 1 (Deceleration limit switch signal + latch signal)

(1) The C1 master sends ZRET command. Select latch signal[*1] with LT_SEL1 of SVCMD_CTRL and output latch request by setting LT_REQ1 = 1.

(2) The slave starts feeding in the direction specified by MODE.HOME_DIR at the speed set in the feed speed field.

(3) When deceleration limit switch is closed (DEC = 1), the rapid speed is switched to the parameter of “Approach Speed of Zero Point Return” (common parameter 84).

(4) When latch signal is input after deceleration limit switch is opened (DEC = 0), the slave executes positioning by using the parameters of “Final Travel Distance for Zero Point Return” (common parameter 86) and “Creep Speed of Zero Point Return” (common parameter 85). After positioning completes, the slave sets current position as the zero point of the coordinates.

Note: *1Only Z phase signal or EXT1 are supported by LT_SEL1 of SVCMD_CTRL now.
Set SVCMD_CTRL.LT_SEL1 to 0 or 1 to select Z phase signal as latch signal.

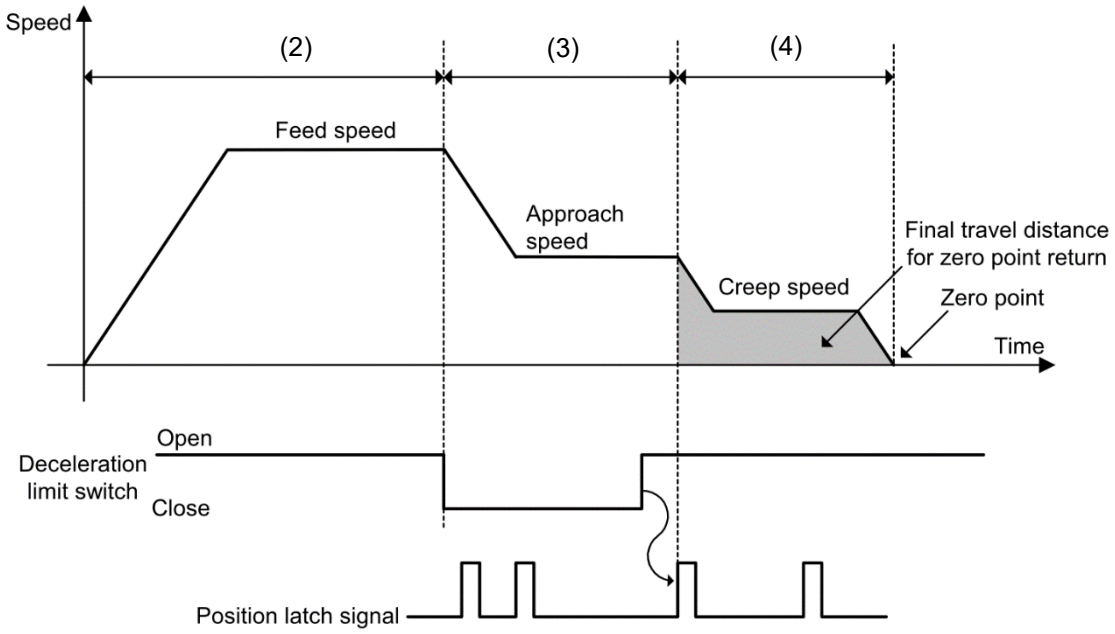

Figure 3.2.12.2 Zero point return sequence (MODE = 1)

- Supplementary information

Differing from ZRET in MECHATROLINK-II, the motion direction after latching is determined by the sign of the value set for final travel distance for zero point return.

1. If final travel distance for zero point return is a positive value
   - If latching occurs during motion in positive direction, the motor rotates in positive direction (the same direction) for positioning.
   - If latching occurs during motion in negative direction, the motor rotates in positive direction (the reverse direction) for positioning.
     (For ZRET in MECHATROLINK-II, the motor rotates in negative direction (the same direction) for positioning.)

2. If final travel distance for zero point return is a negative value
   - If latching occurs during motion in positive direction, the motor rotates in negative direction (the reverse direction) for positioning.
   - If latching occurs during motion in negative direction, the motor rotates in negative direction (the same direction) for positioning.
     (For ZRET in MECHATROLINK-II, the motor rotates in positive direction (the reverse direction) for positioning.)

3.2.13 Velocity control (VELCTRL: 3Ch)

VELCTRL command is used to send reference speed to a slave to perform speed control. The slave performs speed control without position control. To cancel speed control, set VREF = 0 or set SVCMD_CTRL.CMD_CANCEL to 1. To pause speed control, set SVCMD_CTRL.CMD_PAUSE to 1.

- Data format

Table 3.2.13.1

Byte	Command	Response
0	VELCTRL (3Ch)	VELCTRL (3Ch)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	TFF	CPRM_SEL_MON1
16 – 19	VREF	CPRM_SEL_MON2
20 – 23	ACCR	MONITOR1
24 – 27	DECR	MONITOR2
28 – 31	TLIM	MONITOR3

■ Command description

Table 3.2.13.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	(1) Confirm the command is successfully executed by checking RCMD = VELCTRL (3Ch) and CMD_STAT.CMDRDY = 1. (2) Confirm the completion of canceling the command by checking RCMD = VELCTRL (3Ch), CMD_STAT.CMDRDY = 1 and SVCMD_STAT.CMD_CANCEL_CMP = 1. (3) Confirm the completion of pausing the command by checking RCMD = VELCTRL (3Ch), CMD_STAT.CMDRDY = 1, and SVCMD_STAT.CMD_PAUSE_CMP = 1. (4) Confirm the arrival of the feedback speed at the speed reference (VREF) by checking that SVCMD_IO.V_CMP = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88. ● VREF (velocity reference): Set with a signed value. ● TFF (torque feedforward): Set with a signed value. ● ACCR (acceleration): Set with an unsigned value. ● DECR (deceleration): Set with an unsigned value. ● TLIM (torque limit): Set with an unsigned value. When torque limit is not used, set the maximum allowable value. Refer to 3.2.17 for further information of above command parameters. Refer to section 5.2 for units of above command parameters.
Alarm Description	In the following cases, an alarm will occur and the command will not be executed: ● The command is used in servo-off state. ● When VREF data is invalid, CMD_ALM = 9 hex. If ACCR or DECR is 0, current acceleration or deceleration will be applied, and no alarm will occur. In the following cases, an alarm will occur and the relevant value will be clamped at the limit value: ● When ACCR or DECR data is invalid, CMD_ALM = 1 hex. ● When TLIM data is invalid, CMD_ALM = 1 hex.

■ Supplementary information

The control mode before canceling speed control by setting SVCMD_CTRL.CMD_CANCEL to 1 retains after cancellation.

3.2.14 Torque control (TRQCTRL: 3Dh)

TRQCTRL command is used to send reference torque to a slave to perform torque control. The slave performs torque control without speed control and position control.

- Data format

Table 3.2.14.1

Byte	Command	Response
0	TRQCTRL (3Dh)	TRQCTRL (3Dh)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 15	VLIM	CPRM_SEL_MON1
16 – 19	TQREF	CPRM_SEL_MON2
20 – 23	Reserved	MONITOR1
24 – 27		MONITOR2
28 – 31		MONITOR3

- Command description

Table 3.2.14.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = TRQCTRL (3Dh) and CMD_STAT.CMDRDY = 1.
Command Parameter	● CPRM_SEL_MON1/CPRM_SEL_MON2: Monitoring data can be selected by common parameter 87/88. ● VLIM (speed limit): Set with an unsigned value. ● QREF (torque reference): Set with a signed value. Refer to 3.2.17 for further information of above command parameters. Refer to section 5.2 for units of above command parameters.
Alarm Description	In the following case, an alarm will occur and the command will not be executed: ● The command is used in servo-off state. In the following cases, an alarm will occur and the relevant value will be clamped at the limit value: ● When VLIM data is invalid, CMD_ALM = 1 hex. ● When TQREF data is invalid, CMD_ALM = 1 hex.

3.2.15 Read servo parameter (SVPRM_RD: 40h)

SVPRM_RD command is used to read servo parameter by specifying servo parameter number, data size, and reading mode. Select parameter type (common parameter or drive parameter) and reading source (RAM area) in reading mode to read the requested servo parameter. If reading is not completed normally, for example, when a servo parameter that doesn't exist has been specified, the slave detects an alarm and goes into alarm state. The values specified in NO, SIZE and MODE fields will be returned regardless of whether the reading process is completed or not.

■ Data format

Table 3.2.15.1

Byte	Command	Response
0	SVPRM_RD (40h)	SVPRM_RD (40h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 13	NO	NO
14	SIZE	SIZE
15	MODE	MODE
16 – 31	Reserved	PARAMETER

■ Command description

Table 3.2.15.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SVPRM_RD (40h) and CMD_STAT.CMDRDY = 1, and NO, SIZE and MODE in response field.
Command Parameter	● NO: Servo parameter number ● SIZE: Servo parameter data size [byte] ● MODE: Servo parameter reading mode 00h: Common parameter 01h: Not supported 10h: Drive parameter 11h: Not supported ● PARAMETER: Servo parameter data
Alarm Description	● When NO data is invalid, CMD_ALM = 9 hex. ● When SIZE data is invalid, CMD_ALM = 9 hex. ● When MODE data is invalid, CMD_ALM = 9 hex.

3.2.16 Write servo parameter (SVPRM_WR: 41h)

SVPRM_WR command is used to write servo parameters by specifying servo parameter number, data size, and writing mode. Select parameter type (common parameter or drive parameter) and writing destination (RAM area) in writing mode to write the requested servo parameter. When writing offline parameters (Parameters that take effect after power reset.), CONFIG command must be sent for device setup after parameters are written. If writing is not completed normally, for example, when a servo parameter that doesn't exist has been specified, the slave detects an alarm and goes into alarm state. The values specified in NO, SIZE, MODE and PARAMETER fields will be returned regardless of whether the writing process is completed or not.

- Data format

Table 3.2.16.1

Byte	Command	Response
0	SVPRM_WR (41h)	SVPRM_WR (41h)
1	WDT	RWDT
2 – 3	CMD_CTRL	CMD_STAT
4 – 7	SVCMD_CTRL	SVCMD_STAT
8 – 11	SVCMD_IO	SVCMD_IO
12 – 13	NO	NO
14	SIZE	SIZE
15	MODE	MODE
16 – 31	PARAMETER	PARAMETER

■ Command description

Table 3.2.16.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RCMD = SVPRM_RD (40h) and CMD_STAT.CMDRDY = 1, and NO, SIZE and MODE in response field.
Command Parameter	● NO: Servo parameter number ● SIZE: Servo parameter data size [byte] ● MODE: Servo parameter writing mode 00h: Common parameter 01h: Not supported 10h: Drive parameter 11h: Not supported ● PARAMETER: Servo parameter data
Alarm Description	● When NO data is invalid, CMD_ALM = 9 hex. ● When SIZE data is invalid, CMD_ALM = 9 hex. ● When MODE data is invalid, CMD_ALM = 9 hex.

3.2.17 Setting motion command data

Table 3.2.17.1

Name	Description	Operation when data error occurs
TSPD	Target speed For FEED: Set signed 4-byte data. For ZRET, POSING and EX_POSING: Set unsigned 4-byte data.	If a command that exceeds the maximum value is specified, ignore the command and continues the previous command. 9 is set for CMD_ALM.
VREF	Velocity reference Set signed 4-byte data.	If a command that exceeds the maximum value is specified, ignore the command and continues the previous command. 9 is set for CMD_ALM.
VFF	Velocity feedforward Set signed 4-byte data.	
TQREF	Torque reference Set signed 4-byte data.	If a command that exceeds the maximum value is specified, the value is clamped at the maximum value and 1 is set for CMD_ALM.
TFF	Torque feedforward Set signed 4-byte data.	
TLIM	Torque limit Set unsigned 4-byte data.	If a command that exceeds the torque limit value is specified, the torque is clamped at the torque limit value and 1 is set for CMD_ALM. If “FFFFFFFFH” is set for TLIM, the torque is clamped at the torque limit and CMD_ALM does not notify a warning.
VLIM	Speed limit Set unsigned 4-byte data.	If a command that exceeds the speed limit value is specified, the speed is clamped at the speed limit value and 1 is set for CMD_ALM. If “FFFFFFFFH” is set for VLIM, the speed is clamped at the speed limit and CMD_ALM does not notify a warning.
ACCR	Acceleration Set unsigned 4-byte data.	When the unit is the reference unit/s^2. If a command that exceeds the maximum value for acceleration is specified, the acceleration is clamped at the maximum value and 1 is set for CMD_ALM. If “FFFFFFFFH” is set for ACCR, operation is performed at the maximum acceleration and CMD_ALM does not notify a warning.If “0” is set for ACCR, ignore the command and continues the previous command and CMD_ALM would not notify a warning.
DECR	Deceleration Set unsigned 4-byte data.	When the unit is the reference unit/s^2. If a command that exceeds the maximum value for deceleration is specified, the deceleration is clamped at the maximum value and 1 is set for CMD_ALM. If “FFFFFFFFH” is set for DECR, operation is performed at the maximum deceleration and CMD_ALM does not notify a warning.If “0” is set for DECR, ignore the command and continues the previous command and CMD_ALM would not notify a warning.

4. Details of subcommands

4.1 Subcommands

4.1.1 Combinations of main commands and subcommands

The combinations of main commands and subcommands are listed in table 4.1.1.1 and 4.1.1.2. When an invalid combination is specified, an alarm (SUBCMD_ALM = Bh) will occur.

Table 4.1.1.1

Main Command		Subcommand					
		NOP (00h)	ALM_RD (05h)	ALM_CLR (06h)	SMON (30h)	SVPRM_RD (40h)	SVPRM_WR (41h)
Common Command	NOP (00h)	O	O	O	O	O	O
	ID_RD (03h)	O	O	O	O	O	O
	CONFIG (04h)	O	X	X	O	X	X
	ALM_RD (05h)	O	X	X	O	X	X
	ALM_CLR (06h)	O	X	X	O	X	X
	SYNC_SET (0Dh)	O	X	X	O	X	X
	CONNECT (0Eh)	O	X	X	X	X	X
	DISCONNECT (0Fh)	O	X	X	X	X	X

Table 4.1.1.2

Main Command		Subcommand					
		NOP (00h)	ALM_RD (05h)	ALM_CLR (06h)	SMON (30h)	SVPRM_RD (40h)	SVPRM_WR (41h)
Servo Command	BRK_ON (21h)	O	X	X	O	X	X
	BRK_OFF (22h)	O	X	X	O	X	X
	SENS_ON (23h)	O	X	X	O	X	X
	SENS_OFF (24h)	O	X	X	O	X	X
	SMON (30h)	O	O	O	O	O	O
	SV_ON (31h)	O	O	O	O	O	O
	SV_OFF (32h)	O	O	O	O	O	O
	INTERPOLATE (34h)	O	O	O	O	O	O
	POSING (35h)	O	O	O	O	O	O
	FEED (36h)	O	O	O	O	O	O
	EX_POSING (39h)	O	O	O	O	O	O
	ZRET (3Ah)	O	O	O	O	O	O
	VELCTRL (3Ch)	O	O	O	O	O	O

Main Command		Subcommand					
		NOP (00h)	ALM_RD (05h)	ALM_CLR (06h)	SMON (30h)	SVPRM_RD (40h)	SVPRM_WR (41h)
	TRQCTRL (3Dh)	O	O	O	O	O	O
	SVPRM_RD (40h)	O	X	X	O	X	X
	SVPRM_WR (41h)	O	X	X	O	X	X

Note:

O: This combination is supported.

X: This combination is not supported.

4.1.2 No operation (NOP: 00h)

NOP command is used for network control.

■ Data format

Table 4.1.2.1

Byte	Command	Response
32	NOP (00h)	NOP (00h)
33 – 35	SUB_CTRL	SUB_STAT
36 – 47	Reserved	Reserved

■ Command description

Table 4.1.2.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RSUBCMD = NOP (00h) and SUB_STAT.SBCMDRDY = 1.
Alarm Description	N/A

4.1.3 Read alarm or warning (ALM_RD: 05h)

ALM_RD command is used to read alarm or warning state. The alarm or warning code of current alarm or warning can be read in response field.

■ Data format

Table 4.1.3.1

Byte	Command	Response
32	ALM_RD (05h)	ALM_RD (05h)
33 – 35	SUB_CTRL	SUB_STAT
36 – 37	ALM_RD_MOD	ALM_RD_MOD
38 – 39	ALM_INDEX	ALM_INDEX
40 – 47	Reserved	ALM_DATA

Note:

(1) In ALM_DATA fields, an alarm is indicated by 2 bytes.

(2) The alarm arrangement in alarm history is in the order of occurrence. The first alarm is the latest alarm.

(3) In normal state, ALM_DATA is 0.

(4) ALM_INDEX cannot be used. Settings in ALM_INDEX fields will be ignored.

■ Command description

Table 4.1.3.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RSUBCMD = ALM_RD (05h) and SUB_STAT.SBCMDRDY = 1.
Command Parameter	● ALM_RD_MOD 0: Reads current alarm or warning state. 1: Reads alarm history. ● ALM_DATA Stores alarm codes or warning codes.
Alarm Description	● When ALM_RD_MOD data is invalid, SUBCMD_ALM = 9 hex.

4.1.4 Clear alarm or warning (ALM_CLR: 06h)

ALM_CLR command is used to clear alarm or warning state. It changes the state of the slave, but does not eliminate the cause of the alarm or warning. ALM_CLR command should be used to clear the alarm or warning state after the cause of the alarm or warning has been eliminated.

- Data format

Table 4.1.4.1

Byte	Command	Response
32	ALM_CLR (06h)	ALM_CLR (06h)
33 – 35	SUB_CTRL	SUB_STAT
36 – 37	ALM_CLR_MOD	ALM_CLR_MOD
38 – 47	Reserved	Reserved

- Command description

Table 4.1.4.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RSUBCMD = ALM_CLR (06h) and SUB_STAT.SBCMDRDY = 1.
Command Parameter	● ALM_CLR_MODE 0: Clears current alarm or warning state. 1: Clears alarm history.
Alarm Description	● When ALM_CLR_MOD data is invalid, SUBCMD_ALM = 9 hex.

4.1.5 Servo status monitor (SMON: 30h)

SMON command is used to read alarm, status, monitoring information (position, speed, torque, etc.), and the state of I/O signal.

- Data format

Table 4.1.5.1

Byte	Command	Response
32	SMON (30h)	SMON (30h)
33 – 35	SUB_CTRL	SUB_STAT
36 – 39	Reserved	MONITOR4
40 – 43		MONITOR5
44 – 47		MONITOR6

- Command description

Table 4.1.5.2

Command Classification	Common command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RSUBCMD = SMON (30h) and SUB_STAT.SUBCMDRDY = 1.
Command Parameter	● N/A
Alarm Description	● N/A

4.1.6 Read servo parameter (SVPRM_RD: 40h)

SVPRM_RD command is used to read servo parameter by specifying servo parameter number, data size, and reading mode. Select parameter type (common parameter or drive parameter) and reading source (RAM area) in reading mode.

- Data format

Table 4.1.6.1

Byte	Command	Response
32	SVPRM_RD (40h)	SVPRM_RD (40h)
33 – 35	SUB_CTRL	SUB_STAT
36 – 37	NO	NO
38	SIZE	SIZE
39	MODE	MODE
40 – 47	Reserved	PARAMETER

- Command description

Table 4.1.6.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RSUBCMD = SVPRM_RD (40h), SUB_STAT.SUBCMDRDY = 1, and NO, SIZE and MODE in response field.
Command Parameter	● NO: Servo parameter number ● SIZE: Servo parameter data size [byte] ● MODE: Servo parameter reading mode 00h: Common parameter 01h: Not supported 10h: Drive parameter 11h: Not supported ● PARAMETER: Servo parameter data
Alarm Description	● When NO data is invalid, SUBCMD_ALM = 9 hex. ● When SIZE data is invalid, SUBCMD _ALM = 9 hex. ● When MODE data is invalid, SUBCMD _ALM = 9 hex.

4.1.7 Write servo parameter (SVPRM_WR: 41h)

SVPRM_WR command is used to write servo parameter by specifying servo parameter number, data size, and writing mode. Select parameter type (common parameter or drive parameter) and writing destination (RAM area) in writing mode to write the requested servo parameter.

■ Data format

Table 4.1.7.1

Byte	Command	Response
32	SVPRM_WR (41h)	SVPRM_WR (41h)
33 – 35	SUB_CTRL	SUB_STAT
36 – 37	NO	NO
38	SIZE	SIZE
39	MODE	MODE
40 – 47	PARAMETER	PARAMETER

■ Command description

Table 4.1.7.2

Command Classification	Standard servo command
	Asynchronous command
Confirmation Method of Command Completion	Confirm the command is successfully executed by checking RSUBCMD = SVPRM_WR (41h) and SUB_STAT.SUBCMDRDY = 1, and NO, SIZE, MODE and PARAMETER in response field.
Command Parameter	● NO: Servo parameter number ● SIZE: Servo parameter data size [byte] ● MODE: Servo parameter writing mode 00h: Common parameter 01h: Not supported 10h: Drive parameter 11h: Not supported ● PARAMETER: Servo parameter data
Alarm Description	● When NO data is invalid, SUBCMD_ALM = 9 hex. ● When SIZE data is invalid, SUBCMD _ALM = 9 hex. ● When MODE data is invalid, SUBCMD _ALM = 9 hex.

5. Standard servo profile command data

5.1 Standard servo profile command data

This chapter describes the data used with MECHATROLINK-III standard servo profile commands.

5.2 System unit

System unit can be set by common parameters.

5.2.1 Speed

Table 5.2.1.1

Unit	Description
Reference unit/s	[reference unit/s] The unit is fixed and cannot be user-defined.

5.2.2 Position

Table 5.2.2.1

Unit	Description
Reference unit	[reference unit] The unit is fixed and cannot be user-defined.

5.2.3 Acceleration

Table 5.2.3.1

Unit	Description
Reference unit/s^2	[reference unit/s^2] The unit is fixed and cannot be user-defined.

5.2.4 Torque

Table 5.2.4.1

Unit	Description
% of rated torque	[%] The unit is fixed and cannot be user-defined.

5.3 Monitoring information

To read the monitoring information from the slave, the master can set the selection code of the monitoring data in SEL_MON1 to 3 in servo command control field (SVCMD_CTRL) and SEL_MON4 to 6 in subcommand control field (SUB_CTRL). The specified selection code and monitoring data will be returned in response field.

The monitoring selections are listed in table 5.3.1.

Table 5.3.1

Selection Code (Hex.)	Monitoring Name	Contents	Remark
0	APOS	Feedback position	-
1	CPOS	Command position	-
2	PERR	Position error	-
3	LPOS1	Latched position 1	-
4	LPOS2	Latched position 2	-
5	FSPD	Feedback speed	-
6	CSPD	Reference speed	-
7	TRQ	Torque (force) reference	-
8	ALARM	Detailed information of current alarm	-
9	MPOS	Command position	Internal command position of control loop.
C	CMN1	Common monitoring 1	Selects monitoring data specified by common parameter 89.
D	CMN2	Common monitoring 2	Selects monitoring data specified by common parameter 8A.
E	OMN1	Optional monitoring 1	Not supported.
F	OMN2	Optional monitoring 2	Not supported.

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6. Operation sequence

6.1 Operation when managing parameters by controller

When common parameters and device-specific parameters are managed by a controller, the parameters are transmitted to the servo drive from the controller when power is turned on. In this operation, it is not necessary to change the servo drive setting values when the servo drive is changed, since parameters are stored in the controller. The operation sequence is shown in table 6.1.1.

Table 6.1.1

Step	Operation	Command to Send
1	Turns on the control and main power supplies.	NOP/DISCONNECT
2	Establishes connection. Start the counting of WDT.	CONNECT
3	Reads device type and other information.	ID_RD/SVPRM_RD
4	Sets the necessary parameters in RAM.	SVPRM_WR
5	Enables the set parameters.	CONFIG
6	Turns on the encoder power and acquires position data.	SENS_ON
7	Enables the motor.	SV_ON
8	Starts operation.	POSING, INTERPOLATE, etc.
9	Disables the motor.	SV_OFF
10	Releases connection.	DISCONNECT
11	Turns off the control and main power supplies.	-

Note: Send NOP command when connection is released correctly. If it is not released correctly, send DISCONNECT command for two or more communication cycles before reconnection. After that, send CONNECT command.

7. Parameters

7.1 Common parameters

The common parameters listed below allow the controller to modify servo drive settings via MECHATROLINK communication.

7.1.1 Parameters related to device information

Parameter No. (Hex.)	Size (bytes)	Name	Setting Range	Unit	Default	Attribute	Enabling Time
1	4	Encoder Type	0 to 1	-	-	Read	-
	00H: Absolute encoder 01H: Incremental encoder						
2	4	Motor Type	0 to 1	-	-	Read	-
	00H: Rotary 01H: Linear						
3	4	Semi-closed/ Fully-closed Type	0 to 1	-	-	Read	-
	00H: Semi-closed 01H: Fully-closed						
4	4	Rated Speed	0 to 2147483647	Rotary: rpm Linear: mm/s	-	Read	-
5	4	Maximum Output Speed	0 to 2147483647	Rotary: rpm Linear: mm/s	-	Read	-
6	4	Speed Multiplier	0	-	0	Read	-
7	4	Rated Torque	0 to 2147483647	N•m	-	Read	-
8	4	Maximum Output Torque	0 to 2147483647	N•m	-	Read	-
9	4	Torque Multiplier	-1	-	-1	Read	-
A	4	Resolution (Rotary)	0 to 1073741824	-	-	Read	-
B	4	Linear Scale Pitch	0 to 2147483647	1 nm	-	Read	-
C	4	Pulse Per Scale Pitch	0 to FFFFFFFF	pulse/pitch	-	Read	-

7.1.2 Parameters related to machine specification

Parameter No. (Hex.)	Size (bytes)	Name	Setting Range	Unit	Default	Attribute	Enabling Time
21	4	Electronic Gear Ratio (Numerator)	1 to 1073741824	-	32	Read/ Write	□
22	4	Electronic Gear Ratio (Denominator)	1 to 1073741824	-	1	Read/ Write	□

Note:

Versions below 2.8.9 (included) do not support settings other than electronic gear ratio of 1:1.

Enabling time:

◎: Immediately (online common parameter)

△: Enabled after CONFIG command is received

□: Enabled after power off and on.

7.1.3 Parameters related to system unit

Parameter No. (Hex.)	Size (bytes)	Name	Setting Range	Unit	Default	Attribute	Enabling Time
41	4	Speed Unit	0	-	00h	Read/Write	△
	00H	Reference unit/sec (default)					
42	4	Speed Base Unit	0	-	0	Read/Write	△
43	4	Position Unit	0	-	00h	Read/Write	△
	00H	Reference unit (default)					
44	4	Position Base Unit	0	-	0	Read/Write	△
45	4	Acceleration Unit	0	-	00h	Read/Write	△
	00H	Reference unit/sec^2 (default)					
46	4	Acceleration Base Unit	0	-	0	Read/Write	△
47	4	Torque Unit	1	-	01h	Read/Write	△
	00H	Percentage (%) of rated torque (default)					

<table>
<tr><td>48</td><td>4</td><td>Torque Base Unit</td><td>-5 to 0</td><td>-</td><td>0</td><td>Read/Write</td><td>△</td></tr>
<tr><td rowspan="2">49</td><td>4</td><td>Supported Unit</td><td>-</td><td>-</td><td>2010101h</td><td>Read</td><td>-</td></tr>
<tr><td colspan="7">
<table>
<tr><th colspan="2">Speed Units</th></tr>
<tr><td>Bit 0</td><td>Reference unit/sec</td></tr>
<tr><td>Bit 1</td><td>Reference unit/min</td></tr>
<tr><td>Bit 2</td><td>Percentage (%) of rated speed</td></tr>
<tr><td>Bit 3</td><td>min^{-1} (rpm)</td></tr>
<tr><td>Bit 4</td><td>Maximum motor speed / 4000000hex</td></tr>
<tr><td>Bit 5 - 7</td><td>Reserved</td></tr>
<tr><th colspan="2">Position Units</th></tr>
<tr><td>Bit 8</td><td>Reference unit</td></tr>
<tr><td>Bit 9 - 15</td><td>Reserved</td></tr>
<tr><th colspan="2">Acceleration Units</th></tr>
<tr><td>Bit 16</td><td>Reference unit/sec^2</td></tr>
<tr><td>Bit 17</td><td>ms</td></tr>
<tr><td>Bit 18 - 23</td><td>Reserved</td></tr>
<tr><th colspan="2">Torque Units</th></tr>
<tr><td>Bit 24</td><td>N•m</td></tr>
<tr><td>Bit 25</td><td>Percentage (%) of rated torque</td></tr>
<tr><td>Bit 26</td><td>Maximum torque / 40000000hex</td></tr>
<tr><td>Bit 27 - 31</td><td>Reserved</td></tr>
</table>
Bit setting: (1: Enable, 0: Disable)
</td></tr>
</table>

Note:

Enabling time:

◎: Immediately (online common parameter)

△: Enabled after CONFIG command is received

□: Enabled after power off and on.

7.1.4 Parameters for adjustment

Parameter No. (Hex.)	Size (bytes)	Name	Setting Range	Unit	Default	Attribute	Enabling Time
61	4	Speed Loop Gain	10 to 20000	0.001 Hz	40000	Read/Write	◎
62	4	Speed Loop Integral Time Constant	15 to 51200	0.001 ms	20000	Read/Write	◎
63	4	Position Loop Gain	10 to 40000	0.001/s	40000	Read/Write	◎
64	4	Feed Forward Compensation	0 to 100	1%	0	Read/Write	◎
65	4	Position Loop Integral Time Constant	1 to 50000	0.001 ms	100	Read/Write	◎
66	4	In-position Range	0 to 1073741824	Reference unit	7	Read/Write	◎
67	4	Near-position Range	1 to 1073741824	Reference unit	1073741824	Read/Write	◎

Note:

Enabling time:

◎: Immediately (online common parameter)

△: Enabled after CONFIG command is received

□: Enabled after power off and on.

7.1.5 Parameters related to command

Parameter No. (Hex.)	Size (bytes)	Name	Setting Range	Unit	Default	Attribute	Enabling Time
83	4	Final Travel Distance for External Input Positioning (EX_POSING)	-2147483648 to 2147483647	Reference unit	0	Read/Write	◎
84	4	Approach Speed of Zero Point Return	Rotary: 0 to 3000 Linear: 0 to 1000	Rotary: $\times 10^{-3}$ min^{-1} Linear: $\times 10^{-3}$ mm/s	Rotary: 6 rpm Linear: 3 mm/s	Read/Write	◎
85	4	Creep Speed of Zero Point Return	Rotary: 0 to 3000 Linear: 0 to 1000	Rotary: $\times 10^{-3}$ min^{-1} Linear: $\times 10^{-3}$ mm/s	Rotary: 20 rpm Linear: 10 mm/s	Read/Write	◎
86	4	Final Travel Distance for Zero Point Return	1073741824 to 1073741824	Reference unit	0	Read/Write	◎
87	4	Monitoring Selection 1	0 to F	-	1	Read/Write	◎

0 hex	APOS
1 hex	CPOS
2 hex	PEER
3 hex	LPOS1
4 hex	LPOS2
5 hex	FSPD
6 hex	CSPD
7 hex	TRQ
8 hex	ALARM
9 hex	MPOS
A hex	Reserved
B hex	Reserved
C hex	CMN1 (Common monitoring 1)
D hex	CMN2 (Common monitoring 2)
E hex	Reserved
F hex	Reserved

88	4	Monitoring Selection 2	0 to F	-	0	Read/Write	◎

<table>
<tr><th>Parameter No. (Hex.)</th><th>Size (bytes)</th><th>Name</th><th>Setting Range</th><th>Unit</th><th>Default</th><th>Attribute</th><th>Enabling Time</th></tr>
<tr><td></td><td colspan="7">
<table>
<tr><td>0 hex to F hex</td><td>The settings are the same as the settings of parameter 87.</td></tr>
</table>
</td></tr>
<tr><td rowspan="2">89</td><td>4</td><td>Monitoring Selection for SEL_MON1</td><td>0 to 9</td><td>-</td><td>0</td><td>Read/Write</td><td>◎</td></tr>
<tr><td colspan="7">
<table>
<tr><td>0 hex</td><td>TPOS (target position in command coordinate system)</td></tr>
<tr><td>1 hex</td><td>IPOS (reference position in command coordinate system)</td></tr>
<tr><td>2 hex</td><td>POS_OFST (offset value set in POS_SET)</td></tr>
<tr><td>3 hex</td><td>TSPD (target speed)</td></tr>
<tr><td>4 hex</td><td>SPD_LIM (speed limit value)</td></tr>
<tr><td>5 hex</td><td>TRQ_LIM (torque limit value)</td></tr>
<tr><td>6 hex</td><td>SV_STAT (actual operating state of the slave)
● Byte 1: Current communication phase
00h: Phase 0
01h: Phase 1
02h: Phase 2
03h: Phase 3
● Byte 2: Current control mode
00h: Position mode
01h: Velocity mode
02h: Torque mode
● Byte 3: Reserved
● Byte 4: Expanded signal monitor
<table>
<tr><td>Bit 0</td><td>LT_RDY1</td></tr>
<tr><td>Bit 1</td><td>LT_RDY2</td></tr>
<tr><td>Bit 2 - 3</td><td>LT_SEL1R</td></tr>
<tr><td>Bit 4 - 5</td><td>LT_SEL2R</td></tr>
<tr><td>Bit 6 - 7</td><td>Reserved</td></tr>
</table>
</td></tr>
<tr><td>7 hex</td><td>Reserved</td></tr>
<tr><td>8 hex</td><td>Reserved</td></tr>
<tr><td>9 hex</td><td>Reserved</td></tr>
</table>
</td></tr>
<tr><td rowspan="2">8A</td><td>4</td><td>Monitoring Selection for SEL_MON2</td><td>0 to 9</td><td>-</td><td>0</td><td>Read/Write</td><td>◎</td></tr>
<tr><td colspan="7">
<table>
<tr><td>0 hex to 9 hex</td><td>The settings are the same as the settings of parameter 89.</td></tr>
</table>
</td></tr>
<tr><td>8B</td><td>4</td><td>Zero Point Detection Range</td><td>0 to 2147483647</td><td>Reference unit</td><td>100</td><td>Read/Write</td><td>◎</td></tr>
<tr><td rowspan="2">8C</td><td>4</td><td>Forward Torque Limit</td><td>0 to 800</td><td>1%</td><td>100</td><td>Read/Write</td><td>◎</td></tr>
<tr><td colspan="7">The unit is 1% of the motor continuous current.</td></tr>
<tr><td rowspan="2">8D</td><td>4</td><td>Reverse Torque Limit</td><td>0 to 800</td><td>1%</td><td>100</td><td>Read/Write</td><td>◎</td></tr>
<tr><td colspan="7">The unit is 1% of the motor continuous current.</td></tr>
</table>

Parameter No. (Hex.)	Size (bytes)	Name	Setting Range	Unit	Default	Attribute	Enabling Time
8E	4	Zero Speed Detection Range	1 to 10000	Rotary: $\times 10^{-3}$ min^{-1} Linear: $\times 10^{-3}$ mm/s	Rotary: 20 rpm Linear: 20 mm/s	Read/Write	◎
8F	4	Speed Match Signal Detection Range	0 to 100	Rotary: $\times 10^{-3}$ min^{-1} Linear: $\times 10^{-3}$ mm/s	Rotary: 10 rpm Linear: 10 mm/s	Read/Write	◎
90	4	Supported Bits of SVCMD_CTRL	-	-	0FFF3F0Fh	Read	-

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

Bit setting: (1: Enable, 0: Disable)

91	4	Supported Bits of SVCMD_STAT	-	-	0FFF3F03h	Read	-

Bit 7	Bit 6	Bit 5	Bit 4	Bit 3	Bit 2	Bit 1	Bit 0
Reserved		ACCFIL		Reserved		CMD_ CANCEL_ CMP	CMD_ PAUSE_ CMP
Bit 15	Bit 14	Bit 13	Bit 12	Bit 11	Bit 10	Bit 9	Bit 8
Reserved		SV_ON	M_RDY	PON	POS_RDY	LT_CMP2	LT_CMP1
Bit 23	Bit 22	Bit 21	Bit 20	Bit 19	Bit 18	Bit 17	Bit 16
SEL_MON2				SEL_MON1			
Bit 31	Bit 30	Bit 29	Bit 28	Bit 27	Bit 26	Bit 25	Bit 24
Reserved				SEL_MON3			

Bit setting: (1: Enable, 0: Disable)

<table>
<tr><th>Parameter No. (Hex.)</th><th>Size (bytes)</th><th>Name</th><th>Setting Range</th><th>Unit</th><th>Default</th><th>Attribute</th><th>Enabling Time</th></tr>
<tr><td rowspan="2">92</td><td>4</td><td>Supported Bits for I/O Signal (Output)</td><td>-</td><td>-</td><td>00F000C0h</td><td>Read</td><td>-</td></tr>
<tr><td colspan="7">
<table>
<tr><td>Bit 7</td><td>Bit 6</td><td>Bit 5</td><td>Bit 4</td><td>Bit 3</td><td>Bit 2</td><td>Bit 1</td><td>Bit 0</td></tr>
<tr><td>N_CL</td><td>P_CL</td><td>P_PPI</td><td>V_PPI</td><td colspan="4">Reserved</td></tr>
<tr><td>Bit 15</td><td>Bit 14</td><td>Bit 13</td><td>Bit 12</td><td>Bit 11</td><td>Bit 10</td><td>Bit 9</td><td>Bit 8</td></tr>
<tr><td colspan="4">Reserved</td><td colspan="4">G_SEL</td></tr>
<tr><td>Bit 23</td><td>Bit 22</td><td>Bit 21</td><td>Bit 20</td><td>Bit 19</td><td>Bit 18</td><td>Bit 17</td><td>Bit 16</td></tr>
<tr><td colspan="4">Output 1 to Output 4</td><td colspan="4">Reserved</td></tr>
<tr><td>Bit 31</td><td>Bit 30</td><td>Bit 29</td><td>Bit 28</td><td>Bit 27</td><td>Bit 26</td><td>Bit 25</td><td>Bit 24</td></tr>
<tr><td colspan="8">Reserved</td></tr>
</table>
Bit setting: (1: Enable, 0: Disable)
</td></tr>
<tr><td rowspan="2">93</td><td>4</td><td>Supported Bits for I/O Signal (Input)</td><td>-</td><td>-</td><td>FF0FF20Eh</td><td>Read</td><td>-</td></tr>
<tr><td colspan="7">
<table>
<tr><td>Bit 7</td><td>Bit 6</td><td>Bit 5</td><td>Bit 4</td><td>Bit 3</td><td>Bit 2</td><td>Bit 1</td><td>Bit 0</td></tr>
<tr><td>ESTP</td><td>EXT3*1</td><td>EXT2*1</td><td>EXT1</td><td>N-OT</td><td>P-OT</td><td>DEC</td><td>Reserved</td></tr>
<tr><td>Bit 15</td><td>Bit 14</td><td>Bit 13</td><td>Bit 12</td><td>Bit 11</td><td>Bit 10</td><td>Bit 9</td><td>Bit 8</td></tr>
<tr><td>ZPOINT</td><td>PSET</td><td>NEAR</td><td>DEN</td><td>N-SOT</td><td>P-SOT</td><td>BRK_ON</td><td>Reserved</td></tr>
<tr><td>Bit 23</td><td>Bit 22</td><td>Bit 21</td><td>Bit 20</td><td>Bit 19</td><td>Bit 18</td><td>Bit 17</td><td>Bit 16</td></tr>
<tr><td colspan="4">Reserved</td><td>ZSPD</td><td>V_CMP</td><td>V_LIM</td><td>T_LIM</td></tr>
<tr><td>Bit 31</td><td>Bit 30</td><td>Bit 29</td><td>Bit 28</td><td>Bit 27</td><td>Bit 26</td><td>Bit 25</td><td>Bit 24</td></tr>
<tr><td colspan="8">Input 1 to Input 8</td></tr>
</table>
Bit setting: (1: Enable, 0: Disable)
</td></tr>
</table>

Note:

*1 Not supported.

Enabling time:

◎: Immediately (online common parameter)

△: Enabled after CONFIG command is received

□: Enabled after power off and on.

7.1.6 Common Parameters and Corresponding Drive Parameters

Table 7.1.6.1

Category	Common Parameter (Hex)	Name	Corresponfing Drive Parameter
Device information	1	Encoder Type	-
	2	Motor Type	-
	3	Semi-closed/Fully-closed Type	-
	4	Rated Speed	-
	5	Maximum Output Speed	-
	6	Speed Multiplier	-
	7	Rated Torque	-
	8	Maximum Output Torque	-
	9	Torque Multiplier	-
	A	Resolution (Rotary)	-
	B	Linear Scale Pitch	-
	C	Pulse Per Scale Pitch	-
Machine specification	21	Electronic Gear Ratio (Numerator)	Pt20E
	22	Electronic Gear Ratio (Denominator)	Pt210
System unit	41	Speed Unit	-
	42	Speed Base Unit	-
	43	Position Unit	-
	44	Position Base Unit	-
	45	Acceleration Unit	-
	46	Acceleration Base Unit	-
	47	Torque Unit	-
	48	Torque Base Unit	-
	49	Supported Unit	-
Adjustment	61	Speed Loop Gain	Pt100
	62	Speed Loop Integral Time Constant	Pt101
	63	Position Loop Gain	Pt102
	64	Feed Forward Compensation	Pt109
	65	Position Loop Integral Time Constant	Pt11F
	66	In-position Range	Pt522
	67	Near-position Range	Pt524
	83	Final Travel Distance for External Input Positioning	-
	84	Approach Speed of Zero Point Return	Rotary: Pt702 Linear: Pt706
	85	Creep Speed of Zero Point Return	Rotary: Pt701 Linear: Pt705

Category	Common Parameter (Hex)	Name	Corresponfing Drive Parameter
Command related	86	Final Travel Distance for Zero Point Return	Pt704
	87	Monitoring Selection 1	-
	88	Monitoring Selection 2	-
	89	Monitoring Selection for SEL_MON1	-
	8A	Monitoring Selection for SEL_MON2	-
	8B	Zero Point Detection Range	-
	8C	Forward Torque Limit	Pt404
	8D	Reverse Torque Limit	Pt405
	8E	Zero Speed Detection Range	Rotary: Pt502 Linear: Pt581
	8F	Speed Match Signal Detection Range	Rotary: Pt503 Linear: Pt582
	90	Supported Bits of SVCMD_CTRL	-
	91	Supported Bits of SVCMD_STAT	-
	92	Supported Bits for I/O Signal (Output)	-
	93	Supported Bits for I/O Signal (Input)	-

Note:

Enabling time:

◎: Immediately (online common parameter)

△: Enabled after CONFIG command is received

□: Enabled after power off and on.

7.2 Drive parameters (Pt parameters)

Each drive Pt parameter is accessible by a specific parameter number (NO) of SVPRM_RD and SVPRM_WR commands. NO is defined by the following rule.

(NO of Pt parameter) = (Pt No.) + 2000h

For example, NO of parameter “Pt100” is (2100h) = (100) + 2000h, and its size is 2 bytes.
For the details of each Pt parameter (such as size, unit and setting range), refer to chapter 15 **Parameters** in “E1 Series Servo Drive User Manual” and “E2 Series Servo Drive User Manual.”

7.3 Manufacturer specific profile area

7.3.1 Device parameters

<table>
<tr><th>Parameter number (Hex.)</th><th>Name</th><th>Properties</th><th>Parameter size (bytes)</th><th>Op mode</th><th>Valid value</th><th>Unit</th></tr>
<tr><td rowspan="2">3000h</td><td>Motor type</td><td>read</td><td>2</td><td>All</td><td>0 ~ 2</td><td>-</td></tr>
<tr><td colspan="6">Motor type used with the drive
0: Linear motor (LM)
1: Direct drive motor / Torque motor (DM / TM)
2: AC servo motor (AC)</td></tr>
<tr><td rowspan="2">3001h</td><td>Inner encoder resolution</td><td>read</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Encoder resolution for internal loop</td></tr>
<tr><td>3002h
|
3055h</td><td colspan="6">The objects in this section are not supported. Do not operate them.</td></tr>
<tr><td rowspan="2">3056h</td><td>Software state[12]</td><td>read</td><td>2</td><td>All</td><td>0 ~ 0xFFFF</td><td>-</td></tr>
<tr><td colspan="6">Software state table. The state corresponding to each bit is described as follows.
<table>
<tr><th>Bit</th><th>State Name</th><th>State Definition</th></tr>
<tr><td>0</td><td>Reserved</td><td>N/A</td></tr>
<tr><td>1</td><td>Reserved</td><td>N/A</td></tr>
<tr><td>2</td><td>Reserved</td><td>N/A</td></tr>
<tr><td>3</td><td>Homing state</td><td>0: Homing not executed
1: Homing in process</td></tr>
<tr><td>4</td><td>Position trigger function state</td><td>0: Position trigger function not enabled
1: Position trigger function enabled</td></tr>
<tr><td>5</td><td>Communication state of gantry system</td><td>0: No comminication for gantry system
1: Normal comminication for gantry system</td></tr>
<tr><td>6</td><td>Motor power state of gantry yaw axis</td><td>0: Motor without power supply for gantry yaw axis
1: Motor with power supply for gantry yaw axis</td></tr>
<tr><td>7</td><td>Alarm state of gantry yaw axis</td><td>0: No alarm in gantry yaw axis
1: An alarm occurs in in gantry yaw axis</td></tr>
<tr><td>8</td><td>Activated state of gantry</td><td>0: Gantry not activated
1: Gantry activated</td></tr>
<tr><td>9</td><td>Homing state of gantry yaw axis</td><td>0: Gantry yaw axis homing not completed
1: Gantry yaw axis homing completed</td></tr>
<tr><td>10</td><td>Near home state of gantry yaw axis</td><td>0: Gantry yaw axis not in the range of near home
1: Gantry yaw axis in the range of near home</td></tr>
<tr><td>11</td><td>Regulation state of gantry yaw axis</td><td>0: Gantry yaw axis regulation not completed
1: Gantry yaw axis regulation completed</td></tr>
<tr><td>12</td><td>In-position state of gantry yaw axis</td><td>0: Gantry yaw axis not in-position
1: Gantry yaw axis in-position</td></tr>
<tr><td>13</td><td>Ready state of gantry yaw axis</td><td>0: Drive not ready for gantry yaw axis
1: Drive ready and STO not triggered for gantry yaw axis</td></tr>
<tr><td>14</td><td>Reserved</td><td>N/A</td></tr>
<tr><td>15</td><td>Reserved</td><td>N/A</td></tr>
</table></td></tr>
<tr><td rowspan="2">3057h</td><td>Apply mode of gantry system</td><td>read/write</td><td>2</td><td>All</td><td>1, 2, 11</td><td>-</td></tr>
<tr><td colspan="6">Application mode setting of gantry. The applicable modes are as follows.
Please refer to “E Series Servo Drive Gantry Control System User Manual” for detailed settings.</td></tr>
</table>

<table>
<tr><th>Parameter number (Hex.)</th><th>Name</th><th>Properties</th><th>Parameter size (bytes)</th><th>Op mode</th><th>Valid value</th><th>Unit</th></tr>
<tr><td></td><td colspan="6">1: Ativate gantry
2: Deactivate gantry
11: Execute yaw axis regulation</td></tr>
<tr><td rowspan="2">3058h</td><td>Yaw target position</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>inc</td></tr>
<tr><td colspan="6">Target position for gantry yaw axis</td></tr>
<tr><td rowspan="2">3059h</td><td>Yaw feedback position</td><td>read</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>inc</td></tr>
<tr><td colspan="6">Feedback position for gantry yaw axis</td></tr>
<tr><td rowspan="2">305Ah</td><td>Master feedback position</td><td>read</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>inc</td></tr>
<tr><td colspan="6">Feedback position for gantry master axis</td></tr>
<tr><td rowspan="2">305Bh</td><td>Slave feedback position</td><td>read</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>inc</td></tr>
<tr><td colspan="6">Feedback position for gantry slave axis</td></tr>
<tr><td rowspan="2">3060h</td><td>Use LT_REQ enable specific function</td><td>read/write</td><td>2</td><td>All</td><td>0 ~ 1</td><td>-</td></tr>
<tr><td colspan="6">Enable specific function with LT_REQ1 or LT_REQ2.

<table>
<tr><th>Bit</th><th>Function</th><th>Definition</th></tr>
<tr><td>0</td><td>Error map</td><td>0: Do not use LT_REQ to enable error map.
1: Use LT_REQ to enable error map.</td></tr>
<tr><td>1</td><td>Position trigger function</td><td>(Before using this function, set Pt00E = t.1□□□.)
0: Do not use LT_REQ to enable position trigger function.
1: Use LT_REQ to enable position trigger function.</td></tr>
<tr><td>2~15</td><td>Reserved</td><td>N/A</td></tr>
</table>

For the details of error map and position trigger function, please refer to each servo drive user manual. LT_REQ corresponds to descriptions regarding touch probe function.</td></tr>
<tr><td rowspan="2">3061h</td><td>Enable position trigger function</td><td>read/write</td><td>2</td><td>All</td><td>0 ~ 1</td><td>-</td></tr>
<tr><td colspan="6">Enable position trigger function. Please refer to section 8.13 in “E1 Series Servo Drive User Manual” and “E2 Series Servo Drive User Manual” for position trigger function.
0: Disable position trigger function
1: Enable position trigger function</td></tr>
<tr><td rowspan="2">3062h</td><td>Over travel stop mode selection</td><td>read/write</td><td>2</td><td>All</td><td>0 ~ 1</td><td>-</td></tr>
<tr><td colspan="6">Reserved.</td></tr>
<tr><td rowspan="2">3069h</td><td>Position trigger array value</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Position trigger array’s value</td></tr>
<tr><td rowspan="2">306Ah</td><td>Position trigger array index</td><td>read/write</td><td>2</td><td>All</td><td>0 ~ 255</td><td>-</td></tr>
<tr><td colspan="6">Position trigger array’s index value</td></tr>
<tr><td rowspan="2">306Bh</td><td>Position trigger array control object</td><td>read/write</td><td>2</td><td>All</td><td>0 ~ 65535</td><td>-</td></tr>
<tr><td colspan="6">Writing procedure of operating position trigger array
Set 0x0001~0x0080 to select the writing procedure. The writing result will be displayed by 0x1000~0x2000.

<table>
<tr><th>Value</th><th>Definition</th><th>Category</th></tr>
<tr><td>0x0001</td><td>Write the value of object 3069h to the “position array” corresponding to object 306Ah.
(At this time, object 306Ah cannot exceed 255.)</td><td rowspan="2">Command</td></tr>
<tr><td>0x0008</td><td>Set all the values in the “position array” to 0.</td></tr>
</table></td></tr>
</table>

<table>
<tr><th>Parameter number (Hex.)</th><th>Name</th><th>Properties</th><th>Parameter size (bytes)</th><th>Op mode</th><th>Valid value</th><th>Unit</th></tr>
<tr><td></td><td colspan="6">
<table>
<tr><td>0x0010</td><td>Write the value of object 3069h to the “status array” corresponding to object 306Ah.
(At this time, object 306Ah cannot exceed 7.)</td><td rowspan="2"></td></tr>
<tr><td>0x0080</td><td>Set all the values in the “status array” to 0.</td></tr>
<tr><td>0x1000</td><td>The writing succeeds.</td><td rowspan="2">Result</td></tr>
<tr><td>0x2000</td><td>The writing fails. Refer to object 306Ch for the reason.</td></tr>
</table>
</td></tr>
<tr><td rowspan="2">306Ch</td><td>Position trigger function error code</td><td>read</td><td>2</td><td>All</td><td>0 ~ 65535</td><td>-</td></tr>
<tr><td colspan="6">The reasons that the writing of position trigger array or the enabling of position trigger function fails.
<table>
<tr><th>Bit</th><th>Definition</th></tr>
<tr><td colspan="2">※ The reasons that the writing of position trigger array fails</td></tr>
<tr><td>0</td><td>Fixed interval PT mode does not support the writing of position trigger array.</td></tr>
<tr><td>1</td><td>Wrong index value of array (object 306Ah)</td></tr>
<tr><td>2</td><td>Undefined command (object 306Bh)</td></tr>
<tr><td>3~7</td><td>Reserved</td></tr>
<tr><td colspan="2">※ The reasons that the enabling of position trigger function fails</td></tr>
<tr><td>8</td><td>The encoder does not support position trigger function.</td></tr>
<tr><td>9</td><td>Homing is not executed.</td></tr>
<tr><td>10</td><td>The parameter setting of Pt00E or Pt230~Pt232 is wrong.</td></tr>
<tr><td>11</td><td>The current motor position exceeds the end position set by Pt232 (fixed interval PT mode Pt00E = t.□□1□).</td></tr>
<tr><td>12~15</td><td>Reserved</td></tr>
</table>
</td></tr>
<tr><td rowspan="2">306Dh</td><td>Position trigger function status</td><td>read</td><td>2</td><td>All</td><td>0 ~ 32767</td><td>-</td></tr>
<tr><td colspan="6">Status of position trigger function.
<table>
<tr><th>Value</th><th>Definition</th></tr>
<tr><td>0</td><td>Position trigger function is not enabled.</td></tr>
<tr><td>3</td><td>Fixed interval position trigger function is executing (trigger direction: position decreasing).</td></tr>
<tr><td>4</td><td>Fixed interval position trigger function is executing (trigger direction: position increasing).</td></tr>
<tr><td>13</td><td>Random interval position trigger function is executing (trigger direction: index value decreasing).</td></tr>
<tr><td>14</td><td>Random interval position trigger function is executing (trigger direction: index value increasing).</td></tr>
<tr><td>20</td><td>Wait until it goes back to the first set trigger position (if repeat mode is enabled Pt012 = t.□□□1).</td></tr>
<tr><td>99</td><td>Position trigger function is invalid (Pt00E = t.□□□0).</td></tr>
</table>
</td></tr>
<tr><td rowspan="2">306Eh</td><td>Expected total number of position trigger</td><td>read</td><td>2</td><td>All</td><td>0 ~ 65535</td><td>-</td></tr>
<tr><td colspan="6">Expected total number of position trigger</td></tr>
<tr><td rowspan="2">306Fh</td><td>Triggered number of position trigger</td><td>read</td><td>2</td><td>All</td><td>0 ~ 65535</td><td>-</td></tr>
<tr><td colspan="6">Triggered number of position trigger</td></tr>
<tr><td rowspan="2">3070h</td><td>Remaining number of position trigger</td><td>read</td><td>2</td><td>All</td><td>0 ~ 65535</td><td>-</td></tr>
<tr><td colspan="6">Remaining number of position trigger</td></tr>
</table>

<table>
<tr><th>Parameter number (Hex.)</th><th>Name</th><th>Properties</th><th>Parameter size (bytes)</th><th>Op mode</th><th>Valid value</th><th>Unit</th></tr>
<tr><td rowspan="2">3080h</td><td>Gantry control: index</td><td>read/write</td><td>2</td><td>All</td><td>0x2000 ~ 0x4FFF</td><td>-</td></tr>
<tr><td colspan="6">The index value of the operation object for gantry slave axis parameter.
Example: If this object is set to 0x2100, it indicates that index 2100h of gantry slave axis parameter is designated.</td></tr>
<tr><td rowspan="2">3081h</td><td>Gantry control: subindex</td><td>read/write</td><td>2</td><td>All</td><td>0</td><td>-</td></tr>
<tr><td colspan="6">The subindex value of the operation object for gantry slave axis parameter.
The current version only supports the object with subindex value being 0.</td></tr>
<tr><td rowspan="2">3082h</td><td>Gantry control: data type of selected object</td><td>read</td><td>2</td><td>All</td><td>-3 ~ 8</td><td>-</td></tr>
<tr><td colspan="6">The data type of the gantry slave axis parameter designated by object 3080h.
Different data type has different input / output register, the corresponding register is described as follows:
<table>
<tr><th>Value</th><th>Definition</th><th>Corresponding Input / Output Register</th></tr>
<tr><td>1</td><td>The data type of the designated object is BOOL.</td><td rowspan="7">3085h / 3086h (DINT)</td></tr>
<tr><td>2</td><td>The data type of the designated object is I8.</td></tr>
<tr><td>3</td><td>The data type of the designated object is I16.</td></tr>
<tr><td>4</td><td>The data type of the designated object is I32.</td></tr>
<tr><td>5</td><td>The data type of the designated object is U8.</td></tr>
<tr><td>6</td><td>The data type of the designated object is U16.</td></tr>
<tr><td>7</td><td>The data type of the designated object is U32.</td></tr>
<tr><td>8</td><td>The data type of the designated object is F32.</td><td>3087h / 3088h (REAL)</td></tr>
<tr><td>-1</td><td>The index value cannot be operated.</td><td rowspan="3">N/A</td></tr>
<tr><td>-2</td><td>The designated index object does not exist.</td></tr>
<tr><td>-3</td><td>The designated subindex object does not exist.</td></tr>
</table>
Note: When object 3084h = -1, this object is not applicable.</td></tr>
<tr><td rowspan="2">3083h</td><td>Gantry control: command</td><td>read/write</td><td>2</td><td>All</td><td>0 ~ 3</td><td>-</td></tr>
<tr><td colspan="6">The operation command of gantry slave axis parameter. The function of each command is described as follows:
<table>
<tr><th>Value</th><th>Definition</th><th>Description</th></tr>
<tr><td>0</td><td>Idle / Reset state</td><td>Idle / Reset state.</td></tr>
<tr><td>1</td><td>Writing command</td><td>The command will be triggered (positive edge) when this object is switched from 0 to 1. When the command is triggered, the value of the input register will be written to the designated object (3080h).
Note: If the command is given during data processing (object 3084h is 1), it will be invalid.</td></tr>
<tr><td>2</td><td>Single reading command</td><td>The command will be triggered (positive edge) when this object is switched from 0 to 2. When the command is triggered, the value of the designated object (3080h) will be put into the corresponding output register.
Note: If the command is given during data processing (object 3084h is 1), it will be invalid.</td></tr>
<tr><td>3</td><td>Continuous reading command</td><td>The values of the designated object (3080h) will be continuously put into the corresponding output register.
Note: Continuous reading command is not periodically updated.</td></tr>
</table></td></tr>
<tr><td rowspan="2">3084h</td><td>Gantry control: status</td><td>read</td><td>2</td><td>All</td><td>-6 ~ 2</td><td>-</td></tr>
<tr><td colspan="6">The operation status of gantry slave axis parameter. The definition is as follows:</td></tr>
</table>

Parameter number (Hex.)	Name	Properties	Parameter size (bytes)	Op mode	Valid value	Unit
	Value: 0 — Not in operation. 1 — Data is being processed. 2 — Data processing succeeds. -1 — The operation function of gantry slave axis parameter cannot be operated. Check if the firmware versions of master axis and slave axis are the same and the gantry control system is activated. -2 — The designated object (3080h) cannot be operated. -3 — The value of the input register exceeds the upper limit of the designated object (3080h)'s data type. -4 — The writing command is executed to read-only object. -5 — The unsupported operation command is used in object 3083h. -6 — Data processing timeout.					
3085h	Gantry control: input register of DINT	read/write	4	All	-2147483648 ~ 2147483647	-
	Input register for data type being BOOL, I8, I16, I32, U8, U16 or U32					
3086h	Gantry control: output register of DINT	read	4	All	-2147483648 ~ 2147483647	-
	Output register for data type being BOOL, I8, I16, I32, U8, U16 or U32					
3087h	Gantry control: input register of REAL	read/write	-	All	-	-
	Input register for data type being F32 (Not supported)					
3088h	Gantry control: output register of REAL	read	-	All	-	-
	Output register for data type being F32 (Not supported)					
3100h | 3104h	This section is about alarm state table, and it is not supported yet. Use object 4095h (error code) to check the contents.					
3110h	Drive warning events 1	read	2	All	0 ~ 0xFFFF	-

Warning state table 1. The warning corresponding to each bit is described as follows.
It is recommended to replace this object with the object 4096h (Warning code).

Bit	Waning No.	Warning Name
0	AL.900	Position deviation overflow
1	AL.901	<Not supported>
2	AL.910	Overload
3	AL.911	<Not supported>
4	AL.912	<Not supported>
5	AL.920	Regenerative resistor overload
6	AL.921	<Not supported>
7	AL.923	Internal fan stop
8	AL.930	Encoder battery malfunction
9	AL.941	Change of parameters and functions with save and restart requirement
10	AL.971	Undervoltage
11	AL.9A0	Overtravel detected when servo ON (P-OT or N-OT signal is received.)
12	AL.9A1	P-OT signal is received.
13	AL.9A2	N-OT signal is received.
14	AL.9AA	<Not supported>
15	AL.9Ab	<Not supported>

When the value of the bit is 1, the warning occurs.

<table>
<tr><th>Parameter number (Hex.)</th><th>Name</th><th>Properties</th><th>Parameter size (bytes)</th><th>Op mode</th><th>Valid value</th><th>Unit</th></tr>
<tr><td rowspan="2">3111h</td><td>Drive warning events 2</td><td>read</td><td>2</td><td>All</td><td>0 ~ 0xFFFF</td><td>-</td></tr>
<tr><td colspan="6">Warning state table 2. The warning corresponding to each bit is described as follows.
It is recommended to replace this object with the object 4096h (Warning code).

<table>
<tr><th>Bit</th><th>Waning No.</th><th>Warning Name</th></tr>
<tr><td>0</td><td>AL.9F0</td><td>Main circuit voltage too big</td></tr>
<tr><td>1</td><td>AL.943</td><td>Fieldbus synchronous cycle time warning</td></tr>
<tr><td>2</td><td>AL.944</td><td>System warning</td></tr>
<tr><td>3</td><td>AL.945</td><td>Torque limit warning</td></tr>
<tr><td>4</td><td>AL.946</td><td>Encoder communication warning</td></tr>
<tr><td>5</td><td>AL.947</td><td>Multi-motion malfunction warning</td></tr>
<tr><td>6</td><td>AL.924</td><td>I^2T</td></tr>
</table>
When the value of the bit is 1, the warning occurs.</td></tr>
<tr><td rowspan="2">3200h</td><td>Absolute encoder initialization</td><td>read/write</td><td>4</td><td>All</td><td>0 ~ 1</td><td>-</td></tr>
<tr><td colspan="6">Initialize absolute encoder. When it is set to 1, the multi-turn data of motor will be cleared. Keep servo off during the execution. The object will set the value according to the execution state:

<table>
<tr><th>Value</th><th>Definition</th></tr>
<tr><td>0</td><td>Not in operation.</td></tr>
<tr><td>1</td><td>When object 3200h is set to 1, send the command of clearing multi-turn data.</td></tr>
<tr><td>2</td><td>The command of clearing multi-turn data is being executed.</td></tr>
<tr><td>4</td><td>The command of clearing multi-turn data is successfully executed.</td></tr>
<tr><td>16</td><td>Do not send the command of clearing multi-turn data because the motor is enabled.</td></tr>
<tr><td>32</td><td>Fail to execute the command of clearing multi-turn data.</td></tr>
</table></td></tr>
<tr><td rowspan="2">3201h</td><td>General object i1</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (1)</td></tr>
<tr><td rowspan="2">3202h</td><td>General object i2</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (2)</td></tr>
<tr><td rowspan="2">3203h</td><td>General object i3</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (3)</td></tr>
<tr><td rowspan="2">3204h</td><td>General object i4</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (4)</td></tr>
<tr><td rowspan="2">3205h</td><td>General object i5</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (5)</td></tr>
<tr><td rowspan="2">3206h</td><td>General object i6</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (6)</td></tr>
<tr><td rowspan="2">3207h</td><td>General object i7</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (7)</td></tr>
<tr><td rowspan="2">3208h</td><td>General object i8</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (8)</td></tr>
</table>

<table>
<tr><th>Parameter number (Hex.)</th><th>Name</th><th>Properties</th><th>Parameter size (bytes)</th><th>Op mode</th><th>Valid value</th><th>Unit</th></tr>
<tr><td rowspan="2">3209h</td><td>General object i9</td><td>read/write</td><td>4</td><td>All</td><td>-2147483648 ~ 2147483647</td><td>-</td></tr>
<tr><td colspan="6">Self-defined object with data type of DINT (9)</td></tr>
<tr><td rowspan="2">3210h</td><td>General object f0</td><td>read/write</td><td>-</td><td>All</td><td>-</td><td>-</td></tr>
<tr><td colspan="6">Not supported</td></tr>
<tr><td rowspan="2">3211h</td><td>General object f1</td><td>read/write</td><td>-</td><td>All</td><td>-</td><td>-</td></tr>
<tr><td colspan="6">Not supported</td></tr>
<tr><td rowspan="2">3212h</td><td>General object f2</td><td>read/write</td><td>-</td><td>All</td><td>-</td><td>-</td></tr>
<tr><td colspan="6">Not supported</td></tr>
<tr><td rowspan="2">3213h</td><td>General object f3</td><td>read/write</td><td>-</td><td>All</td><td>-</td><td>-</td></tr>
<tr><td colspan="6">Not supported</td></tr>
<tr><td rowspan="2">3214h</td><td>General object f4</td><td>read/write</td><td>-</td><td>All</td><td>-</td><td>-</td></tr>
<tr><td colspan="6">Not supported</td></tr>
<tr><td rowspan="2">3215h</td><td>Reset driver</td><td>read/write</td><td>2</td><td>All</td><td>-1 ~ 2</td><td>-</td></tr>
<tr><td colspan="6">Reset the drive.

<table>
<tr><th>Value</th><th>Definition</th></tr>
<tr><td>0</td><td>Not in operation.</td></tr>
<tr><td>1</td><td>Reset the drive.
After it is done, the object will be automatically set to 0.</td></tr>
<tr><td>2</td><td>Reset the drives in gantry group mode.
After it is done, the object will be automatically set to 0.</td></tr>
<tr><td>-1</td><td>Fail to reset.
Check the following statuses:
(1) The communication between the gantry axes is normal.
(2) The firmware versions of the gantry axes are the same.</td></tr>
</table>

Note: Disconnection may occurs after this function is executed. Users need to request for communication reconnection from the controller.</td></tr>
<tr><td rowspan="2">3216h</td><td>Send parameter to flash</td><td>read/write</td><td>2</td><td>All</td><td>0 ~ 1</td><td>-</td></tr>
<tr><td colspan="6">Save parameters to drive. When it is set to 1, the current drive parameters will be saved. After it is done, the object will be automatically set to 0.
Note: Synchronous communication may be abnormal after this function is executed. Users need to clear the exception to reconnect.</td></tr>
</table>

7.3.2 Monitoring parameters (Ut parameters)

Parameter number (Hex.)	Name	Properties	Parameter size (bytes)	Op mode	Valid value	Unit
4000h	Ut000 - Motor velocity	read	-	All	-	-
	Not supported					
4001h	Ut001 - Velocity command	read	-	All	-	-
	Not supported					
4005h	Ut005 - Input signal monitoring	read	2	All	0 ~ 0xFFFF	-
	The table of digital input signal status, each bit is as below. 15...10 | 9 | 8 | 7 | 6 | 5 | 4 | 3 | 2 | 1 | 0 N/A | I10 | I9 | I8 | I7 | I6 | I5 | I4 | I3 | I2 | I1					
4006h	Ut006 - Output signal monitoring	read	2	All	0 ~ 0xFFFF	-
	The table of digital output signal status, each bit is as below. 15...5 | 4 | 3 | 2 | 1 | 0 N/A | O5 | O4 | O3 | O2 | O1					
4007h	Ut007 - Command pulse velocity (for position control only)	read	-	pp	-	-
	Not supported					
4008h	Ut008 - Peak loading rate	read	4	pp	-2147483648 ~ 2147483647	inc
	The errors between command position and actual position.					
4009h	Ut009 - Peak loading rate	read	-	All	-	-
	Not supported					
400Ah	Ut00A - Regenerative loading rate	read	4	All	0 ~100	%
	Display the percentage of actual regenerative load and upper limit of the regenerative load.					
400Ch	Ut00C - Command pulse counter	read	4	pp	-2147483648 ~ 2147483647	inc
	Input command pulse counter.					
400Dh	Ut00D - Feedback pulse counter	read	4	All	-2147483648 ~ 2147483647	count
	Encoder feedback pulse counter read by the servo drive. The unit is the encoder pulse.					
400Eh	Ut00E - Feedback pulse counter (full-closed loop)	read	4	All	-2147483648 ~ 2147483647	count
	The encoder feedback pulse counter read by the servo drive. The unit is the encoder pulse. In dual loop control, the value is from an external unit of measure.					
4013h	Ut013 - Feedback pulse counter (unit: control unit)	read	4	All	-2147483648 ~ 2147483647	inc
	Feedback pulse counter after being converted into the electronic gear ratio. The unit is the control unit.					
4020h	Ut020 - Rated velocity of motor	read	2	All	0 ~ 65535	rpm
	Rated velocity of motor					
4021h	Ut021 - Maximum velocity of motor	read	2	All	0 ~ 65535	rpm
	Maximum velocity of motor					
4041h	Ut041 - Single-turn absolute position	read	4	All	-2147483648 ~ 2147483647	count
	Absolute single-turn position of the motor, it will only valid when using an absolute encoder.					

Parameter number (Hex.)	Name	Properties	Parameter size (bytes)	Op mode	Valid value	Unit
4054h	Ut054 - Motor current	read	-	All	-	-
	Not supported					
4055h	Ut055 - Servo voltage percentage	read	-	All	-	-
	Not supported					
4056h	Ut056 - Position amplifier deviation	read	4	pp	-2147483648 ~ 2147483647	count
	Position deviation converted by electronic gear ratio, only valid in position control.					
4058h	Ut058 - Motor overload protection	read	-	All	-	-
	Not supported					
4061h	Ut061 - Load side position	read	4	All	-2147483648 ~ 2147483647	inc
	Position of load side. Linear mechanism: Display linear position of load side. Rotary mechanism: With the function of Pt205, single-turn position of load side can be displayed.					
4062h	Ut062 - Voltage of the main power	read	-	All	-	-
	Not supported					
4095h	Ut095 - Alarm code	read	2	All	0 ~ 0xFFFF	-
	Display the last alarm that occurred. The value of alarm code is ****h, where**** indicates the alarm code of E series servo drive. For example, 0d00h means the alarm of ALd00. Refer to section 13.2 in “E1 Series Servo Drive User Manual” and “E2 Series Servo Drive User Manual” for alarm list.					
4096h	Ut096 - Warning code	read	2	All	0 ~ 0xFFFF	-
	Display the last warning that occurred. The value of warning code is ****h, where**** indicates the alarm code of E series servo drive. For example, 0941h means the alarm of AL941. Refer to section 13.3 in “E1 Series Servo Drive User Manual” and “E2 Series Servo Drive User Manual” for warning list.					
4097h	Ut097 - Firmware version	read	4	All	0 ~ 0xFFFFFFFF	-
	Firmware version. The 3 Bytes in the lower bits are respectively the major, medium, and minor version numbers, expressed in hexadecimal. For example, 2.8.10 is expressed as 0x0002080A.					

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8. Alarms and warnings

8.1 Drive alarm / warning codes

■ Drive alarm and warning

The alarm and warning codes directly correspond to the drive alarm and warning numbers, as the example in Table 8.1.1 and Table 8.1.2. For the details of each drive alarm and warning, please refer to the “E1 Series Servo Drive User Manual” and “E2 Series Servo Drive User Manual.”

Table 8.1.1

Drive Alarm No.	Alarm Code
AL.800	0x0800
AL.FB0	0x0FB0

Table 8.1.2

Drive Warning No.	Warning Code
AL.900	0x0900
AL.9A0	0x09A0

■ Detailed information of communication related drive alarm

Table 8.1.3

Drive Alarm No.*1	Name	Description	Troubleshooting
AL.FB0	Fieldbus communication hardware malfunction	1. The Fieldbus communication is broken. 2. The data size setup is invalid. 3. The station address setup is invalid or conflict in the communication network.	1. Check if the station address setup is correct and reset the power of the servo drive. 2. Check if the data length setup is correct and reset the power of the servo drive.
AL.FB1	Fieldbus communication error	MECHATROLINK communication error.	1. Check if the communication cable is correctly connected. 2. Clear the cause of COMM_ALM and send ALM_CLR command and then SYNC_SET command. 3. Restart the controller communication or reset the power of the servo drive.

Drive Alarm No.*1	Name	Description	Troubleshooting
AL.FB2	Fieldbus communication setup error	The setting of the communication hardware or parameters is out of the product specification or does not fulfill the communication requirements.	1. Check if the setting of the station address is in the range of 0x03 to 0xEF. 2. Check if the setting of the data length is 32bytes or 48bytes. 3. Check if the station address setting is duplicated.

Note: *1 The alarm number and warning number are displayed by Thunder and 7-segment display.

8.2 Communication alarm / warning codes

The communication alarm and warning codes are displayed on the controller only after the connection has been established. The communication alarms will also trigger the drive AL.FB1 alarm.

■ Alarms

Table 8.2.1

Response Alarm Code*1	Description	Troubleshooting	Drive Alarm
0x0E62	FCS error	1. Check the connection. 2. Check the grounding and noise resistance.	AL.FB1
0x0E60	Command data is not received.		
0x0E63	Synchronous frame is not received.		
0x0E61	Synchronization interval error		
0x0E50	WDT error		
0x0E51	Synchronization failure		

■ Warnings

Table 8.2.2

Response Warning Code*1	Description	Troubleshooting	Drive Warning
0x0962	FCS error	1. Check the connection. 2. Check the grounding and noise resistance.	-
0x0960	Command data is not received.		
0x0963	Synchronous frame is not received.		

Note: *1 The alarm or warning code that a servo drive responds to a controller.

8.3 Command alarm / warning codes

The command alarm and warning codes are displayed on the controller only after the connection has been established. The command alarms and warnings will be automatically reset when a correct command is received.

■ Alarms

Table 8.3.1

Response Alarm Code *1	Description	Troubleshooting	Drive Alarm
0x095B	Unsupported command.	Check the command data from the controller.	-
0x095E	The combination of subcommand and main command is not allowed.		
0x094A	Parameter number or data address is incorrect.	Check if the command data from the controller is valid.	
0x094B	The data in the command is invalid.		
0x094D	The data size specified by the command is incorrect.		
0x095A	Command execution condition error.	Check the command sequence of the controller.	
0x095F	An illegal command has been received.		
0x097A	Phase error.		

■ Warnings

Table 8.3.2

Response Warning Code *1	Description	Troubleshooting	Drive Warning
0x097B	Invalid data	Check if the command data from the controller is valid.	-

Note: *1 The alarm or warning code that a servo drive responds to a controller

9. Virtual memory space

9.1 Allocation of virtual memory space

MECHATROLINK-III protocol defines the address space of virtual memory as figure 9.1.1. The vendor-specific area can be used by each vendor as needed.

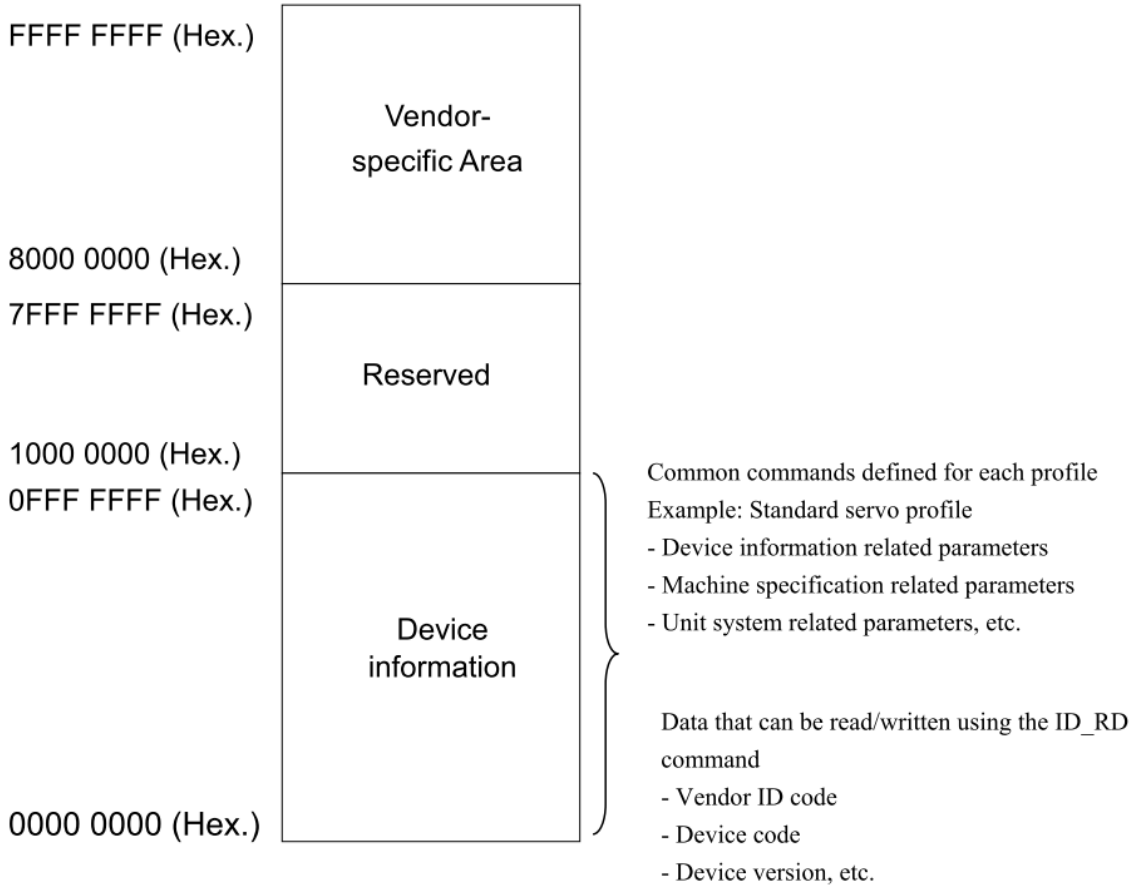
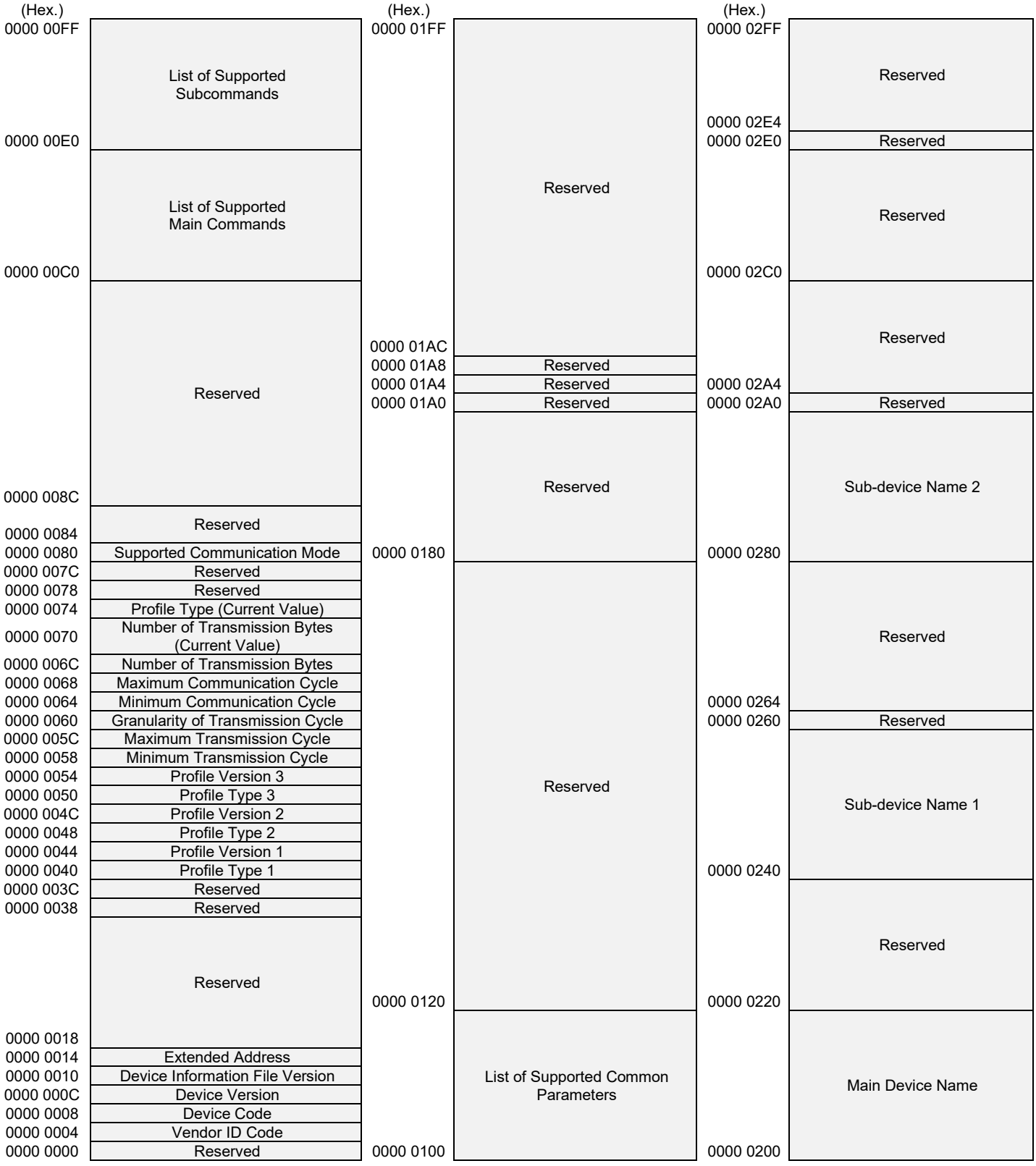


Figure 9.1.1

9.2 ID information area



Note: 0300h - 0x3FFh: Reserved

9.3 Common parameter area

(Hex.)		(Hex.)		(Hex.)	
0000 00FF	Reserved	0000 01FF	Reserved	0000 02FF	Reserved
0000 00A8					
0000 00A4	Reserved				
0000 00A0	Reverse Software Limit	0000 01A0			
0000 009C	Reserved	0000 019C	Near-position Range		
0000 0098	Forward Software Limit	0000 0198	In-position Range		
0000 0094	Limit Setting	0000 0194	Reserved		
0000 0090	Multiturn Limit	0000 0190	Reserved		
0000 008C	Absolute Encoder Origin Offset	0000 018C	Reserved		
0000 0088	Electronic Gear Ratio (Denominator)	0000 0188	Reserved		
0000 0084	Electronic Gear Ratio (Numerator)	0000 0184	Reserved		
	Reserved		Reserved	0000 0250	
				0000 024C	Supported Bits for I/O Signal
				0000 0248	Supported Bits for I/O Signal
				0000 0244	Supported Bits of SVCMD_STAT
				0000 0240	Supported Bits of SVCMD_CTRL
				0000 023C	Reserved
				0000 0238	Zero Speed Detection Range
0000 0034				0000 0234	Reserved
0000 0030	Pulses Per Scale Pitch			0000 0230	Reserved
0000 002C	Linear Scale Pitch			0000 022C	Zero Point Detection Range
0000 0028	Resolution (Rotary)	0000 0128		0000 0228	Monitoring Selection for SEL_MON2
0000 0024	Torque Multiplier	0000 0124	Supported Unit	0000 0224	Monitoring Selection for SEL_MON1
0000 0020	Maximum Output Torque	0000 0120	Torque Base Unit	0000 0220	Monitoring Selection 2
0000 001C	Rated Torque	0000 011C	Torque Unit	0000 021C	Monitoring Selection 1
0000 0018	Speed Multiplier	0000 0118	Acceleration Base Unit	0000 0218	Final Travel Distance for Zero Point Return
0000 0014	Maximum Output Speed	0000 0114	Acceleration Unit	0000 0214	Creep Speed of Zero Point Return
0000 0010	Rated Speed	0000 0110	Position Base Unit	0000 0210	Approach Speed of Zero Point Return
0000 000C	Semi-closed/Fully-closed Type	0000 010C	Position Unit	0000 020C	Final Travel Distance for External Input Positioning
0000 0008	Motor Type	0000 0108	Speed Base Unit	0000 0208	Reserved
0000 0004	Encoder Type	0000 0104	Speed Unit	0000 0204	Reserved
0000 0000	Reserved	0000 0100	Reserved	0000 0200	Reserved