# Operation Manual

## Goodrive270 Series
## VFD for Fan and Pump

SHENZHEN INVT ELECTRIC CO., LTD.

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|---|---|---|---|
| 1 | First release. | V1.0 | May 2021 |
| 2 | ● Added product data about the 1.5–22kW VFD models.<br>● Added the description of the expansion card EC-IO-503-00 in appendix A.4.<br>● Added appendix D.8 List of other optional accessories.<br>● Corrected minor errors. | V1.1 | April 2022 |
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| 4 | ● Modified model code and description in section 3.5.<br>● Modified 1.5kW–132kW VFD models and notes in section 3.6, and updated VFD models in other sections.<br>● Modified Figure 4-19 and Figure 4-41.<br>● Modified notes of sections 4.2.3 and 4.3.2.<br>● Modified the keypad description in sections 5.2 and 5.3, and added the LCD keypad display and operation in section 5.4.<br>● Modified Figure 5-29, and added Figure 5-30 and Figure 5-31 in section 5.5.16.<br>● Modified the function parameter list in section 6.2, and updated other function parameters in other sections.<br>● Deleted the command code 08H from section 9.4.<br>● Deleted the indicator definition contents from Appendix A.<br>● Modified the EMC content in section B.4.1. | V1.3 | August 2023 |

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| | ● Modified the keypad structure diagram and keypad mounting bracket description in section C.2.<br>● Modified the product dimensions and diagrams in section C.4.<br>● Modified reactor model selection table in section D.6.<br>● Modified filter contents in section D.7 and added section D.7.1.1 SCHAFFNER input filters.<br>● Deleted the description of altitude exceeding 3000m. | | |
| 5 | ● Updated product models and added models with built-in filters.<br>● Added PTC temperature detection function*.<br>● Added fan control noise reduction function*.<br>● Added the function to select grid frequencies (50/60Hz) and voltage levels (within 380–480V range).<br>● Added new communication expansion card information for software adaptation: EtherNet IP*, BACnet MS/TP*, Modbus TCP communication card*, 24V power supply expansion card*.<br>**Note:** Updates with "*" require support from software versions V1.06 and later. Please refer to P07.13 for version information.<br>● Updated the selection of harmonic filters.<br>● Added installation of 1.5–7.5kW output magnetic ring to meet C2 level requirements.<br>● Added sections 3.7 Product heat dissipation, 4.2.3 Cabinet design, 4.2.4 Installation instructions for reverse connection of input aluminum bars, 4.2.5 Top cardboard removal instructions.<br>● Added recommended cable size, brand, and models in section 4.3.1.1 Length requirements of motor cables.<br>● Added output filter selection for motor cable lengths.<br>● Updated section B.4.1 EMC compatibility and motor cable length.<br>● Updated section 6.2 Function parameter list.<br>● Updated section 5.5 Basic operation description. | V1.4 | July 2025 |

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|---|---|---|---|
| | ● Added sections 4.2.6 and 5.5.35.<br>● Updated section 5.5.16.1.<br>● Added screw location diagrams in section 7.7.4.<br>● Added product information of 560–800kW VFD models. | | |

# Preface

Thank you for choosing Goodrive270 series variable-frequency drive (VFD).

If not otherwise specified, the VFD in the manual always indicates Goodrive270 series VFD, which is an optimized VFD special for fan and pump. Simple and easy to use, the VFD can drive the fans and pumps in wastewater treatment, HVAC, chemical, metallurgical, electric power and other industries.

Using advanced vector control technologies, the VFD can drive both synchronous motors (SMs) and asynchronous motors (AMs) in various complex work conditions. In addition, the VFD has been embedded with various fan and pump application macros, such as PID, multi-pump control, constant pressure water supply, effectively relieving engineers from the difficulty in debugging. The VFD uses an independent air duct design and thickened circuit board coating, helping to adapt to hostile environments, ensuring long and reliable run, and reducing maintenance cost. The VFD also supports communication bus add-on, such as CAN bus and PROFINET bus, providing better industrial control system compatibility. The VFD power density is improved, facilitating the in-cabinet design and reducing customer system costs. The VFD circuit optimization design has excellent electromagnetic compatibility characteristics to ensure stable run in complex electromagnetic environments.

This manual instructs you how to install, wire, set parameters for, diagnose and remove faults for, and maintain the VFD, and also lists related precautions. Before installing the VFD, read through this manual carefully to ensure the proper installation and running with the excellent performance and powerful functions into full play.

The manual is subject to change without prior notice.

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# 1 Safety precautions

## 1.1 What this chapter contains

Read this manual carefully and follow all safety precautions before moving, installing, operating and servicing the product. Otherwise, equipment damage or physical injury or death may be caused.

We shall not be liable or responsible for any equipment damage or physical injury or death caused due to your or your customers' failure to follow the safety precautions.

## 1.2 Safety definition

**Danger**: Severe personal injury or even death can result if related requirements are not followed.

**Warning:** Personal injury or equipment damage can result if related requirements are not followed.

**Note**: Actions taken to ensure proper running.

**Trained and qualified professionals**: People operating the equipment must have received professional electrical and safety training and obtained the certificates, and must be familiar with all steps and requirements of equipment installing, commissioning, running and maintaining and capable to prevent any emergencies.

## 1.3 Warning symbols

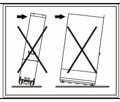
Warnings caution you about conditions that can result in severe injury or death and/or equipment damage and advice on how to prevent dangers. The following table lists the warning symbols in this manual.

| Symbol | Name | Description | Abbreviation |
|---|---|---|---|
| Danger | Danger | Severe personal injury or even death can result if related requirements are not followed. | |
| Warning | Warning | Personal injury or equipment damage can result if related requirements are not followed. | |
| Forbid | Electrostatic sensitive | The PCBA may be damaged if related requirements are not followed. | |
| Hot | Hot sides | Do not touch. The VFD base may become hot. | |
| 5 min | Electric shock | As high voltage still presents in the bus capacitor after power off, wait for at least five minutes (or 15 min / 25 min, depending on the warning symbols on the machine) after power off to prevent electric shock. | 5 min |
| | Read manual | Read the operation manual before operating the equipment. | |
| **Note** | Note | Actions taken to ensure proper running. | **Note** |

## 1.4 Safety guidelines

<table>
<tr><td></td><td>✧ Only trained and qualified professionals are allowed to carry out related operations.<br>✧ Do not perform wiring, inspection or component replacement when power supply is applied. Ensure all the input power supplies have been disconnected before wiring or inspection, and wait for at least the time designated on the VFD or until the DC bus voltage is less than 36V. The minimum waiting time is listed in the following.
<table>
<tr><th colspan="2">VFD model</th><th>Minimum waiting time</th></tr>
<tr><td rowspan="3">380V</td><td>1.5kW–110kW</td><td>5 minutes</td></tr>
<tr><td>132kW–315kW</td><td>15 minutes</td></tr>
<tr><td>355kW and higher</td><td>25 minutes</td></tr>
</table>
</td></tr>
<tr><td></td><td>✧ Do not refit the VFD unless authorized; otherwise fire, electric shock or other injury may result.</td></tr>
<tr><td></td><td>✧ The base may become hot when the machine is running. Do not touch. Otherwise, you may get burnt.</td></tr>
<tr><td></td><td>✧ The electrical parts and components inside the VFD are electrostatic sensitive. Take measurements to prevent electrostatic discharge when performing related operations.</td></tr>
</table>

### 1.4.1 Delivery and installation

<table>
<tr><td></td><td>✧ Do not install the inverter on inflammables. In addition, prevent the inverter from contacting or adhering to inflammables.<br>✧ Do not run the VFD if it is damaged or incomplete.<br>✧ Do not contact the VFD with damp objects or body parts. Otherwise, electric shock may result.</td></tr>
<tr><td></td><td>✧ Do not push the VFD sideward during moving.<br>✧ Prevent the VFD from tipping sideward.</td></tr>
</table>

**Note:**

✧ Select appropriate tools for VFD delivery and installation to ensure the safe and proper running and avoid physical injury or death. To ensure personal safety, take mechanical protective measures like wearing safety shoes and working uniforms.

✧ Protect the VFD against physical shock or vibration during the delivery and installation.

✧ Do not carry the product only by its front cover as the cover may fall off.

✧ The installation site must be away from children and other public places.

✧ When the altitude exceeds 1000m, derate by 1% for every increase of 100m.

✧ Use the VFD in proper environments. (For details, see section 4.2.1 Installation environment.)

✧ Prevent the screws, cables and other conductive parts from falling into the VFD.

✧ As leakage current of the VFD during running may exceed 3.5mA, ground properly and ensure the grounding resistance is less than 10Ω. The conductivity of PE grounding conductor is the same as that of the phase conductor (with the same cross sectional area).

✧ R, S and T are the power input terminals, and U, V and W are the output motor terminals. Connect the input power cables and motor cables properly; otherwise, damage to the VFD may occur.

**1.4.2 Commissioning and running**

| | |
|---|---|
|  | ✧ Cut off all power supplies connected to the VFD before terminal wiring, and wait for at least the time designated on the VFD after disconnecting the power supplies.<br>✧ High voltage presents inside the VFD during running. Do not carry out any operation on the VFD during running except for keypad setup. The VFD control terminals form extra-low voltage (ELV) circuits. Therefore, you need to prevent the control terminals from connecting to accessible terminals of other devices when there is no isolation protection mechanism configured.<br>✧ The VFD may start up by itself when P01.21 is set to 1 (restart after power off). Do not get close to the VFD and motor.<br>✧ The VFD cannot be used as an "Emergency-stop device".<br>✧ The VFD cannot act as an emergency brake for the motor; it is a must to install a mechanical braking device.<br>✧ During driving a permanent magnet SM, besides above-mentioned items, the following work must be done before installation and maintenance:<br>✓All input power supplies have been disconnected, including the main power and control power.<br>✓The permanent-magnet SM has been stopped, and the voltage on output end of the VFD is lower than 36V.<br>✓After the permanent-magnet SM has stopped, wait for at least the time designated on the VFD, and ensure the voltage between + and - is lower than 36V.<br>✓During operation, it is a must to ensure the permanent-magnet SM cannot run again by the action of external load; it is recommended to install an effective external braking device or cut off the direct electrical connection between the permanent-magnet SM and the VFD. |

**Note:**

✧ Do not switch on or switch off the input power supplies of the VFD frequently.

✧ If the VFD has been stored without use for a long time, perform capacitor reforming (described in chapter 8 Maintenance), inspection and pilot run for the VFD before the reuse.

✧ Close the VFD front cover before running; otherwise, electric shock may occur.

### 1.4.3 Maintenance and component replacement

| | |
|---|---|
| | ✧ Only trained and qualified professionals are allowed to perform maintenance, inspection, and component replacement for the VFD.<br>✧ Cut off all power supplies connected to the VFD before terminal wiring, and wait for at least the time designated on the VFD after disconnecting the power supplies.<br>✧ During maintenance and component replacement, take measures to prevent screws, cables and other conductive matters from falling into the internal of the VFD. |

**Note:**

✧ Use proper torque to tighten screws.

✧ During maintenance and component replacement, keep the VFD and its parts and components away from combustible materials and ensure they have no combustible materials adhered.

✧ Do not carry out insulation voltage-endurance test on the VFD, or measure the control circuits of the VFD with a megohmmeter.

✧ During maintenance and component replacement, take proper anti-static measures on the VFD and its internal parts.

### 1.4.4 Disposal

| | |
|---|---|
| | ✧ The VFD contains heavy metals. Dispose of a scrap VFD as industrial waste. |
| | ✧ Dispose of a scrap product separately at an appropriate collection point but not place it in the normal waste stream. |

# 2 Quick startup

## 2.1 What this chapter contains

This chapter introduces the basic installation and commissioning rules that you need to follow to realize quick installation and commissioning.

## 2.2 Unpacking inspection

Check the following after receiving the product.

| | |
|---|---|
| 1. | Whether the packing box is damaged or dampened. If any problems are found, contact the local INVT dealer or office. |
| 2. | Whether the model identifier on the exterior surface of the packing box is consistent with the purchased model. If any problems are found, contact the local INVT dealer or office. |
| 3. | Whether the interior surface of the packing box is abnormal, for example, in wet condition, or whether the enclosure of the VFD is damaged or cracked. If any problems are found, contact the local INVT dealer or office. |
| 4. | Whether the VFD nameplate is consistent with the model identifier on the exterior surface of the packing box. If any problems are found, contact the local INVT dealer or office. |
| 5. | Whether the accessories (including the manual, keypad, and expansion card) inside the packing box are complete. If any problems are found, contact the local INVT dealer or office. |

## 2.3 Checking before use

Check the following before using the VFD.

| | |
|---|---|
| 1. | Mechanical type of the load to be driven by the VFD to verify whether the VFD will be overloaded during work. Whether the power class of the VFD needs to be increased. |
| 2. | Whether the actual running current of the motor is less than the rated current of the product. |
| 3. | Whether the control accuracy required by the load is the same as that is provided by the VFD. |
| 4. | Whether the grid voltage is consistent with the rated voltage of the VFD. |
| 5. | Check whether expansion cards are needed for selected functions. |

## 2.4 Environment checking

Check the following before installing the VFD:

| | |
|---|---|
| 1. | Whether the actual ambient temperature exceeds 40°C. When the temperature exceeds 40°C, derate 1% for every increase of 1°C. Do not use the VFD when the ambient temperature exceeds 50°C.<br>**Note:** When the VFD is built in a cabinet, the ambient temperature is the temperature of air in the cabinet. |

| | |
|---|---|
| 2. | Whether the actual ambient temperature is lower -10°C. If the temperature is lower than -10°C, use heating devices.<br>**Note:** When the VFD is built in a cabinet, the ambient temperature is the temperature of air in the cabinet. |
| 3. | Whether the altitude of the application site exceeds 1000m. When the installation site altitude exceeds 1000 m, derate 1% for every increase of 100m. |
| 4. | Whether the actual environment humidity exceeds 90% or condensation occurs. If yes, take additional protective measures. |
| 5. | Whether there is direct sunlight or biological invasion in the environment where the VFD is to be used. If yes, take additional protective measures. |
| 6. | Whether there is dust or inflammable and explosive gas in the environment where the VFD is to be used. If yes, take additional protective measures. |

## 2.5 Checking after installation

Check the following after the VFD installation is complete.

| | |
|---|---|
| 1. | Whether the input power cables and motor cables meet the current-carrying capacity requirements of the actual load. |
| 2. | Whether correct accessories are selected for the VFD, the accessories are correctly and properly installed, and the installation cables meet the capacity carrying requirements of all components (including the input reactor, input filter, output reactor, output filter, and DC reactor). |
| 3. | Whether the product is installed on non-flammable materials and the heat-radiating accessories (such as reactors) are away from flammable materials. |
| 4. | Whether all the control cables and power cables are separately routed and whether EMC specification requirements are taken into full account during the routing. |
| 5. | Whether all grounding systems are properly grounded according to the requirements of the VFD. |
| 6. | Whether all the installation clearances of the VFD meet the requirements in the manual. |
| 7. | Whether the installation mode conforms to the instructions in the operation manual. Vertical installation is recommended whenever possible. |
| 8. | Whether the external connection terminals of the product are tightly fastened and the torque is appropriate. |
| 9. | Whether there are screws, cables, or other conductive items left in the VFD. If yes, get them out. |

## 2.6 Basic commissioning

Complete the basic commissioning as follows before the actual use of the VFD:

| | |
|---|---|
| 1. | According to the actual motor parameters, select the motor type, set motor parameters, and select the VFD control mode. |
| 2. | Check whether autotuning is required. If possible, de-couple the VFD from the motor load to start dynamic parameter autotuning. If the VFD cannot be de-coupled from the load, perform static autotuning. |
| 3. | Adjust the ACC/DEC time according to the actual work condition of the load. |
| 4. | Perform device commissioning by means of jogging and check whether the motor rotational direction is correct. If not, change the rotation direction by swapping any two phase wires of the motor. |
| 5. | Set all control parameters and then perform actual run. |

# 3 Product overview

## 3.1 What this chapter contains

This chapter mainly introduces the working principles, product features, layouts, nameplates and model designation rules.

## 3.2 Basic principles

The VFD is used to control asynchronous AC induction motors and permanent magnetic synchronous motors. The following figure shows the main circuit diagram of the VFD. The rectifier converts 3PH AC voltage into DC voltage, the capacitor bank of intermediate circuit stabilizes the DC voltage, and then the inverter converts DC voltage into AC voltage that can be used by an AC motor.

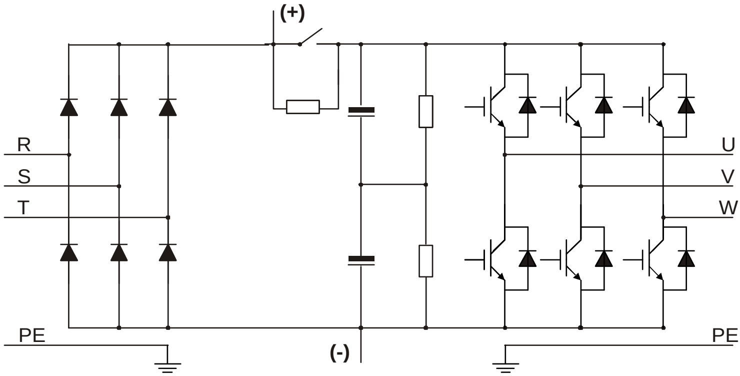



Figure 3-1 1.5–355kW main circuit of VFD models (optional DC reactors for 1.5–355kW models)

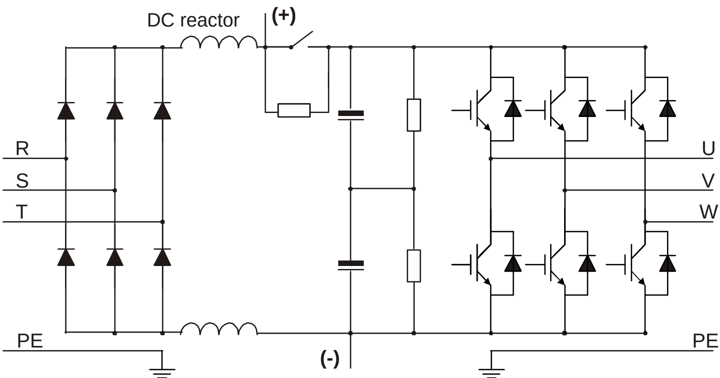



Figure 3-2 400–630kW main circuit (built-in DC reactors)

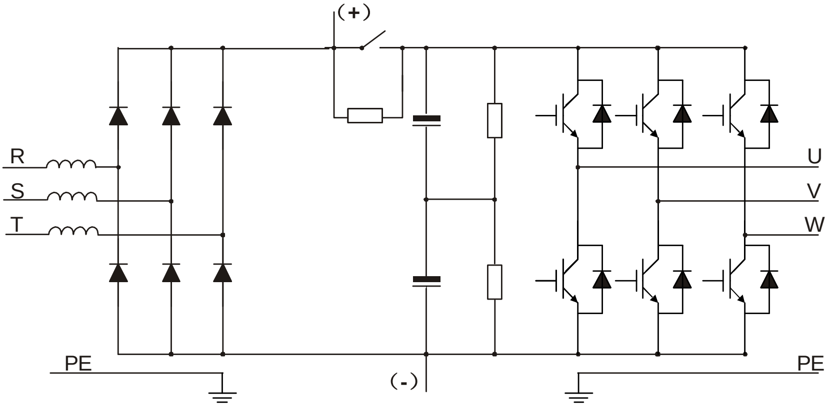



Figure 3-3 710–800kW main circuit (built-in DC reactors)

**Note:** Built-in DC reactors are standard parts only for 400–630kW models.

## 3.3 Product specifications

| Function description | | Specifications |
|---|---|---|
| Power input | Input voltage (V) | AC 3PH 380–480V, rated voltage: 380V |
| | Allowed voltage transient fluctuation | -15%–+10% |
| | Input current (A) | For details, see section 3.6 "Product ratings". |
| | Input frequency (Hz) | 50Hz or 60Hz; Allowed range: 47–63Hz |
| Power output | Output voltage (V) | 0–Input voltage |
| | Output current (A) | For details, see section 3.6 "Product ratings". |
| | Output power (kW) | For details, see section 3.6 "Product ratings". |
| | Output frequency (Hz) | 0–400Hz |
| Technical control performance | Control mode | Space voltage vector control, and sensorless vector control (SVC) |
| | Motor type | Asynchronous motor (AM) and permanent magnetic synchronous motor (SM) |
| | Speed ratio | For asynchronous motors (AMs): 1:200 (SVC); for synchronous motors (SMs): 1:20 (SVC) |
| | Speed control accuracy | ± 0.2% (SVC) |
| | Speed fluctuation | ± 0.3% (SVC) |
| | Torque response | < 20ms (SVC) |
| | Torque control accuracy | ± 10% (SVC) |
| | Overload capacity | Able to run at 110% of rated current for 1min, and an overload allowed for every 5min. |

| Function description | | Specifications |
|---|---|---|
| Running control performance | Frequency setting method | Settings can be implemented through digital, analog, pulse frequency, multi-step speed run, simple PLC, PID, and communication.<br>Settings can be combined and the setting channels can be switched. |
| | Automatic voltage regulation | The output voltage can be kept constant although the grid voltage changes. |
| | Fault protection | Many protection functions available, such as protection against overcurrent, overvoltage, undervoltage, overtemperature, and phase loss |
| | Speed tracking restart | Used to implement impact-free smooth startup for rotating motors |
| Peripheral interface | Terminal analog input resolution | No more than 20mV |
| | Terminal digital input resolution | No more than 2ms |
| | Analog input | Two inputs. AI1: 0(2)–10V / 0(4)–20mA; AI2: -10 – +10V |
| | Analog output | Two outputs. AO0/AO1: 0(2)–10V/0(4)–20mA |
| | Digital input | Five regular inputs. Max. frequency: 1kHz; internal impedance: 3.3kΩ<br>One high-speed input. Max. frequency: 50kHz |
| | Digital output | One Y terminal open collector output, sharing the terminal with S4. The function can be selected through a jumper. |
| | Relay output | Two programmable relay outputs<br>RO1A: NO; RO1B: NC; RO1C: common<br>RO2A: NO; RO2B: NC; RO2C: common<br>Contact capacity: 3A/AC 250V, 1A/DC 30V |
| | Expansion interfaces | Two expansion interfaces, SLOT1 and SLOT2, supporting communication cards, I/O cards, and so on |
| Other | Mounting method | Supports wall mounting, floor mounting, and flange mounting. |
| | Temperature of running environment | -10°C – +50°C; Derating is required when the ambient temperature exceeds 40°C. For details, see section B.2.2.1 Derating due to temperature. |
| | Ingress protection (IP) rating | IP20 for 1.5–200kW<br>IP00 for 220–630kW<br>IP21 for 710–800kW |
| | Pollution degree | Degree 2 |
| | Cooling method | For 1.5kW: Natural air cooling<br>For 2.2kW and higher: Forced air cooling |

## 3.4 Product nameplate

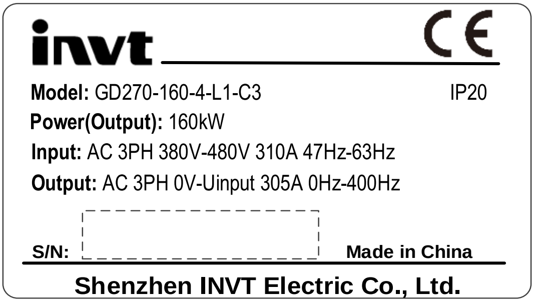



Figure 3-4 Product nameplate

**Note:** The preceding are standard product nameplate examples. The marking such as "CE" or "IP20" on the nameplate is marked according to actual certification conditions.

## 3.5 Model designation code

A model designation code contains product information. You can find the model designation code on the VFD nameplate.

GD270-160-4-L1-C3-EU

① ② ③ ④ ⑤ ⑥

Figure 3-5 Model description

| Field | No. | Field description | Content |
|---|---|---|---|
| Product series abbreviation | ① | Product series abbreviation | GD270: Goodrive270 series VFD for fan and pump |
| Rated power | ② | Power range | 160: 160kW |
| Voltage class | ③ | Voltage class | 4: AC 3PH 380V–480V<br>Rated voltage: 380V |
| Reactor configuration | ④ | Reactor configuration | Default: Empty<br>L1: with built-in DC reactor for 11–630kW models; with built-in inout reactor for 710–800kW models.<br>L3: with built-in DC reactor and output AC reactor for 220–630kW models; with built-in inout reactor and output AC reactor for 710–800kW models.<br>**Note:** DC reactors are standard parts for 400–630kW models. Input reactors are standard parts for 710–800kW models. |
| Built-in filter configuration | ⑤ | Built-in filter configuration | Empty:<br>with built-in C3 filter, applicable to 160kW–800kW |

| Field | No. | Field description | Content |
|---|---|---|---|
| | | | without built-in C3 filter, applicable to 1.5kW–132kW<br>C2: with built-in C2 filter, applicable to 1.5kW–22kW<br>C3: with built-in C3 filter, applicable to 30kW–132kW |
| Safe torque off (STO) function configuration | ⑥ | / | Empty: without STO function<br>EU: with built-in STO function |

## 3.6 Product ratings

Table 3-1 Ratings for AC 3PH 380V models

| VFD model | Output power (kW) | Input current (A) | Output current (A) |
|---|---|---|---|
| GD270-1R5-4(-C2)(-EU) | 1.5 | 5 | 3.7 |
| GD270-2R2-4(-C2)(-EU) | 2.2 | 6 | 5 |
| GD270-004-4(-C2)(-EU) | 4 | 15 | 9.5 |
| GD270-5R5-4(-C2)(-EU) | 5.5 | 20 | 13 |
| GD270-7R5-4(-C2)(-EU) | 7.5 | 27 | 17 |
| GD270-011-4(-L1/-C2)(-EU) | 11 | 35 (35) | 25 |
| GD270-015-4(-L1/-C2)(-EU) | 15 | 44 (44) | 32 |
| GD270-018-4(-L1/-C2)(-EU) | 18.5 | 46 (46) | 38 |
| GD270-022-4(-L1/-C2)(-EU) | 22 | 54 (54) | 45 |
| GD270-030-4(-L1)(-C3)(-EU) | 30 | 75 (56) | 60 |
| GD270-037-4(-L1)(-C3)(-EU) | 37 | 90 (69) | 75 |
| GD270-045-4(-L1)(-C3)(-EU) | 45 | 108 (101) | 92 |
| GD270-055-4(-L1)(-C3)(-EU) | 55 | 142 (117) | 115 |
| GD270-075-4(-L1)(-C3)(-EU) | 75 | 177 (149) | 150 |
| GD270-090-4(-L1)(-C3)(-EU) | 90 | 200 (171) | 180 |
| GD270-110-4(-L1)(-C3)(-EU) | 110 | 240 (205) | 215 |
| GD270-132-4(-L1)(-C3)(-EU) | 132 | 278 (235) | 250 |
| GD270-160-4(-L1)(-EU) | 160 | 310 (296) | 305 |
| GD270-185-4(-L1)(-EU) | 185 | 335 (320) | 330 |
| GD270-200-4(-L1)(-EU) | 200 | 385 (368) | 380 |
| GD270-220-4(-L*n*)(-EU) | 220 | 430 (411) | 425 |
| GD270-250-4(-L*n*)(-EU) | 250 | 465 (444) | 460 |
| GD270-280-4(-L*n*)(-EU) | 280 | 540 (485) | 530 |
| GD270-315-4(-L*n*)(-EU) | 315 | 605 (550) | 600 |
| GD270-355-4(-L*n*)(-EU) | 355 | 655 (600) | 650 |
| GD270-400-4-L*n*(-EU) | 400 | 660 | 720 |
| GD270-450-4-L*n*(-EU) | 450 | 745 | 820 |

| VFD model | Output power (kW) | Input current (A) | Output current (A) |
|---|---|---|---|
| GD270-500-4-L*n*(-EU) | 500 | 800 | 860 |
| GD270-560-4-L*n*(-EU) | 560 | 970 | 1020 |
| GD270-630-4-L*n*(-EU) | 630 | 1100 | 1120 |
| GD270-710-4-L*n*(-EU) | 710 | 1200 | 1260 |
| GD270-800-4-L*n*(-EU) | 800 | 1320 | 1460 |

**Note:**

✧ *n* = 1 or 3.

✧ The parentheses "()" in the "VFD model" column are used to distinguish models when selecting different product configurations. Please note that 11–22kW models can only be configured with one from the built-in DC reactor (L1) and the built-in C2 filter.

✧ The rated output current is the output current when the output voltage is 380V.

✧ The data in the "Input current" column are measured at an input voltage of 380V. The data in "()" are measured when a DCor input reactor is configured.

## 3.7 Product heat dissipation

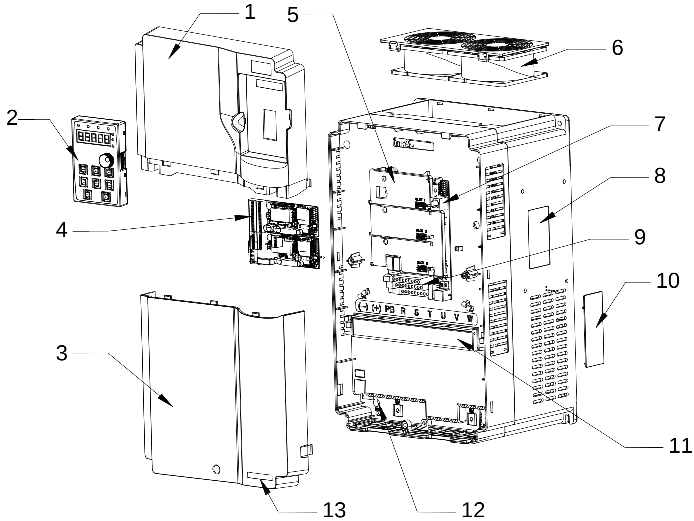
| VFD model | Entire machine full load power dissipation (W) | Heat dissipation (BTU/hr) | Air volume (m^3/h) | Air volume (ft^3/min(CFM)) |
|---|---|---|---|---|
| GD270-1R5-4(-C2)(-EU) | 48 | 164 | / | / |
| GD270-2R2-4(-C2)(-EU) | 60 | 205 | 35 | 21 |
| GD270-004-4(-C2)(-EU) | 125 | 427 | 52 | 30 |
| GD270-5R5-4(-C2)(-EU) | 180 | 614 | 64 | 38 |
| GD270-7R5-4(-C2)(-EU) | 220 | 751 | | |
| GD270-011-4(-L1/-C2)(-EU) | 320 | 1092 | 105 | 61 |
| GD270-015-4(-L1/-C2)(-EU) | 385 | 1314 | | |
| GD270-018-4(-L1/-C2)(-EU) | 460 | 1513 | 120 | 68 |
| GD270-022-4(-L1/-C2)(-EU) | 520 | 1696 | | |
| GD270-030-4(-L1)(-C3)(-EU) | 768 | 2620 | 140 | 83 |
| GD270-037-4(-L1)(-C3)(-EU) | 960 | 3276 | | |
| GD270-045-4(-L1)(-C3)(-EU) | 1090 | 3719 | 290 | 171 |
| GD270-055-4(-C3)(-EU) | 1837 | 6268 | 500 | 295 |
| GD270-055-4-L1(-C3)(-EU) | 1330 | 4538 | | |
| GD270-075-4(-C3)(-EU) | 2400 | 8189 | | |
| GD270-075-4-L1(-C3)(-EU) | 1753 | 5981 | | |
| GD270-090-4(-C3)(-EU) | 2880 | 9827 | | |
| GD270-090-4-L1(-C3)(-EU) | 2082 | 7104 | | |

| VFD model | Entire machine full load power dissipation (W) | Heat dissipation (BTU/hr) | Air volume (m^3/h) | Air volume (ft^3/min(CFM)) |
|---|---|---|---|---|
| GD270-110-4(-C3)(-EU) | 2490 | 8496 | 670 | 394 |
| GD270-110-4-L1(-C3)(-EU) | 2114 | 7213 | | |
| GD270-132-4(-C3)(-EU) | 2780 | 9485 | | |
| GD270-132-4-L1(-C3)(-EU) | 2360 | 8052 | | |
| GD270-160-4(-EU) | 2648 | 9035 | 1120 | 657 |
| GD270-160-4-L1(-EU) | 2890 | 9861 | | |
| GD270-185-4(-EU) | 2898 | 9888 | | |
| GD270-185-4-L1(-EU) | 3140 | 10714 | | |
| GD270-200-4(-EU) | 3453 | 11782 | 1360 | 800 |
| GD270-200-4-L1(-EU) | 3692 | 12597 | | |
| GD270-220-4(-EU) | 3911 | 13344 | 1330 | 785 |
| GD270-220-4-L1(-EU) | 4547 | 15514 | | |
| GD270-220-4-L3(-EU) | 4547 | 15514 | | |
| GD270-250-4(-EU) | 4393 | 14989 | | |
| GD270-250-4-L1(-EU) | 5026 | 17149 | | |
| GD270-250-4-L3(-EU) | 5026 | 17149 | | |
| GD270-280-4(-EU) | 5136 | 17524 | 2160 | 1270 |
| GD270-280-4-L1(-EU) | 5649 | 19274 | | |
| GD270-280-4-L3(-EU) | 5649 | 19274 | | |
| GD270-315-4(-EU) | 5814 | 19837 | | |
| GD270-315-4-L1(-EU) | 6395 | 21820 | | |
| GD270-315-4-L3(-EU) | 6395 | 21820 | | |
| GD270-355-4(-EU) | 6299 | 21492 | | |
| GD270-355-4-L1(-EU) | 6928 | 23638 | | |
| GD270-355-4-L3(-EU) | 6928 | 23638 | | |
| GD270-400-4-L1(-EU) | 6976 | 23802 | 2232 | 1270 |
| GD270-400-4-L3(-EU) | 7674 | 26184 | | |
| GD270-450-4-L1(-EU) | 7946 | 27112 | | |
| GD270-450-4-L3(-EU) | 8740 | 29821 | | |
| GD270-500-4-L1(-EU) | 8333 | 28432 | | |
| GD270-500-4-L3(-EU) | 9166 | 31274 | | |
| GD270-560-4-L1(-EU) | 9122 | 31104 | 2320 | 1365 |
| GD270-560-4-L3(-EU) | 9732 | 33206 | | |
| GD270-630-4-L1(-EU) | 11028 | 37628 | | |
| GD270-630-4-L3(-EU) | 11408 | 38924 | | |

| VFD model | Entire machine full load power dissipation (W) | Heat dissipation (BTU/hr) | Air volume (m^3/h) | Air volume (ft^3/min(CFM)) |
|---|---|---|---|---|
| GD270-710-4-L1(-EU) | 11054 | 37716 | 4141 | 2436 |
| GD270-710-4-L3(-EU) | 11689 | 39883 | | |
| GD270-800-4-L1(-EU) | 12950 | 44185 | | |
| GD270-800-4-L3(-EU) | 13585 | 46352 | | |

## 3.8 Structure

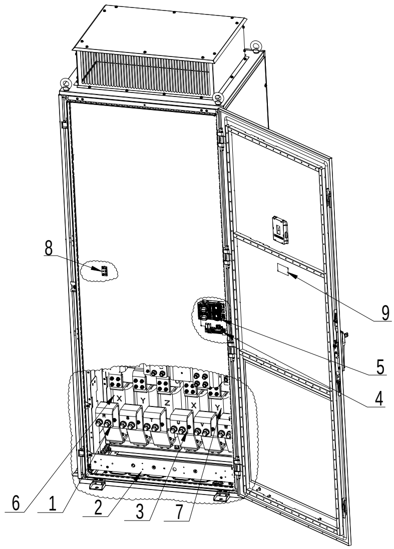
The VFD structure is shown in the following figure (taking the 380V 45kW VFD model as an example).




| No. | Name | Description |
|---|---|---|
| 1 | Upper cover | Protects internal components and parts. |
| 2 | Keypad | See section 5.2 Operation procedure. |
| 3 | Lower cover | Protects internal components and parts. |
| 4 | Expansion card | Optional. For details, see Appendix A Expansion card. |
| 5 | Baffle of control board | Protects the control board and install extension card. |
| 6 | Cooling fan | See section 8 Maintenance. |
| 7 | Keypad interface | Connects the keypad. |
| 8 | Nameplate | See section 3 Product overview. |
| 9 | Control terminals | See section 4.3.4 Wiring of basic control circuit |

| No. | Name | Description |
|---|---|---|
| 10 | Cover plate of heat emission hole | Optional. Cover plate can upgrade protection level, however, as it will also increase internal temperature, derated use is required. |
| 11 | Main circuit terminals | See section 4.3.2 Main circuit terminals |
| 12 | POWER indicator | Power supply indicator |
| 13 | GD270 product series label | See section 3.5 Model designation code. |

The following figure shows the structural layout of the 710–800 kW VFDs (using GD270-800-4-L3 as an example).




| No. | Name | Description |
|---|---|---|
| 1 | 3PH input bar | Wiring of RST 3PH cables |
| 2 | Grounding bar | System grounding |
| 3 | 3PH output bar | Wiring of UVW 3PH cables |
| 4 | Control board | Protects the control board and install extension card. |
| 5 | Expansion card | Optional. For details, see Appendix A Expansion card. |
| 6 | Input reactor | Device that restricts the electromagnetic interference generated by the VFD and transmitted to the public grid through the power cable. |
| 7 | Output reactor | Device used to suppress interference generated from the wiring on the output side of the VFD. |

| No. | Name | Description |
|---|---|---|
| 8 | POWER indicator | Power supply indicator |
| 9 | Nameplate | See chapter 3 Product overview. |

# 4 Installation guidelines

## 4.1 What this chapter contains

This chapter describes the mechanical installation and electrical installation of the VFD.

| | |
|---|---|
|  | ✧ Only trained and qualified professionals are allowed to carry out the operations mentioned in this chapter. Please carry out operations according to instructions presented in chapter 1 Safety precautions. Ignoring these safety precautions may lead to physical injury or death, or device damage.<br>✧ Ensure the VFD power has been disconnected before installation. If the VFD has been powered on, disconnect the VFD power and wait for at least the time specified on the VFD, and ensure the POWER indicator is off. You are recommended to use a multimeter to check and ensure the VFD DC bus voltage is below 36V.<br>✧ The VFD installation must be designed and done according to applicable local laws and regulations. INVT does not assume any liability whatsoever for any VFD installation which breaches local laws or regulations. If recommendations given by INVT are not followed, the VFD may experience problems that the warranty does not cover. |

## 4.2 Mechanical installation

### 4.2.1 Installation environment

The installation environment is essential for the VFD to operate with best performance in the long run. Install the VFD in an environment that meets the following requirements.

| Environment | Condition |
|---|---|
| Installation site | Indoor |
| Ambient temperature | ✧ -10–+50°C.<br>✧ When the ambient temperature exceeds 40°C, derate by 1% for every increase of 1°C.<br>✧ Do not use the VFD when the ambient temperature exceeds 50°C.<br>✧ To improve reliability, do not use the VFD in the places where the temperature changes rapidly.<br>✧ When the VFD is used in a closed space, such as control cabinet, use a cooling fan or air conditioner for cooling, preventing the internal temperature from exceeding the temperature required.<br>✧ When the temperature is too low, if you want to use the VFD that has been idled for a long time, install an external heating device before the use to eliminate the freeze inside the VFD. Otherwise, the VFD may be damaged. |

| Environment | Condition |
|---|---|
| Relative humidity (RH) | ✧ Less than 90%<br>✧ Condensation is not allowed.<br>✧ The max. RH cannot exceed 60% in the environment where there are corrosive gases. |
| Storage temperature | -30–+60.0°C |
| Running environment | Install the VFD in a place:<br>✧ Away from electromagnetic radiation sources<br>✧ Away from oil mist, corrosive gases, and combustible gases<br>✧ Without the chance for foreign objects such as metal powder, dust, oil and water to fall into the VFD (do not install the VFD onto combustible objects such as wood)<br>✧ Without radioactive substances and combustible objects<br>✧ Without hazard gases or liquids<br>✧ With low salt content<br>✧ Without direct sunlight |
| Altitude | ✧ Lower than 1000m<br>✧ When the altitude exceeds 1000m, derate by 1% for every increase of 100m. |
| Vibration | The max. amplitude of vibration cannot exceed 5.8m/s$^2$ (0.6g). |
| Installation direction | Install the VFD vertically to ensure good heat dissipation performance. |

### 4.2.2 Mounting method

The VFD can be installed on the wall or in a cabinet.

The VFD must be installed vertically. Check the installation position according to following requirements. For details about the outline dimensions, see Appendix C Dimension drawings.

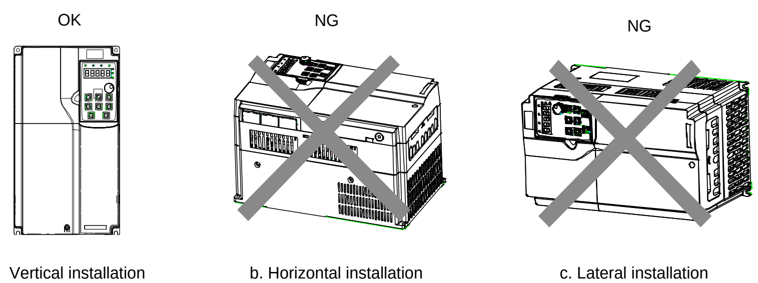
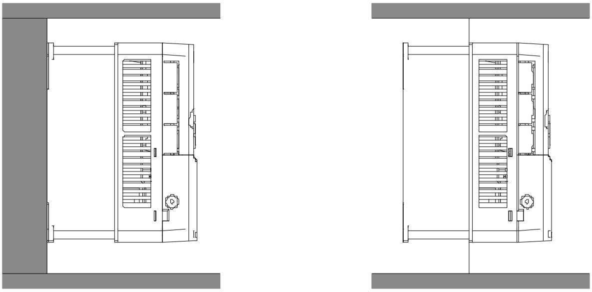



Figure 4-1 Installation direction

The VFD mounting method varies depending on the size.

| VFD power | Wall mounting | Flange mounting | Floor mounting |
|---|---|---|---|
| 1.5–200kW | √ | √ | / |
| 220–250kW | √ | / | √ |
| 280–800kW | / | / | √ |

**Note:** "√" indicates that the installation method is applicable, while "/" indicates that it is not applicable.



Wall mounting Flange mounting

Figure 4-2 Mounting method

The installation procedure is as follows:

Step 1 Mark the installation hole positions. For details about the installation hole positions, see Appendix C Dimension drawings.

Step 2 Secure the screws or bolts to the marked position.

Step 3 Lean the VFD against the wall.

Step 4 Tighten the fastening screws on the wall.

**Note:** The flange mounting plate must be used for flange mounting.

### 4.2.3 Cabinet design

#### 4.2.3.1 Cabinet design for 1.5–200kW

- **Space requirements inside the cabinet**

For 1.5–200kW models, multi-layer installation is recommended. The minimum clearance required between layers is listed in the following table. A heat insulation deflector must be installed above the lower layer VFD.

Table 4-1 Minimum space for multi-layer installations

| Power range | 1.5–22kW | 30–90kW | 110–200kW |
|---|---|---|---|
| D1 | ≥100mm | ≥200mm | ≥300mm |

| Power range | 1.5–22kW | 30–90kW | 110–200kW |
|---|---|---|---|
| D2 | ≥100mm | ≥200mm | ≥300mm |
| … | ≥100mm | ≥200mm | ≥300mm |
| Dn | ≥100mm | ≥200mm | ≥300mm |
| D (side-by-side installation space) | ≥30mm | ≥50mm | ≥100mm |

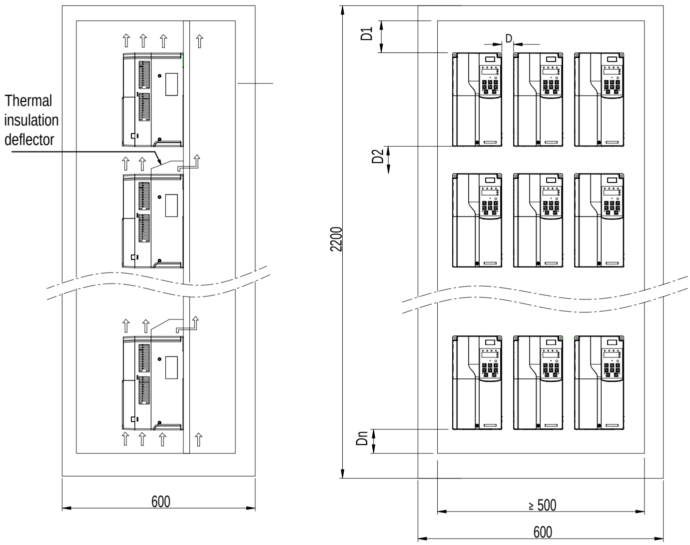



Figure 4-3 Multi-layer installation space requirements

## ■ Installation backplane requirements

To ensure that the VFD is installed and operated with good reliability, the following are detailed instructions regarding the thickness and rigidity reinforcement requirements of the backplate.

- ✧ In practical applications, the VFD may generate vibrations and thermal expansion during operation, so the backplate needs to have sufficient rigidity to withstand environmental and working conditions.
- ✧ The thickness of the backplate should be ≥2mm, which provides the necessary basic rigidity to prevent deformation or damage during equipment operation.
- ✧ The backplate can be reinforced if necessary. It is recommended to weld a transverse reinforcement beam on the back of the backplate (as shown in Figure 4-4). This can significantly improve the load-bearing capacity of the backplate and enhance the overall structural stability.
- ✧ When installing the VFD, ensure that the connection between the backplate and the cabinet is

secure to reduce vibration transmission.

✧ Considering that the VFD will generate heat during operation, sufficient heat dissipation space should be left in the backplate design to avoid overheating.

✧ Regularly inspect the condition of the backplate to ensure there is no deformation or damage. If any issues are found, reinforcement or replacement should be carried out promptly.

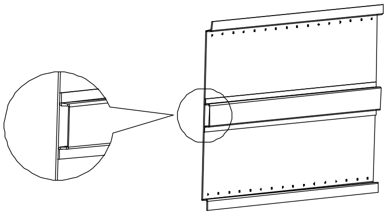


Figure 4-4 Weld a transverse reinforcement beam on the back of the backplane.

■ **Heat dissipation description**

The VFD dissipates heat through built-in fans (1.5kW models rely on natural cooling). To ensure sufficient cooling air enters the cabinet, an adequately large air intake should be opened on the cabinet door panel.

The air intake on the cabinet door panel should be positioned at least 50mm below the air intake of the VFD. This utilizes the natural upward flow of cold air to ensure it can smoothly enter the cabinet.

When installing the fan, pay attention to the airflow direction to ensure the fan extracts air from inside the cabinet to the outside. This effectively discharge the hot air from inside the cabinet, preventing heat buildup that could cause the VFD to overheat or be damaged. The distance between the exhaust cover and the fan outlet should be ≥200mm, otherwise, it will affect the heat dissipation performance of the fan. Ensure that air can flow freely to avoid air blockage.

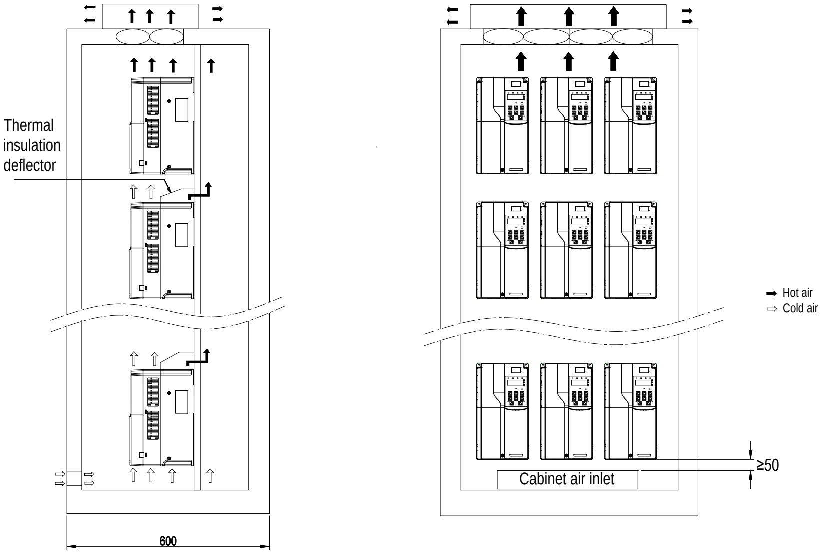



Figure 4-5 Cabinet air intake opening position

**Note:** In cases where multiple devices are installed in the same cabinet, using a fan to blow air into the cabinet intake can cause airflow distribution issues, affecting overall heat dissipation. Therefore, fans should not be installed at the cabinet intake to blow air inward.

After the VFD is installed in the cabinet, the minimum effective area of the air intake is shown in Table 4-2.

The data in Table 4-2 is only for a single VFD. When there are multiple VFDs in the cabinet, the total air intake area should be the sum of the individual areas. For example, if there are 10 units of 5.5kW and 2 units of 15kW, the minimum effective air intake area of the cabinet should be $10\times44+2\times58=556cm^2$.

If the air intake is equipped with a filter, it will cause air resistance. It is recommended to multiply the given air intake area by 1.2–1.5 times during design. The values in Table 4-2 is the minimum effective air intake area of the cabinet. If the design area is smaller than the specified effective area, the cabinet may experience negative pressure, preventing proper airflow and heat dissipation as intended.

1. Passive cooling

Passive cooling utilizes the natural upward flow of hot air, directing the exhaust from the VFD out of the cabinet through the top vent. However, passive exhaust can lead to the accumulation of hot air in the upper part of the cabinet, increasing the temperature in that area. The suction effect of the VFD's fan will create a relatively low pressure at the air intake, resulting in a pressure difference between the exhaust and intake vents inside the cabinet. This pressure difference will cause hot air to circulate inside the cabinet, forming a closed loop.

If hot air continuously flows back to the air intake, the VFD will repeatedly inhale this hot air, significantly increasing the internal temperature. This is undoubtedly detrimental to the device's performance and lifespan. Therefore, to improve the performance of the passive exhaust system, isolation devices must be used to prevent hot air from recirculating.

Isolation devices can be made of plates or exhaust ducts, as shown in Figure 4-6. Inside the cabinet, isolation panels can be used to separate the exhaust and intake areas, effectively reducing the likelihood of hot air recirculation. Additionally, installing dedicated exhaust ducts to guide hot air outside further isolates the flow of cold and hot air, achieving more effective heat dissipation.

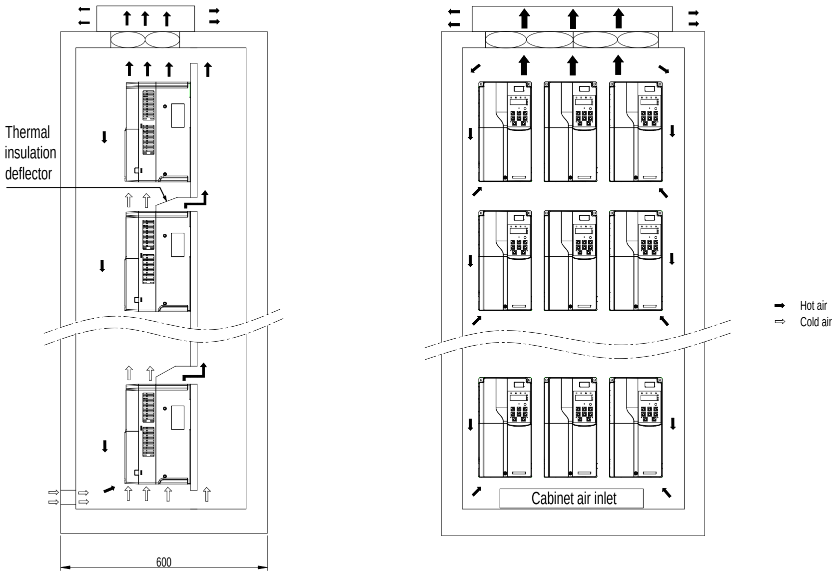



Figure 4-6 Recirculation of hot air in a passive exhaust cabinet (without isolation device)

The exhaust vent of the VFD has a higher temperature and lower air density compared to the intake vent. To ensure hot air is effectively expelled from the cabinet in a passive cooling system, refer to Table 4-2 for the minimum effective area of the cabinet's exhaust vent.

The data in Table 4-2 is only for a single VFD. When there are multiple VFDs in the cabinet, the total air exhaust area should be the sum of the individual areas. If the exhaust vent is equipped with a filter, it will cause air resistance. It is recommended to multiply the reference area value by 1.2–1.5 times during design.

2. Active cooling

Active cooling involves installing fans at the top of the cabinet to extract hot air from the cabinet to the outside. Active exhaust is a commonly used exhaust method. To ensure that hot air inside the cabinet can be effectively expelled, the total airflow of the system fans must not be less than the sum of the airflow of all VFDs in the cabinet. The required cooling airflow is shown in the following table.

Table 4-2 Heat dissipation parameters of 1.5–200kW cabinet

Steps for selecting cabinet fans:

Step 1 Calculate the total cooling airflow required for all VFDs based on the table above.

Step 2 Determine the maximum airflow value of the cabinet fans and select the appropriate fan specifications and quantity.

- ➢ Under normal conditions, the maximum airflow value of the cabinet is recommended to be 1.3–1.5 times the calculated value.
- ➢ When the cabinet exhaust vent is equipped with components such as mesh or louvers, which may increase air resistance, it is recommended to multiply the calculated value by 1.8–2.2 times.

Step 3 The airflow of the selected fan is not less than the maximum airflow, and multiple fans can be used when a single fan cannot meet the requirement.

**4.2.3.2 Cabinet design for 220–630kW**

220–630kW models (L1, L3) can be mounted in cabinets. Heat dissipation must be considered for the cabinet mounting method. Both active cooling and passive cooling solutions can be considered.

1. Passive cooling

When using a passive cooling solution, ensure that the top exhaust area of the cabinet and the air intake area of the cabinet are greater than the values given in Table 4-3. If there are components such as dust filters or louvers, consider increasing the air intake and exhaust areas by 1.3–1.5 times.

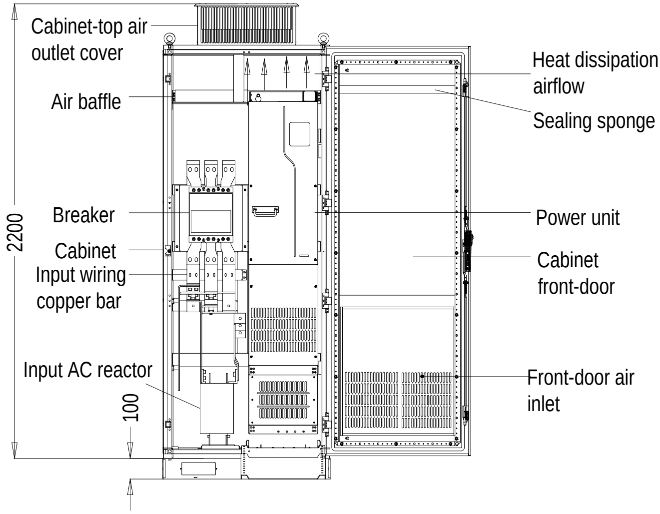



Figure 4-7 Direct exhaust cabinet (without a fan at the top)

Table 4-3 Passive cooling parameters

| VFD power | VFD cooling air volume (CFM) | Minimum actual effective area of the air intake ($mm^2$) | Minimum actual effective area of the exhaust vent ($mm^2$) |
|---|---|---|---|
| 220–250kW | 785 | 172560 | 37280 |
| 280–355kW | 1270 | 200670 | 42800 |
| 400–630kW | 1270 | 259000 | 50230 |

**Note:**

- 1CFM=1.7$m^3$/h .
- The term "actual effective area" mentioned above refers to the through-hole area. In practical design, the cut-out rate must be considered.
- Passive cooling is not suitable for 560–630 kW models.

2. Active cooling

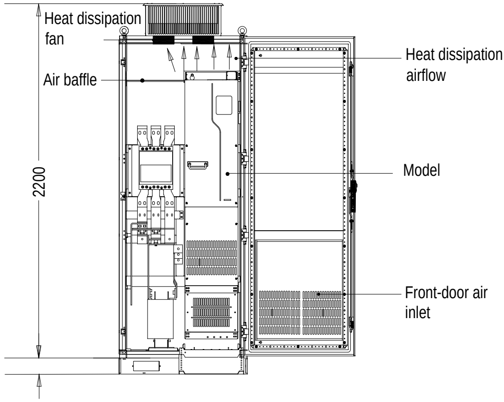



Figure 4-8 Top fan exhaust cabinet

Table 4-4 Active cooling parameters

| VFD power | VFD cooling air volume (CFM) | Minimum actual effective area of the air intake (mm$^2$) | Air volume requirement (CFM) | Actual effective area of top exhaust vent (mm$^2$) |
|---|---|---|---|---|
| 220–250kW | 785 | 172560 | 864 | ≥Total ventilation area of the selected fans |
| 280–355kW | 1270 | 200670 | 1400 | |
| 400–500kW | 1270 | 200670 | 1400 | |
| 560~630kW | 1356 | 259000 | 1492 | |
| **Note:** 1CFM≈1.7m$^3$/h. | | | | |

As shown in Figure 4-9, the air duct of VFD must be isolated within the cabinet to prevent the hot air in the VFD outlet from circulating within the cabinet, and the air baffle design for isolation ensures that the hot air is discharged from the cooling holes at the top of cabinet.

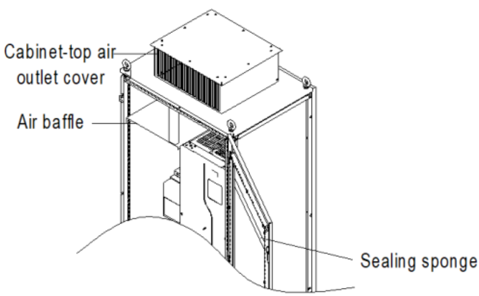



Figure 4-9 Air baffle design

**Note:** A 40×40 sealing sponge must be used at the position corresponding to the air baffle in the front door panel, which prevents air duct short circuit.

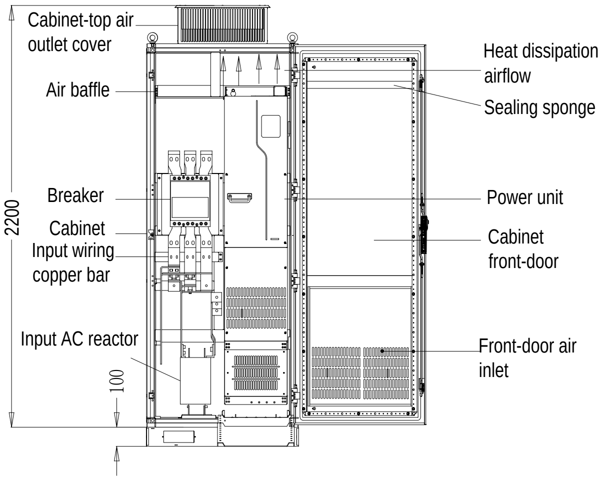



Figure 4-10 Recommended cabinet layout for 220–630kW models

■ **In-cabinet mounting procedure**

| No. | Description |
|---|---|
| 1 | Mount the crossbeam for VFD fixing in the nine-fold profile cabinet. (See Figure 4-11.) |
| 2 | Fix the bottom support crossbeams and mounting bracket in the cabinet. (See Figure 4-13.) |
| 3 | Assemble the mounting rail (optional part) and mount it in the cabinet. |
| 4 | Arrange two people to align the VFD casters with the mounting rail and push the VFD to the cabinet. (See Figure 4-15 and Figure 4-16. Use the auxiliary rope for mounting to prevent the VFD from side tipping during the push-in or push-out, as shown in Figure 4-17.) |
| 5 | Remove the auxiliary rope for mounting, and insert screws into the fixing holes at the back, top, and bottom of VFD to fix the VFD to the mounting crossbeam. (See Figure 4-18.) |
| 6 | Removed the mounting rail when you ensure the mounting is secure. |

1. Fix the mounting crossbeam and reserve fixing holes.

A. The nine-fold profile cabinet (PS cabinet) is recommended. Figure 4-11 shows the nine-fold profile cross section.

B. When mounting a GD270 series 280–630kW VFD into a nine-fold profile cabinet with the depth of 600mm, you must bend the mounting crossbeam inwards (shown in Figure 4-12) to make use of the space of column, which is not necessary for the mounting into a standard cabinet with the depth of 800mm or greater.

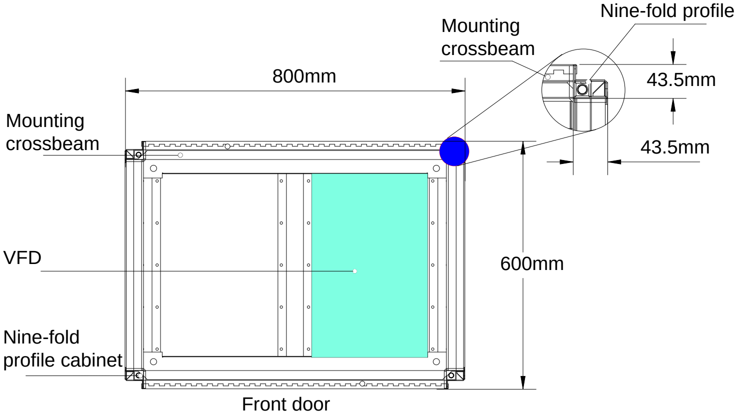



Figure 4-11 Top view of mounting a 280–630kW VFD in a cabinet

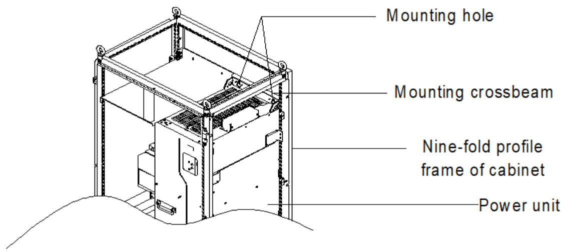



Figure 4-12 Three-dimension view of mounting a 280–630kW VFD in a cabinet

2. Fix the bottom support crossbeams and mounting bracket. See Figure 4-13.

A. Use eight M8 cage nuts to fix the two bottom support crossbeams to the base of the nine-fold profile cabinet frame. (The support crossbeams are user designed, T≥2.5mm, firmly installed.)

B. Fix the mounting bracket to the nine-fold profile cabinet frame base with six M5 self-tapping screws, as shown in the following figure. For details about mounting bracket dimensions, see Figure 4-15 and Table C-8.

C. If you use another type of cabinet but not nine-fold profile cabinet, the fixing holes for the mounting bracket need to be drilled and assembled on site.

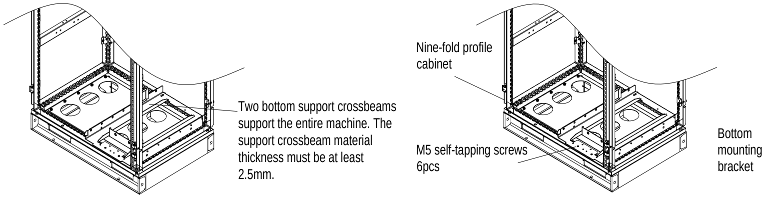



Figure 4-13 Bottom bracket mounting

3. Assemble the mounting rail (optional part).

Assemble the mounting rail, align the two front hooks with the nine-fold profile notch, and snap them into place.

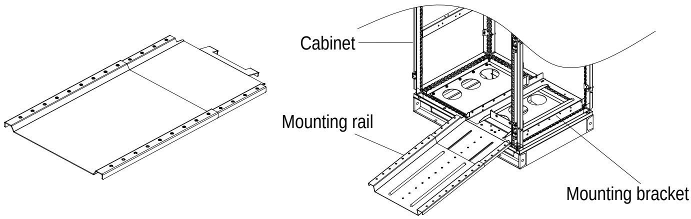
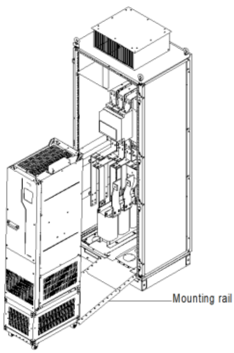
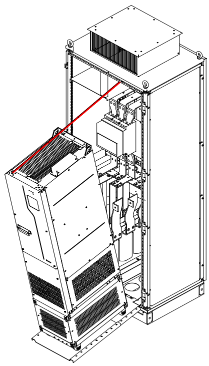



Figure 4-14 Mounting rail

4. Push the VFD into the cabinet.

| | |
|---|---|
|   |  |
| Figure 4-15 Aligning the VFD casters with the mounting rail | Figure 4-16 Pushing the VFD into the cabinet slowly |

**Note:** Since the VFD barycenter is too high, use the auxiliary rope for mounting to prevent the VFD from rollover during the push-in or push-out. See Figure 4-17.

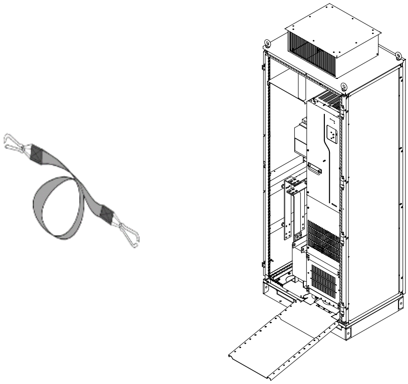


Figure 4-17 VFD already in the cabinet

5. Remove the mounting rail.

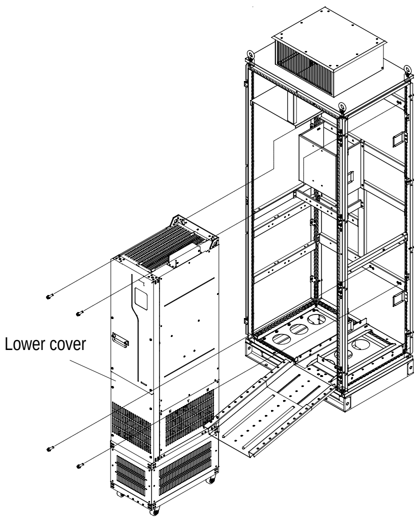


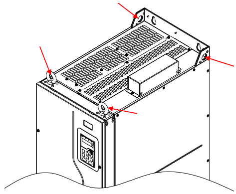

Figure 4-18 Fixing the VFD to the cabinet crossbeam through the four fixing holes at the VFD back

6. Pay attention to the following:

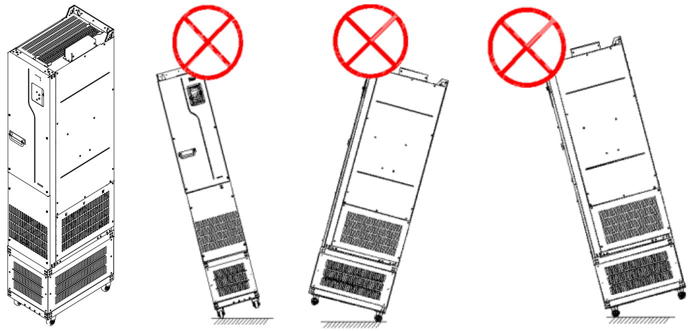
A. Detach the VFD from the cabinet by following the preceding procedure in reverse sequence.

B. When fixing the VFD, ensure that the four mounting holes of VFD have been securely connected to the mounting crossbeam.

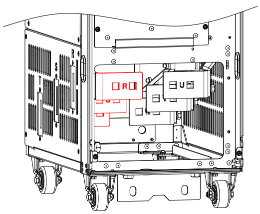
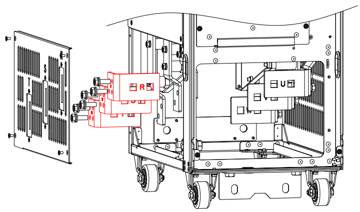
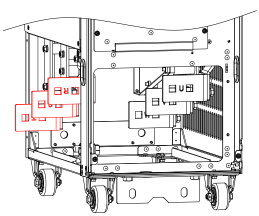
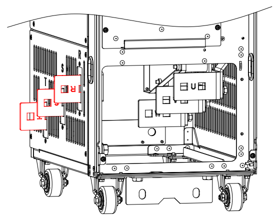
C. Use the lifting ring on the top of VFD for lifting and moving. Never apply force to the positive and negative bus terminals.



D. If you need to place the VFD vertically, avoid applying force to VFD sides or placing the VFD on a tilted surface. If the tilted angle is more than 5°, the VFD may suffer rollover since the VFD has a large size and heavy weight (about 200kg).

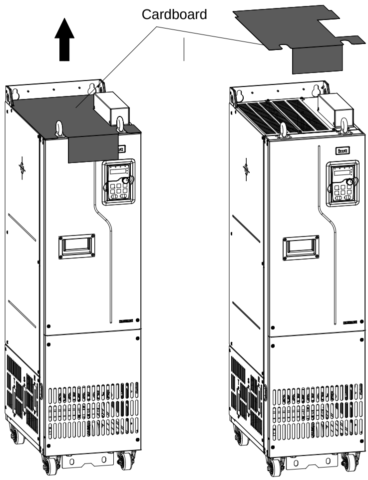


### 4.2.4 Installation instructions for reverse connection of input aluminum bars

| | |
|---|---|
| ① Aluminum bars are installed inside the entire machine.<br> | ② Disassemble the side cover plate and input aluminum busbars.<br> |
| ③ Reversely install the input aluminum bars.<br> | ④ Install the side cover plate.<br> |

### 4.2.5 Top cardboard removal instructions

When installing 220–630kW VFDs, keep the cardboard fixed above the VFD to prevent conductive foreign objects from falling into the VFD during installation. After the VFD installation is completed, the cardboard must be removed before power-on. The position of the cardboard is shown in the figure below.



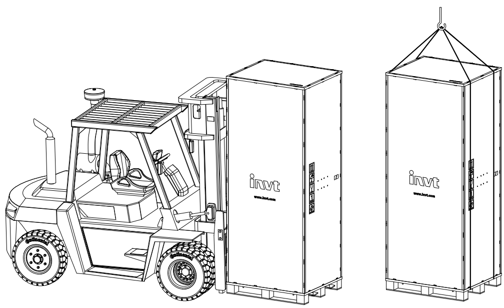

### 4.2.6 VFD cabinet installation

#### 4.2.6.1 Transportation

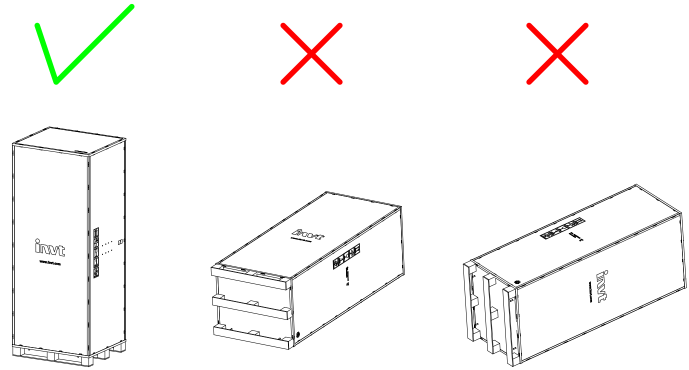
When transported with a forklift, the VFD must be fixed to the pallets and transported together, which means you are not allowed to remove the pallets to transport the VFD alone.

If the forklift's fork tines are too short, it may cause the unit/cabinet to tip over, resulting in serious injury, property damage or even death.

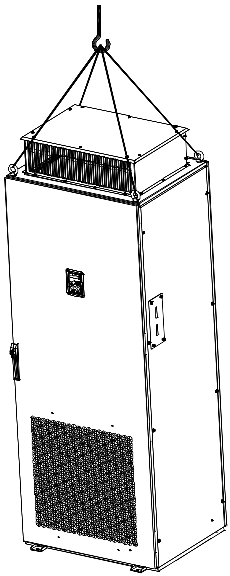
When transported with a crane, the VFD must be fixed to the pallets and lifted together.



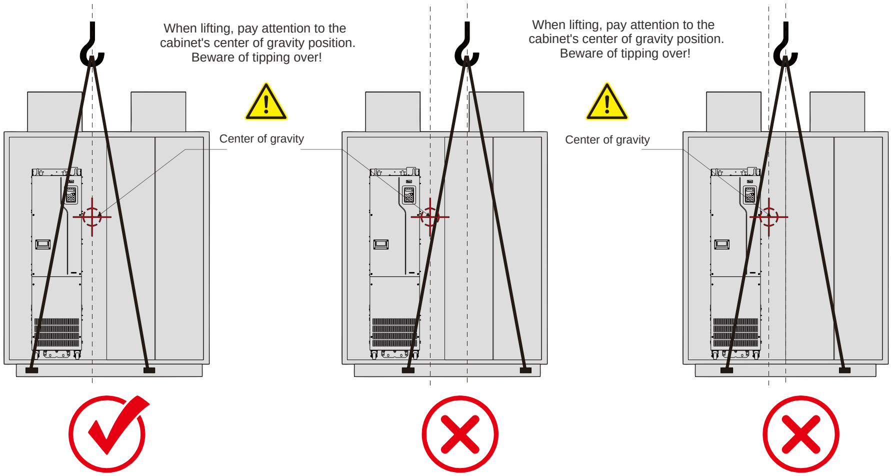
The VFD cabinet is shipped in a wooden box with pallets, which are heavy as a whole and must be carried with a lifting tool, such as a forklift and crane. Operators must be professionally trained. The product must be transported in strict accordance with the allowed ways marked on the box, and not allowed to be transported upside down or on the sides.



To lift and handle the device from the top, pass the lifting rope or sling through the lifting rings and secure it properly. Proceed with the lifting operation only after ensuring safety.



If the VFD is to be installed in a cabinet, the center of gravity of the entire cabinet must be considered during transportation. The VFD is heavy and will significantly affect the cabinet‘s overall weight distribution. When lifting and moving the cabinet with the VFD installed, ensure that the center of gravity is positioned directly below the vertical line of the lifting equipment to prevent the cabinet from tipping over during the hoisting process.




#### 4.2.6.2 Unpacking

The cabinet is delivered in the wooden box padded with EPE.

To remove the packing, do as follows:

Step 1 Place the well-packed unit in an empty and flat place.

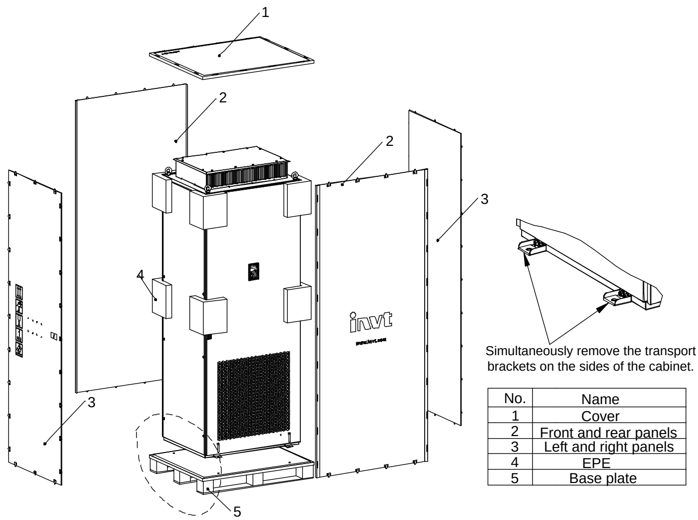
Step 2 Use tools such as a pry bar or large one-piece screwdriver to remove the wooden box cover and the steel tongue nails of the surrounding boards.

Step 3 Remove the surrounding boards and EPE filling materials from the wooden box.

Step 4 Cut off the plastic wrapping tape around the cabinet.

Step 5 Take out the cabinet and confirm that the cabinet is intact without any damage.

Step 6 Dispose of or recycle packaging in accordance with local regulations.




| No. | Name |
|---|---|
| 1 | Cover |
| 2 | Front and rear panels |
| 3 | Left and right panels |
| 4 | EPE |
| 5 | Base plate |

#### 4.2.6.3 Installation site check

The installation site should be well ventilated or shaded for good heat dissipation.

The installation environment meets the specification requirements.

The wall/material near the installation site should be non-combustible material.

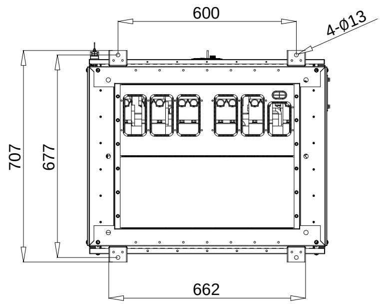
The floor should be made of non-combustible material, and flat and strong to withstand the weight of the equipment. Check the level of the floor with a level, and ensure that the maximum allowable deviation of the level of the ground surface is 5mm per 3m. The installation site should be leveled if necessary, as the cabinet is not equipped with adjustable feet.

For ease of maintenance, do not install the cabinet at a higher position than the area in front of it.

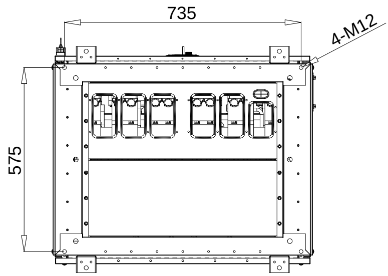
#### 4.2.6.4 nstallation instructions

The cabinet is floor mounted and fixed to the ground.

When the channel steel base is not available on the site, fix the cabinet directly to the ground through 4 fixing anchor bolts. The following figure shows the installation dimensions (unit: mm).

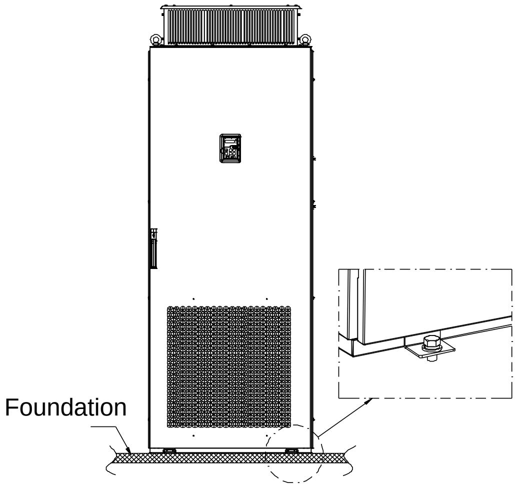



When the channel steel base is available on the site, fix the channel steel base with the ground, and then use bolts to fix the cabinet to the base through the mounting holes. The following figure shows the installation dimensions (unit: mm).




#### 4.2.6.5 Requirements for the foundation

The cabinet must be installed on a level and solid foundation that can support the weight of the equipment. When opening and closing the cabinet doors, proper operation of the door locks must be ensured. When connecting multiple cabinets side by side, make sure there are no gaps between the cabinets and the floor.




The installation procedure is as follows:

Step 1 Mark the installation hole positions. For details about the installation hole positions, see section C.4 Product dimensions.

Step 2 Align the mounting holes and position the VFD on the foundation.

Step 3 Mount the bolts into the marked positions.

Step 4 Tighten the bolts securely.

Installation tools:

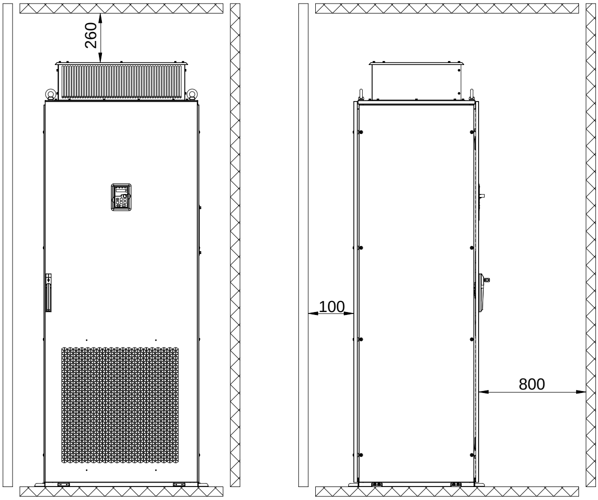
| No. | Tool name | Description |
|---|---|---|
| 1 | Crane | Used to lift the VFD onto the foundation |
| 2 | Socket wrench | Used to tighten bolts |
| 3 | M12*30 bolt + spring & flat washer | / |

#### 4.2.6.6 Installation space

To ensure reliable cabinet installation and good heat dissipation, the ventilation clearances must be kept from the front, back, top and sides of the cabinet. For the minimum clearance, see the following figure.

A minimum clearance of 800mm should be reserved in front of the cabinet to facilitate cabinet maintenance.

Violation of the requirements in the installation space and heat dissipation will shorten the VFD life and may result in VFD failure or malfunction.




#### 4.2.6.7 External braking resistor cabinet or braking unit connection (710–800kW)

Procedure:

Step 1 Open the cabinet door and install the external braking unit adapter busbar as shown in Figure 4-19

Step 2 Connect the external braking unit as shown in Figure 4-20.

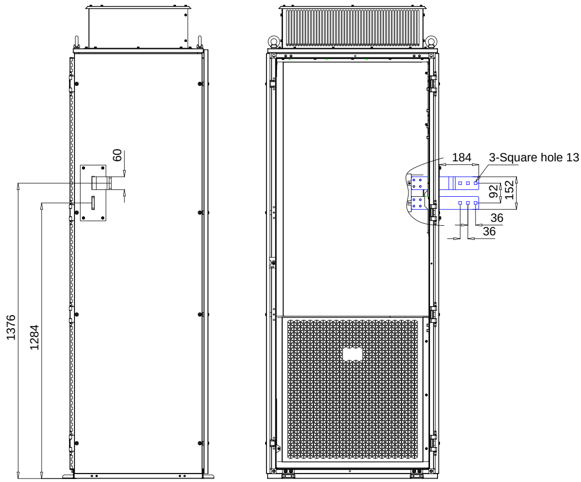



Figure 4-19 Mounting dimensions of adapter busbar (unit: mm)

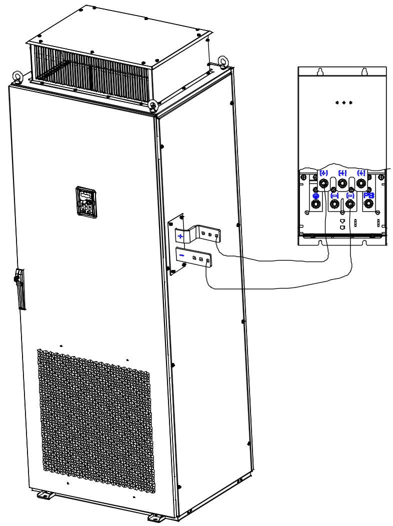


Figure 4-20 Connection diagram between VFD and external braking unit

## 4.3 Electrical installation

### 4.3.1 Main circuit wiring

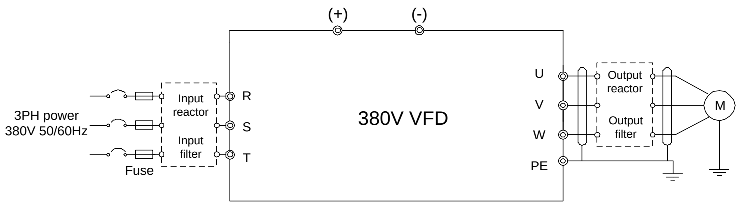



Figure 4-21 AC 3PH 380V VFD main circuit wiring

**Note:**

✧ The fuse, input reactor, input filter, output reactor, and output filter are optional parts. For details, see Appendix D Optional peripheral accessories.

✧ If you require the built-in DC reactor, purchase the VFD model with the suffix "-L1".

#### 4.3.1.1 Length requirements of motor cables

When the distance between the VFD and the motor is too long, the large parasitic capacitance to ground produces high harmonic current, which causes the VFD to frequently enable overcurrent protection and even causes motor insulation damage.

You must configure the output reactor nearby the VFD when the cable length is equal to or greater than the values in the following table.

Refer to section D.5 Harmonic filters for selection based on different cable types and lengths. Note that the supported cable length when a harmonic filter is configured cannot be cumulatively calculated with the supported cable length when no harmonic filter is used.

For example: GD270-5R5-4 supports 50m of unshielded cable. When a 1% output reactor is configured (supporting 150m of unshielded cable), the system long cable capacity is 150m, not 50+150=200m.

Table 4-5 Output filter selection for motor cable lengths (unit: m)

| VFD power (kW) | Cable type | Maximum motor cable length (without reactor/filter) | Maximum motor cable length (with one 1% output reactor) | Maximum motor cable length (with one dv/dt filter) | Maximum motor cable length (with one sine wave filter) |
|---|---|---|---|---|---|
| 1.5–5.5 | Shielded motor cable | 25 | 100 | 230 | 500 |
| 7.5–45 | | 50 | 100 | 230 | 500 |
| 55–800 | | 75 | 100 | 230 | 500 |
| 1.5–5.5 | Non-shielded motor cable | 50 | 150 | 450 | 1000 |
| 7.5–45 | | 100 | 150 | 450 | 1000 |
| 55–800 | | 150 | 150 | 450 | 1000 |

**Note:**

✧ When one VFD drives multiple motors at the same time, you are advised to take the sum of cable lengths of all motors as the total motor cable length.

✧ Since output reactors need to be configured for 220kW–800kW VFDs, choose the GD270-220-4-L3(-EU) – GD270-800-4-L3(-EU) models.

✧ The motor cable lengths given in the table above represent the limit capacity of the VFD. In practical applications, it is recommended to design based on 80% of the motor cable lengths in the table.

### 4.3.2 Main circuit terminals

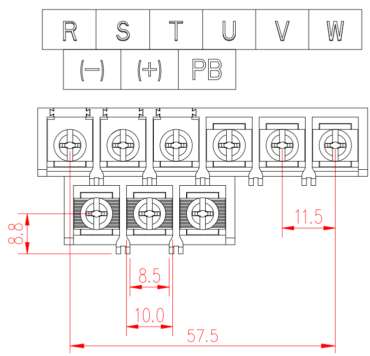



Figure 4-22 Main circuit terminals for 380V 1.5–7.5kW (unit: mm)

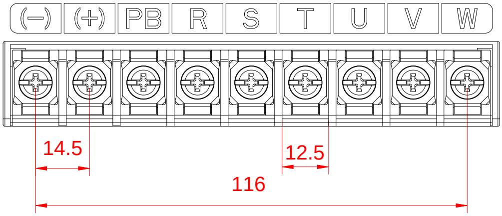



Figure 4-23 Main circuit terminals for 380V 11–15kW (unit: mm)

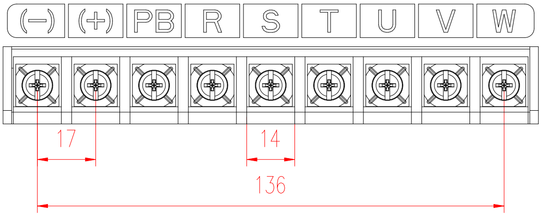



Figure 4-24 Main circuit terminals for 380V 18.5–22kW (unit: mm)

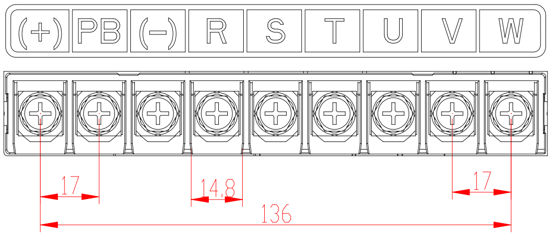



Figure 4-25 Main circuit terminals for 380V 30–37kW (unit: mm)

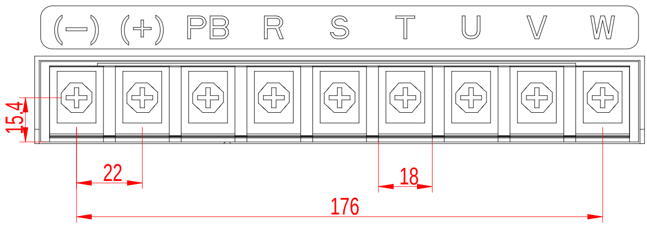



Figure 4-26 Main circuit terminals for 380V 45kW (unit: mm)

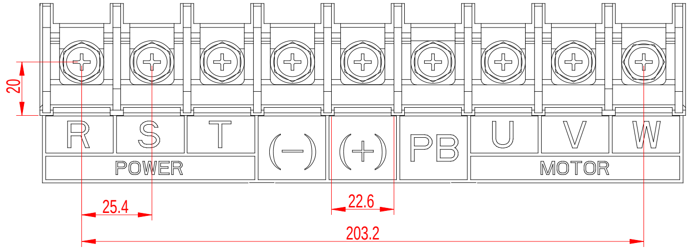



Figure 4-27 Main circuit terminals for 380V 55–90kW (unit: mm)

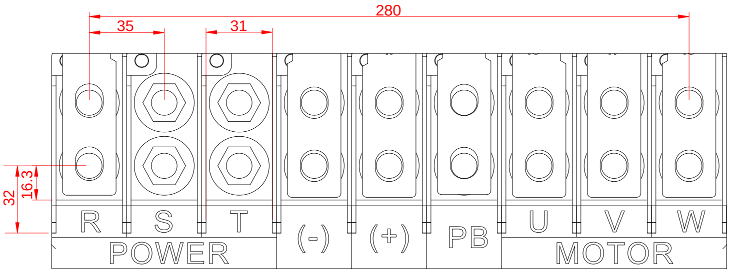



Figure 4-28 Main circuit terminals for 380V 110–132kW (unit: mm)

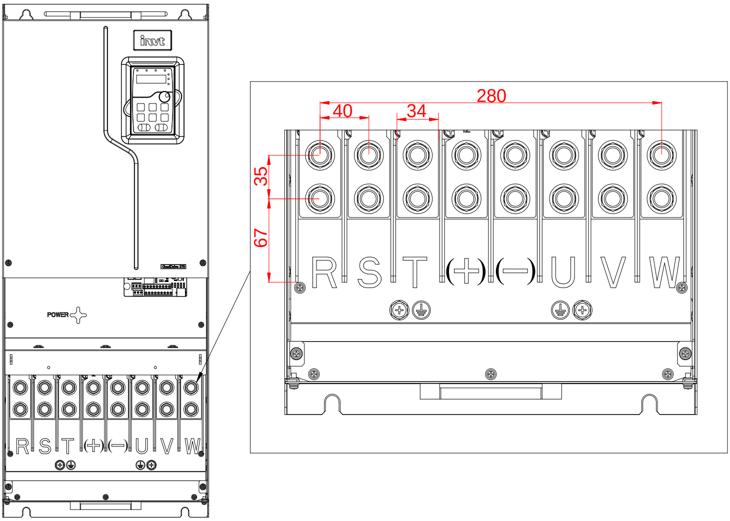



Figure 4-29 Main circuit terminals for 380V 160–200kW (unit: mm)

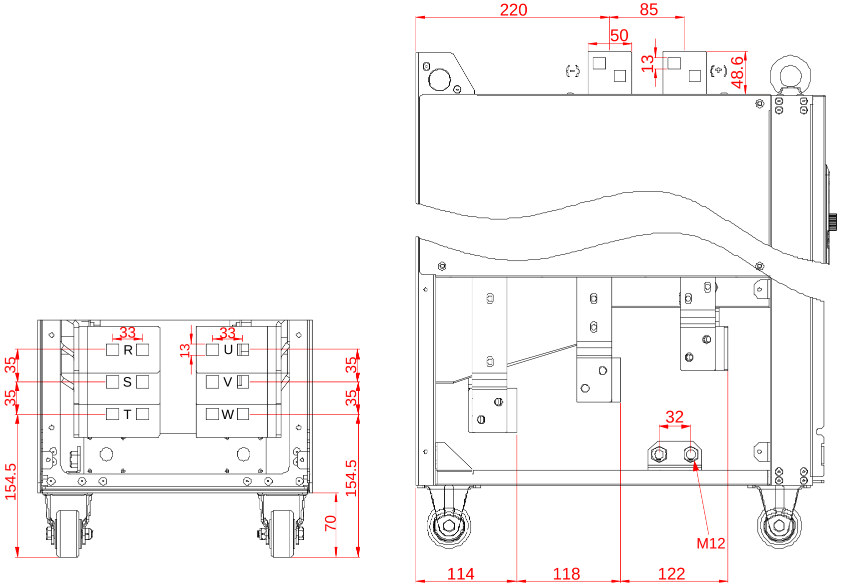
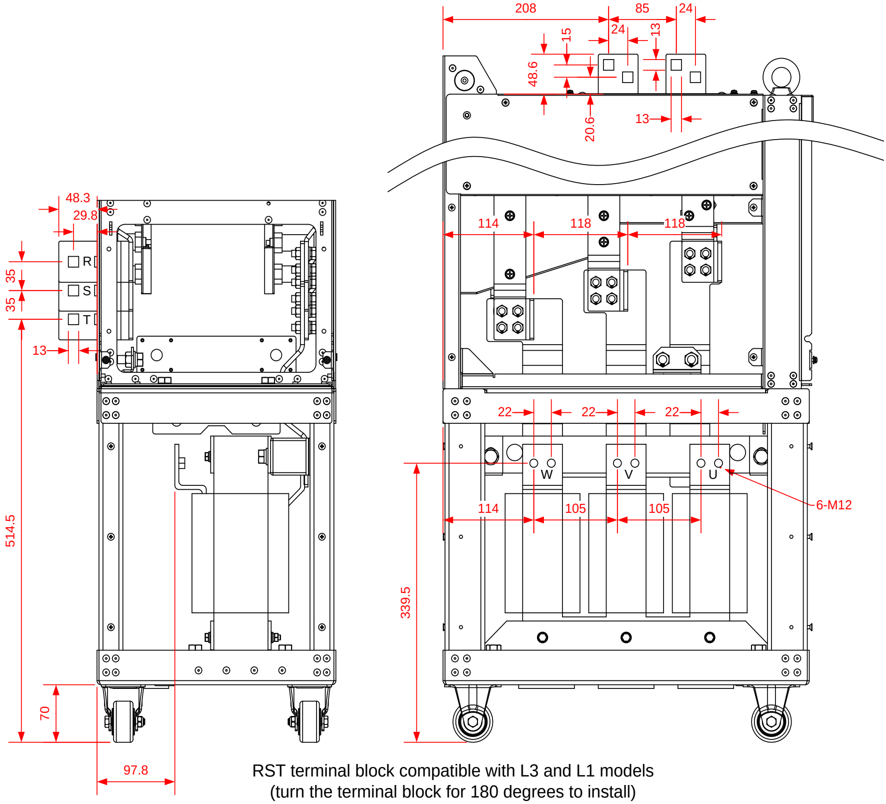



Figure 4-30 Main circuit terminal for 3PH 380V 220–250kW standard models and (-L1) models with built-in DC reactors (unit: mm)




RST terminal block compatible with L3 and L1 models
(turn the terminal block for 180 degrees to install)

Figure 4-31 Main circuit terminal for 3PH 380V 220–250kW (-L3) models with output reactors (unit: mm)

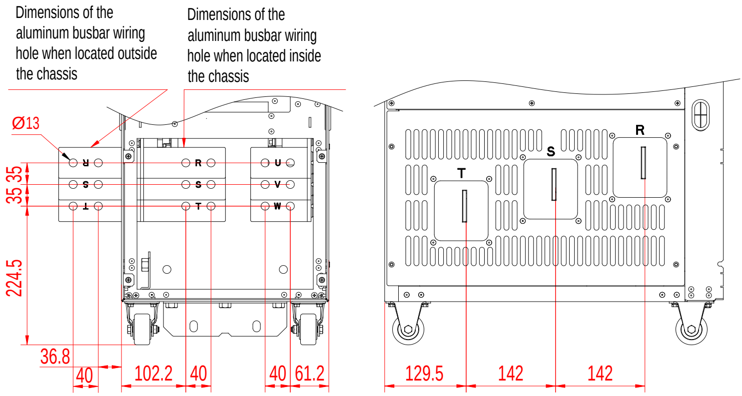



Figure 4-32 Input aluminum row mounting method for 380V 220–250kW models

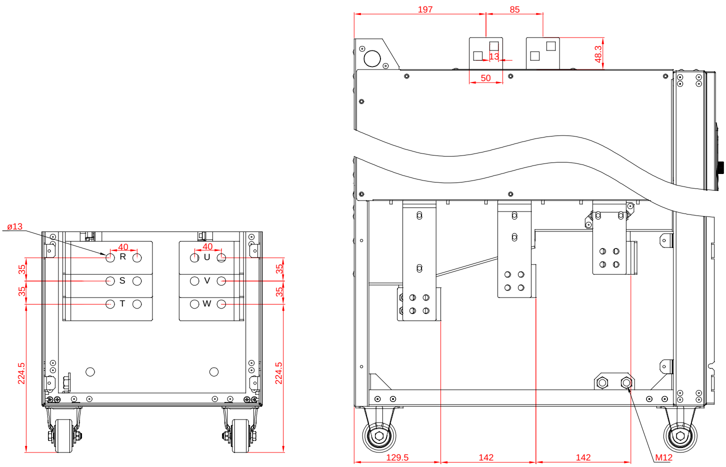
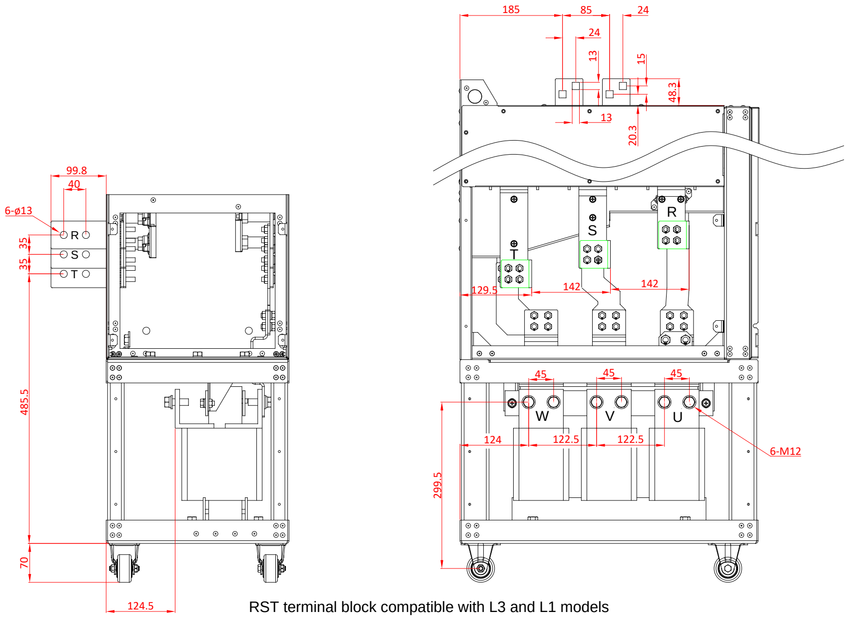



Figure 4-33 Main circuit terminal for 3PH 380V 280–355kW standard models and (-L1) models with built-in DC reactors (unit: mm)




RST terminal block compatible with L3 and L1 models
(turn the terminal block for 180 degrees to install)

Figure 4-34 Main circuit terminal for 3PH 380V 280–355kW (-L3) models with output reactors (unit: mm)

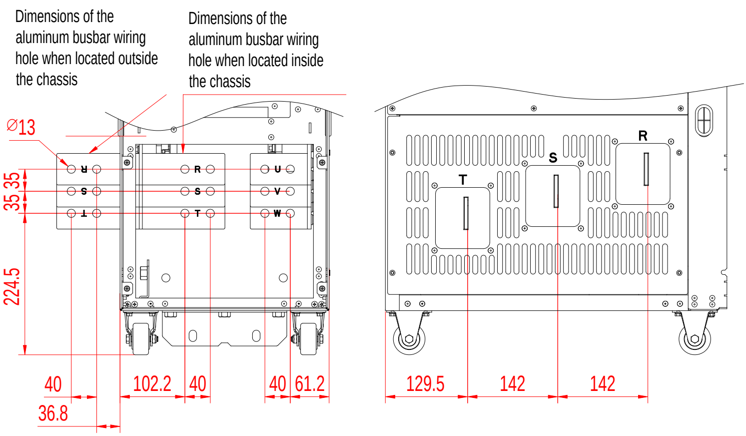



Figure 4-35 Input aluminum row mounting method for 380V 280–355kW models

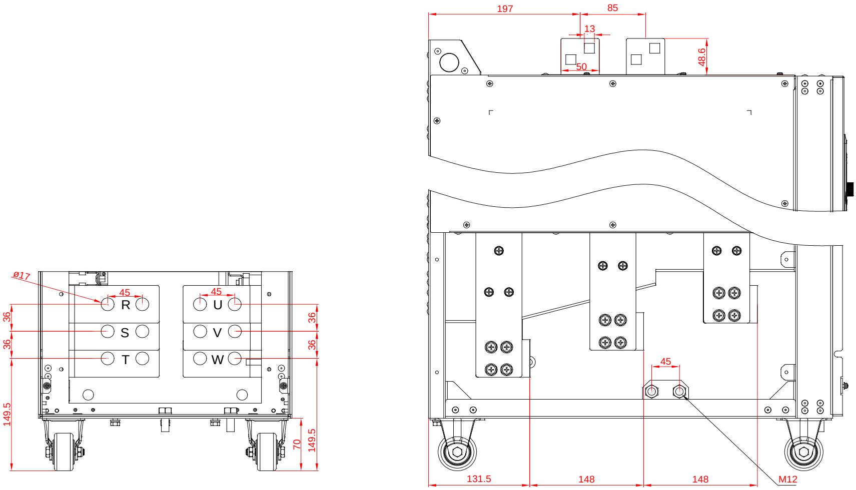
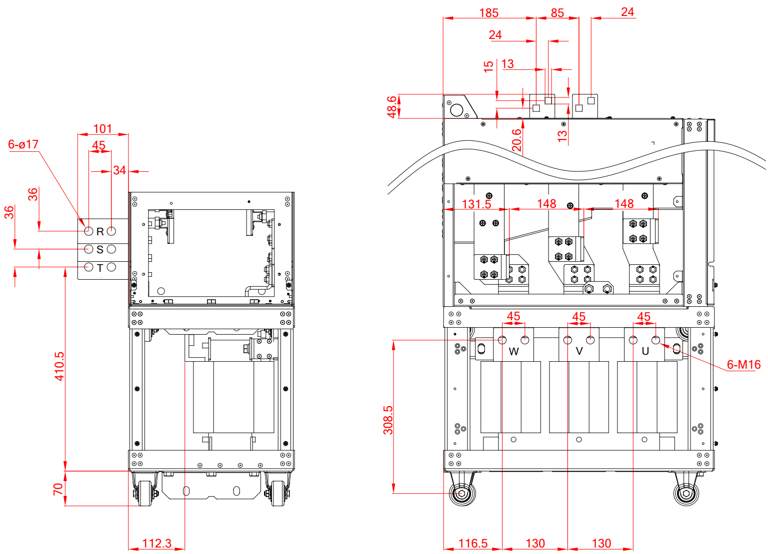



Figure 4-36 Main circuit terminal for 3PH 380V 400–500kW standard models and (-L1) models with built-in DC reactors (unit: mm)




RST terminal block compatible with L3 and L1 models
(turn the terminal block for 180 degrees to install)

Figure 4-37 Main circuit terminal for 3PH 380V 400–500kW (-L3) models with output reactors (unit: mm)

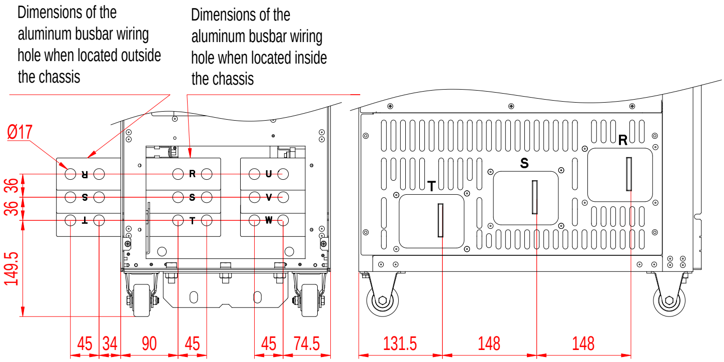



Figure 4-38 Output aluminum row mounting method for 380V 400–500kW models (unit: mm)

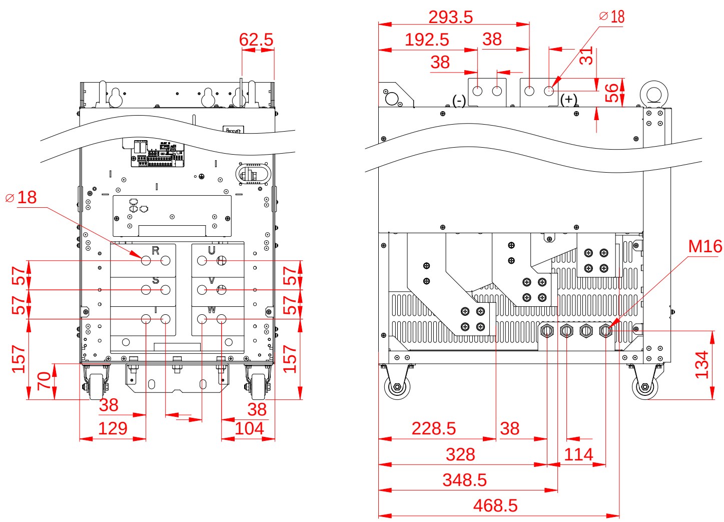



Figure 4-39 Main circuit terminal for 3PH 380V 560–630kW standard models and (-L1) models with built-in DC reactors (unit: mm)

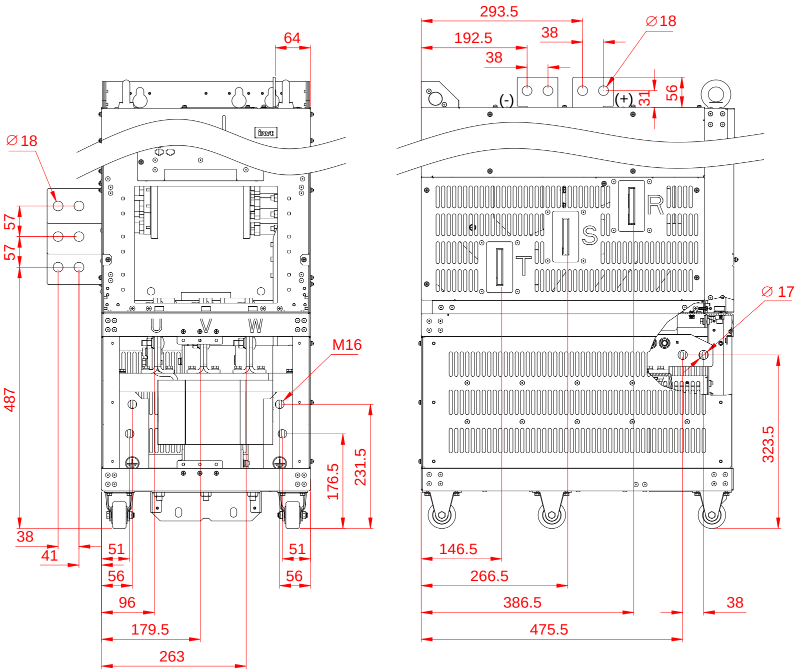



Figure 4-40 Main circuit terminal for 3PH 380V 560–630kW (-L3) models with output reactors (unit: mm)

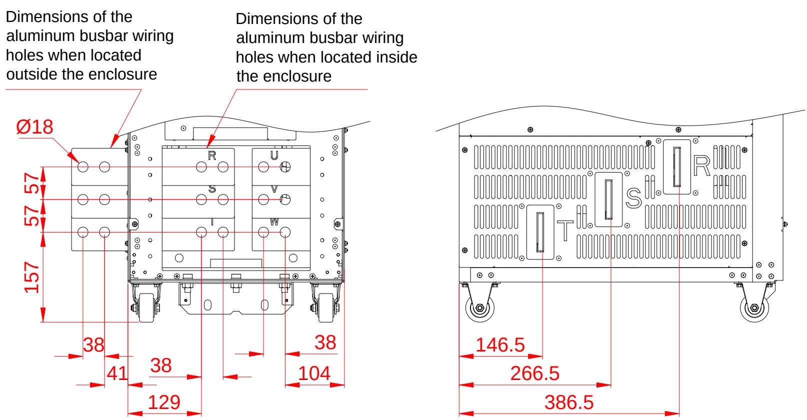



Figure 4-41 Output aluminum row mounting method for 380V 560–630kW models (unit: mm)

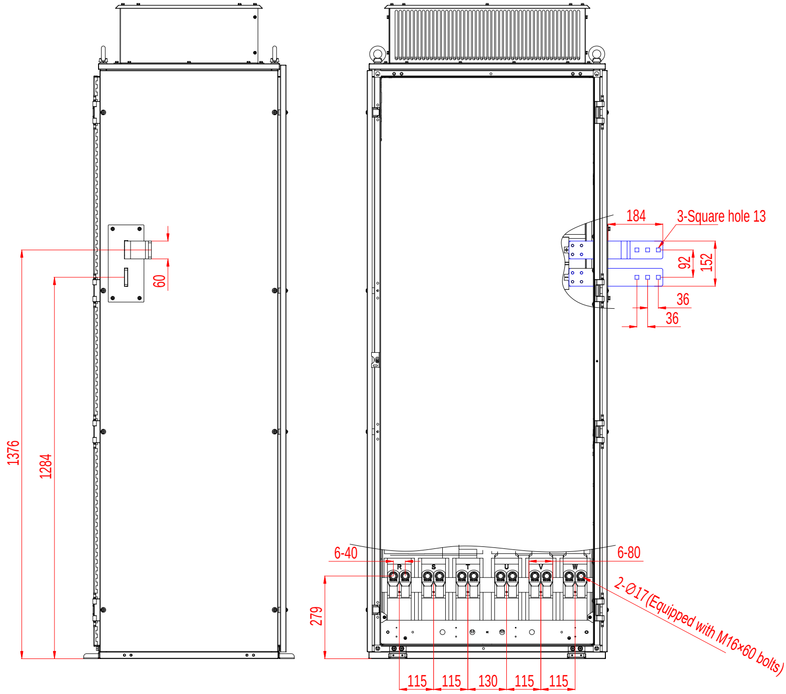



Figure 4-42 Main circuit terminal for 3PH 380V 710–800kW models (unit: mm)

Table 4-6 Terminal description

| Terminal symbol | Function description |
|---|---|
| R, S, T | 3PH AC input terminals, connected to the grid |
| U, V, W | 3PH AC output terminals, connected to the motor usually |
| (+) | (+) and (-) can share the DC bus or connect to an external DC power supply. |
| (-) | |
| PE | Grounding terminal for safe protection; each machine must carry two PE terminals and proper grounding is required |
| PB | Reserved for design only. Braking function is not available. |

**Note:**

✧ It is not recommended to use asymmetrical motor cables. If there is a symmetrical grounding conductor in the motor cable besides the conductive shielded layer, ground the grounding conductor on the inverter end and motor end.

✧ Route the motor cable, input power cable and control cable separately.

### 4.3.3 Wiring procedure for main circuit terminals

1. Connect the grounding line of the input power cable to the grounding terminal (PE) of the VFD, and connect the 3PH input cable to R, S and T terminals and tighten up.
2. Connect the ground wire of the motor cable to the PE terminal of the VFD, connect the motor 3PH cable to the U, V and W terminals, and tighten up.
3. Fasten all the cables outside the VFD mechanically if allowed.

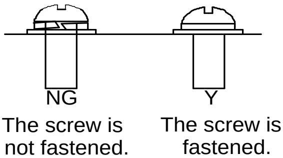



Figure 4-43 Screw installation diagram

### 4.3.4 Wiring of basic control circuit

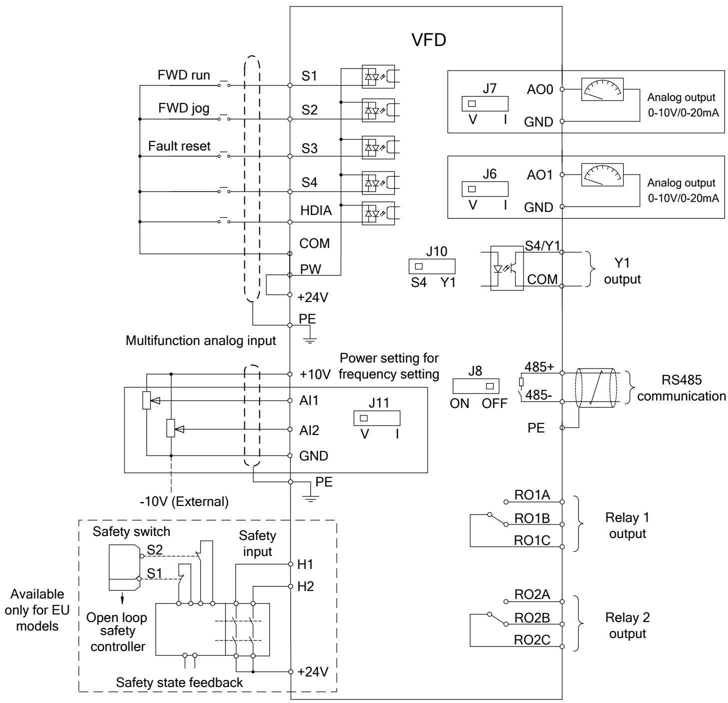



Figure 4-1 Control circuit wiring

**Note:** If wire-passing board outlet space is insufficient when all terminals on the control board are wired, cut the knock-out hole on the lower cover for wire outlet. If a dangerous situation occurs when the knock-out hole is cut for a purpose but not wire outlet, we will not bear any responsibility.

<table>
<tr><th>Terminal name</th><th colspan="2">Description</th></tr>
<tr><td>+10V</td><td colspan="2">Locally provided +10.5V power supply</td></tr>
<tr><td>AI1</td><td colspan="2" rowspan="2">Input range: For AI1, 0(2)–10V or 0(4)–20mA<br>For AI2, -10V–+10V<br>Input impedance: 20kΩ for voltage input or 250Ω for current input<br>Whether voltage or current is used for input is set through jumper J11.<br>Resolution: 5mV when 10V corresponds to 50Hz<br>Deviation: ±0.5% at 25°C, when input is above 5V/10mA</td></tr>
<tr><td>AI2</td></tr>
<tr><td>GND</td><td colspan="2">+10.5V reference ground</td></tr>
<tr><td>AO0</td><td colspan="2" rowspan="2">Output range: 0(2)–10V or 0(4)–20mA<br>Whether voltage or current is used for output of AO0 and AO1 is set through jumpers J7 and J6.<br>Error: ±0.5% when output is 5V at 25℃</td></tr>
<tr><td>AO1</td></tr>
<tr><td>RO1A</td><td colspan="2" rowspan="3">RO1 output; RO1A: NO; RO1B: NC; RO1C: common<br>Contact capacity: 3A/AC250V, 1A/DC30V</td></tr>
<tr><td>RO1B</td></tr>
<tr><td>RO1C</td></tr>
<tr><td>RO2A</td><td colspan="2" rowspan="3">RO2 output; RO2A: NO; RO2B: NC; RO2C: common<br>Contact capacity: 3A/AC250V, 1A/DC30V</td></tr>
<tr><td>RO2B</td></tr>
<tr><td>RO2C</td></tr>
<tr><td>COM</td><td colspan="2">+24V reference ground</td></tr>
<tr><td>Y1</td><td colspan="2">Switch capacity: 50mA/30V<br>Output frequency range: 0–1kHz<br>Y1 and S4 share the output terminal. The selection is made through J10.</td></tr>
<tr><td>485+</td><td colspan="2" rowspan="2">RS485 communication port, RS485 differential signal port and standard RS485 communication port must use shielded twisted pairs; the 120ohm terminal matching resistor for RS485 communication is connected through jumper J8.</td></tr>
<tr><td>485-</td></tr>
<tr><td>PE</td><td colspan="2">Grounding terminal</td></tr>
<tr><td>PW</td><td colspan="2">External power input terminal for digital input circuits<br>Voltage range: 12–30V</td></tr>
<tr><td>24V</td><td colspan="2">User power supply provided by the VFD, 24V(-10%–+15%). Max. output current: 200mA</td></tr>
<tr><td>S1</td><td>Digital input 1</td><td rowspan="4">● Internal impedance: 3.3kΩ<br>● 12–30V voltage input is acceptable<br>● Bi-direction input terminal, supporting both NPN and PNP<br>● Max. input frequency: 1kHz<br>● All are programmable digital input terminals, the functions of</td></tr>
<tr><td>S2</td><td>Digital input 2</td></tr>
<tr><td>S3</td><td>Digital input 3</td></tr>
<tr><td>S4</td><td>Digital input 4</td></tr>
</table>

<table>
<tr><th>Terminal name</th><th colspan="2">Description</th></tr>
<tr><td></td><td></td><td>which can be set through function codes<br>● S4 and Y1 share the output terminal. The selection is made through J10.</td></tr>
<tr><td>HDIA</td><td colspan="2">In addition to digital input functions, the terminal can also act as a high frequency pulse input channel.<br>Max. input frequency: 50kHz<br>Duty ratio: 30%–70%</td></tr>
<tr><td>H1</td><td colspan="2" rowspan="2">● Safe torque off (STO) inputs<br>● STO redundant input, connected to the external NC contact. When the contact opens, STO acts and the VFD stops output.<br>● Safety input signal wires use shielded wires whose length is within 25m.<br>● The H1 and H2 terminals are short connected to +24V by default. Remove the jumper from the terminals before using the STO function.<br>Note:<br>1. Only the -EU Models support safe-torque-off function.<br>2. For the 1.5-7.5kW -EU models, the extended interface SLOT1 will be occupied due to the H1/H2 terminals</td></tr>
<tr><td>H2</td></tr>
</table>

### 4.3.5 Input/output signal connection

Set NPN /PNP mode and internal/external power via U-shaped jumper. NPN internal mode is adopted by default.

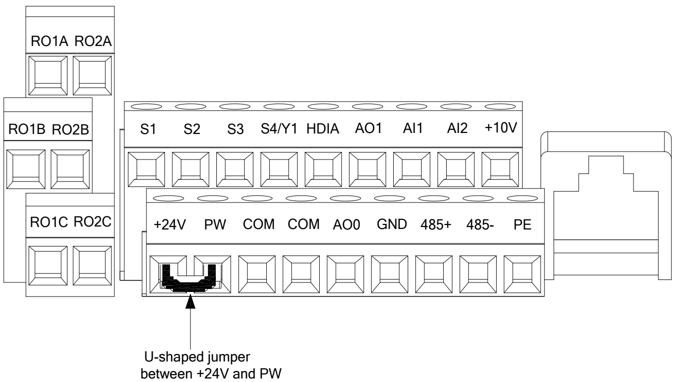



Figure 4-2 3PH 380V 1.5–7.5kW U-shaped short-circuit position

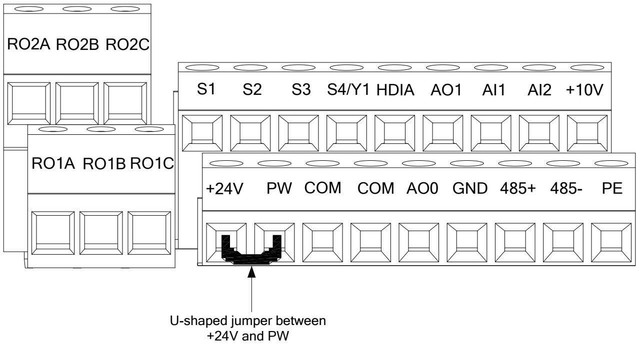



Figure 4-3 3PH 380V 11–800kW U-shaped short-circuit position

If the input signal comes from the NPN transistor, set the U-shaped jumper between +24V and PW based on the power used according to the following figure.

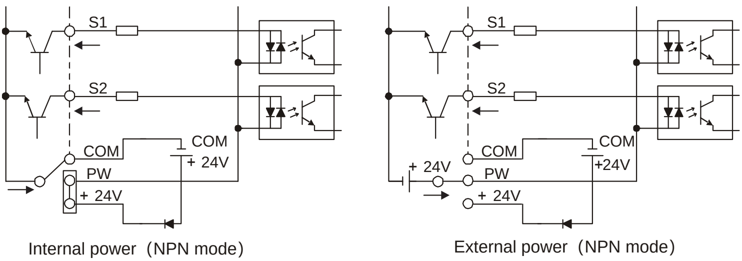



Figure 4-4 NPN mode

If the input signal comes from the PNP transistor, set the U-shaped jumper based on the power used according to the following figure.

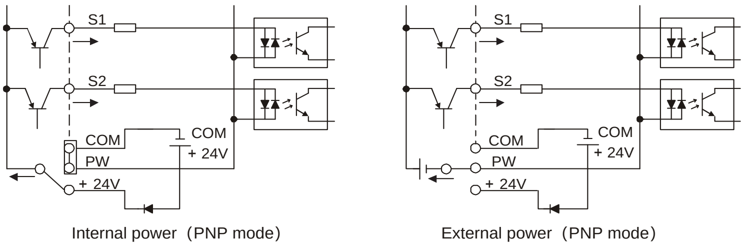



Figure 4-5 PNP mode

#### 4.3.6 External optional keypad wiring

GD270 supports optional LED keypad (BOP-270) and LCD keypad (SOP-270). Note the following when externally connecting an optional keypad:

✧ The 1.5–22kW models use the film keypad design, which allows you to connect an external optional LED or LCD keypad to the electrical cabinet through the keypad interface A. With connection to an external keypad, the VFD support display and operation on both the local film keypad and external keypad.

✧ The 30kW and higher models are configured with independent keypads as standard parts. Before delivery, the local keypad of any of these models has been connected to the keypad interface B by default. If you want to move the keypad from the local to the electrical cabinet, to ease wiring, disconnect the default keypad wiring and connect the keypad through the keypad interface A. Keypad interfaces A and B cannot be connected at the same time. Otherwise, the keypad fails to operate or display properly.

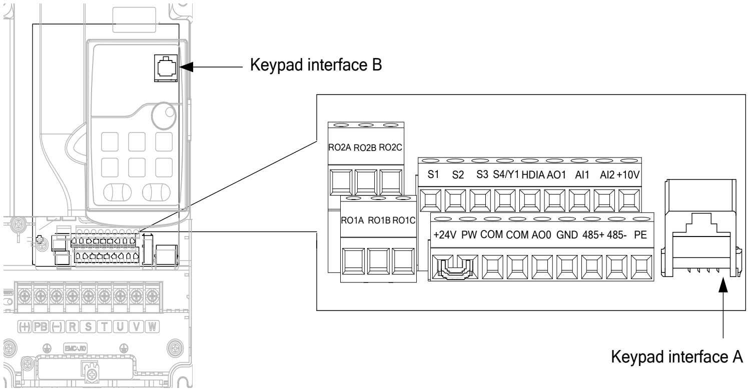



Figure 4-6 External keypad interface

#### 4.3.7 Wiring protection

**1. Protecting the VFD and input power cable in case of short circuit**

The VFD and input power cable can be protected in case of short circuit, avoiding thermal overload. Carry out protective measures according to the following figure.

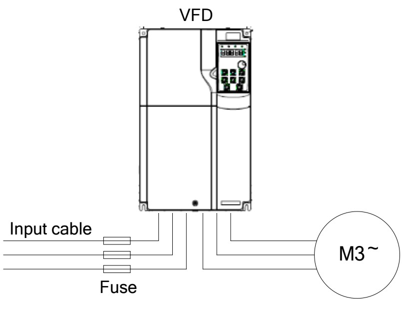



Figure 4-7 Fuse configuration

**Note:** Select the fuse according to the manual. In case of short circuit, the fuse protects input power cables to avoid damage to the VFD; if internal short-circuit occurs to the VFD, it can protect neighboring equipment from being damaged.

**2. Protecting the motor and motor cable in case of short circuit**

If the motor cable is selected based on VFD rated current, the VFD is able to protect the motor cable and motor during short circuit without other protective devices.

| | |
|---|---|
| | If the VFD is connected to multiple motors, use a separated thermal overload switch or breaker to protect the cable and motor, which may require the fuse to cut off the short circuit current. |

**3. Protecting the motor against thermal overload**

The motor must be protected against thermal overload. Once overload is detected, current must be cut off. The VFD is equipped with the motor thermal overload protection function, which can block output and cut off the current (if necessary) to protect the motor.

**4. Bypass connection**

In some critical scenarios, the power/variable frequency conversion circuit needs to be configured to ensure proper operation of the system when a fault occurs to the VFD.

In some special scenarios, such as in soft startup, power-frequency running is directly performed after the startup, which requires bypass connection.

| | |
|---|---|
| | Do not connect any power source to the VFD output terminals U, V, and W. The voltage applied to the motor cable may cause permanent damage to the VFD. |

If frequent switchover is needed, you can use the switch which carries mechanical interlock or a contactor to ensure motor terminals are not connected to input power cables and VFD output ends simultaneously.

# 5 Basic operation guidelines

## 5.1 What this chapter contains

This chapter instructs you how to use the VFD keypad and commission the VFD common functions.

## 5.2 Operation procedure

The VFD is equipped with a LED keypad as a standard configuration part. You can use the keypad to control the start and stop, read status data, and set parameters of the VFD. You can also choose a LCD keypad. The LCD keypad supports multi-language display, parameter copying function, and 10-line high-definition display. Its overall size is the same as the LED keypad.


Figure 5-1 LED keypad


Figure 5-2 Film keypad


Figure 5-3 LCD keypad (optional)

**Note:**

✧ The 1.5–22kW VFDs are equipped with film keypads as standard configuration. If you need an external keypad and bracket, please purchase them separately.

✧ The 30–800kW VFDs come standard with a LED keypad that can be externally led. If you need to do so, you only need to purchase the optional bracket.

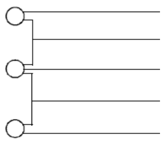
## 5.3 LED keypad (BOP-270) display and operation

The VFD keypad can display the stopped-state parameters, running-state parameters, function parameter editing status, and fault alarm status.

You can operate the VFD by using the keypad. For details about function code descriptions, see the function code list.

Table 5-1 LED keypad (BOP-270) component description

| No. | Name | Description | |
|---|---|---|---|
| 1 | Status indicator | RUN/TUNE | VFD operation status indicator<br>Off: The VFD is stopped. |

<table>
<tr><th>No.</th><th>Name</th><th colspan="4">Description</th></tr>
<tr><td rowspan="4"></td><td rowspan="4"></td><td colspan="2"></td><td colspan="2">Blinking: The VFD is in parameter autotuning<br>On: The VFD is running.</td></tr>
<tr><td colspan="2">FWD/REV</td><td colspan="2">Forward or reverse running indicator<br>Off: The VFD is running forward.<br>On: The VFD is running.</td></tr>
<tr><td colspan="2">LOCAL/REMOT</td><td colspan="2">Indicates whether the VFD is controlled through the keypad, terminals, or communication.<br>Off: The VFD is controlled through the keypad.<br>Blinking: The VFD is controlled through terminals.<br>On: The VFD is controlled remotely.</td></tr>
<tr><td colspan="2">TRIP</td><td colspan="2">Fault indicator<br>Off: The VFD is in normal state.<br>Blinking: The VFD is in pre-alarm state.<br>On: The VFD is in fault state.</td></tr>
<tr><td rowspan="6">2</td><td rowspan="6">Unit indicator</td><td colspan="4">Unit displayed currently</td></tr>
<tr><td colspan="2" rowspan="5"></td><td>Hz</td><td>Frequency unit</td></tr>
<tr><td>RPM</td><td>Rotation speed unit</td></tr>
<tr><td>A</td><td>Current unit</td></tr>
<tr><td>%</td><td>Percentage</td></tr>
<tr><td>V</td><td>Voltage unit</td></tr>
<tr><td>3</td><td>Digital display zone</td><td colspan="4">Five-digit LED displays various monitoring data and alarm codes such as the frequency setting and output frequency.
<table>
<tr><th>Display</th><th>Means</th><th>Display</th><th>Means</th><th>Display</th><th>Means</th></tr>
<tr><td>0</td><td>0</td><td>1</td><td>1</td><td>2</td><td>2</td></tr>
<tr><td>3</td><td>3</td><td>4</td><td>4</td><td>5</td><td>5</td></tr>
<tr><td>6</td><td>6</td><td>7</td><td>7</td><td>8</td><td>8</td></tr>
<tr><td>9</td><td>9</td><td>A</td><td>A</td><td>b</td><td>b</td></tr>
<tr><td>C</td><td>C</td><td>d</td><td>d</td><td>E</td><td>E</td></tr>
<tr><td>F</td><td>F</td><td>H</td><td>H</td><td>I</td><td>I</td></tr>
<tr><td>L</td><td>L</td><td>N</td><td>N</td><td>n</td><td>n</td></tr>
<tr><td>o</td><td>O</td><td>P</td><td>P</td><td>r</td><td>r</td></tr>
<tr><td>S</td><td>S</td><td>t</td><td>t</td><td>U</td><td>U</td></tr>
<tr><td>v</td><td>v</td><td>.</td><td>.</td><td>-</td><td>-</td></tr>
</table></td></tr>
<tr><td>4</td><td>Digital potentiometer</td><td colspan="4">Used for frequency regulation. For details, see the description of P08.42.</td></tr>
<tr><td>5</td><td>Keys</td><td></td><td>Programming key</td><td colspan="2">Press it to enter or exit level-1 menus or delete a parameter.</td></tr>
</table>

| No. | Name | Description | | |
|---|---|---|---|---|
| | |  | Confirmation key | Press it to enter menus in cascading mode or confirm the setting of a parameter. |
| | |  | UP key | Press it to increase data or move upward. |
| | |  | Down key | Press it to decrease data or move downward. |
| | |  | Right-shifting key | Press it to select display parameters rightward in the interface for the product in stopped or running state or to select digits to change during parameter setting. |
| | |  | Run key | Press it to run the product when using the keypad for control. |
| | |  | Stop/Reset key | Press it to stop the VFD that is running. The function of this key is restricted by P07.04. In fault alarm state, this key can be used for reset in any control modes. |
| | |  | Multifunction shortcut key | The function of this key is determined by the ones place of P07.02. |

### 5.3.1 Displaying stopped-state parameters

When the VFD is in stopped state, the keypad displays stopped-state parameters, as shown in Figure 5-4.

In the stopped state, various kinds of parameters can be displayed. You can determine which parameters are displayed in stopped state by setting function code P07.07. For details, see the description of P07.07.

In stopped state, there are 15 parameters that can be selected for display, including the set frequency, bus voltage, PID reference value, PID feedback value, input terminal status, output terminal status, torque setting, PLC and the present step of multi-step speed, AI1 value, AI2 value, AI3 value, high-speed pulse HDI frequency, pulse counting value, length value, and upper limit frequency (Hz on). You can press 》/SHIFT to shift selected parameters from left to right or press QUICK/JOG (when ones place of P07.02=2) to shift selected parameters from right to left.

### 5.3.2 Displaying running-state parameters

After receiving a valid running command, the VFD enters the running state, and the keypad displays running-state parameters, with the RUN/TUNE indicator on. The on/off state of the FWD/REV indicator is determined by the actual running direction. It is shown as Figure 5-4.

In running state, there are 25 parameters that can be selected for display, including the running frequency, set frequency, bus voltage, output voltage, output current, running speed, output power, output torque, PID reference value, PID feedback value, input terminal status, output terminal status, torque setting, length value, PLC and the current step of multi-step speed, AI1, AI2, AI3, high-speed pulse HDI frequency, motor overload percentage, VFD overload percentage, ramp reference value, linear speed, AC input current, and upper limit frequency (Hz on). You can determine which parameters are displayed in stopped state by setting function codes P07.05 and P07.06. You can press 》/SHIFT to shift selected parameters from left to right or press QUICK/JOG (when ones place of P07.02=2) to shift selected parameters from right to left.

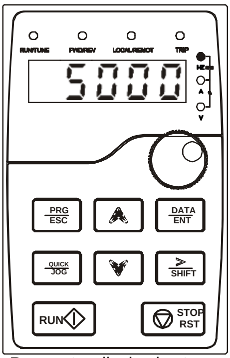
### 5.3.3 Displaying fault alarms

After detecting a fault signal, the VFD enters the fault alarm state immediately, the fault code blinks on the keypad, and the TRIP indicator is on. You can perform fault reset by using the STOP/RST key, control terminals, or communication commands.

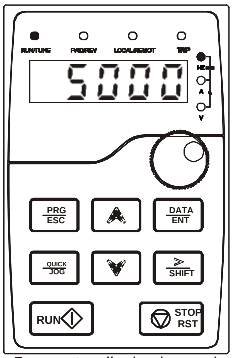
If the fault persists, the fault code is continuously displayed.

### 5.3.4 Editing function codes

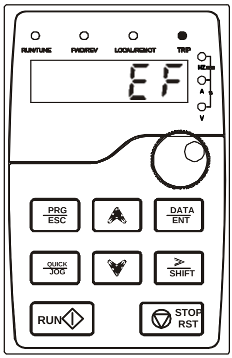
You can press the PRG/ESC key to enter the editing mode in stopped, running, or fault alarm state (if a user password is used, see the description of P07.00). The editing mode contains two levels of menus in the following sequence: Function code group or function code number → Function code setting. You can press the DATA/ENT key to enter the function parameter display interface. In the function parameter display interface, you can press the DATA/ENT key to save parameter settings or press the PRG/ESC key to exit the parameter display interface.




Parameter display in stopped state




Parameter display in running state




Fault display

Figure 5-4 State display

### 5.3.5 Modifying function codes

The VFD provides three levels of menus, including:

- ✧ Function code group number (level-1 menu)
- ✧ Function code number (level-2 menu)
- ✧ Function code setting (level-3 menu)

**Note:** When performing operations on the level-3 menu, you can press the PRG/ESC or DATA/ENT key to return to the level-2 menu. If you press the DATA/ENT key, the set value of the parameter is saved to the control board first, and then the level-2 menu is returned, displaying the next function code. If you press the PRG/ESC key, the level-2 menu is returned directly, without saving the set value of the parameter, and the current function code is displayed.

If you enter the level-3 menu but the parameter does not have a digit blinking, the parameter cannot be modified due to either of the following reasons:

- ✧ It is read only. Read-only parameters include actual detection parameters and running record parameters.
- ✧ It cannot be modified in running state and can be modified only in stopped state.

Example: Change the value of P00.01 from 0 to 1.

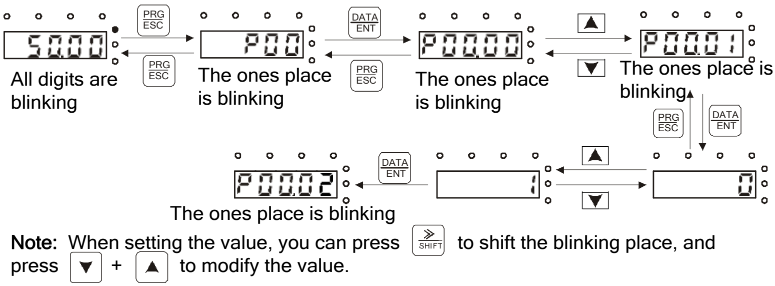



Figure 5-5 Modifying a parameter

### 5.3.6 Setting a password for the VFD

The VFD provides the user password protection function. When P07.00 is set to a non-zero value, the value is the user password. To disable the password protection function, you only need to set P07.00 to 0.

After you exit the function code editing interface, the password protection function is enabled within 1 minute. If password protection is enabled, "0.0.0.0.0" is displayed when you press the PRG/ESC key again to enter the function code editing interface. You need to enter the correct user password to enter the interface.

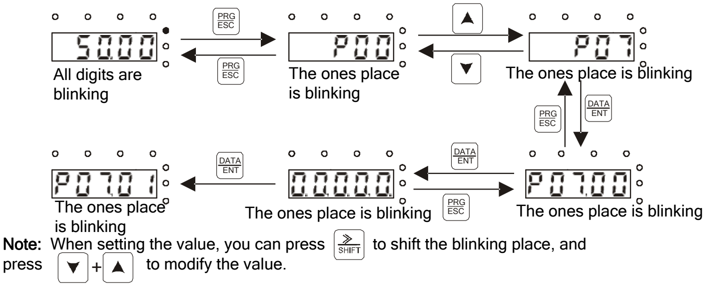



Figure 5-6 Setting a password

### 5.3.7 Viewing VFD status

The VFD provides group P17 for status viewing. You can enter group P17 for viewing.

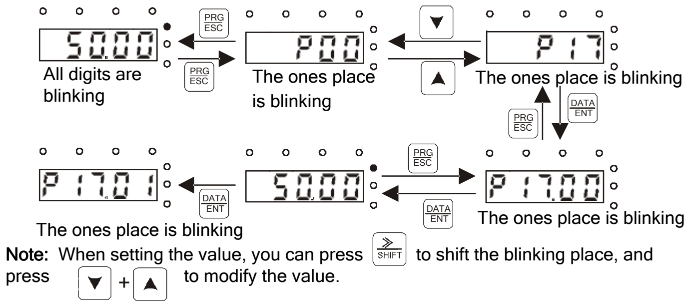
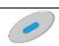
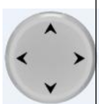
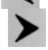



Figure 5-7 Viewing a parameter

## 5.4 LCD keypad (SOP-270) display and operation

Table 5-2 LCD keypad (SOP-270) component description

| No. | Name | Description | | |
|---|---|---|---|---|
| 1 | Status indicator | RUN | | Run indicator<br>Off: The VFD is stopped.<br>Blinking: The VFD is in parameter autotuning.<br>On: The VFD is running. |
| | | TRIP | | Fault indicator<br>Off: The VFD is in normal state.<br>Blinking: The VFD is in pre-alarm state.<br>On: The VFD is in fault state. |
| | | QUICK/JOG | | Short-cut key indicator, which displays different state under different functions, see definition of QUICK/JOG key for details. |
| 2 | Keys |  | Function key | The function of function key varies with the |

| No. | Name | Description | | |
|---|---|---|---|---|
| | | <br> | | menu.<br>The function of function key is displayed in the footer. |
| | |  | Short-cut key | Re-definable. It is defined as JOG function by default, namely jogging. The function of short-cut key can be set by the ones place of P07.02, as shown in the following:<br>0: No function<br>1: Jogging (linkage indicator (3); logic : NO)<br>2: Reserved<br>3: FWD/REV switch-over (linkage indicator (3); logic: NC)<br>4: Clear the UP/DOWN setting (linkage indicator (3) logic: NC)<br>5: Coast to stop (linkage indicator (3); logic : NC)<br>6: Switch command channels in sequence (linkage indicator (3); logic: NC)<br>7: Reserved<br>**Note:** After restoring to default values, the default function of short-cut key is 1. |
| | |  | Confirmation key | The function of confirmation key varies with menus, such as confirming parameter setup, confirming parameter selection, and entering the next menu. |
| | |  | Run key | Under keypad operation mode, the running key is used for running operation or autotuning operation. |
| | |  | Stop/Reset key | Press it to stop the VFD that is running or autotuning. The function of this key is restricted by P07.04. In fault alarm state, this key can be used for reset in any control modes. |
| | |  | Direction key<br>UP: <br>DOWN: <br>LEFT: <br>RIGHT:  | UP: The function of UP key varies with interfaces, such as shifting up the displayed item, shifting up the selected item, and changing digits;<br>DOWN: The function of DOWN key varies with interfaces, such as shifting down the displayed item, shifting down the selected item, changing digits;<br>Left: The Left key function varies with interfaces, |

| No. | Name | Description | | |
|---|---|---|---|---|
| | | | | such as switch over the monitoring interface, such as shifting the cursor leftward, exiting current menu and returning to previous menu.<br>RIGHT: The function of RIGHT key varies with interfaces, such as switch over the monitoring interface, shifting the cursor rightward, enter the next menu etc. |
| 3 | Display area | LCD screen | Display screen | 240×160 dot-matrix LCD; display three monitoring parameters or six sub-menu items simultaneously. |
| 4 | Other | RJ45 interface | RJ45 interface | RJ45 interface is used to connect to the VFD. |
| | | Battery cover | Clock battery cover | Remove this cover when replacing or installing clock battery, and close the cover after battery is installed. |
| | | USB terminal | Mini USB terminal | Mini USB terminal is used to connect to the USB flash drive through an adapter. |

The LCD has different display areas, which displays different contents under different interfaces. The following figure is the main interface of stop state.

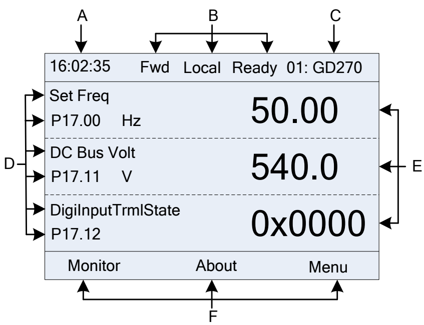



Figure 5-8 LCD main interface

| Area | Name | Display |
|---|---|---|
| Header A | Real-time display area | Display the real-time; clock battery is not included; the time needs to be reset when powering on the VFD |
| Header B | VFD running state display area | Display the running state of the VFD:<br>Display motor rotating direction: "Forward" – Run forward during operation; Reverse – Run reversely during operation; "Forbid" – Reverse running is forbidden; |

| Area | Name | Display |
|---|---|---|
| | | Display VFD running command channel: "Local" – Keypad; "Terminal" – Terminal; "Remote" - Communication;<br>Display current running state of the VFD : "Ready" – The VFD is in stop state (no fault); "Run" – The VFD is in running state; "Jog" – The VFD is in jogging state; "Pre-alarm" – the VFD is under pre-alarm state during running; "Fault" – VFD fault occurred. |
| Header C | VFD station No. and model display area | Display VFD station No.: 01–99, applied in multi-drive applications (reserved function);<br>VFD model display: "GD270" – current VFD is GD270 series VFD. |
| Display D | The parameter name and function code monitored by the VFD | Display the parameter name and corresponding function code monitored by the VFD; three monitoring parameters can be displayed simultaneously. The monitoring parameter list can be edited. |
| Display E | Parameter value monitored by the VFD | Display the parameter value monitoring by the VFD, the monitoring value will be refreshed in real time |
| Footer F | Corresponding menu of function key | The corresponding menu of the function key varies with interfaces, and the content in this area also varies. |

The VFD keypad can display the stopped-state parameters, running-state parameters, function parameter editing status, and fault alarm status.

### 5.4.1 Displaying stopped-state parameters

When the VFD is in stopped state, the keypad displays stopped-state parameters, and this interface is the main interface during power-on by default. Under stop state, parameters in various states can be displayed. Press or to shift the displayed parameter up or down.

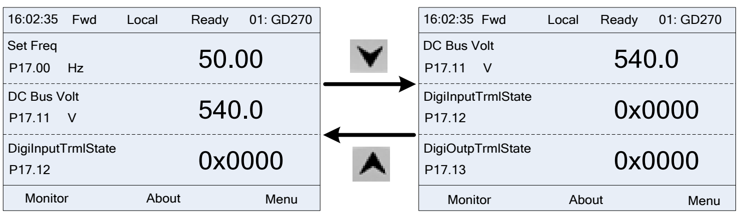



Figure 5-9 Stopped-state parameter display 1

Press or to switch between different display styles, including list display style and progress bar display style.

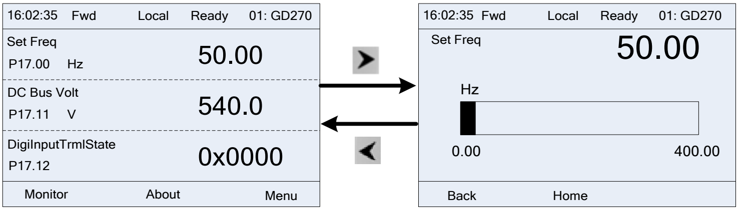



Figure 5-10 Stopped-state parameter display 2

The stopped-state parameter display list is user defined, and each state variable function code can be added to the list as needed. The state variable which has been added to the list can also be deleted or shifted.

### 5.4.2 Displaying running-state parameters

After receiving valid running command, the VFD will enter running state, and the keypad displays running state parameter with RUN indicator on the keypad turning on. Under running state, multiple kinds of state parameters can be displayed. Press or to shift up or down.

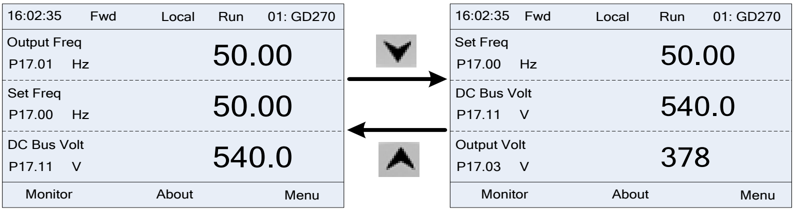



Figure 5-11 Running-state parameter display 1

Press or to switch between different display styles, including list display style and progress bar display style.

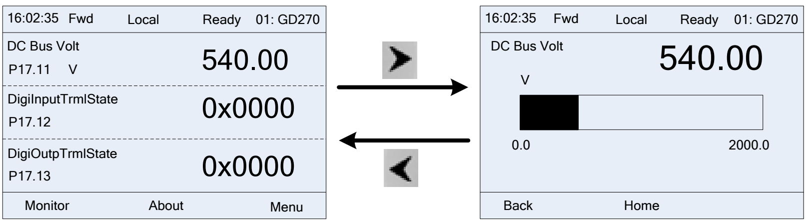



Figure 5-12 Running-state parameter display 2

Under running state, multiple kinds of state parameters can be displayed. The running display parameter list is user defined, and each state variable function code can be added to the running display parameter list as needed. The state variable which has been added to the running display parameter list can also be deleted or shifted.

### 5.4.3 Displaying fault alarms

The VFD enters the fault alarm display state once fault signal is detected, and the keypad displays fault code and fault information with TRIP indicator on the keypad turning on. You can perform fault reset by using the STOP/RST key, control terminals, or communication commands.

If the fault persists, the fault code is continuously displayed.

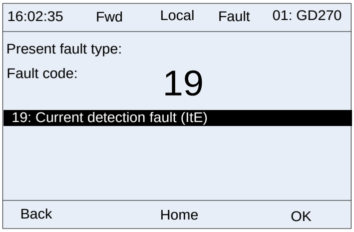



Figure 5-13 Fault alarm display

Various operations can be performed on the VFD, including entering/exiting menu, parameter selection, list modification and parameter addition.

### 5.4.4 Enter/exit menu

Regarding the monitoring menu, the operation relation between entering and exiting is shown as follows.

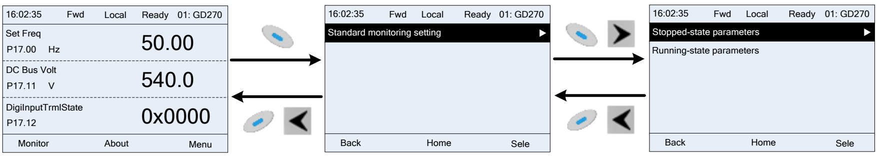



Figure 5-14 Entering/exiting different menus 1

The following figure shows how to enter or exit different menus step by step.

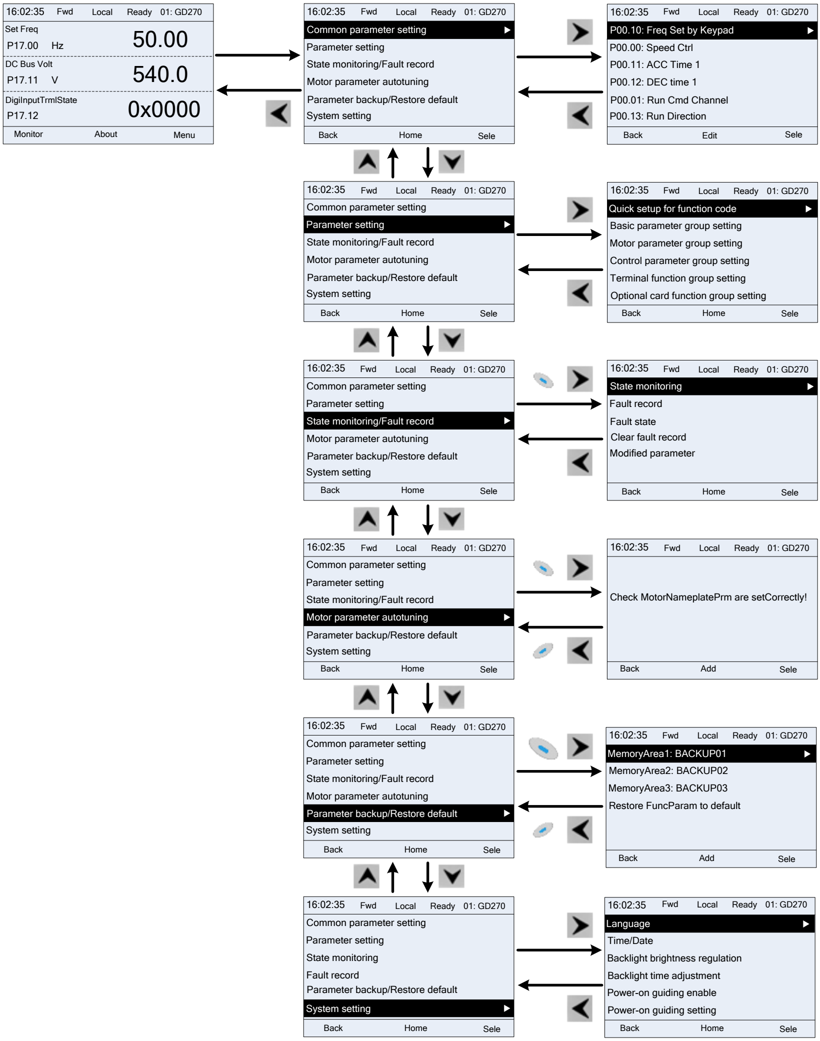



Figure 5-15 Entering/exiting different menus 2

The keypad menu setup is shown as follows:

| Level 1 | Level 2 | Level 3 | Level 4 |
|---|---|---|---|
| Common parameter setup | / | / | P00.10: Setting frequency through keypad |
| | | | P00.00: Speed control mode |
| | | | Pxx.xx: xx |
| Parameter setting | Quick setup for function code | / | Pxx.xx |
| | Basic parameter group setup | P00: Basic functions | P00.xx |
| | | P07: Human-machine interface | P07.xx |
| | | P08: Enhanced functions | P08.xx |
| | | P11: Protection parameters | P11.xx |
| | | P14: Serial communication function group | P14.xx |
| | | P99: Reserved | P99.xx |
| | Motor parameter group setup | P02: Motor 1 parameters | P02.xx |
| | | P12: Motor 2 parameters | P12.xx |
| | | P20: Reserved | P20.xx |
| | | P24: Reserved | P24.xx |
| | Control parameter group setup | P01: Start and stop control | P01.xx |
| | | P03: Vector control of motor 1 | P03.xx |
| | | P04: V/F control | P04.xx |
| | | P09: PID control | P09.xx |
| | | P10: Simple PLC and multi-step speed control | P10.xx |
| | | P13: SM control parameters | P13.xx |
| | | P21: Reserved | P21.xx |
| | | P22: Reserved | P22.xx |
| | | P23: Vector control of motor 2 | P23.xx |
| | Terminal function group setup | P05: Input terminal functions | P05.xx |
| | | P06: Output terminal functions | P06.xx |
| | | P98: Reserved | P98.xx |
| | Optional card function group setup | P15: Communication expansion card 1 functions | P15.xx |
| | | P16: Communication expansion card 2 functions | P16.xx |
| | | P25: Expansion I/O card input functions | P25.xx |
| | | P26: Expansion I/O card output functions | P26.xx |
| | | P27: Reserved | P27.xx |
| | | P28: Master/slave control | P28.xx |
| | Factory-defined control function group setup | P90: PID control 1 | P90.xx |
| | | P91: PID control 2 | P91.xx |
| | | 92: Real-time clock and timer (available at use of LCD keypad) | P92.xx |

| Level 1 | Level 2 | Level 3 | Level 4 |
|---|---|---|---|
| | | P93: Fire control | P93.xx |
| State monitoring/fault record | State monitoring | P07: Human-machine interface | P07.xx |
| | | P17: Status viewing functions | P17.xx |
| | | P18: Reserved | P18.xx |
| | | P19: Status viewing functions of expansion card | P19.xx |
| | Fault record | / | P07.27: Type of present fault |
| | | | P07.28: Type of the last fault |
| | | | P07.29: Type of the 2nd-last fault |
| | | | P07.30: Type of the 3rd-last fault |
| | | | P07.31: Type of the 4th-last fault |
| | | | P07.32: Type of the 5th-last fault |
| | Fault state | / | P07.33: Running frequency at present fault |
| | | | P07.34: Ramp frequency at present fault |
| | | | P07.xx: xx state of the last but xx fault |
| | Clear fault records | / | Are you sure to clear fault history? |
| | Modified parameter | / | Pxx.xx has modified parameter 1 |
| | | | Pxx.xx has modified parameter 2 |
| | | | Pxx.xx has modified parameter xx |
| Motor parameter autotuning | / | / | Dynamic autotuning 1 |
| | | | Complete parameter static autotuning |
| | | | Partial parameter static autotuning 1 |
| | | | Dynamic autotuning 2 |
| | | | Partial parameter static autotuning 2 |
| Parameter backup/restore default value | / | Operate the storage area 1: BACKUP01 | Upload parameters from the local address to the keypad |
| | | | Download all param from keypad |
| | | | Download non motor param from keypad |
| | | | Download motor param from keypad |
| | | Memory area 2: BACKUP02 | / |
| | | Memory area 3: BACKUP03 | / |
| | | Restore function parameter to default | Are you sure to restore function |

| Level 1 | Level 2 | Level 3 | Level 4 |
|---|---|---|---|
| | | value | parameters to default value? |
| System setting | / | / | Language selection |
| | | | Time/date |
| | | | Backlight brightness regulation |
| | | | Backlight time adjustment |
| | | | Power-on guiding enable |
| | | | Power-on guiding settings |
| | | | Keypad burning selection |
| | | | Enable fault time |
| | | | Control board burning selection |

### 5.4.5 Editing list

The parameters in the parameter list in stopped state can be added as needed (through the menu of user defined home parameters), and the list can also be edited such as "Move up", "Move down", "Delete from the list", and "Restore default". The edit function is shown in the following.

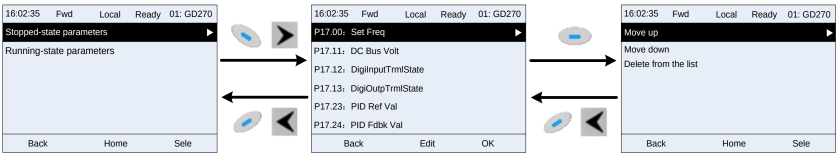



Figure 5-16 Editing list 1

Press key to enter edit interface, select the operation needed, and press the key, key or key to confirm the edit operation and return to the previous menu (parameter list), the returned list is the list edited. If the key or key is pressed in edit interface without selectingan edit operation, it will return to the previous menu (parameter list remain unchanged).

**Note:** For the parameter objects in the list header, move-up operation will be invalid, and the same principle can be applied to the parameter objects in the list footer; after deleting a certain parameter, the parameter objects under it will be moved up automatically.

The items in the parameter list in running state can be added as needed (through the menu of user defined home parameters), and the list can also be edited such as "Place top", "Move up", "Move down", "Delete from the list", and "Restore default parameters". The edit function is shown in the interface below.

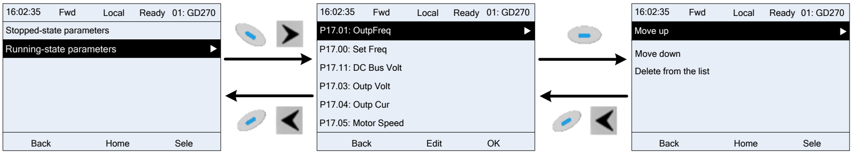



Figure 5-17 Editing list 2

The parameters of user defined parameter setting can be added, deleted or adjusted as needed, such as "Place top", "Move up", "Move down", "Delete from the list", and "Restore default parameters"; the adding function can be set in a certain function code in a function group. The edit function is shown in the figure below.

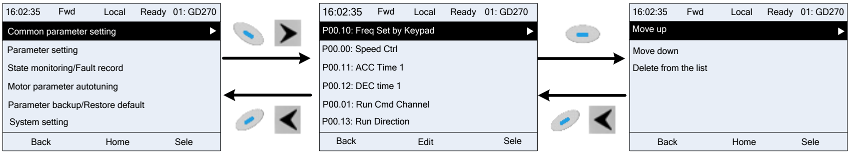



Figure 5-18 Editing list 3

### 5.4.6 Adding parameters to the parameter list displayed in stopped/running state

You can choose **Menu** > **State monitoring**, choose a submenu, and enter a specific function group and then a specific function code to add the parameter to the list of parameters displayed in stopped state or parameters displayed in running state.

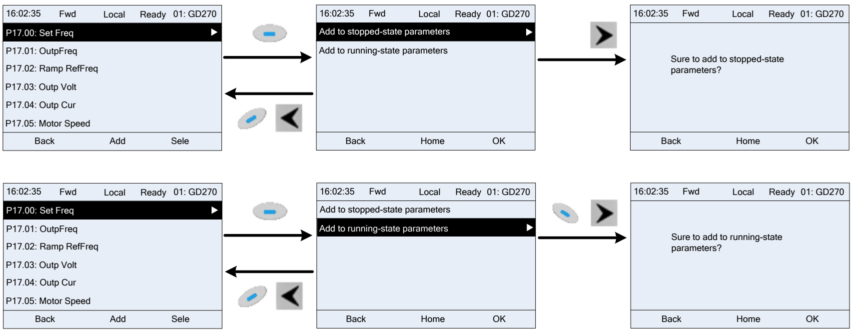



Figure 5-19 Adding parameters 1

After selecting a specific function code, press key to enter parameter addition interface, and press key, key or key to confirm the addition operation. If this parameter is not included in the list of parameters displayed in stopped state or list of parameters displayed in running state, the parameter added will be at the end of the list; if the parameter is already in the list of parameters displayed in stopped state or list of parameters displayed in running state, the addition operation will be invalid. If key or key is pressed without selecting addition operation in "Addition" interface, it will return to monitoring parameter list menu.

Part of the monitoring parameters in P07 HMI group can be added to the "parameter displayed in stop state" list or "parameter displayed in running state" list; all the parameters in P17, P18 and P19 group can be added to the "parameter displayed in stop state" list or "parameter displayed in running state" list.

Up to 16 monitoring parameters can be added to the list of parameters displayed in stopped state; and up to 32 monitoring parameters can be added to the list of parameters displayed in running state.

### 5.4.7 Add parameter to common parameter setup list

You can choose **Menu** > **Parameter groups**, choose a submenu, and enter a specific function group and then a specific function code to add the parameter to the user defined parameter list.

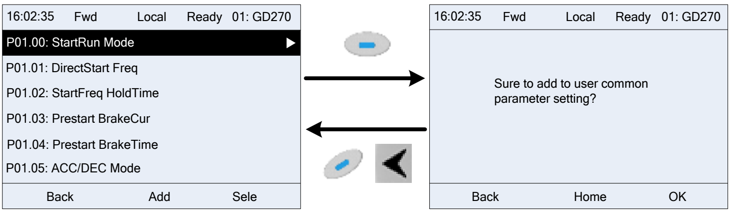



Figure 5-20 Adding parameters 2

Press key to enter addition interface, and press key, key or key to confirm the addition operation. If this parameter is not included in the original user defined parameter list, the newly-added parameter will be at the end of the list; if this parameter is already in the user defined parameter list, the addition operation will be invalid. If key or key is pressed without selecting addition operation, it will return to parameter setup list menu.

All the function code groups under the submenu can be added to user defined parameter list. Up to 64 function codes can be added to the user defined parameter list.

### 5.4.8 Parameter selection edit interface

After accessing a specific function code under the **User defined parameters** menu, you can press the key, key or key to enter the parameter edit interface. After entering the edit interface, the present value is highlighted. Press the key and key to edit the parameter value, and the corresponding parameter item of current value will be highlighted automatically. After the edit operation is completed, press or key to save the selected parameter and return to the previous menu; or press key to maintain the value and return to the previous menu.

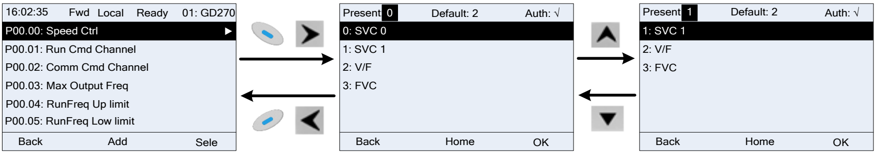



Figure 5-21 Parameter selection edit interface

In parameter selection edit interface, the "Auth" field in the upper right corner indicates whether this parameter is editable or not.

"√" indicates the set value of this parameter can be modified under current state.

"×" indicates the set value of this parameter cannot be modified under the present.

"Present" indicates the actually selected value.

"Default" indicates the default value of this parameter.

### 5.4.9 Parameter setup edit interface

You can choose **Menu** > **Parameter groups**, enter a specific function group and then a specific function code, and then press key, key or key to edit the parameter setting interface. After entering edit interface, set the parameter from low bit to high bit, and the bit under setting will be highlighted. Press key or key to increase or decrease the parameter value (this operation is valid until the parameter value exceeds the max. value or min. value); press or to shift the editing bit. After parameters are set, press or key to save the set parameters and return to the previous menu; press to maintain the original parameter value and return to the previous menu.

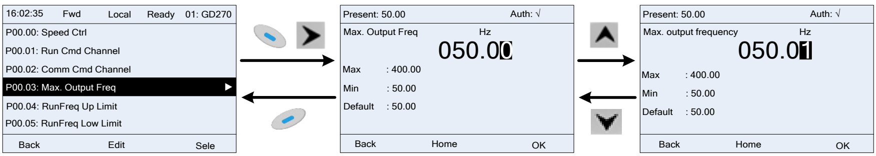



Figure 5-22 Parameter setup edit interface

In parameter selection edit interface, the "Auth" field in the upper right corner indicates whether this parameter is editable or not.

"√" indicates the set value of this parameter can be modified under current state.

"×" indicates the set value of this parameter cannot be modified under the present.

"Present" indicates the value saved last time.

"Default" indicates the default value of this parameter.

### 5.4.10 State monitoring interface

You can choose **Menu** > **State monitoring** > **State monitoring parameter**, enter a specific function group and then a specific function code, and press key, key or key to enter the state monitoring interface. After entering the state monitoring interface, the actual parameter value will be displayed in real time, this value is the actually detected value which cannot be modified.

In the state monitoring interface, you can press key or key to return to the previous menu.

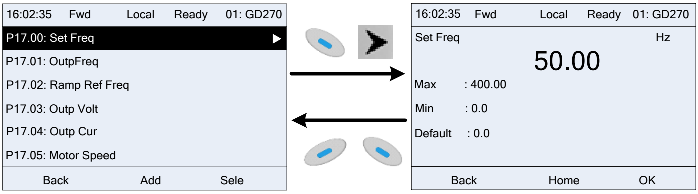



Figure 5-23 State monitoring interface

### 5.4.11 Motor parameter autotuning

You can choose **Menu** > **Motor parameter autotune** and press key, key or key to enter motor parameter autotuning interface. However, before entering the motor parameter autotuning interface, you must set the motor nameplate parameters correctly. After entering the interface, select a motor autotuning type to carry out motor parameter autotuning. In motor parameter autotuning interface, you can press key or key to return to the previous menu.

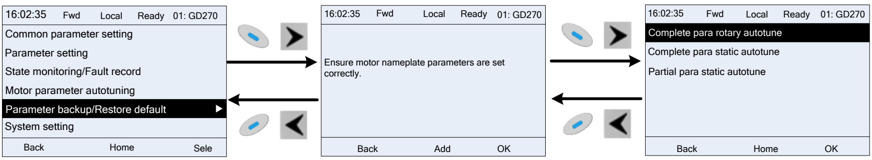



Figure 5-24 Parameter autotuning operation

After selecting a motor autotuning type, enter motor parameter autotuning interface, and press RUN key to start motor parameter autotuning. After autotuning is done, a message will pop up indicating autotuning is succeeded, and then it will return to the main interface of stop. During autotuning, you can press STOP/RST key to terminate autotuning; if any fault occur during autotuning, the keypad will display a fault interface.

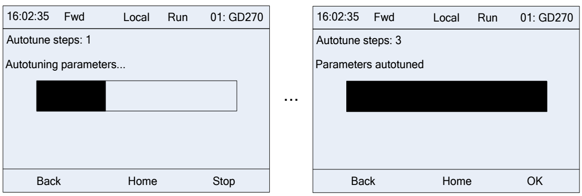



Figure 5-25 Parameter autotuning finished

### 5.4.12 Parameter backup

You can choose **Menu** > **Copy parameter/Restore default**, and press key, key or key to enter the function parameter backup interface and function parameter restoration interface to upload/download VFD parameters, or restore VFD parameters to default values. The keypad has three different storage areas for parameter backup, and each storage area can save the parameters of one VFD, which means the keypad can save parameters of three VFDs in total.

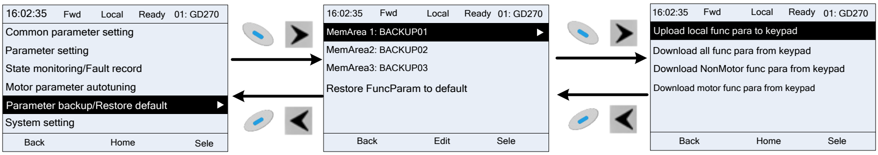



Figure 5-26 Parameter backup

### 5.4.13 System setting

You can choose **Menu** > **System settings**, and press key, key or key to enter system setting interface to set the keypad language, time/date, backlight brightness, backlight time and restore parameters.

**Note:** Clock battery is not included, and the keypad time/date needs to be reset after power off. If time-keeping after power off is needed, you should purchase the clock batteries separately.

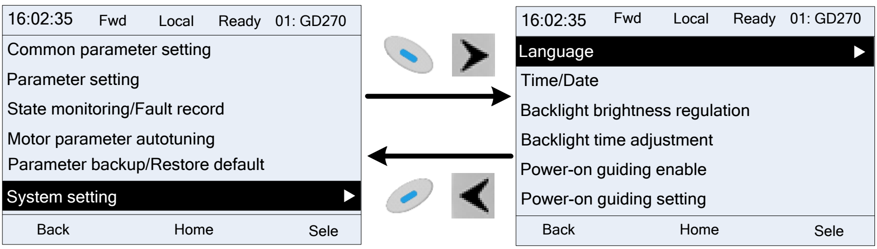



Figure 5-27 System setting

### 5.4.14 Power-on guiding settings

The keypad supports the power-on guiding function, mainly for the first power-on situation, guiding you to enter the setting menu, and gradually implementing basic functions such as basic parameter setting, direction judgment, mode setting and autotuning. The power-on guiding enable menu guides you to enable power-on to boot each time. Power-on guiding setup menu guides you to set step by step according to the functions. The power-on guide is shown as follows:

| Level 1 | | Level 2 | | Level 3 | | Level 4 | |
|---|---|---|---|---|---|---|---|
| Language | 0: Simplified Chinese | Power-on guiding enable | 0: Always | Whether to enter the power-on guiding settings? | 0: Yes | Whether to test the motor rotation direction? | Yes |
| | 1: English | | 1: Only once | | 1: No | | No |
| | | | | P00.06 | 0: Keypad | Press the JOG | Yes |

| Level 1 | | Level 2 | | Level 3 | | Level 4 | |
|---|---|---|---|---|---|---|---|
| | | | | Setting channel of A frequency command | 1: AI1 | button first. It is currently forward. Is it consistent with the expectations? | No |
| | | | | | 2: AI2 | P02.00 Type of motor 1 | 0: AM |
| | | | | | 3: AI3 | | 1: SM |
| | | | | | 4: High-speed pulse HDIA | P02.01 Rated power of AM 1 | |
| | | | | | 5: Simple PLC program | P02.02 Rated frequency of AM 1 | |
| | | | | | 6: Multi-step speed running | P02.03 Rated speed of AM 1 | |
| | | | | | 7: PID control | P02.04 Rated voltage of AM 1 | |
| | | | | | 8: Modbus/Modbus TCP communication | P02.05 Rated current of AM 1 | |
| | | | | | 9: PROFIBUS/CANopen /BACnet MSTP communication | P02.15 Rated power of SM 1 | |
| | | | | | 10: Ethernet communication | P02.16 Rated frequency of SM 1 | |
| | | | | | 11: High-speed pulse HDIB | P02.17 Number of pole pairs of SM 1 | |
| | | | | | 12: Pulse train AB | P02.18 Rated voltage of SM 1 | |
| | | | | | 13: PROFINET/ Ethernet IP communication | P02.19 Rated current of SM 1 | |
| | | | | | 14: Programmable card | Whether to conduct autotuning? | Yes |
| | | | | | 15–17: Reserved | | |
| | | | | | 18: Keypad (applicable to 1.5–22kW models) | | No |

| Level 1 | | Level 2 | | Level 3 | | Level 4 | |
|---|---|---|---|---|---|---|---|
| | | | | P00.01 Running command channel | 0: Keypad | Motor parameter autotuning interface | |
| | | | | | 1: Terminal | | |
| | | | | | 2: Communication | | |
| | | | | P00.02 Communication mode of running commands | 0: Modbus/Modbus TCP communication | | |
| | | | | | 1: PROFIBUS/CANopen /BACnet MSTP communication | | |
| | | | | | 2: Ethernet communication | | |
| | | | | | 3: PROFINET/EtherNet IP communication | | |
| | | | | | 4: Programmable card | | |
| | | | | | 5: Wireless communication card | | |
| | | | | P08.37 Reserved | | | |
| | | | | | | | |
| | | | | P00.00 Speed control mode | 0: SVC mode 0 | | |
| | | | | | 1: SVC mode 1 | | |
| | | | | | 2: Space voltage vector control mode | | |
| | | | | P01.08 Stop mode | 0: Decelerate to stop | | |
| | | | | | 1: Coast to stop | | |
| | | | | P00.11 ACC time 1 | | | |
| | | | | P00.12 DEC time 1 | | | |

## 5.5 Basic operation description

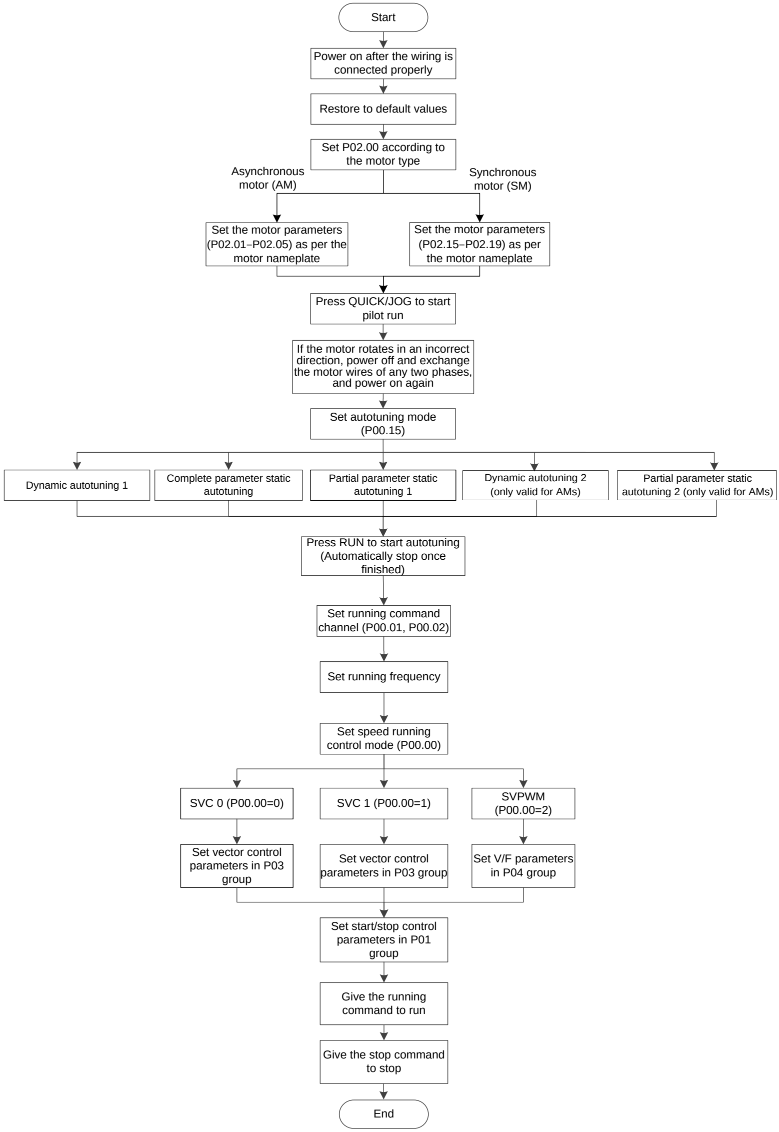
### 5.5.1 What this section describes

This section introduces the function modules inside the VFD.

| | |
|---|---|
|  | ✧ Ensure that all terminals have been securely connected.<br>✧ Ensure that the motor power matches the VFD power. |

### 5.5.2 Common commissioning procedure

The common commissioning procedure is as follows (taking motor 1 as an example).




**Note:** If a fault occurred, remove the fault cause according to "Fault tracking".

The running command channel can be set through terminal commands in addition to P00.01 and P00.02.

| Channel of running commands P00.01 | Multifunction terminal function 36 Switch the running command channel to keypad | Multifunction terminal function 37 Switch the running command channel to terminal | Multifunction terminal function 38 Switch the running command channel to communication |
|---|---|---|---|
| Keypad | / | Terminal | Communication |
| Terminal | Keypad | / | Communication |
| Communication | Keypad | Terminal | / |

**Note:** "/" indicates this multifunction terminal is invalid under present reference channel.

Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P00.00 | Speed control mode | 0: SVC mode 0<br>1: SVC mode 1<br>2: Space voltage vector control mode<br>**Note:** Before using a vector control mode (0 or 1), enable the VFD to perform motor parameter autotuning first. | 2 |
| P00.01 | Channel of running commands | 0: Keypad<br>1: Terminal<br>2: Communication | 0 |
| P00.02 | Communication mode of running commands | 0: Modbus/Modbus TCP communication<br>1: PROFIBUS/CANopen /BACnet MSTP communication<br>2: Ethernet communication<br>3: PROFINET/EtherNet IP communication<br>4: Programmable card<br>5: Wireless communication card | 0 |
| P00.15 | Motor parameter autotuning | 0: No operation<br>1: Dynamic autotuning 1; comprehensive motor parameter autotuning. It is recommended to use dynamic autotuning when high control accuracy is required.<br>2: Complete parameter static autotuning; used in scenarios where the motor cannot be disconnected from load.<br>3: Partial parameter static autotuning 1; | 0 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | when the present motor is motor 1, only P02.06, P02.07, and P02.08 are autotuned; when the present motor is motor 2, only P12.06, P12.07, and P12.08 are autotuned.<br>4: Dynamic autotuning 2; similar to dynamic autotuning 1, but only valid for AMs<br>5: Partial parameter static autotuning 2; only valid for AMs | |
| P00.18 | Function parameter restoration | 0: No operation<br>1: Restore to default values (excluding motor parameters)<br>2: Clear fault records<br>3: Lock keypad parameters<br>4: Reserved<br>5: Restore to default values (factory test mode)<br>6: Restore to default values (including motor parameters)<br>**Note:** After the selected operation is performed, the function code is automatically restored to 0. Restoring the default values may delete the user password. Exercise caution when using this function. | 0 |
| P02.00 | Type of motor 1 | 0: Asynchronous motor (AM)<br>1: Synchronous motor (SM) | 0 |
| P02.01 | Rated power of AM 1 | 0.1–3000.0kW | Model depended |
| P02.02 | Rated frequency of AM 1 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz |
| P02.03 | Rated speed of AM 1 | 1–60000rpm | Model depended |
| P02.04 | Rated voltage of AM 1 | 0–1200V | Model depended |
| P02.05 | Rated current of AM 1 | 0.8–6000.0A | Model depended |
| P02.15 | Rated power of SM 1 | 0.1–3000.0kW | Model depended |
| P02.16 | Rated frequency of SM 1 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz |

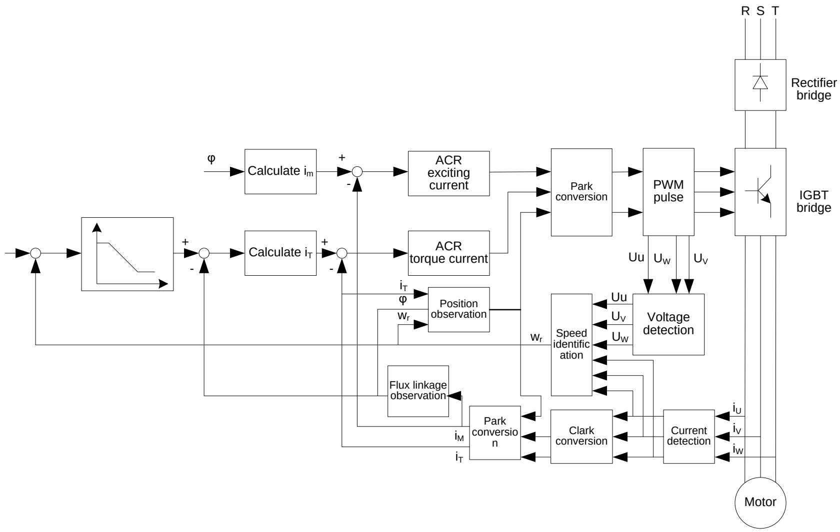
| Function code | Name | Description | Default |
|---|---|---|---|
| P02.17 | Number of pole pairs of SM 1 | 1–50 | 2 |
| P02.18 | Rated voltage of SM 1 | 0–1200V | Model depended |
| P02.19 | Rated current of SM 1 | 0.8–6000.0A | Model depended |
| P05.01–P05.06 | Function selection of multifunction digital input terminals (S1–S4, and HDIA) | 36: Switch the running command channel to keypad<br>37: Switch the running command channel to terminal<br>38: Switch the running command channel to communication | |
| P07.01 | Parameter copy | Used to set the parameter copy mode.<br>0: No operation<br>1: Upload parameters to the keypad<br>2: Download all parameters (including motor parameters)<br>3: Download non-motor parameters<br>4: Download motor parameters<br>**Note:** After any operation among 1–4 is completed, the parameter restores to 0. The upload and download functions are not applicable to group P29. | 0 |
| P07.02 | Function of QUICK/JOG | Range: 0x00–0x28<br>Ones place: Function of QUICK/JOG<br>0: No function<br>1: Jog<br>2: Reserved<br>3: Switch between forward and reverse rotating<br>4: Clear the UP/DOWN setting<br>5: Coast to stop<br>6: Switch command channels in sequence<br>7: Quick commissioning mode<br>8: Switch command channels in sequence + frequency switchover<br>**Note:** When switching to keypad control, the frequency is determined by the setting of P00.10; in other cases, it is determined by P00.06.<br>Tens place: Reserved | 0x01 |

### 5.5.3 Vector control

AMs feature high order, nonlinearity, strong coupling and multi-variables, which increase difficulty to control AMs during actual application. The vector control technology solves this situation as follows: measures and controls the stator current vector of the AM, and then decomposes the stator current vector into exciting current (current component that generates internal magnet field) and torque current (current component that generates torque) based on field orientation principle, and therefore controls the amplitude values and phase positions of the two components (namely, controls the stator current vector of the AM) to realize decoupled control on exciting current and torque current, thus achieving high-performance speed regulation of the AM.

Integrated with the sensor-less vector control algorithm, the VFD can drive both AMs and permanent-magnet SMs. As the core algorithm of vector control is based on accurate motor parameter models, the accuracy of motor parameters affects vector control performance. It is recommended to enter accurate motor parameters and autotune motor parameters before executing vector control.

As the vector control algorithm is complicated, exercise caution before modifying vector control function parameters.




| Function code | Name | Description | Default |
|---|---|---|---|
| P00.00 | Speed control mode | 0: SVC mode 0<br>1: SVC mode 1<br>2: Space voltage vector control mode<br>Note: Before using a vector control mode (0 or 1), enable the VFD to perform motor | 2 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | parameter autotuning first. | |
| P00.15 | Motor parameter autotuning | 0: No operation<br>1: Dynamic autotuning 1<br>Comprehensive motor parameter autotuning. It is recommended to use rotating autotuning when high control accuracy is required.<br>2: Complete parameter static autotuning<br>Used in scenarios where the motor cannot be disconnected from load.<br>3: Partial parameter static autotuning 1<br>When the present motor is motor 1, only P02.06, P02.07, and P02.08 are autotuned; when the present motor is motor 2, only P12.06, P12.07, and P12.08 are autotuned.<br>4: Dynamic autotuning 2; similar to dynamic autotuning 1, but only valid for AMs<br>5: Partial parameter static autotuning 2 (valid only for AMs) | 0 |
| P02.00 | Type of motor 1 | 0: Asynchronous motor (AM)<br>1: Synchronous motor (SM) | 0 |
| P03.00 | Speed-loop proportional gain 1 | 0–200.0 | 20.0 |
| P03.01 | Speed-loop integral time 1 | 0.000–10.000s | 0.200s |
| P03.02 | Low-point frequency for switching | 0.00Hz–P03.05 | 5.00Hz |
| P03.03 | Speed-loop proportional gain 2 | 0–200.0 | 20.0 |
| P03.04 | Speed-loop integral time 2 | 0.000–10.000s | 0.200s |
| P03.05 | High-point frequency for switching | P03.02–P00.03 (Max. output frequency) | 10.00 Hz |
| P03.06 | Speed-loop output filter | 0–8 (0–$2^8$/10ms) | 0 |
| P03.07 | Electromotive slip compensation coefficient of vector control | 50%–200% | 100% |
| P03.08 | Braking slip compensation coefficient of vector control | 50%–200% | 100% |
| P03.09 | Current-loop proportional | 0–65535 | 1000 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | coefficient P | | |
| P03.10 | Current-loop integral coefficient I | 0–65535 | 1000 |
| P03.11 | Torque setting method selection | 1: Keypad (P03.12)<br>2: AI1<br>3: AI2<br>4: AI3<br>5: Pulse frequency HDIA<br>6: Multi-step torque<br>7: Modbus/Modbus TCP communication<br>8: PROFIBUS/CANopen/BACnet MSTP communication<br>9: Ethernet communication<br>10: Pulse frequency HDIB<br>11: PROFINET/EtherNet IP communication<br>12: Programmable card<br>13–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>**Note:** 100% corresponds to the motor rated current. | 1 |
| P03.12 | Torque set through keypad | -300.0%–300.0% (of the motor rated current) | 50.0% |
| P03.13 | Torque reference filter time | 0.000–10.000s | 0.010s |
| P03.14 | Setting source of forward rotation upper-limit frequency in torque control | 0: Keypad (P03.16)<br>1: AI1 (100% corresponds to the max. frequency)<br>2: AI2 (same as the above)<br>3: AI3 (same as the above)<br>4: Pulse frequency HDIA<br>5: Multi-step setting (same as the above)<br>6: Modbus/Modbus TCP communication (same as the above)<br>7: PROFIBUS/CANopen/BACnet MSTP communication (same as the above)<br>8: Ethernet communication (same as the above)<br>9: Pulse frequency HDIB | 0 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 10: PROFINET/EtherNet IP communication (same as the above)<br>11: Programmable card (same as the above)<br>12–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | |
| P03.15 | Setting source of reverse rotation upper-limit frequency in torque control | 0: Keypad (P03.17)<br>1–18: Same as those for P03.14 | 0 |
| P03.16 | Forward rotation frequency upper limit set through keypad in torque control | Setting range: 0.00Hz–P00.03 (Max. output frequency) | 50.00 Hz |
| P03.17 | Reverse rotation upper-limit frequency set through keypad in torque control | | 50.00 Hz |
| P03.18 | Setting source of electromotive torque upper limit | 0: Keypad (P03.20)<br>1: AI1 (100% corresponds to triple the motor rated current)<br>2: AI2 (same as the above)<br>3: AI3 (same as the above)<br>4: Pulse frequency HDIA<br>5: Modbus/Modbus TCP communication<br>6: PROFIBUS/CANopen/BACnet MSTP communication<br>7: Ethernet communication<br>8: Pulse frequency HDIB<br>9: PROFINET/EtherNet IP communication<br>10: Programable card<br>11–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>**Note:** For setting sources 0–18, 100% corresponds to three times the rated motor current. | 0 |
| P03.19 | Setting source of braking torque upper limit | 0: Keypad (P03.21)<br>1–18: Same as those for P03.18 | 0 |

| Function code | Name | Description | Default |
|---|---|---|---|
| P03.20 | Electromotive torque upper limit set through keypad | 0.0–300.0% (of the motor rated current) | 180.0% |
| P03.21 | Braking torque upper limit set through keypad | | 180.0% |
| P03.22 | Weakening coefficient in constant power zone | 0.1–2.0 | 0.3 |
| P03.23 | Lowest weakening point in constant power zone | 10%–100% | 20% |
| P03.24 | Max. voltage limit | 0.0–120.0% | 100.0% |
| P03.25 | Pre-exciting time | 0.000–10.000s | 0.300s |
| P03.32 | Enabling torque control | 0: Disable<br>1: Enable | 0 |
| P03.33 | Flux-weakening integral gain | 0–8000 | 1200 |
| P03.35 | Control optimization setting | Range: 0x0000–0x1111<br>Ones place: Torque command selection<br>0: Torque reference<br>1: Torque current reference<br>Tens place: Reserved<br>Hundreds place: indicates whether to enable speed-loop integral separation<br>0: Disable<br>1: Enable<br>Thousands place: Reserved | 0x0000 |
| P03.36 | Speed-loop differential gain | 0.00–10.00s | 0.00s |
| P03.37 | Proportional coefficient of high-frequency current loop | In the vector control mode (P00.00=3), when the frequency is lower than the current-loop high-frequency switching threshold (P03.39), the current-loop PI parameters are P03.09 and P03.10; and when the frequency is higher than the current-loop high-frequency switching threshold, the current-loop PI parameters are P03.37 and P03.38.<br>Setting range of P03.37: 0–65535<br>Setting range of P03.38: 0–65535<br>Setting range of P03.39: 0.0–100.0% (of the max. frequency) | 1000 |
| P03.38 | High-frequency current-loop integral coefficient | | 1000 |
| P03.39 | Current-loop high-frequency switching threshold | | 100.0% |
| P17.32 | Flux linkage | 0.0–200.0% | 0.0% |

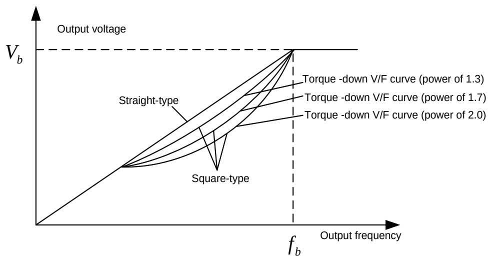
### 5.5.4 Space voltage vector control mode

The VFD also provides the space voltage control function. The space voltage control mode can be used in cases where mediocre control precision is enough and in cases where a VFD needs to drive multiple motors.

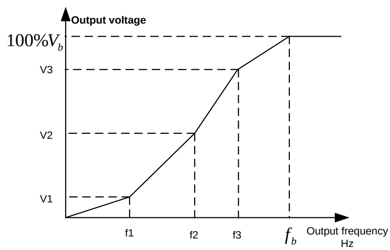
The VFD provides multiple V/F curve modes to meet different requirements. You can select V/F curves or set V/F curves as required.

**Suggestions:**

1. For the load featuring constant moment, such as conveyor belt which runs in straight line, as the whole running process requires constant moment, it is recommended to adopt the straight line V/F curve.
2. For the load featuring decreasing moment, such as fan and water pumps, as there is a power (square or cube) relation between its actual torque and speed, it is recommended to adopt the V/F curve corresponding to the power of 1.3, 1.7 or 2.0.




The VFD also provides multi-point V/F curves. You can change the V/F curves output by the VFD by setting the voltage and frequency of the three points in the middle. A whole curve consists of five points starting from (0Hz, 0V) and ending at (motor fundamental frequency, motor rated voltage). During setting, follow the rule: 0 ≤ f1 ≤ f2 ≤ f3 ≤ Motor fundamental frequency, and 0 ≤ V1 ≤ V2 ≤ V3 ≤ Motor rated voltage.




The VFD provides dedicated function codes for the space voltage control mode. You can improve the space voltage control performance by means of setting.

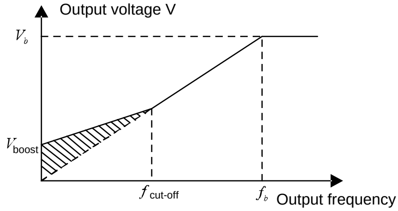
**1. Torque boost**

The torque boost function can effectively compensate for the low-speed torque performance in space voltage control. Automatic torque boost has been set by default, which enables the VFD to adjust the torque boost value based on actual load conditions.

**Note:**

✧ Torque boost takes effect only at the torque boost cut-off frequency.

✧ If torque boost is too large, the motor may encounter low-frequency vibration or overcurrent. If such a situation occurs, reduce the torque boost value.




**2. V/F slip compensation gain**

Space voltage vector control belongs to an open-loop mode. Sudden motor load changes cause motor speed fluctuation. In cases where strict speed requirements must be met, you can set the slip compensation gain to compensate for the speed change caused by load fluctuation through VFD internal output adjustment.

The setting range of slip compensation gain is 0–200%, in which 100% corresponds to the rated slip frequency.

**Note:** Rated slip frequency = (Rated synchronous rotation speed of motor - Rated rotation speed of motor) x (Number of motor pole pairs)/60

**3. Oscillation control**

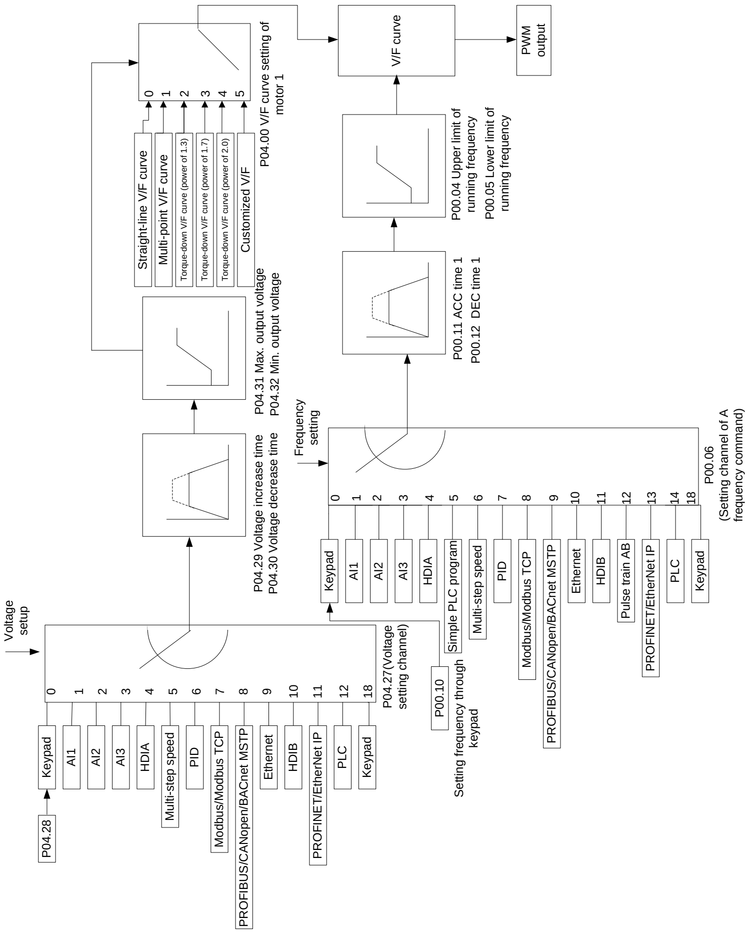
Motor oscillation often occurs in space voltage vector control in large-power driving applications. To solve this problem, the VFD provides two oscillation factor function codes. You can set the function codes based on the oscillation occurrence frequency.

**Note:** A greater value indicates better control effect. However, if the value is too large, the VFD output current may be too large.

**4. AM IF control**

Generally, the IF control mode is valid for AMs. It can be used for SMs only when the frequency is extremely low. Therefore, the IF control mode described in this manual is only involved with AMs. IF control is implemented by performing closed-loop control on the total output current of the VFD. The output voltage adapts to the current reference, and open-loop control is separately performed over the frequency of the voltage and current.

Customized V/F curve (V/F separation) function:




When selecting the customized V/F curve function, you can specify the setting channels and acceleration/deceleration time of voltage and frequency respectively, which form a real-time V/F curve in combination manner.

**Note:** This type of V/F curve separation can be applied in various variable-frequency power sources. However, exercise caution when setting parameters as improper settings may cause equipment damage.

Related function parameters:

| Function code | Name | Description | Default |
|---|---|---|---|
| P00.00 | Speed control mode | 0: SVC mode 0<br>1: SVC mode 1<br>2: Space voltage vector control mode<br>Note: Before using a vector control mode (0 or 1), enable the VFD to perform motor parameter autotuning first. | 2 |
| P00.03 | Max. output frequency | P00.04–400.00Hz | 50.00Hz |
| P00.04 | Upper limit of running frequency | P00.05–P00.03 | 50.00Hz |
| P00.05 | Lower limit of running frequency | 0.00Hz–P00.04 | 0.00Hz |
| P00.11 | ACC time 1 | 0.0–3600.0s | Model depended |
| P00.12 | DEC time 1 | 0.0–3600.0s | Model depended |
| P02.00 | Type of motor 1 | 0: Asynchronous motor (AM)<br>1: Synchronous motor (SM) | 0 |
| P02.02 | Rated frequency of AM 1 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz |
| P02.04 | Rated voltage of AM 1 | 0–1200V | Model depended |
| P04.00 | V/F curve setting of motor 1 | 0: Straight-line V/F curve<br>1: Multi-point V/F curve<br>2: Torque-down V/F curve (power of 1.3)<br>3: Torque-down V/F curve (power of 1.7)<br>4: Torque-down V/F curve (power of 2.0)<br>5: Customized V/F curve (V/F separation) | 0 |
| P04.01 | Torque boost of motor 1 | 0.0% (Automatic); 0.1%–10.0% (of the rated voltage of motor 1) | 0.0% |
| P04.02 | Torque boost cut-off of motor 1 | 0.0%–50.0% (of the rated frequency of motor 1) | 20.0% |
| P04.03 | V/F frequency point 1 of motor 1 | 0.00Hz–P04.05 | 0.00Hz |
| P04.04 | V/F voltage point 1 of motor 1 | 0.0%–110.0% (of the rated voltage of motor 1) | 0.0% |

| Function code | Name | Description | Default |
|---|---|---|---|
| P04.05 | V/F frequency point 2 of motor 1 | P04.03–P04.07 | 0.00Hz |
| P04.06 | V/F voltage point 2 of motor 1 | 0.0%–110.0% (of the rated voltage of motor 1) | 0.0% |
| P04.07 | V/F frequency point 3 of motor 1 | P04.05–P02.02 (Hz, P02.00=0) orP04.05–P02.16 (Hz, P02.00=1) | 0.00Hz |
| P04.08 | V/F voltage point 3 of motor 1 | 0.0%–110.0% (of the rated voltage of motor 1) | 0.0% |
| P04.09 | V/F slip compensation gain of motor 1 | 0.0–200.0% | 100.0% |
| P04.10 | Low-frequency oscillation control factor of motor 1 | 0–100 | 10 |
| P04.11 | High-frequency oscillation control factor of motor 1 | 0–100 | 10 |
| P04.12 | Oscillation control threshold of motor 1 | 0.00Hz–P00.03 (Max. output frequency) | 30.00Hz |
| P04.13 | V/F curve setting of motor 2 | 0: Straight-line V/F curve<br>1: Multi-point V/F curve<br>2: Torque-down V/F curve (power of 1.3)<br>3: Torque-down V/F curve (power of 1.7)<br>4: Torque-down V/F curve (power of 2.0)<br>5: Customized V/F curve (V/F separation) | 0 |
| P04.14 | Torque boost of motor 2 | 0.0% (Automatic); 0.1%–10.0% (of the rated voltage of motor 2) | 0.0% |
| P04.15 | Torque boost cut-off of motor 2 | 0.0%–50.0% (of the rated frequency of motor 2) | 20.0% |
| P04.16 | V/F frequency point 1 of motor 2 | 0.00Hz–P04.18 | 0.00Hz |
| P04.17 | V/F voltage point 1 of motor 2 | 0.0%–110.0% (of the rated voltage of motor 2) | 0.0% |
| P04.18 | V/F frequency point 2 of motor 2 | P04.16–P04.20 | 0.00Hz |
| P04.19 | V/F voltage point 2 of motor 2 | 0.0%–110.0% (of the rated voltage of motor 2) | 0.0% |

| Function code | Name | Description | Default |
|---|---|---|---|
| P04.20 | V/F frequency point 3 of motor 2 | P04.18–P02.02 (Hz, P12.00=0) or P04.18–P02.16 (Hz, P12.00=0) | 0.00Hz |
| P04.21 | V/F voltage point 3 of motor 2 | 0.0%–110.0% (of the rated voltage of motor 2) | 0.0% |
| P04.22 | V/F slip compensation gain of motor 2 | 0.0–200.0% | 100.0% |
| P04.23 | Low-frequency oscillation control factor of motor 2 | 0–100 | 10 |
| P04.24 | High-frequency oscillation control factor of motor 2 | 0–100 | 10 |
| P04.25 | Oscillation control threshold of motor 2 | 0.00Hz–P00.03 (Max. output frequency) | 30.00Hz |
| P04.26 | Energy-saving run | 0: Disable<br>1: Automatic energy-saving run | 0 |
| P04.27 | Voltage setting channel selection | 0: Keypad (output voltage is determined by P04.28)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: HDIA<br>5: Multi-step speed running (The setting is determined by group P10.)<br>6: PID<br>7: Modbus/Modbus TCP communication<br>8: PROFIBUS/CANopen /BACnet MSTP communication<br>9: Ethernet communication<br>10: HDIB<br>11: PROFINET/EtherNet IP communication<br>12: Programmable card<br>13–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | 0 |
| P04.28 | Voltage set through keypad | 0.0%–100.0% (of the motor rated voltage) | 100.0% |
| P04.29 | Voltage increase time | 0.0–3600.0s | 5.0s |

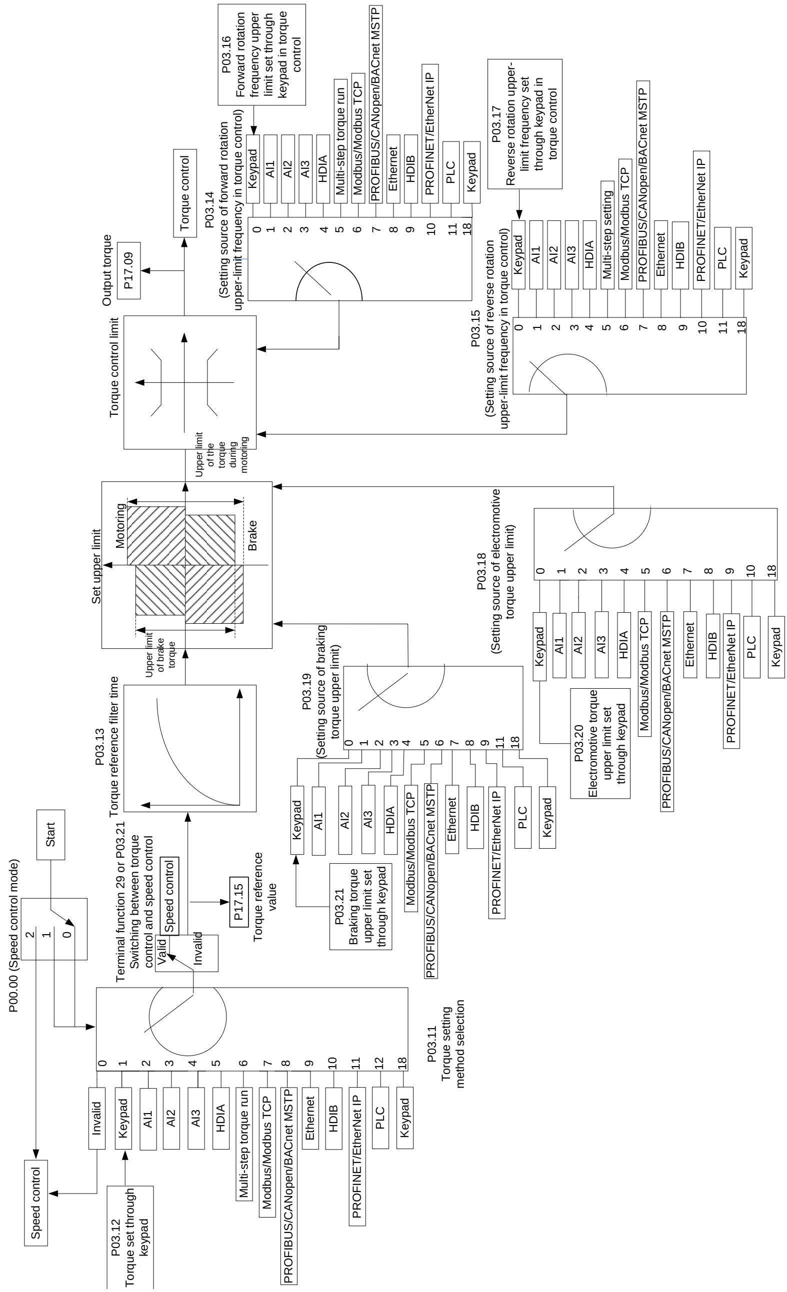
| Function code | Name | Description | Default |
|---|---|---|---|
| P04.30 | Voltage decrease time | 0.0–3600.0s | 5.0s |
| P04.31 | Max. output voltage | P04.32–100.0% (of the motor rated voltage) | 100.0% |
| P04.32 | Min. output voltage | 0.0%–P04.31 (relative to motor rated voltage) | 0.0% |
| P04.33 | Weakening coefficient in constant power zone | 1.00–1.30 | 1.00 |
| P04.34 | Pull-in current 1 in SM V/F control | When the SM VF control mode is enabled, the function code is used to set the reactive current of the motor when the output frequency is lower than the frequency specified by P04.36.<br>Setting range: -100.0%–+100.0% (of the motor rated current) | 20.0% |
| P04.35 | Pull-in current 2 in SM V/F control | When the SM VF control mode is enabled the function code is used to set the reactive current of the motor when the output frequency is greater than the frequency specified by P04.36.<br>Setting range: -100.0%–+100.0% (of the motor rated current) | 10.0% |
| P04.36 | Frequency threshold for pull-in current switching in SM V/F control | When the SM VF control mode is enabled, the function code is used to set the frequency threshold for the switching between pull-in current 1 and pull-in current 2.<br>Setting range: 0.0 –200.0% (of the motor rated frequency) | 20.0% |
| P04.37 | Reactive current closed-loop proportional coefficient in SM V/F control | When the SM VF control mode is enabled, the function code is used to set the proportional coefficient of reactive current closed-loop control.<br>Setting range: 0–3000 | 50 |
| P04.38 | Reactive current closed-loop integral time in SM V/F control | When the SM VF control mode is enabled, the function code is used to set the integral coefficient of reactive current closed-loop control.<br>Setting range: 0–3000 | 30 |
| P04.39 | Reactive current closed-loop output limit in SM VF | When the SM VF control mode is enabled, the function code is used to set the output limit of the reactive current closed-loop control. A greater value | 8000 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | control | indicates a higher reactive closed-loop compensation voltage and higher output power of the motor. In general, you do not need to modify the function code.<br>Setting range: 0–16000 | |
| P04.40 | Enabling IF mode for AM 1 | 0: Invalid<br>1: Enable | 0 |
| P04.41 | Current setting in IF mode for AM 1 | When IF control is adopted for AM 1, the function code is used to set the output current. The value is a percentage in relative to the rated current of the motor.<br>Setting range: 0.0–200.0% | 120.0% |
| P04.42 | Proportional coefficient in IF mode for AM 1 | When IF control is adopted for AM 1, the function code is used to set the proportional coefficient of the output current closed-loop control.<br>Setting range: 0–5000 | 350 |
| P04.43 | Integral coefficient in IF mode for AM 1 | When IF control is adopted for AM 1, the function code is used to set the integral coefficient of the output current closed-loop control.<br>Setting range: 0–5000 | 150 |
| P04.44 | Starting frequency point for switching off IF mode for AM 1 | 0.00Hz–P04.50 | 10.00Hz |
| P04.45 | Enabling IF mode for AM 2 | 0: Invalid<br>1: Enable | 0 |
| P04.46 | Current setting in IF mode for AM 2 | When IF control is adopted for AM 2, the function code is used to set the output current. The value is a percentage in relative to the rated current of the motor.<br>Setting range: 0.0–200.0% | 120.0% |
| P04.47 | Proportional coefficient in IF mode for AM 2 | When IF control is adopted for AM 2, the function code is used to set the proportional coefficient of output current closed-loop control. Setting range: 0–5000 | 350 |
| P04.48 | Integral coefficient in IF mode for AM 2 | When IF control is adopted for AM 2, the function code is used to set the integral coefficient of output current closed-loop control.<br>Setting range: 0–5000 | 150 |
| P04.49 | Starting frequency | 0.00Hz–P04.51 | 10.00Hz |

| Function code | Name | Description | Default |
|---|---|---|---|
| | point for switching off IF mode for AM 2 | | |
| P04.50 | End frequency point for switching off IF mode for AM 1 | P04.44–P00.03 | 25.00Hz |
| P04.51 | End frequency point for switching off IF mode for AM 2 | P04.49–P00.03 | 25.00Hz |
| P04.52 | VF energy-saving mode selection | 0: Max. efficiency (default)<br>1: Optimal power factor<br>2: MTPA | 0 |
| P04.53 | VF energy-saving gain coefficient | 0.0–400.0% | 100.0% |
| P04.54 | VF energy-saving power angle gain coefficient | 0.0–200.0% | 80.0% |

### 5.5.5 Torque control

The VFD supports torque control and speed control. Speed control aims to stabilize the speed to keep the set speed consistent with the actual running speed, meanwhile, the max. load-carrying capacity is restricted by the torque limit. Torque control aims to stabilize the torque to keep the set torque consistent with the actual output torque, meanwhile, the output frequency is restricted by the upper and lower limits.


P00.00 (Speed control mode)
2
1
0
Start
Speed control
P03.12
Torque set through keypad
Invalid
Keypad
AI1
AI2
AI3
HDIA
Multi-step torque run
Modbus/Modbus TCP
PROFIBUS/CANopen/BACnet MSTP
Ethernet
HDIB
PROFINET/EtherNet IP
PLC
Keypad
0 1 2 3 4 5 6 7 8 9 10 11 12 18
P03.11
Torque setting method selection
Terminal function 29 or P03.21
Switching between torque control and speed control
Valid
Invalid
Speed control
P17.15
Torque reference value
P03.13
Torque reference filter time
Upper limit of brake torque
Set upper limit
Motoring
Brake
Upper limit of the torque during motoring
Torque control limit
Output torque
P17.09
Torque control
P03.14
(Setting source of forward rotation upper-limit frequency in torque control)
P03.16
Forward rotation frequency upper limit set through keypad in torque control
Multi-step torque run
0 1 2 3 4 5 6 7 8 9 10 11 18
P03.15
(Setting source of reverse rotation upper-limit frequency in torque control)
P03.17
Reverse rotation upper-limit frequency set through keypad in torque control
Multi-step setting
P03.18
(Setting source of electromotive torque upper limit)
P03.20
Electromotive torque upper limit set through keypad
P03.19
(Setting source of braking torque upper limit)
P03.21
Braking torque upper limit set through keypad

Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P00.00 | Speed control mode | 0: SVC mode 0<br>1: SVC mode 1<br>2: Space voltage vector control mode<br>**Note:** Before using a vector control mode (0 or 1), enable the VFD to perform motor parameter autotuning first. | 2 |
| P03.32 | Enabling torque control | 0: Disable<br>1: Enable | 0 |
| P03.11 | Torque setting method selection | 1: Keypad (P03.12)<br>2: AI1<br>3: AI2<br>4: AI3<br>5: Pulse frequency HDIA<br>6: Multi-step torque<br>7: Modbus/Modbus TCP communication<br>8: PROFIBUS/CANopen/BACnet MSTP communication<br>9: Ethernet communication<br>10: Pulse frequency HDIB<br>11: PROFINET/EtherNet IP communication<br>12: Programmable card<br>13–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>**Note:** 100% corresponds to the motor rated current. | 0 |
| P03.12 | Torque set through keypad | -300.0%–300.0% (of the motor rated current) | 50.0% |
| P03.13 | Torque reference filter time | 0.000–10.000s | 0.010s |
| P03.14 | Setting source of forward rotation upper-limit frequency in torque control | 0: Keypad (P03.16)<br>1: AI1 (100% corresponds to the max. frequency)<br>2: AI2 (same as the above)<br>3: AI3 (same as the above)<br>4: Pulse frequency HDIA<br>5: Multi-step setting (same as the above)<br>6: Modbus/Modbus TCP communication (same as the above)<br>7: PROFIBUS/CANopen/BACnet MSTP | 0 |

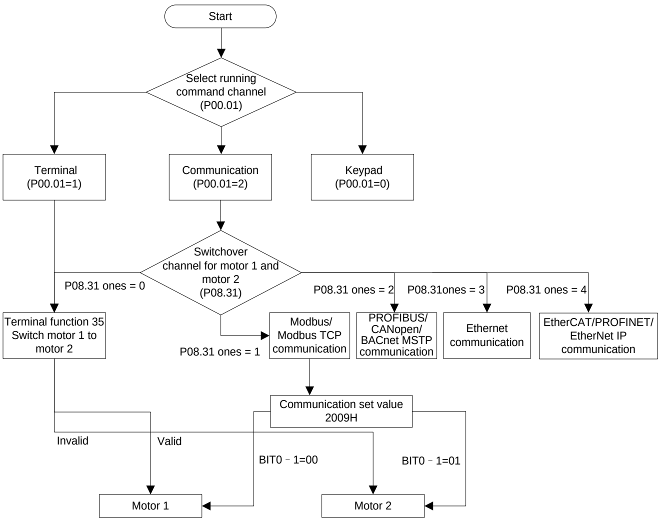
| Function code | Name | Description | Default |
|---|---|---|---|
| | | communication (same as the above)<br>8: Ethernet communication (same as the above)<br>9: Pulse frequency HDIB (same as the above)<br>10: PROFINET/EtherNet IP communication (same as the above)<br>11: Programmable card (same as the above)<br>12–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | |
| P03.15 | Setting source of reverse rotation upper-limit frequency in torque control | 0: Keypad (P03.17)<br>1: AI1 (100% corresponds to the max. frequency)<br>2: AI2 (same as the above)<br>3: AI3 (same as the above)<br>4: Pulse frequency HDIA<br>5: Multi-step setting (same as the above)<br>6: Modbus/Modbus TCP communication (same as the above)<br>7: PROFIBUS/CANopen/BACnet MSTP communication (same as the above)<br>8: Ethernet communication (same as the above)<br>9: Pulse frequency HDIB (same as the above)<br>10: PROFINET/EtherNet IP communication (same as the above)<br>11: Programmable card (same as the above)<br>12–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | 0 |
| P03.16 | Forward rotation frequency upper limit set through keypad in torque control | 0.00Hz–P00.03 (Max. output frequency) | 50.00Hz |
| P03.17 | Reverse rotation upper-limit frequency set through keypad in torque control | 0.00Hz–P00.03 (Max. output frequency) | 50.00Hz |
| P03.18 | Setting source of electromotive torque upper limit | 0: Keypad (P03.20)<br>1: AI1 (100% corresponding to the motor rated current) | 0 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 2: AI2 (same as the above)<br>3: AI3 (same as the above)<br>4: Pulse frequency HDIA<br>5: Modbus/Modbus TCP communication<br>6: PROFIBUS/CANopen/BACnet MSTP communication<br>7: Ethernet communication<br>8: Pulse frequency HDIB<br>9: PROFINET/EtherNet IP communication<br>10: Programable card<br>11–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | |
| P03.19 | Setting source of braking torque upper limit | 0: Keypad (P03.21)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: Pulse frequency HDIA<br>5: Modbus/Modbus TCP communication<br>6: PROFIBUS/CANopen/BACnet MSTP communication<br>7: Ethernet communication<br>8: Pulse frequency HDIB<br>9: PROFINET/EtherNet IP communication<br>11: Programable card<br>12–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>**Note:** 100% corresponds to the motor rated current. | 0 |
| P03.20 | Electromotive torque upper limit set through keypad | 0.0–300.0% (of the motor rated current) | 180.0% |
| P03.21 | Braking torque upper limit set through keypad | 0.0–300.0% (of the motor rated current) | 180.0% |
| P17.09 | Motor output torque | -250.0%–250.0% | 0.0% |
| P17.15 | Torque reference value | -300.0%–300.0% (of the motor rated current) | 20.0% |

### 5.5.6 Motor parameters

| | |
|---|---|
|  | ✧ Check the safety conditions surrounding the motor and load machineries before autotuning as physical injury may occur due to sudden start of motor during autotuning.<br>✧ Although the motor does not run during static autotuning, the motor is still supplied with power. Do not touch the motor during autotuning; otherwise, electric shock may occur. Do not touch the motor before autotuning is completed. |
|  | ✧ If the motor has been connected to a load, do not carry out rotary autotuning. Otherwise, the VFD may malfunction or may be damaged. If rotary autotuning is carried out on a motor which has been connected to a load, incorrect motor parameter settings and motor action exceptions may occur. Disconnect from the load to carry out autotuning if necessary. |

The VFD can drive both asynchronous motors and synchronous motors, and it supports two sets of motor parameters, which can be switched over by multifunction digital input terminals or communication means.



The control performance of the VFD is based on accurate motor models. Therefore, you need to carry out motor parameter autotuning before running a motor for the first time (taking motor 1 as an example).


**Note:**

- ✧ Motor parameters must be set correctly according to the motor nameplate.
- ✧ If rotary autotuning is selected during motor autotuning, disconnect the motor from the load to put the motor in static and no-load state. Otherwise, the motor parameter autotuning results may be incorrect. In addition, autotune P02.06–P02.10 for AMs and autotune P02.20–P02.23 for SMs.
- ✧ If static autotuning is selected for motor autotuning, there is no need to disconnect the motor from the load, but the control performance may be impacted as only a part of the motor parameters have been autotuned. In addition, autotune P02.06–P02.10 for AMs and autotune P02.20–P02.22 for SMs. P02.23 can be obtained through calculation.
- ✧ Motor autotuning can be carried out on the present motor only. If you need to perform autotuning on the other motor, switch the motor through selecting the switch-over channel of motor 1 and motor 2 by setting the ones place of P08.31.

Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P00.01 | Channel of running commands | 0: Keypad<br>1: Terminal<br>2: Communication | 0 |
| P00.15 | Motor parameter autotuning | 0: No operation<br>1: Dynamic autotuning 1<br>Comprehensive motor parameter autotuning. It is recommended to use rotating autotuning when high control accuracy is required.<br>2: Complete parameter static autotuning<br>Used in scenarios where the motor cannot be disconnected from load.<br>3: Partial parameter static autotuning 1<br>When the present motor is motor 1, only P02.06, P02.07, and P02.08 are autotuned; when the present motor is motor 2, only P12.06, P12.07, and P12.08 are autotuned.<br>4: Dynamic autotuning 2; similar to dynamic autotuning 1, but only valid for AMs<br>5: Partial parameter static autotuning 2 (valid only for AMs) | 0 |
| P02.00 | Type of motor 1 | 0: Asynchronous motor (AM)<br>1: Synchronous motor (SM) | 0 |
| P02.01 | Rated power of AM 1 | 0.1–3000.0kW | Model depended |
| P02.02 | Rated frequency of AM 1 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz |
| P02.03 | Rated speed of AM 1 | 1–60000rpm | Model depended |
| P02.04 | Rated voltage of AM 1 | 0–1200V | Model depended |
| P02.05 | Rated current of AM 1 | 0.8–6000.0A | Model depended |
| P02.06 | Stator resistance of AM 1 | 0.001–65.535Ω | Model depended |
| P02.07 | Rotor resistance of AM 1 | 0.001–65.535Ω | Model depended |

| Function code | Name | Description | Default |
|---|---|---|---|
| P02.08 | Leakage inductance of AM 1 | 0.1–6553.5mH | Model depended |
| P02.09 | Mutual inductance of AM 1 | 0.1–6553.5mH | Model depended |
| P02.10 | No-load current of AM 1 | 0.1–6553.5A | Model depended |
| P02.15 | Rated power of SM 1 | 0.1–3000.0kW | Model depended |
| P02.16 | Rated frequency of SM 1 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz |
| P02.17 | Number of pole pairs of SM 1 | 1–50 | 2 |
| P02.18 | Rated voltage of SM 1 | 0–1200V | Model depended |
| P02.19 | Rated current of SM 1 | 0.8–6000.0A | Model depended |
| P02.20 | Stator resistance of SM 1 | 0.001–65.535Ω | Model depended |
| P02.21 | Direct-axis inductance of SM 1 | 0.01–655.35mH | Model depended |
| P02.22 | Quadrature-axis inductance of SM 1 | 0.01–655.35mH | Model depended |
| P02.23 | Counter-emf constant of SM 1 | 0–10000 | 300 |
| P05.01–P05.06 | Function selection of multifunction digital input terminals (S1–S4, and HDIA) | 35: Switch from motor 1 to motor 2 | 0 |
| P08.31 | Switching between motor 1 and motor 2 | 0x00–0x14<br>Ones place: Switchover channel<br>0: Terminal<br>1: Modbus/Modbus TCP communication<br>2: PROFIBUS/CANopen /BACnet MSTP communication<br>3: Ethernet communication<br>4: PROFINET/EtherNet IP communication<br>Tens place: indicates whether to enable switchover during running | 0x00 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 0: Disable<br>1: Enable | |
| P12.00 | Type of motor 2 | 0: Asynchronous motor (AM)<br>1: Synchronous motor (SM) | 0 |
| P12.01 | Rated power of AM 2 | 0.1–3000.0kW | Model depended |
| P12.02 | Rated frequency of AM 2 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz |
| P12.03 | Rated speed of AM 2 | 1–60000rpm | Model depended |
| P12.04 | Rated voltage of AM 2 | 0–1200V | Model depended |
| P12.05 | Rated current of AM 2 | 0.8–6000.0A | Model depended |
| P12.06 | Stator resistance of AM 2 | 0.001–65.535Ω | Model depended |
| P12.07 | Rotor resistance of AM 2 | 0.001–65.535Ω | Model depended |
| P12.08 | Leakage inductance of AM 2 | 0.1–6553.5mH | Model depended |
| P12.09 | Mutual inductance of AM 2 | 0.1–6553.5mH | Model depended |
| P12.10 | No-load current of AM 2 | 0.1–6553.5A | Model depended |
| P12.15 | Rated power of SM 2 | 0.1–3000.0kW | Model depended |
| P12.16 | Rated frequency of SM 2 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz |
| P12.17 | Number of pole pairs of SM 2 | 1–50 | 2 |
| P12.18 | Rated voltage of SM 2 | 0–1200V | Model depended |
| P12.19 | Rated current of SM 2 | 0.8–6000.0A | Model depended |
| P12.20 | Stator resistance of SM 2 | 0.001–65.535Ω | Model depended |
| P12.21 | Direct-axis inductance of | 0.01–655.35mH | Model |

| Function code | Name | Description | Default |
|---|---|---|---|
| | SM 2 | | depended |
| P12.22 | Quadrature-axis inductance of SM 2 | 0.01–655.35mH | Model depended |
| P12.23 | Counter-emf constant of SM 2 | 0–10000 | 300 |

### 5.5.7 Start/stop control

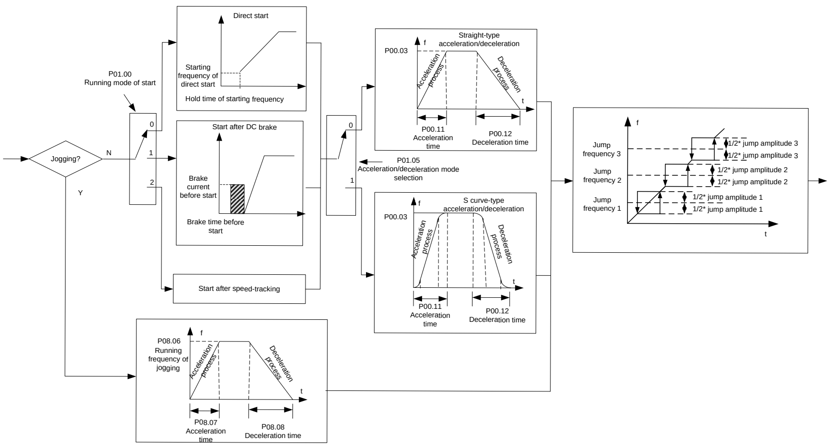
The start/stop control of the VFD involves three states: start after a running command is given at power-on; start after power-off restart is effective; start after automatic fault reset. The three start/stop control states are described in the following.

There are three start modes for the VFD, which are start at starting frequency, start after DC braking, and start after speed tracking. You can select the proper start mode based on actual conditions.

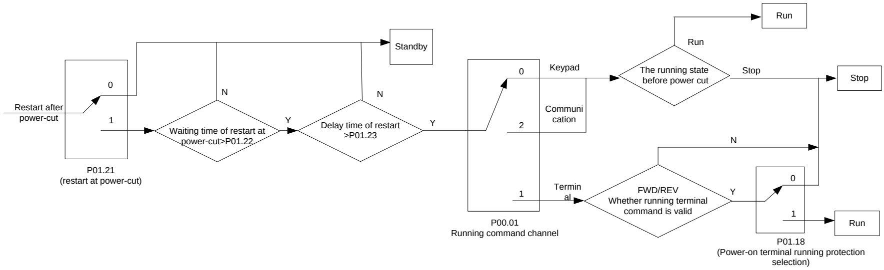
For large-inertia load, especially in cases where reversal may occur, you can choose to start after DC braking or start after speed tracking.

**Note:** It is recommended to drive SMs in direct start mode.

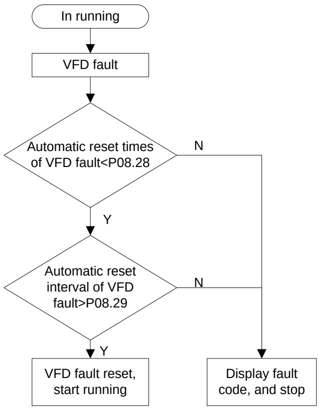
1. Logic diagram for start after a running command is given at power-on



2. Logic diagram for start after power-off restart is effective




3. Logic diagram for start after automatic fault reset




Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P00.01 | Channel of running commands | 0: Keypad<br>1: Terminal<br>2: Communication | 0 |
| P00.11 | ACC time 1 | 0.0–3600.0s | Model depended |
| P00.12 | DEC time 1 | 0.0–3600.0s | Model depended |
| P01.00 | Running mode of start | 0: Direct start<br>1: Start after DC braking<br>2: Start after speed tracking<br>**Note:** For AMs, speed tracking is not supported in SVC 0, and software speed tracking is supported in other modes. For details, see | 0 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | parameters P01.35–P01.41.<br>For SMs, you do not need to modify parameters P01.35–P01.41. | |
| P01.01 | Starting frequency of direct start | 0.00–50.00Hz | 0.50Hz |
| P01.02 | Hold time of starting frequency | 0.0–50.0s | 0.0s |
| P01.03 | Braking current before start | 0.0–100.0% | 0.0% |
| P01.04 | DC braking time before start | 0.00–50.00s | 0.00s |
| P01.05 | ACC/DEC mode | 0: Linear<br>1: S curve<br>**Note:** If mode 1 is selected, set P01.06, P01.07, P01.27, and P01.28 accordingly. | 0 |
| P01.08 | Stop mode | 0: Decelerate to stop<br>1: Coast to stop | 0 |
| P01.09 | Starting frequency of braking for stop | 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz |
| P01.10 | Wait time before DC braking for stop | 0.00–50.00s | 0.00s |
| P01.11 | DC braking current for stop | 0.0–100.0% | 0.0% |
| P01.12 | DC braking time for stop | 0.00–50.00s | 0.00s |
| P01.13 | FWD/REV run deadzone time | 0.0–3600.0s | 0.0s |
| P01.14 | FWD/REV run switching mode | 0: Switch at zero frequency<br>1: Switch at the starting frequency<br>2: Switch after the speed reaches the stop speed with a delay | 0 |
| P01.15 | Stop speed | 0.00–100.00Hz | 0.50 Hz |
| P01.16 | Stop speed detection mode | 0: Detect by the set speed (unique in V/F mode)<br>1: Detect by the feedback speed | 1 |
| P01.18 | Terminal-based running command protection at power-on | 0: The terminal running command is invalid at power-on<br>1: The terminal running command is valid at power-on | 0 |
| P01.19 | Action selected when running frequency less | 0: Run at the frequency lower limit<br>1: Stop | 0 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | than frequency lower limit (valid when frequency lower limit greater than 0) | 2: Sleep | |
| P01.20 | Wake-up-from-sleep delay | 0.0–3600.0s (valid only when P01.19=2) | 0.0s |
| P01.21 | Power-off restart selection | 0: Disable<br>1: Enable | 0 |
| P01.22 | Wait time for restart after power-off | 0.0–3600.0s (valid only when P01.21=1) | 1.0s |
| P01.23 | Start delay time | 0.0–60.0s | 0.0s |
| P01.24 | Stop speed delay | 0.0–100.0s | 0.0s |
| P01.25 | Open-loop 0Hz output selection | 0: Output without voltage<br>1: Output with voltage<br>2: Output with the DC braking current for stop | 0 |
| P01.26 | DEC time for emergency stop | 0.0–60.0s | 2.0s |
| P01.27 | Time of starting segment of DEC S curve | 0.0–50.0s | 0.1s |
| P01.28 | Time of ending segment of DEC S curve | 0.0–50.0s | 0.1s |
| P01.29 | Short-circuit braking current | 0.0–150.0% (of the VFD rated output current) | 0.0% |
| P01.30 | Hold time of short-circuit braking for start | 0.00–50.00s | 0.00s |
| P01.31 | Hold time of short-circuit braking for stop | 0.00–50.00s | 0.00s |
| P01.32 | Pre-exciting time for jogging | 0.000–10.000s | 0.300s |
| P01.33 | Starting frequency of braking for stop in jogging | 0.00Hz–P00.03 | 0.00Hz |
| P01.34 | Sleep delay | 0.0–3600.0s | 0.0s |
| P05.01–P05.06 | Digital input function selection | 1: Run forward<br>2: Run reversely<br>4: Jog forward<br>5: Jog reversely<br>6: Coast to stop<br>7: Fault reset<br>8: Pause running<br>21: ACC/DEC time selection 1<br>22: ACC/DEC time selection 2 | |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 30: Disable ACC/DEC | |
| P08.00 | ACC time 2 | 0.0–3600.0s | Model depended |
| P08.01 | DEC time 2 | 0.0–3600.0s | Model depended |
| P08.02 | ACC time 3 | 0.0–3600.0s | Model depended |
| P08.03 | DEC time 3 | 0.0–3600.0s | Model depended |
| P08.04 | ACC time 4 | 0.0–3600.0s | Model depended |
| P08.05 | DEC time 4 | 0.0–3600.0s | Model depended |
| P08.06 | Running frequency of jog | 0.00Hz–P00.03 (Max. output frequency) | 5.00Hz |
| P08.07 | ACC time for jogging | 0.0–3600.0s | Model depended |
| P08.08 | DEC time for jogging | 0.0–3600.0s | Model depended |
| P08.19 | Switching frequency of ACC/DEC time | 0.00–P00.03 (Max. output frequency)<br>0.00Hz, no switchover.<br>If the running frequency is greater than P08.19, switch to ACC/DEC time 2. | 0.00Hz |
| P08.21 | Reference frequency of ACC/DEC time | 0: Max. output frequency<br>1: Set frequency<br>2: 100Hz<br>Note: Valid only for straight-line ACC/DEC | 0 |
| P08.28 | Auto fault reset count | 0–10 | 0 |
| P08.29 | Auto fault reset interval | 0.1–3600.0s | 1.0s |

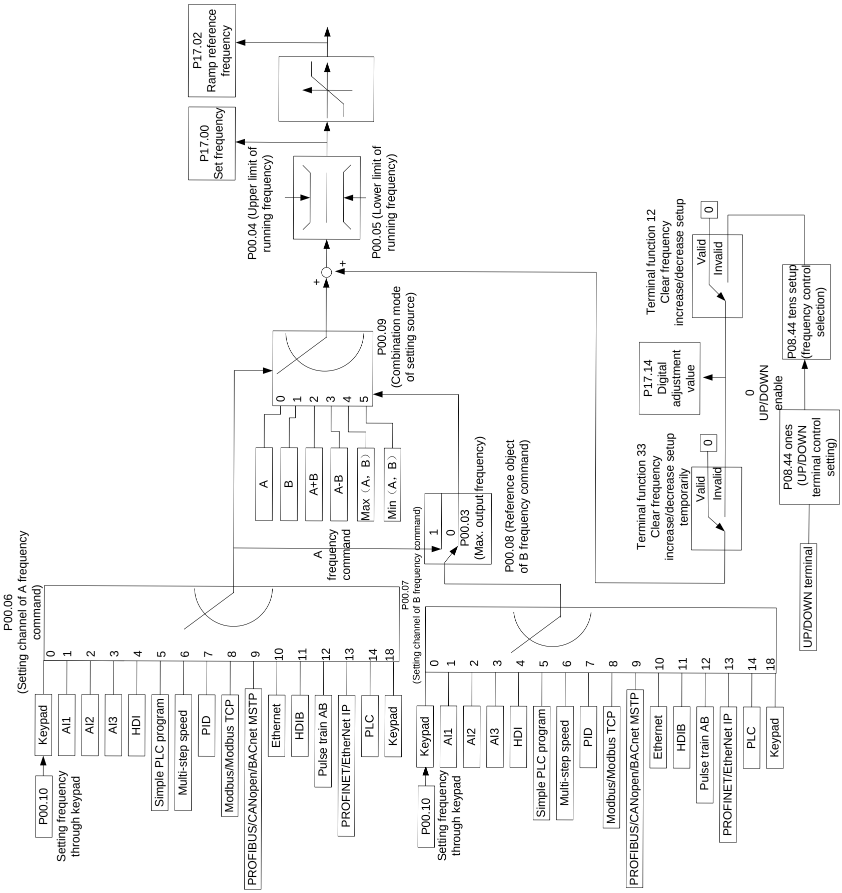
### 5.5.8 Frequency setting

The VFD supports multiple kinds of frequency reference modes, which can be categorized into two types: main reference channel and auxiliary reference channel.

There are two main reference channels, namely frequency reference channel A and frequency reference channel B. These two channels support simple arithmetical operation between each other, and they can be switched dynamically by setting multifunction terminals.

There is one input mode for auxiliary reference channel, namely terminal UP/DOWN switch input. By setting function codes, you can enable the corresponding reference mode and the impact made on the VFD frequency reference by this reference mode.

The VFD actual reference is comprised of the main reference channel and auxiliary reference channel.



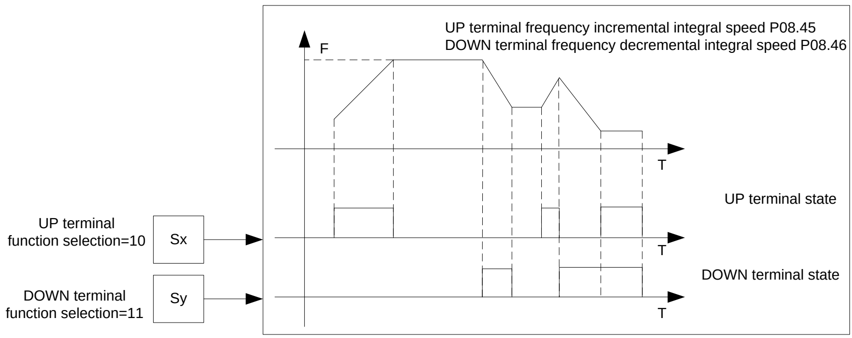

The VFD supports switchover between different reference channels, and the rules for channel switchover are shown as follows.

| Present reference channel P00.09 | Multifunction terminal function 13 (Switch from channel A to channel B) | Multifunction terminal function 14 (Switch from combined setting to channel A) | Multifunction terminal function 15 (Switch from combined setting to channel B) |
|---|---|---|---|
| A | B | / | / |
| B | A | / | / |
| A+B | / | A | B |

| Present reference channel P00.09 | Multifunction terminal function 13 (Switch from channel A to channel B) | Multifunction terminal function 14 (Switch from combined setting to channel A) | Multifunction terminal function 15 (Switch from combined setting to channel B) |
|---|---|---|---|
| A-B | / | A | B |
| Max(A, B) | / | A | B |
| Min(A, B) | / | A | B |

**Note:** "/" indicates this multifunction terminal is invalid under present reference channel.

When setting the auxiliary frequency inside the VFD through multifunction terminals UP (10) and DOWN (11), you can increase/decrease the frequency quickly by setting P08.45 (UP terminal frequency incremental change rate) and P08.46 (DOWN terminal frequency decremental change rate).




Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P00.03 | Max. output frequency | P00.04–400.00Hz | 50.00Hz |
| P00.04 | Upper limit of running frequency | P00.05–P00.03 | 50.00Hz |
| P00.05 | Lower limit of running frequency | 0.00Hz–P00.04 | 0.00Hz |
| P00.06 | Setting channel of A frequency command | 0: Keypad<br>1: AI1<br>2: AI2<br>3: AI3<br>4: High-speed pulse HDIA<br>5: Simple PLC program | 0 |
| P00.07 | Setting channel of B frequency command | | 15 |

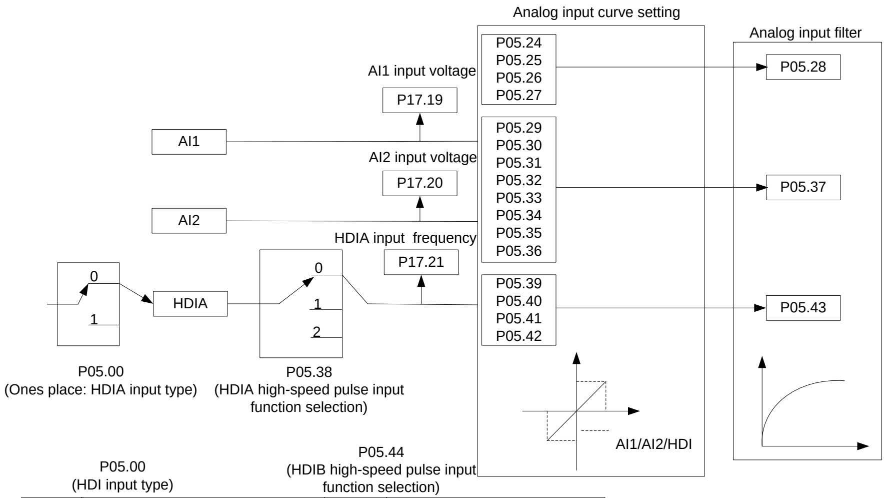
| Function code | Name | Description | Default |
|---|---|---|---|
| | | 6: Multi-step speed running<br>7: PID control<br>8: Modbus/Modbus TCP communication<br>9: PROFIBUS/CANopen /BACnet MSTP communication<br>10: Ethernet communication<br>11: High-speed pulse HDIB<br>12: Pulse train AB<br>13: PROFINET/EtherNet IP communication<br>14: Programmable card<br>15–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | |
| P00.08 | Reference object of B frequency command | 0: Max. output frequency<br>1: A frequency command | 0 |
| P00.09 | Combination mode of setting source | 0: A<br>1: B<br>2: (A+B)<br>3: (A-B)<br>4: Max(A, B)<br>5: Min(A, B) | 0 |
| P05.01–P05.06 | Function selection of multifunction digital input terminals (S1–S4, and HDIA) | 10: Increase frequency setting (UP)<br>11: Decrease frequency setting (DOWN)<br>12: Clear the frequency increase/decrease setting<br>13: Switch between A setting and B setting<br>14: Switch between combination setting and A setting<br>15: Switch between combination setting and B setting | |
| P08.42 | Keypad digital control setting | 0x0000–0x1223<br>Ones place: Frequency setting selection<br>0: Both the UP/DOWN key and digital potentiometer can be used for the control.<br>1: Only control through the UP/ DOWN key is valid.<br>2: Only control through the digital potentiometer is valid. | 0x0000 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 3: Controls through the UP/ DOWN key and digital potentiometer are invalid.<br>Tens place: Frequency control selection<br>0: Valid only when P00.06=0 or P00.07=0<br>1: Valid for all frequency setting methods<br>2: Invalid for multi-step speed running when multi-step speed running has the priority<br>Hundreds place: Action selection for stop<br>0: Setting is valid.<br>1: Valid during running, cleared after stop<br>2: Valid during running, cleared after a stop command is received<br>Thousands place: Indicates whether to enable the integral function through the UP/DOWN key and digital potentiometer.<br>0: Enable the integral function<br>1: Disable the integral function<br>**Note:** It is valid for LED keypad. | |
| P08.43 | Keypad digital potentiometer integral rate | 0.01–10.00s | 0.10s |
| P08.44 | UP/DOWN terminal control setting | 0x000–0x221<br>Ones place: Frequency setting selection<br>0: The setting made through UP/DOWN is valid.<br>1: The setting made through UP/DOWN is invalid.<br>Tens place: Frequency control selection<br>0: Valid only when P00.06=0 or P00.07=0<br>1: Valid for all frequency setting methods<br>2: Invalid for multi-step speed running when multi-step speed running has the priority<br>Hundreds place: Action selection for stop<br>0: Setting is valid.<br>1: Valid during running, cleared after stop<br>2: Valid during running, cleared after a stop command is received | 0x000 |
| P08.45 | Frequency increment change rate of the UP terminal | 0.01–50.00Hz/s<br>**Note:** The value is also used as the frequency increment or decrement that is made by pressing | 0.50Hz/s |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | the UP/DOWN key on the LCD keypad. | |
| P08.46 | Frequency reduce rate of the DOWN terminal | 0.01–50.00Hz/s | 0.50Hz/s |
| P17.00 | Set frequency | 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz |
| P17.02 | Ramp reference frequency | 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz |
| P17.14 | Digital adjustment value | 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz |

### 5.5.9 Analog input

The VFD carries two analog input terminals AI1 and AI2, in which AI1 supports the range of 0(2)–10V/0(4)–20mA (whether AI1 uses voltage input or current input can be set by P05.50; when AI1 uses current input, change the AI1 jumper cap on the control board from V to I) and AI2 supports the range of -10–+10V), and one high-speed pulse input terminal. Each input can be filtered separately, and the corresponding reference curve can be set by adjusting the reference corresponds to the max. value and min. value.




| | | | |
|---|---|---|---|
| P05.00 | Ones place:<br>0: HDIA is high-speed pulse input<br>1: HDIA is digital input | P05.38 | 0: Input set through frequency<br>1: Reserved<br>2: Reserved |
| | Tens place: (reserved)<br>0: HDIB is high-speed pulse input<br>1: HDIB is digital input | P05.44 | 0: Input set through frequency<br>1: Reserved<br>2: Reserved |

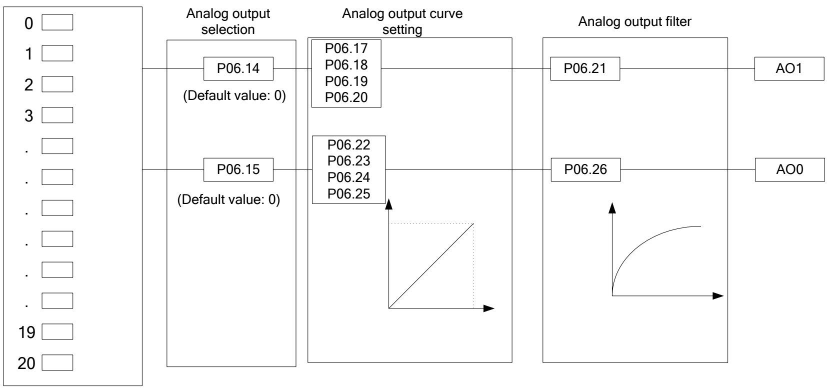
Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P05.00 | HDI input type | 0x00–0x11<br>Ones place: HDIA input type<br>0: HDIA is high-speed pulse input<br>1: HDIA is digital input<br>Tens place: HDIB input type (reserved)<br>0: HDIB is high-speed pulse input (reserved)<br>1: HDIB is digital input (reserved) | 0x00 |
| P05.24 | AI1 lower limit | 0.00V–P05.26 | 0.00V |
| P05.25 | Corresponding setting of AI1 lower limit | -300.0%–300.0% | 0.0% |
| P05.26 | AI1 upper limit | P05.24–10.00V | 10.00V |
| P05.27 | Corresponding setting of AI1 upper limit | -300.0%–300.0% | 100.0% |
| P05.28 | AI1 input filter time | 0.000s–10.000s | 0.100s |
| P05.29 | AI2 lower limit | -10.00V–P05.31 | -10.00V |
| P05.30 | Corresponding setting of AI2 lower limit | -300.0%–300.0% | -100.0% |
| P05.31 | AI2 middle value 1 | P05.29–P05.33 | 0.00V |
| P05.32 | Corresponding setting of AI2 middle value 1 | -300.0%–300.0% | 0.0% |
| P05.33 | AI2 middle value 2 | P05.31–P05.35 | 0.00V |
| P05.34 | Corresponding setting of AI2 middle value 2 | -300.0%–300.0% | 0.0% |
| P05.35 | AI2 upper limit | P05.33–10.00V | 10.00V |
| P05.36 | Corresponding setting of AI2 upper limit | -300.0%–300.0% | 100.0% |
| P05.37 | AI2 input filter time | 0.000s–10.000s | 0.100s |
| P05.38 | HDIA high-speed pulse input function selection | 0: Input set through frequency | 0 |
| P05.39 | HDIA frequency lower limit | 0.000kHz–P05.41 | 0.000kHz |
| P05.40 | Corresponding setting of HDIA frequency lower limit | -300.0%–300.0% | 0.0% |
| P05.41 | HDIA frequency upper limit | P05.39–50.000kHz | 50.000kHz |
| P05.42 | Corresponding setting of HDIA upper limit frequency | -300.0%–300.0% | 100.0% |

| Function code | Name | Description | Default |
|---|---|---|---|
| P05.43 | HDIA frequency input filter time | 0.000s–10.000s | 0.030s |
| P05.50 | AI1 input signal type | 0x00–0x11<br>Ones place: Input signal type<br>0: Voltage<br>1: Current<br>Tens place: Input value unit selection<br>0: All voltage type<br>1: Voltage for voltage-type input, current for current-type input<br>**Note:** After selecting voltage and current inputs for the function code, you also need to install the jumper on the control board in the correct position. | 0x00 |

### 5.5.10 Analog output

The VFD carries two analog output terminals (0–10V/0–20mA) and one high-speed pulse output terminal. Analog output signals can be filtered separately, and the proportional relation can be adjusted by setting the max. value, min. value, and the percentage of their corresponding output. Analog output signal can output motor speed, output frequency, output current, motor torque and motor power at a certain proportion.




AO output relationship description:

(The min. value and max. value of the output correspond to 0.0% and 100.00% of the pulse or analog default output. The actual output voltage or pulse frequency corresponds to the actual percentage, which can be set through function codes.)

| Setting | Function | Description |
|---|---|---|
| 0 | Running frequency | 0–Max. output frequency |
| 1 | Set frequency | 0–Max. output frequency |
| 2 | Ramp reference frequency | 0–Max. output frequency |
| 3 | Rotational speed | 0–Synchronous speed corresponding to max. output frequency |
| 4 | Output current (relative to the VFD) | 0–Twice the VFD rated current |
| 5 | Output current (relative to motor) | 0–Twice the motor rated current |
| 6 | Output voltage | 0–1.5 times the VFD rated voltage |
| 7 | Output power | 0–Twice the motor rated power |
| 8 | Set torque value (bipolar) | 0–Twice the motor rated current. A negative value corresponds to 0.0% by default. |
| 9 | Output torque (absolute value) | 0–±(Twice the motor rated torque) |
| 10 | AI1 input | 0–10V/0–20mA |
| 11 | AI2 input | 0V–10V. A negative value corresponds to 0.0% by default. |
| 12 | AI3 input | 0–10V/0–20mA |
| 13 | High-speed pulse HDIA input | 0.00–50.00kHz |
| 14 | Value 1 set through Modbus communication | 0–1000 |
| 15 | Value 2 set through Modbus communication | 0–1000 |
| 16 | Value 1 set through PROFIBUS/CANopen /BACnet MSTP communication | 0–1000 |
| 17 | Value 2 set through PROFIBUS/CANopen communication | 0–1000 |
| 18 | Value 1 set through Ethernet communication | 0–1000 |
| 19 | Value 2 set through Ethernet communication | 0–1000 |
| 20 | HDIB input value | 0.00–50.00kHz |
| 21 | Value 1 set through PROFINET/EtherNet IP communication | 0–1000. A negative value corresponds to 0.0% by default. |
| 22 | Torque current (bipolar) | 0–Three times the motor rated current. A negative value corresponds to 0.0% by default. |
| 23 | Exciting current | 0–Three times the motor rated current. A |

| Setting | Function | Description |
|---|---|---|
| | | negative value corresponds to 0.0% by default. |
| 24 | Set frequency (bipolar) | 0–Max. output frequency. A negative value corresponds to 0.0% by default. |
| 25 | Ramp reference frequency (bipolar) | 0–Max. output frequency. A negative value corresponds to 0.0% by default. |
| 26 | Rotational speed (bipolar) | 0–Synchronous rotation speed corresponding to max. output frequency. A negative value corresponds to 0.0% by default. |
| 27 | Value 2 set through PROFINET/EtherNet IP communication | 0–1000 |
| 28 | C_AO1 from CODESYS (Set P27.00 to 1.) | |
| 29 | C_AO2 from CODESYS (Set P27.00 to 1.) | |
| 30 | Rotational speed | 0–Twice the motor rated synchronous rotation speed |
| 31 | Output torque (bipolar) | 0–Twice the motor rated torque. A negative value corresponds to 0.0% by default. |
| 32 | PID1 output | |
| 33 | PID2 output | |
| 34 | PID1 reference value | |
| 35 | PID1 feedback value | |
| 36 | PID2 reference value | |
| 37 | PID2 feedback value | |
| 40 | Value 0 set through PROFIBUS/CANopen /BACnet MSTP communication | |
| 41 | Value 0 set through PROFINET/EtherNet IP communication | |

Related function parameters

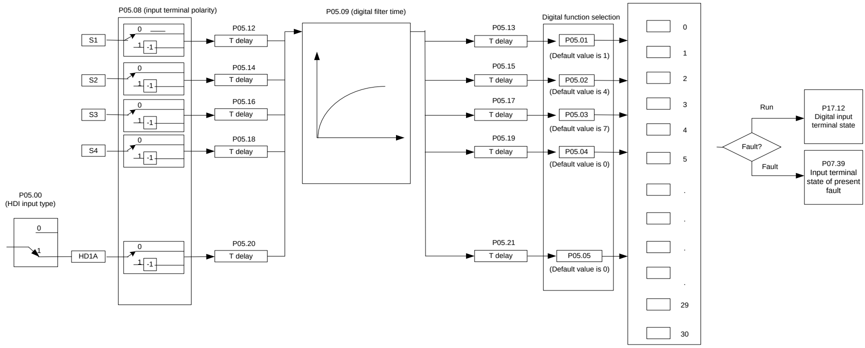
| Function code | Name | Description | Default |
|---|---|---|---|
| P06.14 | AO1 output | 0–47<br>0: Running frequency<br>1: Set frequency<br>2: Ramp reference frequency | 0 |
| P06.15 | AO0 output | | 0 |
| P06.16 | Reserved | | 0 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 3: Rotational speed<br>4: Output current (relative to the VFD)<br>5: Output current (relative to the motor)<br>6: Output voltage<br>7: Output power<br>8: Set torque<br>9: Output torque<br>10: AI1 input<br>11: AI2 input value<br>12: AI3 input value<br>13: High-speed pulse HDIA input<br>14: Value 1 set through Modbus communication<br>15: Value 2 set through Modbus communication<br>16: Value 1 set through PROFIBUS/CANopen /BACnet MSTP communication<br>17: Value 2 set through PROFIBUS/CANopen communication<br>18: Value 1 set through Ethernet communication<br>19: Value 2 set through Ethernet communication<br>20: HDIB input value<br>21: Value 1 set through PROFINET/EtherNet IP communication<br>22: Torque current (bipolar, 100% corresponding to 10V)<br>23: Exciting current (100% corresponding to 10V)<br>24: Set frequency (bipolar)<br>25: Ramp reference frequency (bipolar)<br>26: Rotational speed (bipolar)<br>27: Value 2 set through PROFINET/EtherNet IP communication<br>28: C_AO1 from CODESYS (Set P27.00 to 1.)<br>29: C_AO2 from CODESYS (Set P27.00 to 1.)<br>30: Rotational speed<br>31: Output torque<br>32: PID1 output<br>33: PID2 output<br>34: PID1 reference value<br>35: PID1 feedback value | |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 36: PID2 reference value<br>37: PID2 feedback value<br>38–39: Reserved<br>40: Value 0 set through PROFIBUS/CANopen /BACnet MSTP communication<br>41: Value 0 set through PROFINET/EtherNet IP communication<br>42–47: Reserved | |
| P06.17 | AO1 output lower limit | -300.0%–P06.19 | 0.0% |
| P06.18 | AO1 output corresponding to lower limit | 0.00V–10.00V | 0.00V |
| P06.19 | AO1 output upper limit | P06.17–300.0% | 100.0% |
| P06.20 | AO1 output corresponding to upper limit | 0.00V–10.00V | 10.00V |
| P06.21 | AO1 output filter time | 0.000s–10.000s | 0.000s |
| P06.22 | AO0 output lower limit | -300.0%–P06.23 | 0.0% |
| P06.23 | AO0 output corresponding to lower limit | 0.00V–10.00V | 0.00V |
| P06.24 | AO0 output upper limit | P06.35–300.0% | 100.0% |
| P06.25 | AO0 output corresponding to upper limit | 0.00V–10.00V | 10.00V |
| P06.26 | AO0 output filter time | 0.000s–10.000s | 0.000s |

### 5.5.11 Digital input

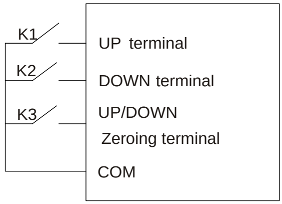
The VFD carries four programmable digital input terminals and two HDI input terminals. The function of all the digital input terminals can be programmed through function codes. HDI input terminal can be set to act as high-speed pulse input terminal or common digital input terminal; if it is set to act as a high-speed pulse input terminal, you can also set HDIA high-speed pulse input to serve as the frequency reference and encoder signal input.




This parameter is used to set the corresponding function of digital multi-function input terminals.

**Note:** Two different multifunction input terminals cannot be configured with a same function.

| Setting | Function | Description |
|---|---|---|
| 0 | No function | The VFD does not act even if there is signal input. Set unused terminals to "no function" to avoid misaction. |
| 1 | Run forward | External terminals are used to control the forward/reverse running of the inverter. |
| 2 | Run reversely | |
| 3 | Three-wire running control | The terminal is used to determine the three-wire running control of the VFD.<br>For details, see the description for P05.13. |
| 4 | Jog forward | For details about frequency of jogging running and ACC/DEC time of jogging running, see the description for P08.06, P08.07, and P08.08. |
| 5 | Jog reversely | |
| 6 | Coast to stop | The inverter blocks output, and the stop process of motor is uncontrolled by the inverter. This mode is applied in the scenarios with large-inertia loads and without stop time requirements.<br>Its definition is the same as P01.08, and it is mainly used in remote control. |
| 7 | Fault reset | External fault reset function, same as the reset function of the STOP/RST key on the keypad. You can use this function to reset faults remotely. |
| 8 | Pause running | The inverter decelerates to stop, however, all the run parameters are in memory state, such as PLC and PID parameters. After this signal disappears, the inverter will revert to the state before stop. |
| 9 | External fault input | When external fault signal is transmitted to the inverter, the inverter releases fault alarm and stops. |
| 10 | Increase frequency | Used to change the frequency increase/decrease command |

<table>
<tr><th>Setting</th><th>Function</th><th>Description</th></tr>
<tr><td></td><td>setting (UP)</td><td>when the frequency is given by external terminals.</td></tr>
<tr><td>11</td><td>Decrease frequency setting (DOWN)</td><td rowspan="2">

The terminal used to clear frequency-increase/decrease setting can clear the frequency value of auxiliary channel set by UP/DOWN, thus restoring the reference frequency to the frequency given by main reference frequency command channel.</td></tr>
<tr><td>12</td><td>Clear the frequency increase/decrease setting</td></tr>
<tr><td>13</td><td>Switch between A setting and B setting</td><td rowspan="3">The function is used to switch between the frequency setting channels.<br>Function 13 can implement the switchover between A frequency reference channel and B frequency reference channel; function 14 can implement the switchover between the combination channel set by P00.09 and the A frequency reference channel; function 15 can implement the switchover between the combination channel set by P00.09 and the B frequency reference channel.</td></tr>
<tr><td>14</td><td>Switch between combination setting and A setting</td></tr>
<tr><td>15</td><td>Switch between combination setting and B setting</td></tr>
<tr><td>16</td><td>Multi-step speed terminal 1</td><td rowspan="4">A total of 16-step speeds can be set by combining digital states of these four terminals.<br>Note: Multi-step speed 1 is the low-order bit, and multi-step speed 4 is the high-order bit.
<table>
<tr><th>Multi-step speed 4</th><th>Multi-step speed 3</th><th>Multi-step speed 2</th><th>Multi-step speed 1</th></tr>
<tr><td>Bit3</td><td>Bit2</td><td>Bit1</td><td>Bit0</td></tr>
</table></td></tr>
<tr><td>17</td><td>Multi-step speed terminal 2</td></tr>
<tr><td>18</td><td>Multi-step speed terminal 3</td></tr>
<tr><td>19</td><td>Multi-step speed terminal 4</td></tr>
<tr><td>20</td><td>Pause multi-step speed running</td><td>The multi-step speed selection function can be screened to keep the set value in the present state.</td></tr>
<tr><td>21</td><td>ACC/DEC time selection 1</td><td rowspan="2">The status of the two terminals can be combined to select four groups of ACC/DEC time.
<table>
<tr><th>Terminal 1</th><th>Terminal 2</th><th>ACC/DEC time</th><th>Parameter</th></tr>
<tr><td>OFF</td><td>OFF</td><td>ACC/DEC time 1</td><td>P00.11/P00.12</td></tr>
<tr><td>ON</td><td>OFF</td><td>ACC/DEC time 2</td><td>P08.00/P08.01</td></tr>
<tr><td>OFF</td><td>ON</td><td>ACC/DEC time 3</td><td>P08.02/P08.03</td></tr>
<tr><td>ON</td><td>ON</td><td>ACC/DEC time 4</td><td>P08.04/P08.05</td></tr>
</table></td></tr>
<tr><td>22</td><td>ACC/DEC time selection 2</td></tr>
<tr><td>23</td><td>Simple PLC stop reset</td><td>Used to clear the previous PLC state memory information and restart the simple PLC process.</td></tr>
<tr><td>24</td><td>Pause simple PLC</td><td>Used to pause the simple PLC. When the function is revoked,</td></tr>
</table>

| Setting | Function | Description |
|---|---|---|
| | | the simple PLC resumes the running. |
| 25 | Pause PID1 control | PID is ineffective temporarily, and the VFD maintains current frequency output. |
| 26 | Pause wobbling frequency | - |
| 27 | Reset wobbling frequency | - |
| 28 | Reset the counter | The counter is cleared. |
| 29 | Switch between speed control and torque control | The VFD switches from torque control mode to speed control mode, or vice versa. |
| 30 | Disable ACC/DEC | Used to ensure the VFD is not impacted by external signals (except for stop command), and maintains the present output frequency. |
| 31 | Trigger the counter | Used to enable the counter to count pulses. |
| 33 | Clear the frequency increase/decrease setting temporarily | When the terminal is closed, the frequency value set by UP/DOWN can be cleared to restore the reference frequency to the frequency given by frequency command channel; when the terminal is opened, it restores to the frequency value after frequency increase/decrease setting. |
| 34 | DC braking | The VFD starts DC brake immediately after the command becomes valid. |
| 35 | Switchover between motors 1 and 2 | When the function is enabled, you can realize switchover control of two motors. |
| 36 | Switch the running command channel to keypad | When the function is enabled, the running command channel is switched to keypad. When the function is disabled, the running command channel is restored to the previous setting. |
| 37 | Switch the running command channel to terminal | When the function is enabled, the running command channel is switched to terminal. When the function is disabled, the running command channel is restored to the previous setting. |
| 38 | Switch the running command channel to communication | When the function is enabled, the running command channel is switched to communication. When the function is disabled, the running command channel is restored to the previous setting. |
| 39 | Pre-exciting command | When the function is enabled, motor pre-exciting is started until the function becomes invalid. |
| 40 | Clear power consumption quantity | After this command becomes valid, the power consumption quantity of the VFD will be zeroed out. |
| 41 | Keep power consumption quantity | When the function is enabled, the present operation of the VFD does not impact the power consumption quantity. |
| 42 | Switch the setting source of braking torque | The torque upper limit is set through the keypad when the command is valid. |

| Setting | Function | Description |
|---|---|---|
| | upper limit to keypad | |
| 73 | PID2 start | When the command is valid, PID2 starts. |
| 74 | PID2 stop | When the command is valid, PID2 stops. |
| 75 | Pause PID2 integral | When the command is valid, PID2 integral is paused. |
| 76 | Pause PID2 control | When the command is valid, PID2 control is paused. |
| 77 | Switch PID2 polarities | When the command is valid, PID2 polarity is switched. |
| 78 | HVAC disabled (only in stopped state) | When the command is valid, HVAC is disabled (only in stopped state). |
| 79 | Trigger fire signal | When the command is valid, fire signal is triggered. |
| 80 | Pause PID1 control | When the command is valid, PID1 control is paused. |
| 81 | Pause PID1 integral | When the command is valid, PID1 integral is paused. |
| 82 | Switch PID1 polarities | When the command is valid, PID1 polarity is switched. |
| 83 | Trigger sleep mode | When the command is valid, the sleep mode is triggered. |
| 84 | Trigger wakeup mode | When the command is valid, the wakeup mode is triggered. |
| 85 | Manual alternation | When the command is valid, manual alternation is enabled. |
| 86 | Pump cleaning signal | When the command is valid, pump cleaning signal is triggered. |
| 87 | Water level upper limit of inlet pool | When the command is valid, the water level upper limit of inlet pool is reached. |
| 88 | Water level lower limit of inlet pool | When the command is valid, the water level lower limit of inlet pool is reached. |
| 89 | Water shortage level of inlet pool | When the command is valid, the water shortage level of inlet pool is reached. |
| 104 | Disable motor A | When the command is valid, motor A is disabled. |
| 105 | Disable motor B | When the command is valid, motor B is disabled. |
| 106 | Disable motor C | When the command is valid, motor C is disabled. |
| 107 | Disable motor D | When the command is valid, motor D is disabled. |
| 108 | Disable motor E | When the command is valid, motor E is disabled. |
| 109 | Disable motor F | When the command is valid, motor F is disabled. |
| 110 | Disable motor G | When the command is valid, motor G is disabled. |
| 111 | Disable motor H | When the command is valid, motor H is disabled. |

Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P05.00 | HDI input type | 0x00–0x11<br>Ones place: HDIA input type<br>0: HDIA is high-speed pulse input<br>1: HDIA is digital input<br>Tens place: Reserved | 0x00 |
| P05.01 | Function of S1 | 0: No function<br>1: Run forward | 1 |
| P05.02 | Function of S2 | | 4 |
| P05.03 | Function of S3 | | 7 |

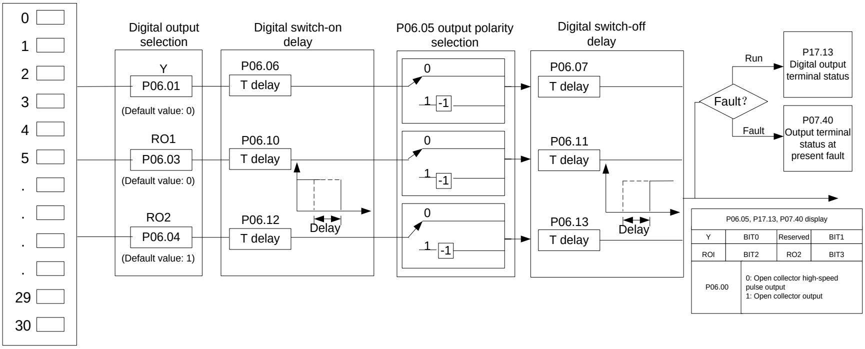
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th></tr>
<tr><td>P05.04</td><td>Function of S4</td><td rowspan="4">2: Run reversely<br>3: Three-wire running control<br>4: Jog forward<br>5: Jog reversely<br>6: Coast to stop<br>7: Fault reset<br>8: Pause running<br>9: External fault input<br>10: Increase frequency setting (UP)<br>11: Decrease frequency setting (DOWN)<br>12: Clear the frequency increase/decrease setting<br>13: Switch between A setting and B setting<br>14: Switch between combination setting and A setting<br>15: Switch between combination setting and B setting<br>16: Multi-step speed terminal 1<br>17: Multi-step speed terminal 2<br>18: Multi-step speed terminal 3<br>19: Multi-step speed terminal 4<br>20: Pause multi-step speed running<br>21: ACC/DEC time selection 1<br>22: ACC/DEC time selection 2<br>23: Simple PLC stop reset<br>24: Pause simple PLC<br>25: Pause PID1 control<br>26: Pause wobbling frequency<br>27: Reset wobbling frequency<br>28: Counter reset<br>29: Switch between speed control and torque control<br>30: Disable ACC/DEC<br>31: Trigger the counter<br>32: Reserved<br>33: Clear the frequency increase/decrease setting temporarily<br>34: DC braking</td><td>0</td></tr>
<tr><td>P05.05</td><td>Function of HDIA</td><td>0</td></tr>
<tr><td>P05.06</td><td>Reserved</td><td>/</td></tr>
<tr><td>P05.07</td><td>Reserved</td><td>/</td></tr>
</table>

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 35: Switch from motor 1 to motor 2<br>36: Switch the running command channel to keypad<br>37: Switch the running command channel to terminal<br>38: Switch the running command channel to communication<br>39: Pre-exciting command<br>40: Clear electricity consumption<br>41: Keep electricity consumption<br>42: Switch the setting source of braking torque upper limit to keypad<br>43–72: Reserved<br>73: PID2 start<br>74: PID2 stop<br>75: Pause PID2 integral<br>76: Pause PID2 control<br>77: Switch PID2 polarities<br>78: Disable HVAC (only in stopped state)<br>79: Trigger fire signal<br>80: Pause PID1 control<br>81: Pause PID1 integral<br>82: Switch PID1 polarities<br>83: Trigger sleep mode<br>84: Trigger wakeup mode<br>85: Manual alternation<br>86: Pump cleaning signal<br>87: Water level upper limit of inlet pool<br>88: Water level lower limit of inlet pool<br>89: Water shortage level of inlet pool<br>90–103: Reserved<br>104: Disable motor A<br>105: Disable motor B<br>106: Disable motor C<br>107: Disable motor D<br>108: Disable motor E<br>109: Disable motor F<br>110: Disable motor G | |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 111: Disable motor H | |
| P05.08 | Input terminal polarity selection | 0x00–0x3F | 0x00 |
| P05.09 | Digital input filter time | 0.000–1.000s | 0.010s |
| P05.10 | Virtual terminal setting | 0x00–0x3F (0: disable, 1: enable)<br>Bit0: S1 virtual terminal<br>Bit1: S2 virtual terminal<br>Bit2: S3 virtual terminal<br>Bit3: S4 virtual terminal<br>Bit 4: HDIA virtual terminal<br>Bit5: HDIB (reserved) | 0x00 |
| P05.11 | Terminal control mode | 0: Two-wire control mode 1<br>1: Two-wire control mode 2<br>2: Three-wire control mode 1<br>3: Three-wire control mode 2 | 0 |
| P05.12 | S1 switch-on delay | 0.000–50.000s | 0.000s |
| P05.13 | S1 switch-off delay | 0.000–50.000s | 0.000s |
| P05.14 | S2 switch-on delay | 0.000–50.000s | 0.000s |
| P05.15 | S2 switch-off delay | 0.000–50.000s | 0.000s |
| P05.16 | S3 switch-on delay | 0.000–50.000s | 0.000s |
| P05.17 | S3 switch-off delay | 0.000–50.000s | 0.000s |
| P05.18 | S4 switch-on delay | 0.000–50.000s | 0.000s |
| P05.19 | S4 switch-off delay | 0.000–50.000s | 0.000s |
| P05.20 | HDIA switch-on delay | 0.000–50.000s | 0.000s |
| P05.21 | HDIA switch-off delay | 0.000–50.000s | 0.000s |
| P07.39 | Input terminal status at present fault | 0x0000–0xFFFF | 0x0000 |
| P17.12 | Digital input terminal state | 0x0000–0xFFFF | 0x0000 |

### 5.5.12 Digital output

The VFD carries two groups of relay output terminals and one open collector Y output terminal. All the digital output terminal functions can be used for programming through function code setting.




The following table lists the function code options. A same output terminal function can be repeatedly selected.

| Setting | Function | Description |
|---|---|---|
| 0 | Invalid | The output terminal does not have any function. |
| 1 | Running | The ON signal is output when there is frequency output during running. |
| 2 | Running forward | The ON signal is output when there is frequency output during forward running. |
| 3 | Running reversely | The ON signal is output when there is frequency output during reverse running. |
| 4 | Jogging | The ON signal is output when there is frequency output during jogging. |
| 5 | Inverter fault | The ON signal is output when an inverter fault occurred. |
| 6 | Frequency level detection FDT1 | Refer to the descriptions for P08.32 and P08.33. |
| 7 | Frequency level detection FDT2 | Refer to the descriptions for P08.34 and P08.35. |
| 8 | Frequency reached | Refer to the description for P08.36. |
| 9 | Running in zero speed | The ON signal is output when the VFD output frequency and reference frequency are both zero. |
| 10 | Upper limit frequency reached | The ON signal is output when the running frequency reaches the upper limit frequency. |
| 11 | Lower limit frequency reached | Output ON signal when the running frequency reached lower limit frequency |
| 12 | Ready for running | Main circuit and control circuit powers are established, the protection functions do not act; when the VFD is ready to run, output ON signal. |
| 13 | Pre-exciting | Output ON signal during pre-exciting of the VFD |

| Setting | Function | Description |
|---|---|---|
| 14 | Overload pre-alarm | The ON signal is output when the pre-alarm time elapsed based on the pre-alarm threshold; for details, see descriptions for P11.08–P11.10. |
| 15 | Underload pre-alarm | The ON signal is output after the alarm time elapsed based on the alarm threshold. For details, see the descriptions for P11.11–P11.12. |
| 16 | Simple PLC stage completed | When the present state of the simple PLC is completed, it outputs a signal. |
| 17 | Simple PLC cycle completed | When a single cycle of the simple PLC is completed, it outputs a signal. |
| 18 | Set counting value reached | - |
| 19 | Designated counting value reached | - |
| 20 | External fault is valid | - |
| 22 | Running time reached | - |
| 23 | Modbus communication virtual terminal output | A signal is output based on the value set through Modbus communication. When the value is 1, the ON signal is output; when the value is 0, the OFF signal is output. |
| 24 | POROFIBUS/CANopen/BACnet MSTP communication virtual terminal output | Output corresponding signal based on the set value of PROFIBUS/CANopen/BACnet MSTP. (Output ON signal when it is set to 1, output OFF signal when it is set to 0.) |
| 25 | Ethernet communication virtual terminal output | A signal is output based on the value set through Ethernet communication. When the value is 1, the ON signal is output; when the value is 0, the OFF signal is output. |
| 26 | DC bus voltage established | When the bus voltage is above the inverter undervoltage, the output is valid. |
| 33 | In speed limit | - |
| 34 | PROFINET/EtherNet IP communication virtual terminal output | A signal is output based on the value set through PROFINET/EtherNet IP communication. (Output ON signal when it is set to 1, output OFF signal when it is set to 0.) |
| 37 | Any frequency reached | - |
| 48 | Fire mode activated | - |
| 49 | Pre-alarm of PID1 feedback too low | - |
| 50 | Pre-alarm of PID1 feedback too high | - |
| 51 | PID1 in sleep | - |
| 52 | PID2 in startup | - |
| 53 | PID2 stopped | - |

| Setting | Function | Description |
|---|---|---|
| 54 | Indication of run with backup pressure | - |
| 55 | Water shortage indication of inlet pool | - |
| 56 | Pre-alarm output | - |
| 57 | Control variable-frequency circulation motor A | - |
| 58 | Control variable-frequency circulation motor B | - |
| 59 | Control variable-frequency circulation motor C | - |
| 60 | Control variable-frequency circulation motor D | - |
| 61 | Control variable-frequency circulation motor E | - |
| 62 | Control variable-frequency circulation motor F | - |
| 63 | Control variable-frequency circulation motor G | - |
| 64 | Control variable-frequency circulation motor H | - |
| 65 | Low temperature pre-alarm | - |
| 66 | Stalling pre-alarm | - |
| 67 | Dry-pumping pre-alarm | - |
| 68 | PTC overtemperature pre-alarm | - |

Related function parameters

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th></tr>
<tr><td>P06.01</td><td>Y1 output</td><td rowspan="4">0: Invalid<br>1: Running<br>2: Running forward<br>3: Running reversely<br>4: Jogging<br>5: VFD in fault<br>6: Frequency level detection FDT1<br>7: Frequency level detection FDT2<br>8: Frequency reached<br>9: Running in zero speed</td><td>0</td></tr>
<tr><td>P06.02</td><td>Reserved</td><td>-</td></tr>
<tr><td>P06.03</td><td>RO1 output</td><td>1</td></tr>
<tr><td>P06.04</td><td>Reserved</td><td>-</td></tr>
</table>

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 10: Upper limit frequency reached<br>11: Frequency lower limit reached<br>12: Ready for running<br>13: Pre-exciting<br>14: Overload pre-alarm<br>15: Underload pre-alarm<br>16: Simple PLC stage completed<br>17: Simple PLC cycle completed<br>18: Set counting value reached<br>19: Designated counting value reached<br>20: External fault is valid<br>21: Reserved<br>22: Running time reached<br>23: MODBUS communication virtual terminal output<br>24: PROFIBUS/CANopen/BACnet MSTP communication virtual terminal output<br>25: Ethernet communication virtual terminal output<br>26: DC bus voltage established<br>27–32: Reserved<br>33: In speed limit<br>PROFINET/EtherNet IP communication virtual terminal output<br>35–36: Reserved<br>37: Any frequency reached<br>38–47: Reserved<br>48: Fire mode activated<br>49: Pre-alarm of PID1 feedback too low<br>50: Pre-alarm of PID1 feedback too high<br>51: PID1 in sleep<br>52: PID2 in startup<br>53: PID2 stopped<br>54: Indication of run with backup pressure<br>55: Water shortage indication of inlet pool<br>56: Pre-alarm output<br>57: Control variable-frequency circulation motor A<br>58: Control variable-frequency circulation motor B | |

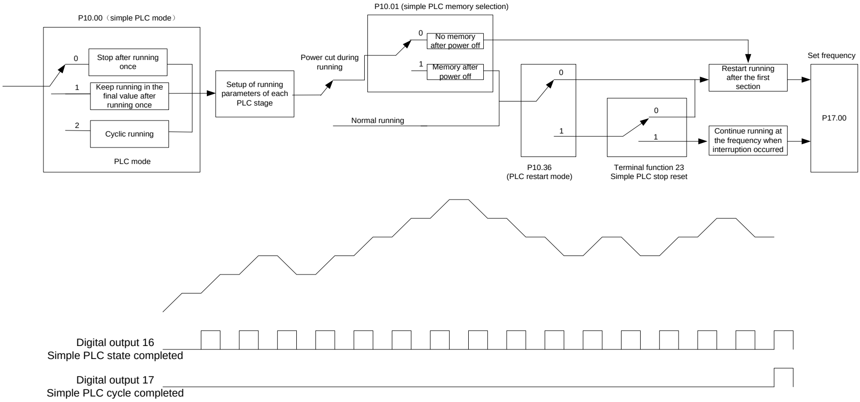
| Function code | Name | Description | Default |
|---|---|---|---|
| | | 59: Control variable-frequency circulation motor C<br>60: Control variable-frequency circulation motor D<br>61: Control variable-frequency circulation motor E<br>62: Control variable-frequency circulation motor F<br>63: Control variable-frequency circulation motor G<br>64: Control variable-frequency circulation motor H<br>65: Low-temperature pre-alarm<br>66: Stalling pre-alarm<br>67: Dry-pumping pre-alarm<br>68: PTC overtemperature pre-alarm | |
| P06.05 | Output terminal polarity | 0x00–0x0F | 0x00 |
| P06.06 | Y switch-on delay | 0.000–50.000s | 0.000s |
| P06.07 | Y switch-off delay | 0.000–50.000s | 0.000s |
| P06.10 | RO1 switch-on delay | 0.000–50.000s | 0.000s |
| P06.11 | RO1 switch-off delay | 0.000–50.000s | 0.000s |
| P07.40 | Output terminal status at present fault | 0x0000–0xFFFF | 0x0000 |
| P17.13 | Digital output terminal status | 0x0000–0x000F | 0x0000 |

### 5.5.13 Simple PLC

Simple PLC is a multi-step speed generator, and the VFD can change the running frequency and direction automatically based on the running time to fulfill process requirements. Previously, such function was realized with external PLC, while now, the VFD itself can achieve this function.

The VFD can realize 16-step speeds control, and provide four groups of acceleration/deceleration time for choose.

After the set PLC completes one cycle (or one step), one ON signal can be output by the multifunction relay.



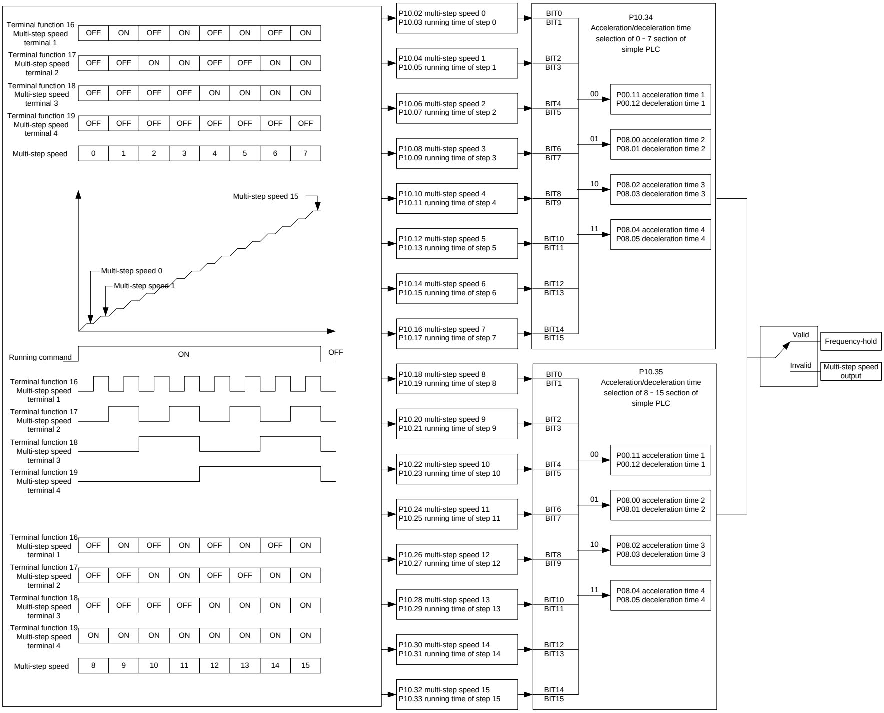

Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P05.01–P05.06 | Digital input function selection | 23: Simple PLC stop reset<br>24: Pause simple PLC<br>25: Pause PID control | 0 |
| P06.01–P06.04 | Digital output function selection | 16: Simple PLC stage reached<br>17: Simple PLC cycle reached | 0 |
| P10.00 | Simple PLC mode | 0: Stop after running once<br>1: Keep running with the final value after running once<br>2: Cyclic running | 0 |
| P10.01 | Simple PLC memory selection | 0: Do not memorize at power outage<br>1: Memorize at power outage | 0 |
| P10.02 | Multi-step speed 0 | -300.0%–300.0% | 0.0% |
| P10.03 | Running time of step 0 | 0.0–6553.5s (min) | 0.0s |
| P10.04 | Multi-step speed 1 | -300.0%–300.0% | 0.0% |
| P10.05 | Running time of step 1 | 0.0–6553.5s (min) | 0.0s |
| P10.06 | Multi-step speed 2 | -300.0%–300.0% | 0.0% |
| P10.07 | Running time of step 2 | 0.0–6553.5s (min) | 0.0s |
| P10.08 | Multi-step speed 3 | -300.0%–300.0% | 0.0% |
| P10.09 | Running time of step 3 | 0.0–6553.5s (min) | 0.0s |
| P10.10 | Multi-step speed 4 | -300.0%–300.0% | 0.0% |
| P10.11 | Running time of step 4 | 0.0–6553.5s (min) | 0.0s |
| P10.12 | Multi-step speed 5 | -300.0%–300.0% | 0.0% |
| P10.13 | Running time of step 5 | 0.0–6553.5s (min) | 0.0s |
| P10.14 | Multi-step speed 6 | -300.0%–300.0% | 0.0% |
| P10.15 | Running time of step 6 | 0.0–6553.5s (min) | 0.0s |

| Function code | Name | Description | Default |
|---|---|---|---|
| P10.16 | Multi-step speed 7 | -300.0%–300.0% | 0.0% |
| P10.17 | Running time of step 7 | 0.0–6553.5s (min) | 0.0s |
| P10.18 | Multi-step speed 8 | -300.0%–300.0% | 0.0% |
| P10.19 | Running time of step 8 | 0.0–6553.5s (min) | 0.0s |
| P10.20 | Multi-step speed 9 | -300.0%–300.0% | 0.0% |
| P10.21 | Running time of step 9 | 0.0–6553.5s (min) | 0.0s |
| P10.22 | Multi-step speed 10 | -300.0%–300.0% | 0.0% |
| P10.23 | Running time of step 10 | 0.0–6553.5s (min) | 0.0s |
| P10.24 | Multi-step speed 11 | -300.0%–300.0% | 0.0% |
| P10.25 | Running time of step 11 | 0.0–6553.5s (min) | 0.0s |
| P10.26 | Multi-step speed 12 | -300.0%–300.0% | 0.0% |
| P10.27 | Running time of step 12 | 0.0–6553.5s (min) | 0.0s |
| P10.28 | Multi-step speed 13 | -300.0%–300.0% | 0.0% |
| P10.29 | Running time of step 13 | 0.0–6553.5s (min) | 0.0s |
| P10.30 | Multi-step speed 14 | -300.0%–300.0% | 0.0% |
| P10.31 | Running time of step 14 | 0.0–6553.5s (min) | 0.0s |
| P10.32 | Multi-step speed 15 | -300.0%–300.0% | 0.0% |
| P10.33 | Running time of step 15 | 0.0–6553.5s (min) | 0.0s |
| P10.34 | ACC/DEC time of steps 0–7 of simple PLC | 0x0000–0xFFFF | 0x0000 |
| P10.35 | ACC/DEC time of steps 8–15 of simple PLC | 0x0000–0xFFFF | 0x0000 |
| P10.36 | PLC restart mode | 0: Restart from multi-step speed 0.<br>1: Resume from the paused step. | 0 |
| P17.00 | Set frequency | 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz |
| P17.27 | Present step of simple PLC | Used to display the present step of the simple PLC function. | 0 |

### 5.5.14 Multi-step speed running

Set the parameters used in multi-step speed running. The VFD allows you to set 16-step speeds, which are selectable by multi-step speed terminals 1–4, corresponding to multi-step speed 0 to multi-step speed 15.



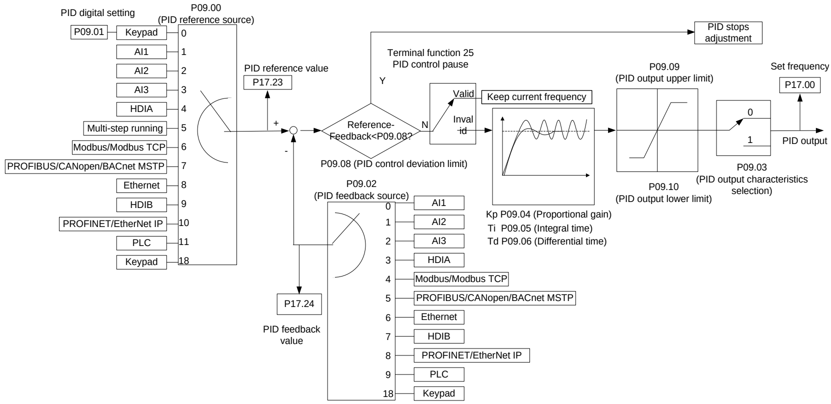

Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P05.01–P05.06 | Digital input function selection | 16: Multi-step speed terminal 1<br>17: Multi-step speed terminal 2<br>18: Multi-step speed terminal 3<br>19: Multi-step speed terminal 4<br>20: Pause multi-step speed running | 0 |
| P10.02 | Multi-step speed 0 | -300.0%–300.0% | 0.0% |
| P10.03 | Running time of step 0 | 0.0–6553.5s (min) | 0.0s |
| P10.04 | Multi-step speed 1 | -300.0%–300.0% | 0.0% |
| P10.05 | Running time of step 1 | 0.0–6553.5s (min) | 0.0s |
| P10.06 | Multi-step speed 2 | -300.0%–300.0% | 0.0% |
| P10.07 | Running time of step 2 | 0.0–6553.5s (min) | 0.0s |
| P10.08 | Multi-step speed 3 | -300.0%–300.0% | 0.0% |
| P10.09 | Running time of step 3 | 0.0–6553.5s (min) | 0.0s |
| P10.10 | Multi-step speed 4 | -300.0%–300.0% | 0.0% |
| P10.11 | Running time of step 4 | 0.0–6553.5s (min) | 0.0s |

| Function code | Name | Description | Default |
|---|---|---|---|
| P10.12 | Multi-step speed 5 | -300.0%–300.0% | 0.0% |
| P10.13 | Running time of step 5 | 0.0–6553.5s (min) | 0.0s |
| P10.14 | Multi-step speed 6 | -300.0%–300.0% | 0.0% |
| P10.15 | Running time of step 6 | 0.0–6553.5s (min) | 0.0s |
| P10.16 | Multi-step speed 7 | -300.0%–300.0% | 0.0% |
| P10.17 | Running time of step 7 | 0.0–6553.5s (min) | 0.0s |
| P10.18 | Multi-step speed 8 | -300.0%–300.0% | 0.0% |
| P10.19 | Running time of step 8 | 0.0–6553.5s (min) | 0.0s |
| P10.20 | Multi-step speed 9 | -300.0%–300.0% | 0.0% |
| P10.21 | Running time of step 9 | 0.0–6553.5s (min) | 0.0s |
| P10.22 | Multi-step speed 10 | -300.0%–300.0% | 0.0% |
| P10.23 | Running time of step 10 | 0.0–6553.5s (min) | 0.0s |
| P10.24 | Multi-step speed 11 | -300.0%–300.0% | 0.0% |
| P10.25 | Running time of step 11 | 0.0–6553.5s (min) | 0.0s |
| P10.26 | Multi-step speed 12 | -300.0%–300.0% | 0.0% |
| P10.27 | Running time of step 12 | 0.0–6553.5s (min) | 0.0s |
| P10.28 | Multi-step speed 13 | -300.0%–300.0% | 0.0% |
| P10.29 | Running time of step 13 | 0.0–6553.5s (min) | 0.0s |
| P10.30 | Multi-step speed 14 | -300.0%–300.0% | 0.0% |
| P10.31 | Running time of step 14 | 0.0–6553.5s (min) | 0.0s |
| P10.32 | Multi-step speed 15 | -300.0%–300.0% | 0.0% |
| P10.33 | Running time of step 15 | 0.0–6553.5s (min) | 0.0s |
| P10.34 | ACC/DEC time of steps 0–7 of simple PLC | 0x0000–0xFFFF | 0x0000 |
| P10.35 | ACC/DEC time of steps 8–15 of simple PLC | 0x0000–0xFFFF | 0x0000 |
| P17.27 | Present step of simple PLC | Used to display the present step of the simple PLC function. | 0 |

### 5.5.15 PID control

PID control, a common mode for process control, is mainly used to adjust the VFD output frequency or output voltage by performing scale-division, integral and differential operations on the difference between feedback signal of controlled variables and signal of the target, thus forming a negative feedback system to keep the controlled variables above the target. It is applicable to flow control, pressure control, temperature control, and so on. The following is the basic schematic block diagram for output frequency regulation.




Introduction to the working principles and control methods for PID control:

Proportional control (Kp): When the feedback is different from the reference, the output will be proportional to the difference. If such a difference is constant, the regulating variable will also be constant. Proportional control can respond to feedback changes rapidly, however, it cannot eliminate the difference by itself. A larger proportional gain indicates a faster regulating speed, but a too large gain will result in oscillation. To solve this problem, set the integral time to a large value and the differential time to 0, run the system only with proportional control, and then change the reference to observe the difference (that is, static difference) between the feedback signal and reference. If the static difference occurs in the direction of reference change (such as reference increase, where the feedback is always less than the reference after system stabilizes), continue increasing the proportional gain; otherwise, decrease the proportional gain. Repeat this process until the static difference becomes small.

Integral time (Ti): When feedback is different from reference, the output regulating variable accumulates continuously, if the difference persists, the regulating variable will increase continuously until difference disappears. The integral regulator can be used to eliminate static difference. However, too large regulation may lead to repetitive overshoot, which will cause system instability and oscillation. The feature of oscillation caused by strong integral effect is that the feedback signal fluctuates up and down based on the reference variable, and fluctuation range increases gradually until oscillation occurs. The integral time parameter is generally regulated gradually from large to small until the stabilized system speed fulfills the requirement.

Differential time (Td): When the difference between feedback and reference changes, there is output of the regulating variable that is proportional to the difference variation rate, and this regulating variable is only related to the direction and magnitude of the difference change rather than the direction and magnitude of the difference itself. Differential control is used to control the feedback signal variation based on the change trend. Exercise caution before using the differential regulator since it may enlarge the system interferences, especially those with high change frequency.

When P00.06 or P00.07 (Setting channel of A/B frequency command) is 7 or P04.27 (Voltage setting channel) is 6, the VFD is process PID controlled.

#### 5.5.15.1 General procedures for PID parameter setup

1. Determine proportional gain P.

   When determining proportional gain P, first, remove the integral term and derivative term of PID by making Ti=0 and Td=0 (see PID parameter setup for details), thus turning PID into pure proportional control. Set the input to 60%–70% of the max. allowable value, and increase proportional gain P gradually from 0 until system oscillation occurred, and then in turn, decrease proportional gain P gradually from current value until system oscillation disappears, record the proportional gain P at this point and set the proportional gain P of PID to 60%–70% of current value. This is the entire commissioning procedure of proportional gain P.

2. Determine integral time Ti.

   After proportional gain P is determined, set the initial value of integral time Ti to a large value, and decrease Ti gradually until system oscillation occurs. Then in reverse, increase Ti until system oscillation disappears. Record the value of Ti at this point. Set the integral time constant Ti of PID to 150%–180% of this value. This is the commissioning procedure of integral time constant Ti.

3. Determine derivative time Td.

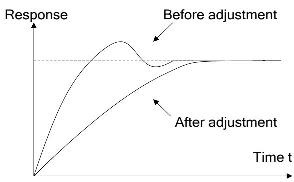
   The differential time Td is generally set to 0. If you need to set Td to another value, the setting method is similar to that for P and Ti, namely, set Td to 30% of the value when there is no oscillation.

4. Empty system load, perform load-carrying joint debugging, and then adjust PID parameters until fulfilling the requirement.

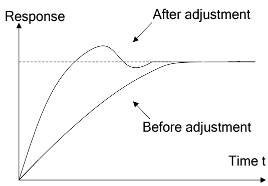
#### 5.5.15.2 How to fine-tune PID

After setting the parameters controlled by PID, you can adjust these parameters by the following means.

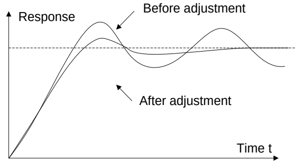
Control overshoot: When overshoot occurred, shorten the derivative time (Td) and prolong integral time (Ti).



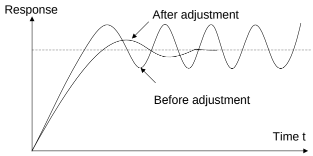

Stabilize the feedback value as fast as possible: When overshoot occurred, shorten integral time (Ti) and prolong derivative time (Td) to stabilize control as fast as possible.



Control long-term vibration: If the cycle of periodic vibration is longer than the set value of integral time (Ti), it indicates the integral action is too strong, prolong the integral time (Ti) to control vibration.




Control short-term vibration: If the vibration cycle is as short almost the same as the set value of differential time (Td), it indicates the differential action is too strong. Shorten the differential time (Td) to control vibration. When the differential time (Td) is set to 0.00 (namely no differential control), and there is no way to control vibration, decrease the proportional gain.




Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P09.00 | PID reference source | 0: Keypad (P09.01)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: High-speed pulse HDIA<br>5: Multi-step running<br>6: Modbus/Modbus TCP communication<br>7: PROFIBUS/CANopen /BACnet MSTP communication<br>8: Ethernet communication<br>9: High-speed pulse HDIB<br>10: PROFINET/EtherNet IP communication<br>11: Programable card<br>12–17: Reserved<br>18: Keypad analog | 0 |
| P09.01 | PID digital setting | -100.0%–100.0% | 0.0% |
| P09.02 | PID feedback source | 0: AI1<br>1: AI2<br>2: AI3<br>3: High-speed pulse HDIA<br>4: Modbus/Modbus TCP communication | 0 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 5: PROFIBUS/CANopen /BACnet MSTP communication<br>6: Ethernet communication<br>7: High-speed pulse HDIB<br>8: PROFINET/EtherNet IP communication<br>9: Programable card<br>10–17: Reserved<br>18: Keypad analog | |
| P09.03 | PID output characteristics selection | 0: PID output is positive.<br>1: PID output is negative. | 0 |
| P09.04 | Proportional gain (Kp) | 0.00–100.00 | 1.80 |
| P09.05 | Integral time (Ti) | 0.01–10.00s | 0.90s |
| P09.06 | Differential time (Td) | 0.00–10.00s | 0.00s |
| P09.07 | Sampling cycle (T) | 0.000–10.000s | 0.100s |
| P09.08 | PID control deviation limit | 0.0–100.0% | 0.0% |
| P09.09 | PID output upper limit | P09.10–100.0% (of max. frequency or voltage) | 100.0% |
| P09.10 | PID output lower limit | -100.0%–P09.09 (of max. frequency or voltage) | 0.0% |
| P09.11 | Feedback offline detection value | 0.0–100.0% | 0.0% |
| P09.12 | Feedback offline detection time | 0.0–3600.0s | 1.0s |
| P09.13 | PID control selection | 0x0000–0x1111<br>Ones place:<br>0: Continue integral control after the frequency reaches upper/lower limit<br>1: Stop integral control after the frequency reaches upper/lower limit<br>Tens place:<br>0: Same as the main reference direction<br>1: Contrary to the main reference direction<br>Hundreds place:<br>0: Limit as per the max. frequency<br>1: Limit as per A frequency<br>Thousands place:<br>0: A+B frequency. Acceleration /deceleration of main reference A frequency source buffering is invalid. | 0x0001 |

| Function code | Name | Description | Default |
|---|---|---|---|
| | | 1: A+B frequency. ACC/DEC of main reference A frequency source precharging is valid. **Note:** The ACC/DEC time corresponding to the thousands place is determined by ACC time 4 of P08.04. | |
| P09.14 | Low frequency proportional gain (Kp) | 0.00–100.00 | 1.00 |
| P09.15 | ACC/DEC time of PID command | 0.0–1000.0s | 0.0s |
| P09.16 | PID output filter time | 0.000–10.000s | 0.000s |
| P09.18 | Low frequency integral time (Ti) | 0.00–10.00s | 0.90s |
| P09.19 | Low frequency differential time (Td) | 0.00–10.00s | 0.00s |
| P09.20 | Low frequency point for PID parameter switching | 0.00–P09.21 | 5.00Hz |
| P09.21 | High frequency point for PID parameter switching | P09.20–P00.04 | 10.00Hz |
| P17.00 | Set frequency | 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz |
| P17.23 | PID1 reference value | -100.0%–100.0% | 0.0% |
| P17.24 | PID1 feedback value | -100.0%–100.0% | 0.0% |

### 5.5.16 Water pump control

The VFD provides the multi-pump control function, applicable to the scenario with the simultaneous operation of up to eight water pumps, capable of balancing fluctuations in water pressure and flow. This function simplifies the control system and controls the start and stop of each pump motor in balance mode to ensure optimal performance of the water system. To use this function, configure the following sub-functions based on requirements:

- ✧ Motor adding or reducing
- ✧ Multi-pump alternation
- ✧ Water pump maintenance
- ✧ Smooth switchover

**Function description**

The following describes the function by illustrating a typical case in which one VFD controls four water pump motors.

The VFD must use the four relay function terminals RO5–RO8 (requiring the use of the optional part EC-IO503-00), and also use two groups of contactor KM to switch between the two water pump working states, variable-frequency run mode and power-frequency run mode. All motors are started and stopped at the ramp speed to achieve soft motor switchover to ensure stable water supply pressure and reduce the impact on water pipes. You need to refer to Figure 5-28 and Figure 5-29 to connect the multi-pump variable-frequency control main circuit and external relay control circuit. In addition, make the following settings:

1. Enable the multi-pump control function (P94.00=1).

2. Set the variable-frequency motor run mode to circular (P94.10=1).

3. Set the motor quantity to 4 (P94.11=4).

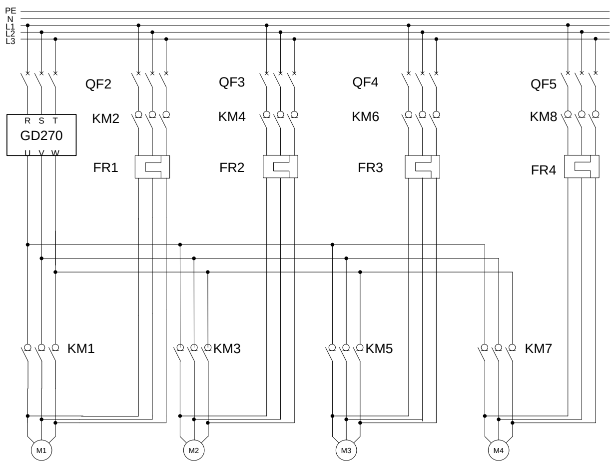
4. Set RO5–RO8 to control variable-frequency circulation pumps A, B, C, and D (that is, set P26.06–P26.09 to 57–60 respectively).

5. Set the contactor closing delay, which is the interval of switchover between the variable-frequency run mode and power-frequency run mode.

6: Set the S digital input terminal functions to 104–107 to cut out circulation motors M1–M4.

**Note:**

- ✧ After the multi-pump control function is enabled, the VFD setting frequency can be given only by the water supply dedicated PID—PID1.
- ✧ It is not recommended to use the multi-pump control function on the 30kW or higher VFDs.
- ✧ Connected water pump motors must have the same rated power.




KM1–KM8: Contactors FR1–FR4: Thermal protection overload relays

QF2–QF5: Low-voltage circuit breaker M1–M4: Asynchronous motor

Figure 5-28 Main circuit wiring in variable-frequency control mode of one VFD driving four pumps

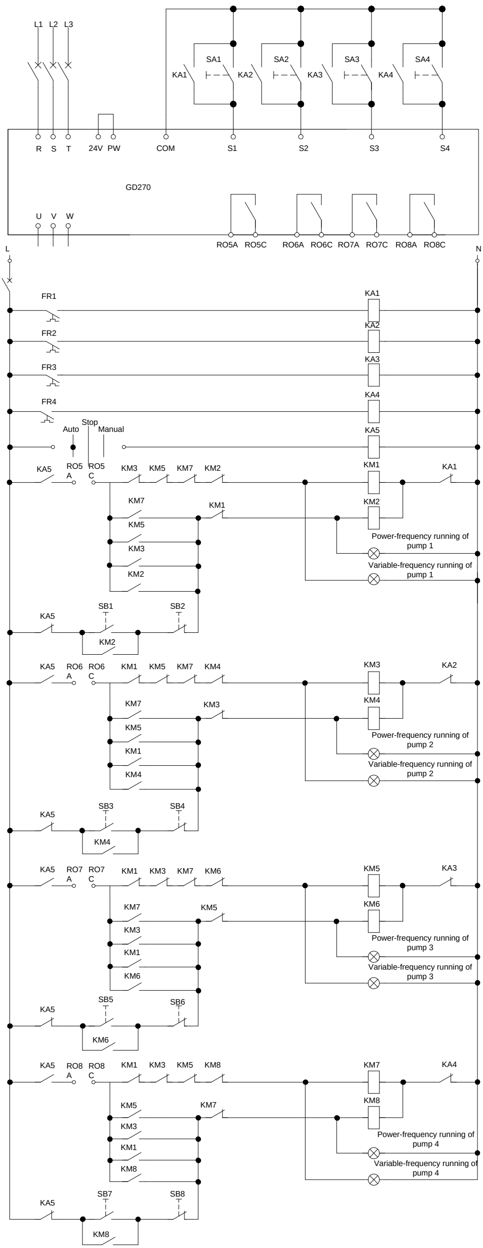



Figure 5-29 External relay control wiring (with four pumps)

If you use one VFD to control three water pump motors for variable-frequency circulation, refer to Figure 5-30 to connect the external relay control circuit.

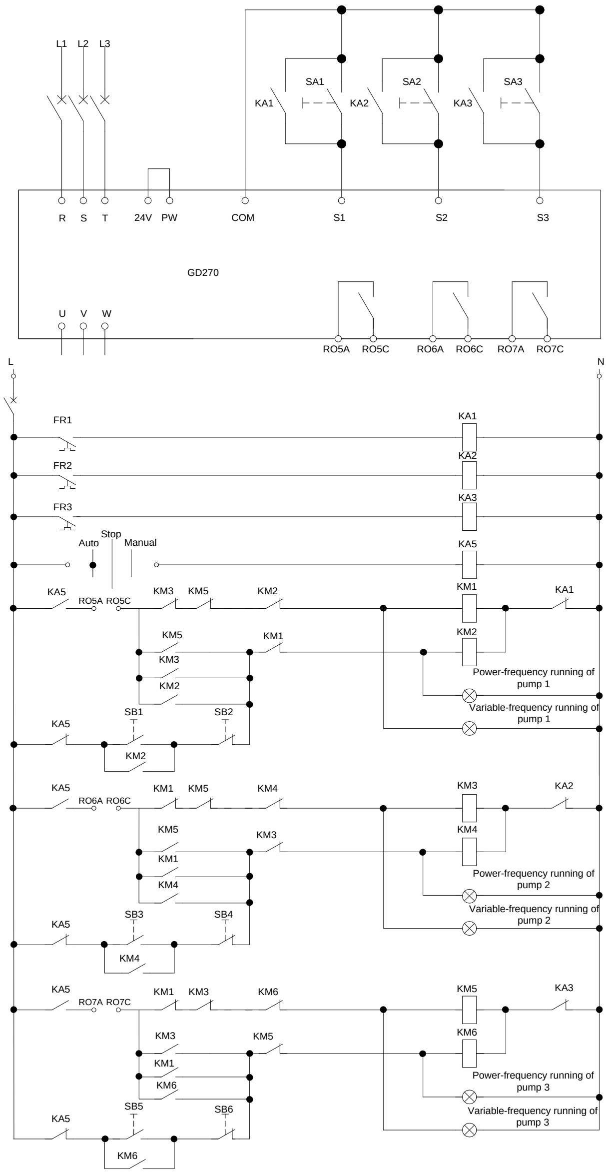



Figure 5-30 External relay control wiring (with three pumps)

If you use one VFD to control two water pump motors for variable-frequency circulation, refer to Figure 5-31 to connect the external relay control circuit.

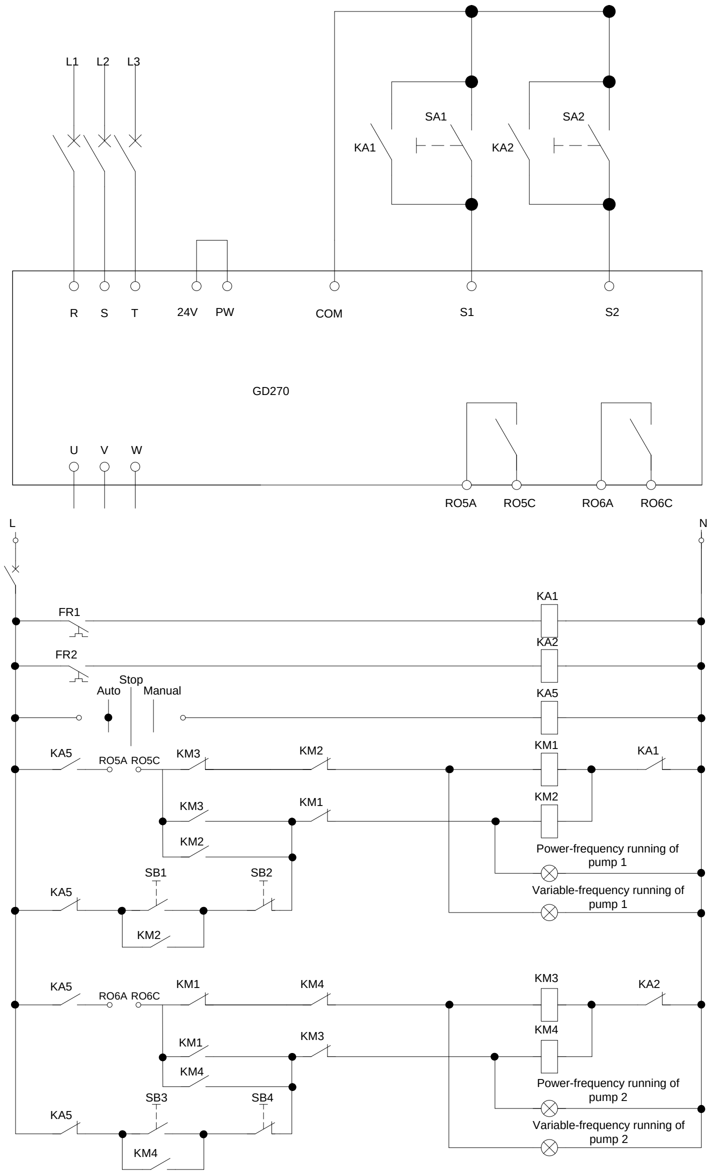



Figure 5-31 External relay control wiring (with two pumps)

Related function parameters

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Setting</th></tr>
<tr><td>P94.00</td><td>Multi-pump and fan control function enabling</td><td>0: Invalid<br>1: Valid</td><td>1</td></tr>
<tr><td>P94.10</td><td>Variable-frequency motor run mode</td><td>0: Fixed<br>1: Circular</td><td>1</td></tr>
<tr><td>P94.11</td><td>Number of motors</td><td>0–8: corresponding to motors A–H. The sequence numbers must be successive.</td><td>4</td></tr>
<tr><td>P26.06</td><td>RO5 output</td><td rowspan="4">0–47: Same as those for standard models<br>48: Fire mode activated<br>49: Pre-alarm of PID1 feedback too low<br>50: Pre-alarm of PID1 feedback too high<br>51: PID1 in sleep<br>52: PID2 in startup<br>53: PID2 stopped<br>54: Indication of run with backup pressure<br>55: Water shortage indication of inlet pool<br>56: Pre-alarm output<br>57: Control variable-frequency circulation pump A<br>58: Control variable-frequency circulation pump B<br>59: Control variable-frequency circulation pump C<br>60: Control variable-frequency circulation pump D<br>61: Control variable-frequency circulation motor E<br>62: Control variable-frequency circulation motor F<br>63: Control variable-frequency circulation motor G<br>64: Control variable-frequency circulation motor H<br>65: Low-temperature pre-alarm<br>66: Stalling pre-alarm<br>67: Dry-pumping pre-alarm<br>68: PTC overtemperature pre-alarm</td><td>57</td></tr>
<tr><td>P26.07</td><td>RO6 output</td><td>58</td></tr>
<tr><td>P26.08</td><td>RO7 output</td><td>59</td></tr>
<tr><td>P26.09</td><td>RO8 output</td><td>60</td></tr>
<tr><td>P94.36</td><td>Contactor closing delay</td><td>0.0–100.0s</td><td>0.5s</td></tr>
<tr><td>P94.37</td><td>Contactor opening delay</td><td>0.0–100.0s</td><td>0.5s</td></tr>
</table>

#### 5.5.16.1 Motor adding or reducing

**Motor adding**

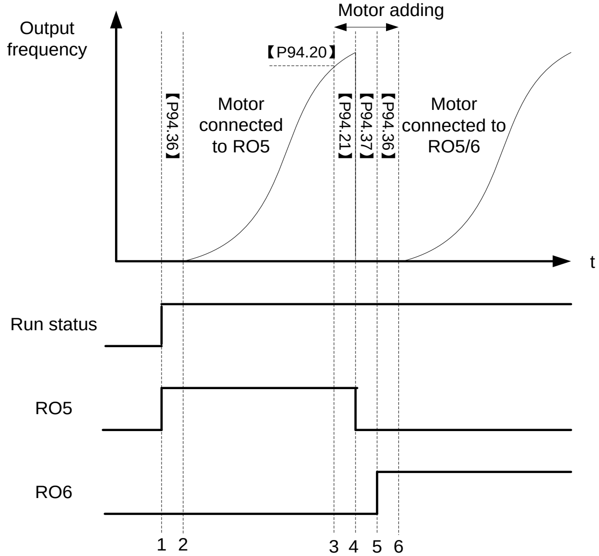



Figure 5-32 Motor adding timing

This figure assumes that the VFD outputs and controls motor M1 and the other motors are in the stopped state. At this time, if the output frequency is equal to or higher than P94.20 (Running frequency for motor adding), PID1 feedback is less than the difference between PID1 reference and P94.19 (Pressure tolerance for motor adding), and this condition lasts a period of time longer than P94.21 (Motor adding delay), the motor adding function is triggered.

If this condition lasts a period of time longer than P94.21 (Motor adding delay), motors are added, and then the VFD coasts to stop and disconnects the contactor with a contactor opening delay (P94.37) to ensure completed disconnection. The VFD closes the relay with a contactor closing delay (P94.36) to ensure completed closing.

The following table lists the relay action logic in the motor adding process.

Table 5-3 Motor adding logic in circular variable-frequency motor run mode

| RO5 | RO6 | RO7 | RO8 | Motor M1 | Motor M2 | Motor M3 | Motor M4 |
|---|---|---|---|---|---|---|---|
| 0 | 0 | 0 | 0 | Stop | Stop | Stop | Stop |
| 1 | 0 | 0 | 0 | Variable frequency | Stop | Stop | Stop |
| 0 | 0 | 0 | 0 | Stop | Stop | Stop | Stop |
| 0 | 1 | 0 | 0 | Stop | Variable | Stop | Stop |

| RO5 | RO6 | RO7 | RO8 | Motor M1 | Motor M2 | Motor M3 | Motor M4 |
|---|---|---|---|---|---|---|---|
| | | | | | frequency | | |
| 1 | 1 | 0 | 0 | Power frequency | Variable frequency | Stop | Stop |
| 1 | 0 | 0 | 0 | Power frequency | Stop | Stop | Stop |
| 1 | 0 | 1 | 0 | Power frequency | Stop | Variable frequency | Stop |
| 1 | 1 | 1 | 0 | Power frequency | Power frequency | Variable frequency | Stop |
| 1 | 1 | 0 | 0 | Power frequency | Power frequency | Stop | Stop |
| 1 | 1 | 0 | 1 | Power frequency | Power frequency | Stop | Variable frequency |
| 1 | 1 | 1 | 1 | Power frequency | Power frequency | Power frequency | Variable frequency |

**Motor reducing**

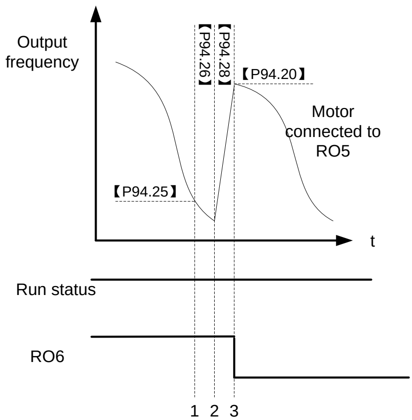



Figure 5-33 Motor reducing timing

This figure assumes that the VFD outputs and controls motor M2, M1 is in power-frequency run mode, and M3–M4 are in the stopped state. At this time, if the VFD output frequency is equal to or lower than P94.25 (Running frequency for motor reducing), PID1 feedback is less than the difference between PID1 reference and P94.24 (Pressure tolerance for motor reducing), and this condition lasts a period of time longer than P94.26 (Motor reducing delay), the motor reducing function is triggered. There are two motor reducing actions for selection, which can be set by P94.27 (Variable-frequency motor action for motor reducing).

If P94.27 (Variable-frequency motor action for motor reducing) is set to 1, the VFD not only disconnects the relay but also increases the output frequency to P94.20 (Running frequency for motor adding) within the time specified by P94.28 (Variable-frequency motor ACC time for motor reducing).

When the ACC is completed or P94.27 (Variable-frequency motor action for motor reducing) is set to 0 (Keep the frequency unchanged), the VFD disconnects the relay corresponding to the power-frequency motor.

The following table lists the relay action logic in the motor reducing process.

Table 5-4 Motor reducing logic in circular variable-frequency run mode

| RO5 | RO6 | RO7 | RO8 | Motor M1 | Motor M2 | Motor M3 | Motor M4 |
|---|---|---|---|---|---|---|---|
| 1 | 1 | 1 | 1 | Power frequency | Power frequency | Variable frequency | Variable frequency |
| 0 | 1 | 1 | 1 | Stop | Power frequency | Power frequency | Variable frequency |
| 0 | 0 | 1 | 1 | Stop | Stop | Power frequency | Variable frequency |
| 0 | 0 | 0 | 1 | Stop | Stop | Stop | Variable frequency |
| 0 | 0 | 0 | 0 | Stop | Stop | Stop | Stop |

Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P94.19 | Pressure tolerance for motor adding | 0.0–30.0% (relative to PID1 max. value) | 5.0% |
| P94.20 | Running frequency for motor adding | P94.25 (Running frequency for motor reducing)–P00.03 | 50.00Hz |
| P94.21 | Motor adding delay | 0.0–3600.0s | 10.0s |
| P94.22 | Switching frequency for variable-frequency motor adding | P00.05 (Lower limit of running frequency)–P00.03 | 50.00Hz |
| P94.23 | Variable-frequency motor DEC time for power-frequency motor adding | 0.0–300.0s | 10.0s |
| P94.24 | Pressure tolerance for motor reducing | 0.0–30.0% (relative to PID1 max. value) | 4.0% |
| P94.25 | Running frequency for motor reducing | P00.05–P94.20 (Running frequency for motor adding) | 5.00Hz |
| P94.26 | Motor reducing delay | 0.0–3600.0s | 10.0s |

| Function code | Name | Description | Default |
|---|---|---|---|
| P94.27 | Variable-frequency motor action for motor reducing | 0: Keep the frequency unchanged<br>1: Accelerate to the motor running frequency | 1 |
| P94.28 | Variable-frequency motor ACC time for motor reducing | 0.0–300.0s | 10.0s |

#### 5.5.16.2 Alternation function

**Automatic alternation**

The VFD supports the automatic water pump alternation function to achieve two goals: First, to keep the run time of each pump the same to balance the loss; Second, to prevent any pump from stopping for too long, which could lead to blocking. Automatic switching can also be triggered by a timer function, i.e., the auxiliary pump is switched on at a set time.

When the initial motor running time exceeds P94.34 (Variable-frequency motor alternation cycle) (P94.34 $\neq$ 0) and the present frequency is less than or equal to P94.35 (Alternation running frequency threshold), and there is an idle pump in the current system, the VFD starts automatic alternation in the way of adding a motor first and then reducing a motor. Then the second-run motor becomes the first-run motor, and the alternation time is calculated again. During normal use, the alternation time is also recalculated for motor reducing.

**Note:** Alternation time recalculation is also triggered by motor adding or reducing that occurs during normal PID adjustment.

Related function parameters

| Function code | Name | Description | Default |
|---|---|---|---|
| P94.34 | Variable-frequency motor cycling period | 0.0–6000.0h<br>Automatic alternation is targeted at idle variable-frequency motors. The value 0 indicates no alternation. | 0.0h |
| P94.35 | Alternation frequency threshold | P00.05–P00.03<br>When the running frequency is greater than the value of this function code, variable-frequency motor alternation is not performed. Otherwise, great water pressure change impacts water supply. | 45.00Hz |

**Manual alternation**

Manual alternation is used for testing to check whether the main circuit wiring and control circuit wiring are correct and motors can run properly. If alternation is completed or terminated, a stop command must be given so that the next alternation mode can be entered after restart.

The function is implemented as follows: When the VFD is in stopped stated, set the terminal input function to 85 (Manual alternation), enable the terminal function, and then send a startup command. The VFD starts all connected motors from motor M1 in alternation mode. During alternation, all motors are started by means of adding motors in sequence. When all motors have been started, motors are automatically reduced in sequence until the end.

**Note:** During alternation, if the enabling signal of an S terminal is canceled, the alternation persists until the end. If you want to terminate the alternation, you need to trigger a stop signal.

#### 5.5.16.3 Water pump maintenance

You can set the S digital input terminal functions to 104–107 to lock motors M1–M4, which will not be under multi-pump control. You only need to disconnect the motor wiring contactors from the grid to maintain the pumps, without adjusting the onsite wiring.

#### 5.5.16.4 Smooth switchover

When a motor switches from the variable-frequency run mode to the power-frequency run mode, the water pressure fluctuates greatly. You can set P94.22 (Switching frequency for variable-frequency motor adding) to enable the motor runs from a high switching frequency to the power-frequency run mode, preventing the water pressure from dropping too quick so as to ensure water pressure steady.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P94.22 | Switching frequency for variable-frequency motor adding | P00.05 (Lower limit of running frequency)–P00.03 | 50.00Hz | ○ |

#### 5.5.16.5 Fixed variable-frequency run mode

The fixed variable-frequency control logic is relatively simple. The following assumes one VFD drives four motors in fixed variable-frequency run mode. Se the following parameters.

1. Enable the multi-pump control function (P94.00=1).

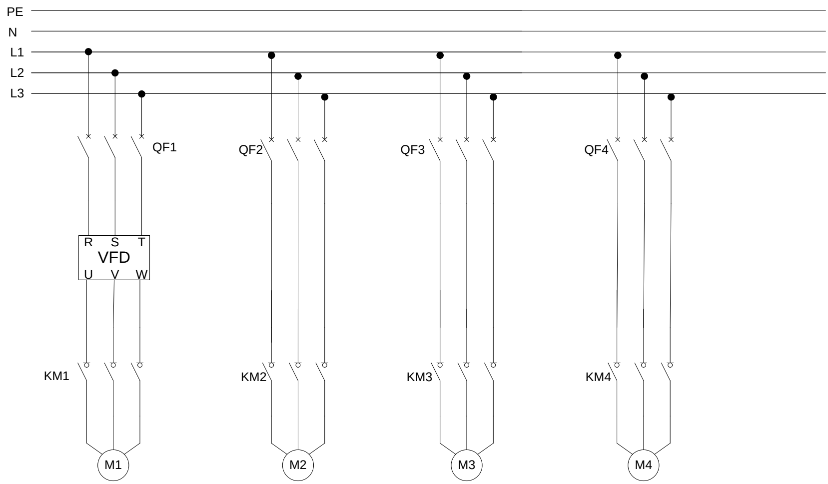
2. Set the variable-frequency motor run mode to fixed (P94.10=0).

3. Set the motor quantity to 4 (P94.11=4).

4. Set RO5–RO8 to control motors A, B, C, and D respectively (set P26.06–P26.09 to 57–60 respectively).

5. Set the contactor closing delay, which is the interval of switchover between the variable-frequency run mode and power-frequency run mode.

The following figures and tables show the control logic.




KM1–KM4: Contactors QF1–QF4: Low-voltage breakers M1–M4: Asynchronous motors

Figure 5-34 Main circuit wiring in fixed variable-frequency run mode

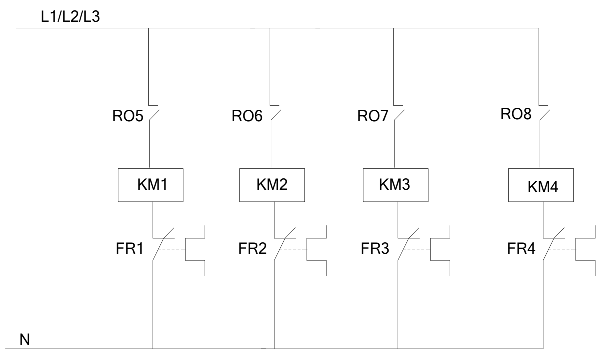



Figure 5-35 Control circuit wiring in fixed variable-frequency run mode

Table 5-5 Motor adding logic in fixed variable-frequency run mode

| RO5 | RO6 | RO7 | RO8 | Motor 1 | Motor 2 | Motor 3 | Motor 4 |
|---|---|---|---|---|---|---|---|
| 0 | 0 | 0 | 0 | Stop | Stop | Stop | Stop |
| 1 | 0 | 0 | 0 | Variable frequency | Stop | Stop | Stop |
| 1 | 1 | 0 | 0 | Variable frequency | Power frequency | Stop | Stop |
| 1 | 1 | 1 | 0 | Variable | Power frequency | Power | Stop |

| RO5 | RO6 | RO7 | RO8 | Motor 1 | Motor 2 | Motor 3 | Motor 4 |
|---|---|---|---|---|---|---|---|
| | | | | frequency | | frequency | |
| 1 | 1 | 1 | 1 | Variable frequency | Power frequency | Power frequency | Power frequency |

Table 5-6 Motor reducing logic with fixed variable-frequency motors

| RO5 | RO6 | RO7 | RO8 | Motor 1 | Motor 2 | Motor 3 | Motor 4 |
|---|---|---|---|---|---|---|---|
| 1 | 1 | 1 | 1 | Variable frequency | Power frequency | Power frequency | Power frequency |
| 1 | 0 | 1 | 1 | Variable frequency | Stop | Power frequency | Power frequency |
| 1 | 0 | 0 | 1 | Variable frequency | Stop | Stop | Power frequency |
| 1 | 0 | 0 | 0 | Variable frequency | Stop | Stop | Stop |
| 0 | 0 | 0 | 0 | Stop | Stop | Stop | Stop |

### 5.5.17 PID function only for water supply

The VFD provides two groups of PID only for water supply, only by which HVAC related PID setting can be implemented. The following takes PID1 as an example to describe the function.

The unit of PID1 reference and PID1 feedback can be specified by P90.00. PID source 1 (P90.06 and P90.08, that is, PID reference and feedback) can be set for PID1, and PID source 2 (P90.11 and P90.13, that is, PID reference and feedback) can be set for PID2. P90.16 is the combination method of PID source1 and source 2.

PID1 reference and PID1 feedback can be set to the actual water pressure values but not a percentage. P90.01 can specify the number of decimal places of PID1 reference and PID1 feedback. P90.02 can specify the actual water pressure corresponding to 100% of PID1 reference. P90.03 and P90.04 can specify the upper limit and lower limit of PID1 reference. In most cases, P90.02 and P90.03 are set to the same value. P89.09 and P89.10 can be used to view the percentage of PID1 reference and PID1 feedback.

**Note:** PID2 differs from PID1: PID2 cannot participate in the running frequency regulation. You can only convert PID2 output to analog signal by setting the AO function (setting 32).

For the related function codes, see Group P90—PID1 control and Group P91—PID2 control.

### 5.5.18 Segmented wind and water pressure function (used with LCD keypad)

If you have purchased the optional LCD keypad, you can install batteries into the keypad to enable the clock function. Then you can set working days through P92.04 and set start time and stop time of working days through P92.05–P92.08. P95 can specify water pressure by time segment. P92.06 is set to 0. Within a specific time segment, P90.07 (PID1 reference value 1 through keypad) will be overwritten by the multi-segment water pressure setpoint.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P95.00 | Actual time | 00.00–23.59<br>Set the clock date and time in group P92. | 00.00 | ● |
| P95.01 | Number of pressure segments | 0–8 (0 indicates that this function is disabled.) | 0 | ○ |
| P95.02 | Start time of T1 | After the Tx moment, the water pressure will become the pressure of the Tx period. The water pressure before T1 is set to 0.<br>Please note to set the end period. The segment selection in P95.01 indicates the number of valid segments. Settings beyond the selected segments will be invalid.<br>If the start time of Tx is later than the start time of T(x+1), T(x+1) automatically changes to Tx.<br>Start time range of Tx: 00.00–23.59<br>Pressure range of Tx period: 0.0–100.0% | 00.00 | ○ |
| P95.03 | Pressure at T1 | | 0.0% | ○ |
| P95.04 | Start time of T2 | | 23.00 | ○ |
| P95.05 | Pressure at T2 | | 0.0% | ○ |
| P95.06 | Start time of T3 | | 23.00 | ○ |
| P95.07 | Pressure at T3 | | 0.0% | ○ |
| P95.08 | Start time of T4 | | 23.00 | ○ |
| P95.09 | Pressure at T4 | | 0.0% | ○ |
| P95.10 | Start time of T5 | | 23.00 | ○ |
| P95.11 | Pressure at T5 | | 0.0% | ○ |
| P95.12 | Start time of T6 | | 23.00 | ○ |
| P95.13 | Pressure at T6 | | 0.0% | ○ |
| P95.14 | Start time of T7 | | 23.00 | ○ |
| P95.15 | Pressure at T7 | | 0.0% | ○ |
| P95.16 | Start time of T8 | | 23.59 | ○ |
| P95.17 | Pressure at T8 | | 0.0% | ○ |

### 5.5.19 Automatic sleep

Function code P94.01 specifies the sleep method. When the condition specified by P94.02 or P94.03 and the condition lasts the time specified by P94.04, the PID increases by P94.05 (PID boost value for sleep) with a duration specified by P94.06 (PID boost time), and the VFD enters the sleep state. When P94.08 (Wakeup condition) is met and this condition lasts the time specified by P94.09 (Wakeup time), the VFD automatically wakes up from sleep and directly runs at the frequency specified by P94.07, and the frequency is PID regulated later.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P94.00 | Multi-pump and fan control function enabling | 0: Invalid<br>1: Valid | 0 | ◎ |
| P94.01 | Sleep method | 0:Sleep according to terminal input | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | selection | 1:Sleep according to run frequency<br>2:Sleep according to deviation | | |
| P94.02 | Sleep start frequency | P00.05–P00.04 (Upper limit of running frequency)<br>Sleep mode is only allowed when the running frequency is less than or equal to the sleep start frequency and the duration exceeds P94.04. | 5.00Hz | ○ |
| P94.03 | Sleep starting deviation | 0.0–30.0% (relative to PID1 max. value)<br>When output is positive, if the feedback is greater than the reference, sleep is allowed only when the absolute difference is greater than the sleep starting deviation and the situation lasts the time longer than P94.04.<br>When output is negative, if the feedback is less than the reference, sleep is allowed only when the absolute difference is greater than the sleep starting deviation and the situation lasts the time longer than P94.04. | 5.0% | ○ |
| P94.04 | Sleep delay | P94.49–3600.0s | 60.0s | ○ |
| P94.05 | PID1 reference boost value | -100.0–100.0% (relative to PID1 reference value) | 10.0% | ○ |
| P94.06 | Longest boost time | 0.000–6000.0s<br>This function is used for continuous VFD running when the running frequency reaches the upper limit frequency but the feedback value cannot reach the setting after boost. In this situation, the VFD enters the sleep mode at once after the boost time. | 10.0s | ○ |
| P94.07 | Sleep wakeup frequency | P00.05–P00.04 (Upper limit of running frequency)<br>In closed-loop PID, the PID output is superimposed directly from the corresponding value of this frequency when the VFD is woken up. | 5.00Hz | ○ |
| P94.08 | Wake-up-from-sleep deviation | 0.0–30.0% (relative to PID1 max. value)<br>In closed-loop PID, when output is positive, if the feedback is less than the reference, wakeup is allowed only when the actual | 5.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | difference is greater than the wake-up-from-sleep deviation and this situation lasts the time longer than P94.09.<br>When the output characteristic is negative, wake-up is only allowed when the feedback is greater than the reference, the absolute value of the actual deviation exceeds the wake-up-from-sleep deviation, and the duration exceeds P94.09. | | |
| P94.09 | Wake-up-from-sleep delay | P94.49–3600.0s<br>Min. sleep time | 40.0s | ○ |

### 5.5.20 Water level control

The VFD receives the inlet water level signal in real time. If the water level of the inlet pool changes from high to low, then when the water level value is above the lower limit water level, the PID1 reference value is the normal set value; when the water level value is below the lower limit water level and above the water shortage level, the PID1 reference value is the backup reference value P94.43; when the water level value is below the water shortage level, then the control system will shut down all water pumps. If the water level of the inlet pool changes from low to high, then when the water level is below the lower water level limit, the system will stop; when the water level is below the upper water level limit and above the lower water level limit, the PID1 reference value is the backup reference value P94.43; when the water level is above the upper water level limit, the PID1 reference value is the normal set value.

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P94.39 | Water level signal input selection of inlet pool | 0: None<br>1: Digital<br>2: AI1<br>3: AI2<br>4: AI3<br>5: HDIA<br>6: Reserved<br>7: Communication card | 0 | ○ |
| P94.40 | Water level upper limit of inlet pool | 0.0–100.0% | 60.0% | ○ |
| P94.41 | Water level lower limit of inlet pool | 0.0%–P94.40 | 40.0% | ○ |
| P94.42 | Water shortage | 0.0%–P94.41 | 20.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | level of inlet pool | | | |
| P94.43 | Backup pressure upon exceptions | 0.0–100.0% (relative to PID1 max. value) | 0.0% | ○ |
| P94.44 | Protection value for PID1 feedback too low | 0.0–100.0% (relative to PID1 max. value) | 10.0% | ○ |
| P94.45 | Delay of PID1 feedback too low | 0.0–3600.0s<br>Corresponding terminal output that is set when PID1 feedback value is less than P94.44 and this situation lasts the time longer than P94.45. | 500.0s | ○ |
| P94.46 | Protection value for PID1 feedback too high | 0.0–100.0% (relative to PID1 max. value) | 80.0% | ○ |
| P94.47 | Delay of PID1 feedback too high | 0.0–3600.0s<br>Corresponding terminal output that is set when PID1 feedback value is greater than P94.46 and this situation lasts the time longer than P94.47. | 500.0s | ○ |

### 5.5.21 Pump cleaning

The VFD supports water pump cleaning, which is shown in Figure 5-36. The motor runs forward for certain time, it runs reversely for certain time after a period of stop, and then it runs forward after a period of stop. The motor repeats the procedure circularly.

Similar to manual alternation, the pump cleaning function can be triggered only when the VFD is in stopped state. To enable the pump cleaning function, set the terminal function to 86, enable the terminal, and send a startup signal.

After the pump cleaning function is enabled, all water pumps are cleared in order. Then the VFD automatically stops. During pump cleaning, you can terminate the pump cleaning by sending a stop command. If you want to restart pump cleaning after pump cleaning is completed or terminated, you need to send a stop command.

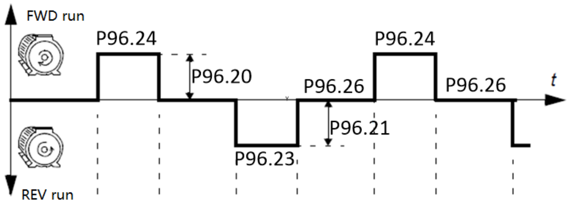



Figure 5-36 Pump cleaning logic

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.20 | Forward run frequency for pump cleaning | 0.00Hz–P00.04 | 50.00Hz | ◎ |
| P96.21 | Reverse run frequency for pump cleaning | 0.00Hz–P00.04 | 50.00Hz | ◎ |
| P96.22 | Forward run ACC time for pump cleaning | 0–3600.0s | 5.0s | ○ |
| P96.23 | Reverse run ACC time for pump cleaning | 0–3600.0s | 5.0s | ○ |
| P96.24 | Forward run duration for pump cleaning | 0–3600.0s | 5.0s | ○ |
| P96.25 | Reverse run duration for pump cleaning | 0–3600.0s | 5.0s | ○ |
| P96.26 | Forward/reverse run interval for pump cleaning | 0–3600.0s | 5.0s | ○ |
| P96.27 | Number of pump cleaning cycles | 1–1000 | 1 | ◎ |

### 5.5.22 Water pipe break detection control

Water pipe break detection control function can detect water pipe break and stop pump motors in time to reduce the loss.

This function is implemented as follows:

You can set P96.00 to 1 to enable this function. If water pipe break occurs and the water pressure cannot reach the setting, the VFD running frequency boosts up to the upper limit or the PID output upper limit frequency. You can determine the situation by setting P96.01. When the condition reaches the time specified by P96.02, the VFD stops the motor.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.00 | Action upon water pipe break | 0: Disable<br>1: Report a fault | 0 | ○ |
| P96.01 | Detection level of water pipe break | After water pipe break, the VFD running frequency boosts up to the upper limit or the PID output upper limit frequency. When it is set to 0, the water pipe break detection function is invalid.<br>Range: 0.0–100.0% | 10.0% | ○ |
| P96.02 | Detection time of water pipe break | Used to check the detection time of water pipe break.<br>Range: 0.0–6000.0s | 120.0s | ○ |

### 5.5.23 Water pipe soft padding

In a water supply system, the rapid influx of water into the empty water pipe can cause a water hammer effect, which damages the water pipe or valve. After water pipe soft padding is enabled, the VFD implements water injection into the water pipe slowly and steadily for every startup, avoiding the water hammer effect. If the VFD stops due to a fault during water injection, the VFD still runs the function setting after restart. This function is implemented as follows: Set P96.03 to 1 to enable soft padding. After the VFD is started, the VFD exits from the soft padding process when the motor reaches any of the two conditions, and the PID takes over the frequency control:

Condition 1: The VFD runs at the frequency specified by P96.04, and the run time reaches the time specified by P96.05.

Condition 2: The PID feedback value reaches the value specified by P96.06 (Soft padding cutoff detection level).

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.03 | Water pipe soft padding function | 0: Disable<br>1: Enable | 0 | ○ |
| P96.04 | Reference frequency for soft padding | 0.00Hz–P00.03 | 30.00Hz | ○ |
| P96.05 | Duration of reference frequency for soft padding | 0.0–6000.0s | 10.0s | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.06 | Soft padding cutoff detection level | The PID function is valid when the feedback value is greater than the value of this function code.<br>Range: 0.0–100.0% | 10.0% | ○ |

### 5.5.24 Freezing protection

At low temperature, water freezing in the water tube damages the water pump. After protection against freezing is enabled, the motor automatically rotates to prevent against water freezing when the ambient temperature reaches a specified value.

The VFD provides the AI/AO temperature measuring function, which supports PT100, PT1000, and KTY84 sensors. During use, select current output for AO, connect one end of the temperature resistor to AI1 and AO1 and the other end to GND. P89.23 will display the measured temperature. If the full range is exceeded, the temperature is displayed as 0℃. When P96.10 (Enabling freezing protection) is activated, if P89.32 (Measured temperature) is lower than P96.12 (Freezing protection threshold), the freezing protection signal will be activated. The VFD runs at P96.14 (Freezing protection frequency). This signal is ignored if the VFD is running. If a run command is received after the freezing protection has been activated, the protection is terminated and the run command is executed. If a stop command is received after the protection has been activated, the motor is stopped and automatic protection is disabled. Automatic protection can be enabled only when the temperature is higher than the protection threshold.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P89.32 | AI/AO measured temperature | -20.0–200.0°C | 0.0°C | ● |
| P96.10 | Enabling freezing protection | Freezing protection: The freezing protection signal is activated when the detected temperature is lower than the protection threshold. This signal is ignored if the VFD is running.<br>If the run command is received after the protection has been activated, the protection is terminated and the run command is executed.<br>If a stop command is received after the protection has been activated, the motor is stopped and automatic protection is disabled.<br>Automatic protection can be enabled when the | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | temperature is higher than the protection threshold.<br>0: Disable<br>1: Enable | | |
| P96.11 | Temperature sensor type | 0: Invalid<br>1: PT100<br>2: PT1000<br>3: KTY84<br>4: PTC (AO+AI terminal combination)<br>5: PTC (AI1+10V terminal combination)<br>6: PTC (AI2+10V terminal combination)<br>Usage of functions 1–4: To select current-type output for AO, connect one end of the temperature resistor to AI1 (voltage-type) and AO1 (current-type), and the other end to GND.<br>Usage of functions 5–6: Connect the PTC sensor between the +10V terminal and AI1 or AI2. | 0 | ○ |
| P96.12 | Freezing protection threshold | -20.0–20.0°C | -5.0°C | ○ |
| P96.13 | Low temperature pre-alarm threshold | -20.0–20.0°C<br>When the temperature is lower than the value of this function code, the pre-alarm terminal outputs a signal. | 0.0°C | ○ |
| P96.14 | Freezing protection frequency | 0.00–45.00Hz | 0.0Hz | ○ |

Related fault codes

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| FrOST | Freezing fault | The temperature is lower than the freezing protection threshold. | Check the temperature. |

### 5.5.25 Condensation protection

Motors can condense in wet and cold environments, leading to motor failure, which can be avoided by outputting a DC current that slightly raises the temperature of the motor surface during work interruptions.

When the external condensation sensor detects intensive condensation, the VFD injects DC current into the motor to raise the motor surface temperature to prevent condensation.

To implement the function: Set the S digital input terminal function to 91 to enable condensation protection. If this terminal is enabled through external signal, the VFD sends DC current and automatically stops the sending 40s later. If this function needs to be triggered again, re-enable this function terminal. You can set P96.15 to adjust the DC current proportion.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.15 | Current of triggering condensation protection | 0.0–100.0%<br>When an external terminal triggers the condensation protection signal, the VFD transfers DC current and stops the transfer if the duration reaches 40s. The condensation protection signal needs to be triggered again. | 30.0% | ○ |

### 5.5.26 Anti-stalling and dry pumping function

Anti-stalling and dry pumping function can effectively avoid motor damage and energy waste.

Prerequisite for selecting the function: The VFD exceeds the stalling current limit, the output frequency is lower than the stalling frequency upper limit, and the duration of this situation exceeds the stalling time.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.28 | Motor stalling function selection | 0: Disable<br>1: Pre-alarm<br>2: Faulty | 0 | ○ |
| P96.29 | Stalling current limit | 0.0–300.0%(100.0% corresponds to the motor rated current.) | 200.0% | ○ |
| P96.30 | Stalling frequency upper limit | 0.00Hz–P00.04<br>**Note:** It cannot be lower than 10Hz. | 15.00Hz | ○ |
| P96.31 | Stalling detection time | 0.0–3600.0s | 2.0s | ○ |
| P96.32 | Motor dry pumping function selection | 0–2<br>0: Disable<br>1: Pre-alarm<br>2: Faulty | 0 | ○ |
| P96.33 | Current limit for motor dry pumping | 0.0%–100.0%(100.0% corresponds to the motor rated current.) | 0.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.34 | Detection time for motor dry pumping | 0.0–3600.0s | 2.0s | ○ |

Related fault codes

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| BLOCK | Stalling fault | The current is greater than the stalling current. | Check for stalling. |
| Dr | Dry pumping | The current is lower than the current limit for motor dry pumping. | Check whether dry pumping occurred |

### 5.5.27 Speed tracking function

When P01.00=2, the speed-tracking start is valid.

AM: software speed tracking implementation, currently supporting software in both vector control mode 1 and V/F control mode.

**Note:** In SVC 0, speed tracking cannot be selected, which indicates P01.00 can be 0 or 1.

The software-implemented speed tracking provides three modes, applicable as follows:

- P01.35=1 is suitable for most scenarios
- P01.35=2 is suitable for scenarios with long power outages and very low motor frequency
- P01.35=3 is suitable for scenarios with generative loads

Advanced speed tracking function: for the function code P01.39, only the tens place needs to be adjusted. Some motors may experience oscillation during software speed tracking when using three-phase modulation, so switching to two-phase modulation is recommended.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P01.00 | Running mode of start | 0: Direct start<br>1: Start after DC braking<br>2: Speed tracking restart (not supported in SVC 0 for AMs) | 0 | ◎ |
| P01.35 | Speed tracking method | 0: From stop frequency (Usually selected)<br>1: From low frequency (Applicable to restart after a long time of coasting to stop)<br>2: From max. output frequency P00.03 (Applicable to common power generation load | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | situation) | | |
| P01.36 | Quick/slow selection for speed tracking | 1–100s<br>A great value of this parameter indicates a fast rotation-speed tracking speed, but an excessively great value may result in unreliable tracking. | 15s | ○ |
| P01.37 | Speed tracking current | 30%–200%<br>Closed-loop current reference value (motor) during rotation.<br>Great value of this parameter indicates high reliability of rotation-speed tracking, but an excessively great value may result in VFD overcurrent. | 100% | ○ |
| P01.38 | Demagnetization time for speed tracking | 0.0–10.0s | Model depended | ○ |
| P01.39 | Advanced control for speed tracking | 0x000–0x111<br>LED ones place: Current giving mode in vector control<br>0: 120% of current is given during startup, which is switched to the given value based on P01.35<br>1: The current is given based on P01.35<br>LED ones place: PWM mode selection<br>0: 2PH modulation mode<br>1: Based on P08.40<br>LED hundreds place: Search direction for speed tracking<br>0: Allow both forward and reverse search<br>1: Disallow reverse search | 0x110 | ○ |

### 5.5.28 Motor thermal protection function

GD270 supports temperature measurement functions for various types of temperature sensors, including PT100/PT1000/KTY84/PTC, etc. For different types of temperature sensors, the following two detection schemes are provided.

Scheme 1: Implemented through the combination of function terminals AI1 and AO1. It requires setting AI1 to voltage type and AO1 to current type. The wiring is as shown in the figure below. This scheme supports all types of temperature sensors.

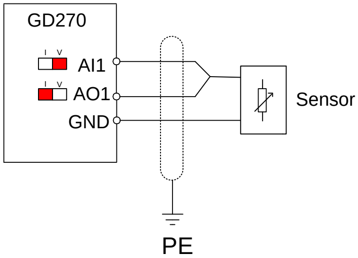
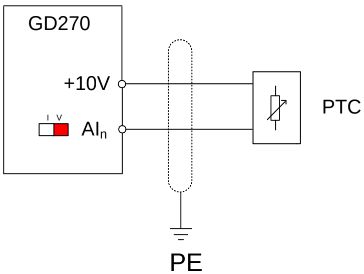



Figure 5-37 AI/AO motor temperature detection wiring diagram

Scheme 2: Implemented through A11 or AI2 and the +10V terminal. It requires setting AI1 or AI2 to voltage type. The wiring is as shown in the figure below. This scheme only supports three-wire PTC sensors that comply with DIN44082 standards. Compared to Scheme 1, it does not require the use of the AO1 terminal.



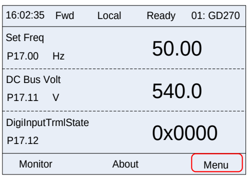

Related function parameters

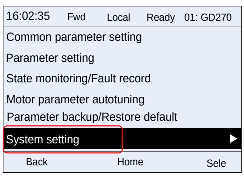
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.11 | Temperature sensor type | 0: Invalid<br>1: PT100<br>2: PT1000<br>3: KTY84<br>4: PTC (AO+AI terminal combination)<br>5: PTC (AI1+10V terminal combination)<br>6: PTC (AI2+10V terminal combination)<br>Usage of functions 1–4: To select current-type output for AO, connect one end of the temperature resistor to AI1 (voltage-type) and AO1 (current-type), and the other end to GND.<br>Usage of functions 5–6: Connect the PTC sensor between the +10V terminal and AI1 or | 0 | ○ |

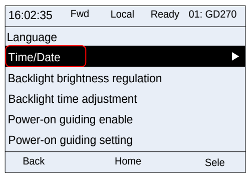
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | AI2. | | |
| P96.35 | Motor overtemperature protection threshold | -20.0–200.0 | 110.0 | ○ |
| P96.36 | AI/AO detected temperature offset value | -40.0–40.0 | 0.0 | ○ |
| P96.37 | PTC constant output current setting | 0.000–20.000mA | 4.000mA | ○ |
| P96.38 | PTC resistance alarm threshold | 0–60000Ω | 750Ω | ○ |
| P96.39 | PTC resistance alarm recovery threshold | 0–60000Ω | 150Ω | ○ |
| P96.40 | Actual PTC resistance | 0–60000Ω | 0Ω | ● |

### 5.5.29 Real-time clock function (Keypad with button battery)

Set the current time according to the following figure and check from P92.00 to P92.03.








Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P92.00 | Displaying year | 2020–2099 YY | 2020 YY | ● |
| P92.01 | Displaying month and date | 01.01–12.31 MMDD | 01.01 MMDD | ● |
| P92.02 | Displaying day of a week | 1–7 : Corresponding to Monday through Sunday | 1 | ● |
| P92.03 | Displaying hour and minute | 00.00–23.59 HHMM<br>00.00 is the earliest hour and time of a day, while 23.59 is the latest hour and time of a day. | 00.00 HHMM | ● |

### 5.5.30 Fire ride-through control

The fire ride-through function enables the VFD product to respond normally in the event of a fire or when life safety is threatened. Therefore, the fire ride-through mode in GD270 allows the drive to control the motor in a preset manner to assist the building smoke control system during evacuation and firefighting after a fire occurs.

Once a fire trigger signal [S terminal function 79] is input to the VFD and the fire control function code [P93.00] is set to a non-zero value, the VFD enters the fire ride-through mode, controlling the motor to run at the set fire frequency [93.01] and running direction in fire mode [93.02].

| Function description | Running conditions |
|---|---|
| P93.00=0, the VFD runs in normal mode. | The VFD runs in normal mode and stops when encountering a fault. |
| P93.00=0, fire mode 1<br>The VFD always runs at the speed specified by P11.54 except when the VFD has been damaged. | 1. In fire mode 1, the VFD's target frequency will be forced to run at the fire mode frequency, unaffected by any frequency setting, jog setting, multi-step speed setting, deceleration stop setting, pause setting, emergency stop command, or automatic frequency decrease selection at voltage drop.<br>The running frequency is affected by power-down frequency fall, automatic current limiting, overvoltage stall, and upper/lower frequency limits.<br>2. The VFD will continue to run under any fault, any control command channel, coast to stop command, or keypad run+stop key command (except for STO, STL1, STL2, STL3, and hardware wave blocking faults).<br>If the fire ride-through control is triggered when the VFD is in the Poff state, the VFD will automatically run after the bus voltage is established.<br>3. The motor running direction is set according to the set motor running direction in fire mode, unaffected by P00.13, forward run, reverse run, forward jog, reverse jog, etc. |
| P93.00=2, fire mode 1<br>In this mode, the VFD always runs at the speed specified by P11.54, but stops upon the following faults: OUT1, OUT2, OUT3, OC1, OC2, OC3, OV1, OV2, OV3, and SPO. | 1. In fire mode 1, the VFD's target frequency will be forced to run at the fire mode frequency, unaffected by any frequency setting, jog setting, multi-step speed setting, deceleration stop setting, pause setting, emergency stop command, or automatic frequency decrease selection at voltage drop.<br>The running frequency is affected by power-down frequency fall, automatic current limiting, overvoltage stall, and upper/lower frequency limits.<br>2. The VFD will run all the time for any control command channel, coast to stop command, or keypad run+stop key command (except STO, STL1, STL2, STL3, hardware blocking fault) except for OUT1, OUT2, |

| Function description | Running conditions |
|---|---|
| | OUT3, OC1, OC2, OC3, OV1, OV2, OV3, SPO fault.<br>If the fire ride-through control is triggered when the VFD is in the Poff state, the VFD will automatically run after the bus voltage is established.<br>3. The motor running direction is set according to the set motor running direction in fire mode, unaffected by P00.13, forward run, reverse run, forward jog, reverse jog, etc. |
| P93.03 Fire mode flag | If the fire mode has lasted 5 minutes flag is reset to 1.<br>Once the flag is set, no warranty of repair is granted. |
| P93.04 Actual month and date when fire activated | Time recording function configuration requirement: Select LCD keypad and install a button battery. |
| P93.05 Actual time when fire activated | Time recording function configuration requirement: Select LCD keypad and install a button battery. |

### 5.5.31 Fault classification

Trigger condition: If the fire ride-through function [P93.00] is invalid, or the fire ride-through function is valid but no fire trigger signal [S terminal function 79] is input to the VFD, the VFD will execute the fault classification function.

GD270 software classifies all faults into 4 levels of protection, with lower numbers indicating higher fault severity.

- Level 0: Coast to stop
- Level 1: Stop according to the stop mode
- Level 2: Pre-alarm and run
- Level 3: Keep running

P11.31–P11.50 set the fault severity for corresponding faults, P11.51 sets the output frequency for warning operation, and P11.52 sets the abnormal backup frequency.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P11.31 | Fault severity group 1 | 0x0000–0x3313<br>Ones place (fault 11=OL1):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Tens place (fault 12=OL2): | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 0: Report a fault<br>1: Report a fault after deceleration to stop<br>Hundreds place (fault 13=SPI):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place (fault 14=SPO):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | | |
| P11.32 | Fault severity group 2 | 0x0000–0x3300<br>Ones place(fault 15=OH1):<br>0: Report a fault<br>Tens place(fault 16=OH2):<br>0: Report a fault<br>Hundreds place(fault 17=EF):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place(fault 18=CE):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | 0x0000 | ○ |
| P11.51 | Action for fault alarm | 0: Run at the set frequency<br>1: Run at the output frequency at the time of failure<br>2: Run at the upper limit frequency<br>3: Run at the lower limit frequency<br>4: Run at the backup frequency upon exceptions | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P11.52 | Backup frequency upon exceptions | 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz | ○ |

### 5.5.32 Input phase loss detection

Phase loss detection condition: Phase loss cannot be detected when the VFD is stopped or running under no load or light load.

Detection principle: When there is a phase loss and the VFD is under load, the waveform of the bus voltage fluctuation is an asymmetric triangle wave, containing integer harmonics of the fluctuation frequency (100Hz). By extracting the amplitude [P11.29] and duration [P11.30] of the 100Hz component, input phase loss can be determined. Generally, the factory default values do not need to be changed.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P11.28 | Software input phase loss detection method | 0: Sine-wave detection<br>1: Square-wave detection<br>**Note:** Since phase loss detection is implemented through software, output phase loss cannot be detected when the VFD is running without a motor, and input phase loss cannot be detected during no-load or light-load operation. Input phase loss can only be detected normally when the load current is above 60% of the rated current. | 1 | ○ |
| P11.29 | Software input phase loss detection limit value | 0–200.0V<br>**Note:** Larger values are less likely to report a fault. | 40.0V | ○ |
| P11.30 | Software input phase loss detection time | 0–20.0s<br>**Note:** Larger values are less likely to report a fault. | 2.0s | ○ |

### 5.5.33 Carrier frequency reduction with temperature

When this function is enabled, to ensure the control performance of the motor at high running frequencies, a certain carrier ratio must be maintained. The reduced carrier frequency must be ≥ the minimum carrier frequency (see description for P00.14) and 10 times the output frequency (P00.03), i.e., the reduced carrier frequency ≥ max(minimum carrier frequency, P00.03 set value*10).

Example: For an 11kW VFD, the default factory value is 4kHz, and the minimum carrier frequency limit is 2kHz. When P00.03 is set to 300Hz and P08.55 is enabled, the reduced carrier frequency ≥ max(2kHz, 300Hz*10)=3kHz.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P08.55 | Enabling auto carrier frequency reduction | 0: Disable<br>1: Enable<br>**Note:** Automatic carrier frequency reduction indicates that the VFD automatically reduces the carrier frequency when detecting the heat sink temperature exceeds the rated temperature. When the temperature decreases to a certain degree, the carrier frequency recovers. This function reduces the chance of VFD overheat alarm. | 1 | ○ |
| P08.56 | Temperature point of auto carrier frequency reduction | 40.0–85.0°C | 65.0°C | ○ |
| P08.57 | Interval of carrier frequency reduction | 0–30Min (Setting it to 0 means carrier frequency reduction is invalid.) | 10min | ○ |

### 5.5.34 Cooling fan noise control

GD270 series products in the 160-800kW power range are equipped with speed-adjustable cooling fans. When the VFD load rate is low and the operating environment temperature is good, the fan speed can be reduced by setting the tens place of P08.39 to a percentage value, which can appropriately reduce the operating noise of the VFD.

Related function parameters

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P08.39 | Fan operating mode | 0x0000–0x0161<br>Ones place: Run mode<br>0: Normal mode<br>1: Permanent running after power-on<br>Tens place: Set speed<br>0: 100%<br>1: 95% | 0x0100 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 2: 90%<br>3: 85%<br>4: 80%<br>5: 75%<br>6: 70%<br>**Note:** Setting this bit can reduce the fan speed, but it may cause the VFD to overheat. Please set it with caution.<br>Hundreds place: Speed control method<br>0:Tens setting of P08.39<br>1: Automatic speed regulation | | |

### 5.5.35 Grid frequency and voltage selection

Use parameter P08.62 to select the grid frequency (50Hz or 60Hz) and voltage level (380V or 460V) applicable to the VFD. The system will automatically adjust related parameter defaults to ensure proper matching with the power grid and optimize operation.

| Function code | Name | Description | Default |
|---|---|---|---|
| P08.62 | Grid voltage and frequency selection | Range: 0x00–0x21<br>Ones place: Frequency selection<br>0: 50Hz<br>1: 60Hz<br>Tens place:Voltage selection<br>0: Indicates the 220V range, suitable for a voltage range of 208–240.<br>1: Indicates the 380V range, suitable for a voltage range of 380–415.<br>2: Indicates the 460V range, suitable for a voltage range of 440–480.<br>When the VFD model is -2, the tens place of P08.62 automatically becomes 0. If changed to 1 or 2, it will not take effect.<br>When the VFD model is -4, the tens place of P08.62 defaults to 1. If changed to 0, it will not take effect. | 0x10 |

■ **Grid frequency setting (P08.62 ones place)**

The table below lists parameters whose default values depend on the ones place of P08.62.

| Function code | Name | Default value at 50Hz (P08.62 ones place=0) | Default value at 60Hz (P08.62 ones place=1) |
|---|---|---|---|
| P00.03 | Max. output frequency | 50Hz | 60Hz |
| P00.04 | Upper limit of running frequency | 50Hz | 60Hz |
| P00.10 | Setting frequency through keypad | 50Hz | 60Hz |
| P02.02 | Rated frequency of AM 1 | 50Hz | 60Hz |
| P03.16 | Forward rotation upper limit frequency set through keypad in torque control | 50Hz | 60Hz |
| P03.17 | Reverse rotation upper limit frequency set through keypad in torque control | 50Hz | 60Hz |
| P08.32 | FDT1 electrical level detection value | 50Hz | 60Hz |
| P08.34 | FDT2 electrical level detection value | 50Hz | 60Hz |
| P12.02 | Rated frequency of AM 2 | 50Hz | 60Hz |
| P12.16 | Rated frequency of SM 2 | 50Hz | 60Hz |

**Note:** When it is set to 60Hz, the AM default rated speed will be 300rpm higher than the rated speed at 50Hz.

■ **Grid voltage setting (P08.62 tens place)**

The table below lists parameters whose default values depend on the tens place of P08.62.

| Function code | Name | Default value at 380V (P08.62 tens place=1) | Default value at 460V (P08.62 tens place=2) |
|---|---|---|---|
| P02.04 | Rated voltage of AM 1 | 380V: suitable for a voltage range of 380–415V. | 460V: suitable for a voltage range of 440–480V. |
| P11.04 | Overvoltage stall protection voltage | 136% | 120% |

**Note:**

- After changing P08.62, the default values of related parameters will be automatically updated. However, you may still change them as needed.
- When selecting 60Hz, ensure that the motor's rated speed allows for the increase to avoid overspeed risks.
- Make sure the grid voltage matches the selected setting; otherwise, device protection may be triggered or damage may occur.

It is recommended to reset P08.62 and verify parameter compatibility during initial commissioning or when the power grid changes.

# 6 Function parameter list

## 6.1 What this chapter contains

This chapter lists all the function codes and corresponding description of each function code.

## 6.2 Function parameter list

The function parameters of the VFD are divided into groups by function. Among the function parameter groups, the P98 group is the analog input and output calibration group, while the P99 group contains the factory function parameters, which are user inaccessible. Each group includes several function codes (each function code identifies a function parameter). A three-level menu style is applied to function codes. For example, "P08.08" indicates the 8th function code in the group P8.

The function group numbers correspond to the level-1 menus, the function codes correspond to the level-2 menus, and the function parameters correspond to the level-3 menus.

1. The content of the function code table is as follows:

   Column 1 "Function code": Code of the function group and parameter

   Column 2 "Name": Full name of the function parameter

   Column 3 "Description": Detailed description of the function parameter

   Column 4 "Default": Initial value set in factory

   Column 5 "Modify": Whether the function parameter can be modified, and conditions for the modification

   "○" indicates that the value of the parameter can be modified when the VFD is in stopped or running state.

   "◎" indicates that the value of the parameter cannot be modified when the VFD is in running state.

   "●" indicates that the value of the parameter is detected and recorded, and cannot be modified.

   (The VFD automatically checks and constrains the modification of parameters, which helps prevent incorrect modifications.)

2. The parameters adopt the decimal system (DEC) and hexadecimal system (0–F). If the hexadecimal system is adopted, all bits are mutually independent on data during parameter editing.

3. "Default" indicates the factory setting of the function parameter. If the value of the parameter is detected or recorded, the value cannot be restored to the factory setting.

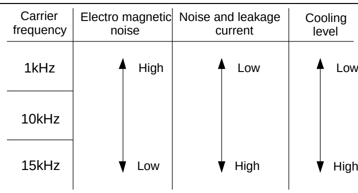
4. To better protect parameters, the VFD provides the password protection function. After a password is set (that is, P07.00 is set to a non-zero value), "0.0.0.0.0" is displayed when you press the PRG/ESC key to enter the function code editing interface. You need to enter the

correct user password to enter the interface. For the factory parameters, you need to enter the correct factory password to enter the interface. (You are not advised to modify the factory parameters. Incorrect parameter setting may cause operation exceptions or even damage to the VFD.) If password protection is not in locked state, you can change the password any time. You can set P07.00 to 0 to cancel the user password. When P07.00 is set to a non-zero value during power-on, parameters are prevented from being modified by using the user password function. When you modify function parameters through serial communication, the user password protection function is also applicable and compliant with the same rule.

**Group P00—Basic functions**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P00.00 | Speed control mode | 0: SVC mode 0<br>1: SVC mode 1<br>2: Space voltage vector control mode<br>**Note:** Before using a vector control mode (0 or 1), enable the VFD to perform motor parameter autotuning first. | 2 | ◎ |
| P00.01 | Channel of running commands | 0: Keypad<br>1: Terminal<br>2: Communication | 0 | ○ |
| P00.02 | Communication mode of running commands | 0–5<br>0: Modbus/Modbus TCP communication<br>1: PROFIBUS/CANopen /BACnet MSTP communication<br>2: Ethernet communication<br>3: PROFINET/EtherNet IP communication<br>4: Programmable card<br>5: Wireless communication card<br>**Note:** The options 1, 2, 3, 4, and 5 are add-on functions and are available only when corresponding expansion cards are configured. | 0 | ○ |
| P00.03 | Max. output frequency | The function code is used to set the max. output frequency of the VFD. Pay attention to the function code because it is the foundation of the frequency setting and the speed of acceleration (ACC) and deceleration (DEC).<br>Setting range: Max(P00.04,10.00)–400.00Hz | 50.00Hz | ◎ |
| P00.04 | Upper limit of | The upper limit of the running frequency is the | 50.00Hz | ◎ |

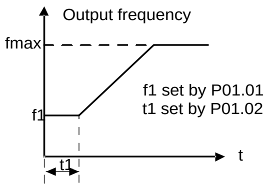
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td>running frequency</td><td>upper limit of the output frequency of the VFD, which is lower than or equal to the max. output frequency.<br>When the set frequency is higher than the upper limit of the running frequency, the upper limit of the running frequency is used for running.<br>Setting range: P00.05–P00.03 (Max. output frequency)</td><td></td><td></td></tr>
<tr><td>P00.05</td><td>Lower limit of running frequency</td><td>The lower limit of the running frequency is the lower limit of the output frequency of the VFD, When the set frequency is lower than the lower limit of the running frequency, the lower limit of the running frequency is used for running.<br>Note: Max. output frequency ≥ Upper limit of frequency ≥ Lower limit of frequency<br>Setting range: 0.00Hz–P00.04 (Upper limit of running frequency)</td><td>0.00Hz</td><td>◎</td></tr>
<tr><td>P00.06</td><td>Setting channel of A frequency command</td><td rowspan="2">0: Keypad<br>1: AI1<br>2: AI2<br>3: AI3<br>4: High-speed pulse HDIA<br>5: Simple PLC program<br>6: Multi-step speed running<br>7: PID control<br>8: Modbus/Modbus TCP communication<br>9: PROFIBUS/CANopen /BACnet MSTP communication<br>10: Ethernet communication<br>11: High-speed pulse HDIB<br>12: Pulse train AB<br>13: PROFINET/EtherNet IP communication<br>14: Programmable card<br>15–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)</td><td>0</td><td>○</td></tr>
<tr><td>P00.07</td><td>Setting channel of B frequency command</td><td>15</td><td>○</td></tr>
</table>

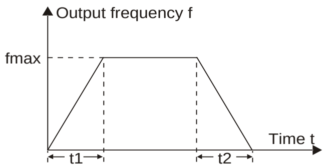
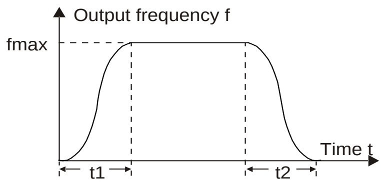
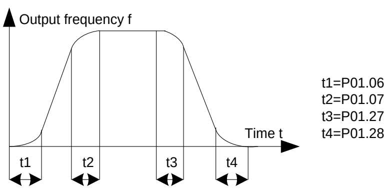
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td></td><td></td><td></td></tr>
<tr><td>P00.08</td><td>Reference object of B frequency command</td><td>0: Max. output frequency<br>1: A frequency command</td><td>0</td><td>○</td></tr>
<tr><td>P00.09</td><td>Combination mode of setting source</td><td>0: A<br>1: B<br>2: (A+B)<br>3: (A-B)<br>4: Max(A, B)<br>5: Min(A, B)</td><td>0</td><td>○</td></tr>
<tr><td>P00.10</td><td>Setting frequency through keypad</td><td>When A and B frequency commands select the keypad for setting, the value of the function code is the original setting one of the frequency data of the VFD.<br>Setting range: 0.00Hz–P00.03 (Max. output frequency)</td><td>50.00Hz</td><td>○</td></tr>
<tr><td>P00.11</td><td>ACC time 1</td><td rowspan="2">ACC time means the time needed if the VFD speeds up from 0Hz to the max. output frequency (P00.03).<br>DEC time means the time needed if the VFD speeds down from the max. output frequency (P00.03) to 0Hz.<br>The VFD has four groups of ACC/DEC time, which can be selected by P05. The factory default ACC/DEC time of the VFD is the first group.<br>Setting range of P00.11 and P00.12: 0.0–3600.0s</td><td>Model depended</td><td>○</td></tr>
<tr><td>P00.12</td><td>DEC time 1</td><td>Model depended</td><td>○</td></tr>
<tr><td>P00.13</td><td>Running direction</td><td>0: Run at the default direction.<br>1: Run at the opposite direction.<br>2: Disable reverse running.</td><td>0</td><td>○</td></tr>
<tr><td>P00.14</td><td>Carrier frequency setting</td><td>
<br>The relationship between models and carrier</td><td>Model depended</td><td>○</td></tr>
</table>

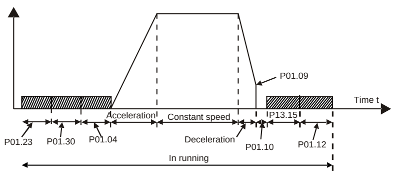
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>frequencies is as follows:
<table>
<tr><th>Model</th><th>Default carrier frequency</th><th>Minimum carrier frequency</th></tr>
<tr><td>1.5–11kW</td><td>4kHz</td><td>2kHz</td></tr>
<tr><td>15kW and higher</td><td>2kHz</td><td>1.5kHz</td></tr>
</table>
Advantage of high carrier frequency: ideal current waveform, little current harmonic wave and motor noise.<br>Disadvantage of high carrier frequency: increasing the switch loss, increasing VFD temperature and the impact to the output capacity. The VFD needs to derate on high carrier frequency. At the same time, the leakage and electrical magnetic interference will increase.<br>On the contrary, an extremely-low carrier frequency may cause unstable operation at low frequency, decrease the torque, or even lead to oscillation.<br>The carrier frequency has been properly set in the factory before the VFD is delivered. In general, you do not need to modify it.<br>When the frequency used exceeds the default carrier frequency, the VFD needs to derate by 10% for each increase of 1k carrier frequency.<br>The VFD can be set by P08.55 to enable or disable the function of reducing the carrier frequency with the heatsink temperature (enabled by default). If a consistently high carrier frequency is required for operation, in addition to setting P00.14 to the target value, it is also necessary to set P08.55 to disable.<br>Setting range: 1.0–15.0kHz</td><td></td><td></td></tr>
<tr><td>P00.15</td><td>Motor parameter autotuning</td><td>0: No operation<br>1: Dynamic autotuning 1<br>Comprehensive motor parameter autotuning. It is recommended to use rotating autotuning</td><td>0</td><td>◎</td></tr>
</table>

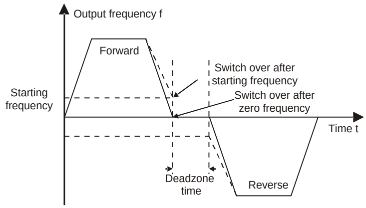
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | when high control accuracy is required.<br>2: Complete parameter static autotuning<br>Used in scenarios where the motor cannot be disconnected from load.<br>3: Partial parameter static autotuning 1<br>When the present motor is motor 1, only P02.06, P02.07, and P02.08 are autotuned; when the present motor is motor 2, only P12.06, P12.07, and P12.08 are autotuned.<br>4: Dynamic autotuning 2; similar to dynamic autotuning 1, but only valid for AMs<br>5: Partial parameter static autotuning 2 (valid only for AMs) | | |
| P00.16 | AVR function selection | 0: Invalid<br>1: Valid during the whole process<br>The auto-adjusting function of the VFD can eliminate the impact on the output voltage of the VFD because of the bus voltage fluctuation. | 1 | ○ |
| P00.17 | Reserved | - | - | - |
| P00.18 | Function parameter restoration | 0: No operation<br>1: Restore to default values (excluding motor parameters)<br>2: Clear fault records<br>3: Lock keypad parameters<br>4: Reserved<br>5: Restore to default values (factory test mode)<br>6: Restore to default values (including motor parameters)<br>**Note:** After the selected operation is performed, the function code is automatically restored to 0. Restoring the default values may delete the user password. Exercise caution when using this function. | 0 | ◎ |

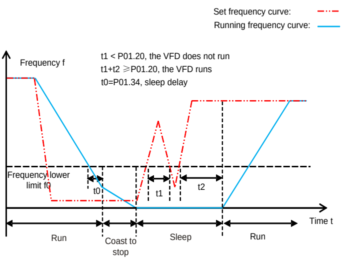
**Group P01—Start and stop control**

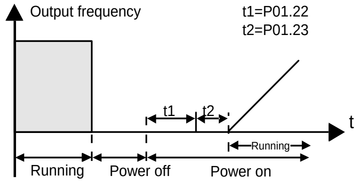
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P01.00 | Running mode of start | 0: Direct start<br>1: Start after DC braking<br>2: Speed tracking restart (not supported in SVC 0 for AMs)<br>**Note:** For AMs, speed tracking is not supported in SVC 0, and software speed tracking is supported in other modes. For details, see parameters P01.35–P01.41. For SMs, you do not need to modify parameters P01.35–P01.41. | 0 | ◎ |
| P01.01 | Starting frequency of direct start | The function code indicates the initial frequency during VFD start. See P01.02 (Starting frequency hold time) for detailed information.<br>Setting range: 0.00–50.00Hz | 0.50Hz | ◎ |
| P01.02 | Starting frequency hold time | <br>Setting a proper starting frequency can increase the torque during VFD start. During the hold time of the starting frequency, the output frequency of the VFD is the starting frequency. And then, the VFD runs from the starting frequency to the set frequency. If the set frequency is lower than the starting frequency, the VFD stops running and keeps in the standby state. The starting frequency is not limited in the lower limit frequency.<br>Setting range: 0.0–50.0s | 0.0s | ◎ |
| P01.03 | Braking current before start | The VFD performs DC braking with the braking current before start and it speeds up after the DC braking time. If the set DC braking time is 0, DC braking is invalid. Stronger braking current indicates larger | 0.0% | ◎ |
| P01.04 | Braking time before start | | 0.00s | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | braking power. The DC braking current before start is a percentage of the VFD rated current.<br>Setting range of P01.03: 0.0–100.0%<br>Setting range of P01.04: 0.00–50.00s | | |
| P01.05 | ACC and DEC mode | Used to indicate the changing mode of the frequency during start and running.<br>0: Linear type. The output frequency increases or decreases linearly.<br><br><br>1: S curve. The output frequency increases or decreases according to the S curve.<br>The S curve is generally applied to elevators, conveyors, and other application scenarios where smoother start or stop is required.<br><br><br>**Note:** If mode 1 is selected, set P01.06, P01.07, P01.27 and P01.28. | 0 | ◎ |
| P01.06 | Time of starting segment of ACC S curve | The curvature of S curve is determined by the ACC range and ACC/DEC time.<br><br><br>Setting range: 0.0–50.0s | 0.1s | ◎ |
| P01.07 | Time of ending segment of ACC S curve | | 0.1s | ◎ |
| P01.08 | Stop mode | 0: Decelerate to stop<br>After a stop command takes effect, the VFD | 0 | ○ |

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>lowers output frequency based on the DEC mode and the defined DEC time; after the frequency drops to the stop speed (P01.15), the VFD stops.<br>1: Coast to stop<br>After a stop command takes effect, the VFD stops output immediately. And the load coasts to stop according to mechanical inertia.</td><td></td><td></td></tr>
<tr><td>P01.09</td><td>Starting frequency of braking for stop</td><td rowspan="4">Starting frequency of DC braking for stop: During the deceleration to stop, the VFD starts DC braking for stop when running frequency reaches the starting frequency determined by P01.09.<br>Wait time before DC braking: The VFD blocks the output before starting DC braking. After this wait time, DC braking is started so as to prevent overcurrent caused by DC braking at high speed.<br>DC braking current for stop: It indicates the applied DC braking energy. Stronger current indicates greater DC braking effect.<br>DC braking time for stop: It indicates the hold time of DC braking. If the time is 0, DC braking is invalid, and the VFD decelerates to stop within the specified time.<br><br><br>Setting range of P01.09: 0.00Hz–P00.03 (Max. output frequency)<br>Setting range of P01.10: 0.00–30.00s<br>Setting range of P01.11: 0.0–100.0%<br>Setting range of P01.12: 0.0–50.0s</td><td>0.00Hz</td><td>○</td></tr>
<tr><td>P01.10</td><td>Demagnetization time</td><td>0.00s</td><td>○</td></tr>
<tr><td>P01.11</td><td>DC braking current for stop</td><td>0.0%</td><td>○</td></tr>
<tr><td>P01.12</td><td>DC braking time for stop</td><td>0.00s</td><td>○</td></tr>
<tr><td>P01.13</td><td>FWD/REV run deadzone time</td><td>This function code specifies the transition time of the switching in FWD/REV running switching mode specified by P01.14.</td><td>0.0s</td><td>○</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | <br>Setting range: 0.0–3600.0s | | |
| P01.14 | FWD/REV run switching mode | 0: Switch at zero frequency<br>1: Switch at the starting frequency<br>2: Switch after the speed reaches the stop speed with a delay | 1 | ◎ |
| P01.15 | Stop speed | 0.00–100.00Hz | 0.50Hz | ◎ |
| P01.16 | Stop speed detection mode | 0: Detect by the set speed (unique in V/F mode)<br>1: Detect by the feedback speed | 0 | ◎ |
| P01.17 | Stop speed detection time | 0.00–100.00s | 0.50s | ◎ |
| P01.18 | Terminal-based running command protection at power-on | When the channel of running commands is terminal control, the system detects the state of the running terminal during power-on.<br>0: The terminal running command is invalid at power-on<br>Even the running command is considered as valid during power-on, the VFD does not run and it keeps the protection state until the running command is canceled and enabled again.<br>1: The terminal running command is valid at power-on<br>If the running command is considered as valid during power-on, the VFD is started automatically after the initialization.<br>**Note:** Exercise caution before using this function. Otherwise, serious results may follow. | 0 | ○ |
| P01.19 | Action selected when running | The function code determines the running state of the VFD when the set frequency is | 0 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | frequency less than frequency lower limit (valid when frequency lower limit greater than 0) | lower than the lower-limit one.<br>0: Run at the frequency lower limit<br>1: Stop<br>2: Sleep<br>The VFD coasts to stop when the set frequency is lower than the lower-limit one. If the set frequency is higher than the lower limit once again and it lasts for the time set by P01.20, the VFD resumes the running state automatically. | | |
| P01.20 | Wake-up-from-sleep delay | Specifies the wake-up-from-sleep delay time.<br>When the running frequency of the VFD is lower than the lower limit, the VFD becomes standby.<br>When the set frequency is higher than the lower limit once again and it lasts for the time set by P01.20, the VFD runs automatically.<br><br>Setting range: 0.0–3600.0s (valid when P01.19=2) | 0.0s | ○ |
| P01.21 | Power-off restart selection | The function code indicates whether the VFD automatically runs after re-power on.<br>0: Disable<br>1: Enable<br>If the restart condition is met, the VFD will run automatically after waiting the time defined by P01.22. | 0 | ○ |
| P01.22 | Wait time for restart after power-off | The function code indicates the wait time before the automatic running of the VFD that is re-powered on. | 1.0s | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | <br>Setting range: 0.0–3600.0s (Valid only when P01.21=1) | | |
| P01.23 | Start delay time | After a VFD running command is given, the VFD is in standby state and restarts with the delay defined by P01.23 to implement brake release.<br>Setting range: 0.0–600.0s | 0.0s | ○ |
| P01.24 | Stop speed delay | 0.0–600.0s | 0.0s | ○ |
| P01.25 | Open-loop 0Hz output selection | 0: Output without voltage<br>1: Output with voltage<br>2: Output with the DC braking current for stop | 0 | ○ |
| P01.26 | DEC time for emergency stop | 0.0–60.0s | 2.0s | ○ |
| P01.27 | Time of starting segment of DEC S curve | 0.0–50.0s | 0.1s | ◎ |
| P01.28 | Time of ending segment of DEC S curve | 0.0–50.0s | 0.1s | ◎ |
| P01.29 | Short-circuit braking current | When the VFD starts in direct start mode (P01.00=0), set P01.30 to a non-zero value to enter short-circuit braking.<br>During stop, if the running frequency of VFD is lower than the starting frequency of brake for stop (P01.09), set P01.31 to a non-zero value to enter short-circuit braking for stop, and then carry out DC braking in the time set by P01.12. (Refer to the descriptions for P01.09–P01.12.)<br>Setting range of P01.29: 0.0–150.0% (of the rated VFD output current)<br>Setting range of P01.30: 0.0–50.0s | 0.0% | ○ |
| P01.30 | Hold time of short-circuit braking for start | | 0.00s | ○ |
| P01.31 | Hold time of short-circuit braking for stop | | 0.00s | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Setting range of P01.31: 0.0–50.0s | | |
| P01.32 | Pre-exciting time for jogging | 0.000–10.000s | 0.300s | ○ |
| P01.33 | Starting frequency of braking for stop in jogging | 0.00Hz–P00.03 | 0.00Hz | ○ |
| P01.34 | Sleep delay | 0.0–3600.0s | 0.0s | ○ |
| P01.35 | Speed tracking method | 0: From stop frequency (Usually selected)<br>1: From low frequency (Applicable to restart after a long time of coasting to stop)<br>2: From max. output frequency P00.03 (Applicable to common power generation load situation) | 0 | ○ |
| P01.36 | Quick/slow selection for speed tracking | 1–100s<br>A great value of this parameter indicates a fast rotation-speed tracking speed, but an excessively great value may result in poor tracking effect. | 15s | ○ |
| P01.37 | Speed tracking current | 30%–200%<br>Closed-loop current reference value (motor) during rotation.<br>Great value of this parameter indicates high reliability of rotation-speed tracking, but an excessively great value may result in VFD overcurrent. | 100% | ○ |
| P01.38 | Demagnetization time for speed tracking | 0.0–10.0s | Model depended | ○ |
| P01.39 | Advanced control for speed tracking | 0x000–0x111<br>Ones place: Current giving mode in vector control<br>0: 120% of current is given during startup, which is switched to the given value based on P01.35<br>1: The current is given based on P01.35<br>Tens place: PWM mode selection<br>0: 2PH modulation mode<br>1: Based on P08.40 | 0x110 | ○ |

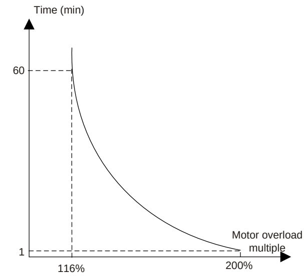
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Hundreds place: Search direction of speed tracking<br>0: Allow both forward and reverse search<br>1: Disallow reverse search | | |
| P01.40 | KP regulation coefficient for speed tracking | 0–3000 | 1500 | ○ |
| P01.41 | KI regulation coefficient for speed tracking | 0–3000 | 1500 | ○ |

**Group P02—Parameters of motor 1**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P02.00 | Type of motor 1 | 0: Asynchronous motor (AM)<br>1: Synchronous motor (SM) | 0 | ◎ |
| P02.01 | Rated power of AM 1 | 0.1–3000.0kW | Model depended (0.4) | ◎ |
| P02.02 | Rated frequency of AM 1 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz | ◎ |
| P02.03 | Rated speed of AM 1 | 1–60000rpm | Model depended (1400) | ◎ |
| P02.04 | Rated voltage of AM 1 | 0–1200V | Model depended (380) | ◎ |
| P02.05 | Rated current of AM 1 | 0.8–6000.0A | Model depended (1.0) | ◎ |
| P02.06 | Stator resistance of AM 1 | 0.001–65.535Ω | Model depended (0.001) | ○ |
| P02.07 | Rotor resistance of AM 1 | 0.001–65.535Ω | Model depended (0.001) | ○ |
| P02.08 | Leakage inductance of AM 1 | 0.1–6553.5mH | Model depended (0.1) | ○ |

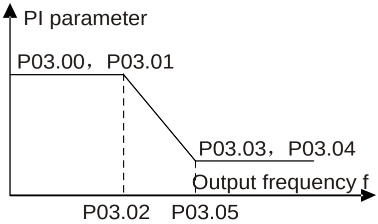
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P02.09 | Mutual inductance of AM 1 | 0.1–6553.5mH | Model depended (0.1) | ○ |
| P02.10 | No-load current of AM 1 | 0.1–6553.5A | Model depended (0.1) | ○ |
| P02.11 | Magnetic saturation coefficient 1 of iron core of AM 1 | 0.0–100.0% | 80.0% | ○ |
| P02.12 | Magnetic saturation coefficient 2 of iron core of AM 1 | 0.0–100.0% | 68.0% | ○ |
| P02.13 | Magnetic saturation coefficient 3 of iron core of AM 1 | 0.0–100.0% | 57.0% | ○ |
| P02.14 | Magnetic saturation coefficient 4 of iron core of AM 1 | 0.0–100.0% | 40.0% | ○ |
| P02.15 | Rated power of SM 1 | 0.1–3000.0kW | Model depended (0.4) | ◎ |
| P02.16 | Rated frequency of SM 1 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz | ◎ |
| P02.17 | Number of pole pairs of SM 1 | 1–128 | 2 | ◎ |
| P02.18 | Rated voltage of SM 1 | 0–1200V | Model depended (380) | ◎ |
| P02.19 | Rated current of SM 1 | 0.8–6000.0A | Model depended (1.0) | ◎ |
| P02.20 | Stator resistance of SM 1 | 0.001–65.535Ω | Model depended (0.001) | ○ |
| P02.21 | Direct-axis inductance of SM 1 | 0.01–655.35mH | Model depended (0.01) | ○ |
| P02.22 | Quadrature-axis inductance of SM 1 | 0.01–655.35mH | Model depended (0.01) | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P02.23 | Counter-emf of SM 1 | 0–10000 | 300 | ○ |
| P02.24 | Initial pole position of SM 1 | 0x0000–0xFFFF | 0x0000 | ● |
| P02.25 | Identification current of SM 1 | 0–50% | 10% | ● |
| P02.26 | Overload protection selection of motor 1 | 0: No protection<br>1: Common motor (with low-speed compensation)<br>As the cooling effect of a common motor is degraded at low speed running, the corresponding electronic thermal protection value needs to be adjusted properly, the low compensation indicates lowering the overload protection threshold of the motor whose running frequency is lower than 30Hz.<br>2: Frequency-variable motor (without low-speed compensation)<br>The heat dissipation function for a variable-frequency motor is not impacted by the rotation speed, and therefore it is not necessary to adjust the protection value at low speed running. | 2 | ◎ |
| P02.27 | Overload protection coefficient of motor 1 | Motor overload multiplication $M = I_{out}/(I_n*K)$<br>$I_n$ indicates the rated motor current, $I_{out}$ indicates the VFD output current, and K indicates the motor overload protection coefficient.<br>A smaller value of "K" indicates a bigger value of "M".<br>When M=116%, protection is performed after motor overload lasts for 1 hour; when M=200%, protection is performed after motor overload lasts for 60 seconds; and when M≥400%, protection is performed immediately. | 100.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | <br>Setting range: 20.0–150.0% | | |
| P02.28 | Power display calibration coefficient of motor 1 | The function code can be used to adjust the power display value of motor 1. However, it does not affect the control performance of the VFD.<br>Setting range: 0.00–3.00 | 1.00 | ○ |
| P02.29 | Parameter display of motor 1 | 0: Display by motor type<br>In this mode, only parameters related to the present motor type are displayed.<br>1: Display all<br>In this mode, all the motor parameters are displayed. | 0 | ○ |
| P02.30 | System inertia of motor 1 | 0.000–30.000kg•m$^2$ | 0.000 kg•m$^2$ | ○ |

**Group P03—Vector control of motor 1**

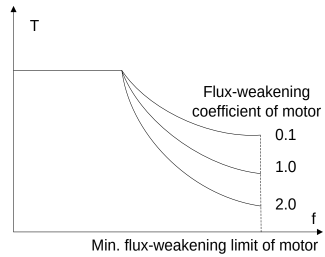
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P03.00 | Speed-loop proportional gain 1 | P03.00–P03.05 are applicable only to vector control. When switching frequency 1 (P03.02) is not reached, the speed-loop PI parameters are: P03.00 and P03.01. When switching frequency 2 (P03.05) is exceeded, the speed-loop PI parameters are: P03.03 and P03.04. PI parameters are obtained according to the linear change of two groups of parameters. See the following figure: | 20.0 | ○ |
| P03.01 | Speed-loop integral time 1 | | 0.200s | ○ |
| P03.02 | Low-point frequency for switching | | 5.00Hz | ○ |
| P03.03 | Speed-loop proportional gain 2 | | 20.0 | ○ |
| P03.04 | Speed-loop integral time 2 | | 0.200s | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P03.05 | High-point frequency for switching | <br>The speed loop dynamic response characteristics of vector control can be adjusted by setting the proportional coefficient and integral time of speed regulator.<br>Increasing proportional gain or reducing integral time can accelerate dynamic response of speed loop; however, if the proportional gain is too large or integral time is too small, system oscillation and overshoot may occur; if proportional gain is too small, stable oscillation or speed offset may occur.<br>PI parameters have a close relationship with the inertia of the system. Adjust PI parameters depending on different loads to meet various demands.<br>Setting range of P03.00: 0.0–200.0<br>Setting range of P03.01: 0.000–10.000s<br>Setting range of P03.02: 0.00Hz –P03.05<br>Setting range of P03.03: 0.0–200.0<br>Setting range of P03.04: 0.000–10.000s<br>Setting range of P03.05: P03.02 –P00.03 | 10.00Hz | ○ |
| P03.06 | Speed-loop output filter | 0–8 (corresponding to 0–$2^8$/10ms) | 0 | ○ |
| P03.07 | Electromotive slip compensation coefficient of vector control | Slip compensation coefficient is used to adjust the slip frequency of the vector control and improve the speed control accuracy of the system. Adjusting the parameter properly can control the speed steady-state error.<br>Setting range: 50–200% | 100% | ○ |
| P03.08 | Power-generation slip compensation coefficient of vector | | 100% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | control | | | |
| P03.09 | Current-loop proportional coefficient P | **Note:**<br>✧ The two function codes impact the dynamic response speed and control accuracy of the system. Generally, you do not need to modify the two function codes.<br>✧ Applicable to SVC mode 0 (P00.00=0).<br>✧ The values of the two function codes are updated automatically after SM parameter autotuning is completed.<br>Setting range: 0–65535 | 1000 | ○ |
| P03.10 | Current-loop integral coefficient I | | 1000 | ○ |
| P03.11 | Torque setting method selection | 0–18<br>0: Keypad (invalid)<br>1: Keypad (P03.12)<br>2: AI1<br>3: AI2<br>4: AI3<br>5: Pulse frequency HDIA<br>6: Multi-step torque<br>7: Modbus/Modbus TCP communication<br>8: PROFIBUS/CANopen/BACnet MSTP communication<br>9: Ethernet communication<br>10: Pulse frequency HDIB<br>11: PROFINET/EtherNet IP communication<br>12: Programmable card<br>13–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>**Note:** 100% corresponds to the rated current of motor 1. | 0 | ○ |
| P03.12 | Torque set through keypad | -300.0%–300.0% (of the rated current of motor 1) | 20.0% | ○ |
| P03.13 | Torque reference filter time | 0.000–10.000s | 0.010s | ○ |
| P03.14 | Setting source of forward rotation frequency upper | 0–18<br>0: Keypad (P03.16)<br>1: AI1 (100% corresponds to the max. | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | limit in torque control | frequency)<br>2: AI2 (same as the above)<br>3: AI3 (same as the above)<br>4: Pulse frequency HDIA<br>5: Multi-step setting (same as the above)<br>6: Modbus/Modbus TCP communication (same as the above)<br>7: PROFIBUS/CANopen/BACnet MSTP communication (same as the above)<br>8: Ethernet communication (same as the above)<br>9: Pulse frequency HDIB<br>10: PROFINET/EtherNet IP communication (same as the above)<br>11: Programmable card (same as the above)<br>12–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | | |
| P03.15 | Setting source of reverse rotation upper-limit frequency in torque control | 0–18<br>0: Keypad (P03.17)<br>1: AI1 (100% corresponds to the max. frequency)<br>2: AI2 (same as the above)<br>3: AI3 (same as the above)<br>4: Pulse frequency HDIA<br>5: Multi-step setting (same as the above)<br>6: Modbus/Modbus TCP communication (same as the above)<br>7: PROFIBUS/CANopen/BACnet MSTP communication (same as the above)<br>8: Ethernet communication (same as the above)<br>9: Pulse frequency HDIB (Same as the above)<br>10: PROFINET/EtherNet IP communication (same as the above)<br>11: Programmable card (same as the above)<br>12–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | 0 | ○ |

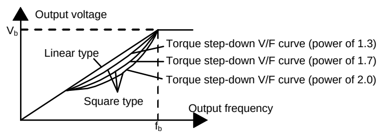
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P03.16 | Forward rotation frequency upper limit set through keypad in torque control | Used to set frequency limits. 100% corresponds to the max. frequency.<br>P03.16 specifies the value when P03.14=1, while P03.17 specifies the value when P03.15=1.<br>Setting range: 0.00Hz–P00.03 (Max. output frequency) | 50.00Hz | ○ |
| P03.17 | Reverse rotation upper-limit frequency set through keypad in torque control | | 50.00Hz | ○ |
| P03.18 | Setting source of electromotive torque upper limit | 0–18<br>0: Keypad (P03.21)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: Pulse frequency HDIA<br>5: Modbus/Modbus TCP communication<br>6: PROFIBUS/CANopen/BACnet MSTP communication<br>7: Ethernet communication<br>8: Pulse frequency HDIB<br>9: PROFINET/EtherNet IP communication<br>10: Programable card<br>11–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>**Note:** 100% corresponds to the rated current of motor 1. | 0 | ○ |
| P03.19 | Setting source of braking torque upper limit | 0–18<br>0: Keypad (P03.21)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: Pulse frequency HDIA<br>5: Modbus/Modbus TCP communication<br>6: PROFIBUS/CANopen/BACnet MSTP communication<br>7: Ethernet communication | 0 | ○ |

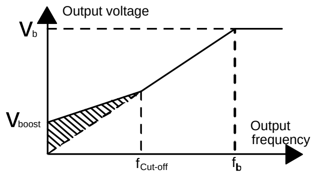
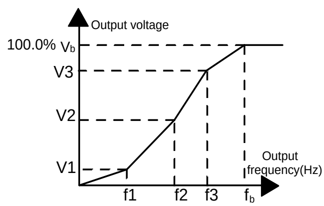
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>8: Pulse frequency HDIB<br>9: PROFINET/EtherNet IP communication<br>10: Programable card<br>11–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>Note: 100% corresponds to the rated current of motor 1.</td><td></td><td></td></tr>
<tr><td>P03.20</td><td>Electromotive torque upper limit set through keypad</td><td rowspan="2">Used to set torque limits.<br>Setting range: 0.0–300.0% (of the rated voltage of motor 1)</td><td>180.0%</td><td>○</td></tr>
<tr><td>P03.21</td><td>Braking torque upper limit set through keypad</td><td>180.0%</td><td>○</td></tr>
<tr><td>P03.22</td><td>Weakening coefficient in constant power zone</td><td rowspan="2">Used when the AM is in flux-weakening control.<br><br><br>The function codes P03.22 and P03.23 are valid at constant power. The motor enters the flux-weakening state when the motor runs above the rated speed. Change the flux-weakening curvature by modifying the flux-weakening control coefficient. The larger the coefficient, the steeper the curve, the smaller the coefficient, the smoother the curve.<br>Setting range of P03.22: 0.1–2.0<br>Setting range of P03.23: 10%–100.0%</td><td>0.3</td><td>○</td></tr>
<tr><td>P03.23</td><td>Lowest weakening point in constant power zone</td><td>20%</td><td>○</td></tr>
<tr><td>P03.24</td><td>Max. voltage limit</td><td>P03.24 sets the max. output voltage of the VFD, which is the percentage of motor rated voltage. Set the value according to onsite</td><td>100.0%</td><td>○</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | conditions.<br>Setting range: 0.0–120.0% (only valid for SM vector 0 weak magnetism) | | |
| P03.25 | Pre-exciting time | Pre-exciting is performed for the motor when the VFD starts up. A magnetic field is built up inside the motor to improve the torque performance during the start process.<br>Setting range: 0.000–10.000s (only valid for SM vector 0 weak magnetism) | 0.300s | ○ |
| P03.26 | Flux-weakening proportional gain | 0–8000 (only valid for SM vector 0 weak magnetism) | 1000 | ○ |
| P03.27 | Speed display selection in vector control | 0: Display the actual value<br>1: Display the set value | 0 | ○ |
| P03.28 | Static friction compensation coefficient | 0.0–100.0% | 0.0% | ○ |
| P03.29 | Corresponding frequency point of static friction | 0.50Hz–P03.31 | 1.00Hz | ○ |
| P03.30 | High speed friction compensation coefficient | 0.0–100.0% | 0.0% | ○ |
| P03.31 | Corresponding frequency of high speed friction torque | P03.29–400.00Hz | 50.00Hz | ○ |
| P03.32 | Enabling torque control | 0: Disable<br>1: Enable | 0 | ◎ |
| P03.33 | Flux-weakening integral gain | 0–8000 | 1200 | ○ |
| P03.34 | Reserved | - | - | - |
| P03.35 | Control mode optimization selection | Range: 0x0000–0x1111<br>Ones place: Torque command selection<br>0: Torque reference<br>1: Torque current reference<br>Tens place: Reserved<br>Hundreds place: indicates whether to enable | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | speed-loop integral separation<br>0: Disable<br>1: Enable<br>Thousands place: Reserved | | |
| P03.36 | Speed-loop differential gain | 0.00–10.00s | 0.00s | ○ |
| P03.37 | Proportional coefficient of high-frequency current loop | Setting range of P03.37: 0–65535<br>P03.38 setting range: 0–65535<br>P03.39 setting range: 0.0–100.0% (of the max. frequency) | 1000 | ○ |
| P03.38 | High-frequency current-loop integral coefficient | | 1000 | ○ |
| P03.39 | Current-loop high-frequency switching threshold | | 100.0% | ○ |
| P03.40 | Enabling inertia compensation | 0: Disable<br>1: Enable | 0 | ○ |
| P03.41 | Upper limit of inertia compensation torque | The max. inertia compensation torque is limited to prevent inertia compensation torque from being too large.<br>Setting range: 0.0–150.0% (of the motor rated torque) | 10.0% | ○ |
| P03.42 | Inertia compensation filter times | Filter times of inertia compensation torque, used to smooth inertia compensation torque.<br>Setting range: 0–10 | 7 | ○ |
| P03.43 | Inertia identification torque | Due to friction force, it is required to set certain identification torque for the inertia identification to be performed properly.<br>0.0–100.0% (of the rated motor torque) | 10.0% | ○ |
| P03.44 | Enabling motor inertia identification | 0: No operation<br>1: Enable | 0 | ◎ |
| P03.45 | Current-loop proportional coefficient after autotuning | 0–65535 | 0 | ○ |
| P03.46 | Current-loop integral coefficient after autotuning | 0–65535 | 0 | ○ |

**Group P04—V/F control**

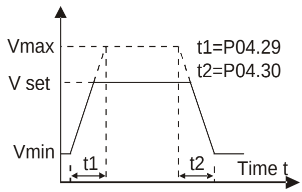
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P04.00 | V/F curve setting of motor 1 | This group of function code defines the V/F curve of motor 1 to meet the needs of different loads.<br>0: Straight-line V/F curve, applicable to constant torque loads<br>1: Multi-point V/F curve<br>2: Torque-down V/F curve (power of 1.3)<br>3: Torque-down V/F curve (power of 1.7)<br>4: Torque-down V/F curve (power of 2.0)<br>Curves 2 – 4 are applicable to the torque loads such as fans and water pumps. You can adjust according to the characteristics of the loads to achieve best performance.<br>5: Customized V/F (V/F separation); in this mode, V can be separated from F and F can be adjusted through the frequency setting channel set by P00.06 or the voltage setting channel set by P04.27 to change the characteristics of the curve.<br>Note: In the following figure, $V_b$ is the motor rated voltage and $f_b$ is the motor rated frequency.<br><br> | 0 | ◎ |
| P04.01 | Torque boost of motor 1 | In order to compensate for low-frequency torque characteristics, you can make some boost compensation for the output voltage. P04.01 is relative to the max. output voltage $V_b$.<br>P04.02 defines the percentage of cut-off frequency of manual torque boost to the rated motor frequency $f_b$. Torque boost can improve the low-frequency torque characteristics of V/F.<br>You need to select torque boost based on the | 0.0% | ○ |
| P04.02 | Torque boost cut-off of motor 1 | | 20.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | load. For example, larger load requires larger torque boost, however, if the torque boost is too large, the motor will run at over-excitation, which may cause increased output current and motor overheating, thus decreasing the efficiency.<br>When torque boost is set to 0.0%, the VFD uses automatic torque boost.<br>Torque boost cut-off threshold: Below this frequency threshold, torque boost is valid; exceeding this threshold will invalidate torque boost.<br><br>Setting range of P04.04: 0.0% (Automatic); 0.1%–10.0% (of the rated voltage of motor 1)<br>Setting range of P04.02: 0.0%–50.0% (of the rated frequency of motor 1) | | |
| P04.03 | V/F frequency point 1 of motor 1 | When P04.00=1 (multi-dot V/F curve), you can set the V/F curve through P04.03–P04.08.<br>The V/F curve is generally set according to the load characteristics of the motor.<br>Note: V1＜ V2＜ V3, f1＜ f2＜ f3 Too high voltage for low frequency will cause motor overheat or damage and cause VFD overcurrent stall or overcurrent protection.<br><br>Setting range of P04.03: 0.00Hz–P04.05<br>Setting range of P04.04: 0.0%–110.0% (of the | 0.00Hz | ○ |
| P04.04 | V/F voltage point 1 of motor 1 | | 00.0% | ○ |
| P04.05 | V/F frequency point 2 of motor 1 | | 0.00Hz | ○ |
| P04.06 | V/F voltage point 2 of motor 1 | | 0.0% | ○ |
| P04.07 | V/F frequency point 3 of motor 1 | | 0.00Hz | ○ |
| P04.08 | V/F voltage point 3 of motor 1 | | 0.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | rated voltage of motor 1)<br>Setting range of P04.05: P04.03–P04.07<br>Setting range of P04.06: 0.0%–110.0% (of the rated voltage of motor 1)<br>Setting range of P04.07: P04.05–P02.02 (of the rated frequency of AM 1) or P04.05–P02.16 (of the rated frequency of SM 1)<br>Setting range of P04.08: 0.0%–110.0% (of the rated voltage of motor 1) | | |
| P04.09 | V/F slip compensation gain of motor 1 | Used to compensate for the motor rotating speed change caused by load change in the space voltage vector mode, and thus improve the rigidity of the mechanical characteristics of the motor. You need to calculate the rated slip frequency of the motor as follows:<br>$\triangle f=f_b-n*p/60$<br>Of which, $f_b$ is the rated frequency of the motor, corresponding to function code P02.02. n is the rated rotating speed of the motor, corresponding to function code P02.03. p is the number of pole pairs of the motor. 100.0% corresponds to the rated slip frequency △f of motor 1.<br>Setting range: 0.0–200.0% | 0.0% | ○ |
| P04.10 | Low-frequency oscillation control factor of motor 1 | In space voltage vector control mode, the motor, especially the large-power motor, may experience current oscillation at certain frequencies, which may cause unstable motor running, or even VFD overcurrent. You can adjust the two function codes properly to eliminate such phenomenon.<br>Setting range of P04.10: 0–100<br>Setting range of P04.11: 0–100<br>Setting range of P04.12: 0.00Hz–P00.03 | 10 | ○ |
| P04.11 | High-frequency oscillation control factor of motor 1 | | 10 | ○ |
| P04.12 | Oscillation control threshold of motor 1 | | 30.00Hz | ○ |
| P04.13 | V/F curve setting of motor 2 | This group of function code defines the V/F curve of motor 2 to meet the needs of different loads.<br>Range: 0–5<br>0: Straight-line V/F curve | 0 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 1: Multi-point V/F curve<br>2: Torque-down V/F curve (power of 1.3)<br>3: Torque-down V/F curve (power of 1.7)<br>4: Torque-down V/F curve (power of 2.0)<br>5: Customized V/F curve (V/F separation)<br>**Note:** Refer to the description for P04.00. | | |
| P04.14 | Torque boost of motor 2 | Setting range of P04.14: 0.0% (Automatic); 0.1%–10.0% (of the rated voltage of motor 2)<br>Setting range of P04.15: 0.0 –50.0% (of the rated frequency of motor 2)<br>Note: Refer to the descriptions for P04.01 and P04.02. | 0.0% | ○ |
| P04.15 | Torque boost cut-off of motor 2 | | 20.0% | ○ |
| P04.16 | V/F frequency point 1 of motor 2 | Setting range of P04.16: 0.00Hz–P04.18<br>Setting range of P04.17: 0.0%–110.0% (of the rated voltage of motor 2)<br>Setting range of P04.18: P04.16–P04.20<br>Setting range of P04.19: 0.0%–110.0% (of the rated voltage of motor 2)<br>Setting range of P04.20: P04.18–P12.02 (of the rated frequency of AM 2) or P04.18–P12.16 (of the rated frequency of SM 2)<br>Setting range of P04.21: 0.0%–110.0% (of the rated voltage of motor 2)<br>**Note:** Refer to the descriptions for P04.03–P04.08. | 0.00Hz | ○ |
| P04.17 | V/F voltage point 1 of motor 2 | | 0.0% | ○ |
| P04.18 | V/F frequency point 2 of motor 2 | | 0.00Hz | ○ |
| P04.19 | V/F voltage point 2 of motor 2 | | 0.0% | ○ |
| P04.20 | V/F frequency point 3 of motor 2 | | 0.00Hz | ○ |
| P04.21 | V/F voltage point 3 of motor 2 | | 0.0% | ○ |
| P04.22 | V/F slip compensation gain of motor 2 | Used to compensate for the motor rotating speed change caused by load change in the space voltage vector mode, and thus improve the rigidity of the mechanical characteristics of the motor. You need to calculate the rated slip frequency of the motor as follows:<br>$\triangle f = f_b - n*p/60$<br>Of which, $f_b$ is the rated frequency of the motor, corresponding to function code P12.02. n is the rated rotating speed of the motor, corresponding to function code P12.03. p is the number of pole pairs of the motor. 100.0% corresponds to the rated slip frequency $\triangle f$ of motor 2. | 0.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Setting range: 0.0–200.0% | | |
| P04.23 | Low-frequency oscillation control factor of motor 2 | In space voltage vector control mode, the motor, especially the large-power motor, may experience current oscillation at certain frequencies, which may cause unstable motor running, or even VFD overcurrent. You can adjust the two function codes properly to eliminate such phenomenon.<br>Setting range of P04.23: 0–100<br>Setting range of P04.24: 0–100<br>Setting range of P04.25: 0.00Hz–P00.03 | 10 | ○ |
| P04.24 | High-frequency oscillation control factor of motor 2 | | 10 | ○ |
| P04.25 | Oscillation control threshold of motor 2 | | 30.00Hz | ○ |
| P04.26 | Energy-saving run | 0: Disable<br>1: Automatic energy-saving run<br>In light-load state, the motor can adjust the output voltage automatically to achieve energy saving. | 0 | ○ |
| P04.27 | Voltage setting channel selection | 0–18<br>0: Keypad (The output voltage is determined by P04.28.)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: HDIA<br>5: Multi-step speed running (The setting is determined by group P10.)<br>6: PID<br>7: Modbus/Modbus TCP communication<br>8: PROFIBUS/CANopen /BACnet MSTP communication<br>9: Ethernet communication<br>10: HDIB<br>11: PROFINET/EtherNet IP communication<br>12: Programmable card<br>13–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models) | 0 | ○ |
| P04.28 | Voltage set through keypad | The function code is the voltage digital setting when "keypad" is selected as the voltage | 100.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | setting channel.<br>Setting range: 0.0%–100.0% (of the rated voltage of motor 1) | | |
| P04.29 | Voltage increase time | Voltage increase time means the time needed for the VFD to accelerate from min. output voltage to the max. output frequency.<br>Voltage decrease time means the time needed for the VFD to decelerate from the max. output frequency to min. output voltage.<br>Setting range: 0.0–3600.0s | 5.0s | ○ |
| P04.30 | Voltage decrease time | | 5.0s | ○ |
| P04.31 | Max. output voltage | The function codes are used to set the upper and lower limits of output voltage.<br><br>Setting range of P04.31: P04.32–100.0% (of the motor rated voltage)<br>Setting range of P04.32: 0.0%–P04.31 (of the motor rated voltage) | 100.0% | ◎ |
| P04.32 | Min. output voltage | | 0.00Hz | ◎ |
| P04.33 | Weakening coefficient in constant power zone | 1.00–1.30<br>**Note:** P04.33 is only valid for V/F mode. | 1.00 | ○ |
| P04.34 | Pull-in current 1 in SM V/F control | When the SM V/F control mode is enabled, the function code is used to set the reactive current of the motor when the output frequency is lower than the frequency specified by P04.36.<br>Setting range: -100.0%–+100.0% (of the motor rated current) | 20.0% | ○ |
| P04.35 | Pull-in current 2 in SM V/F control | When the SM V/F control mode is enabled, the function code is used to set the reactive current of the motor when the output frequency is greater than the frequency specified by P04.36. | 10.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Setting range: -100.0%–+100.0% (of the motor rated current) | | |
| P04.36 | Frequency threshold for pull-in current switching in SM V/F control | When the SM VF control mode is enabled, the function code is used to set the frequency threshold for the switching between pull-in current 1 and pull-in current 2.<br>Setting range: 0.0 –200.0% (of the motor rated frequency) | 20.0% | ○ |
| P04.37 | Reactive current closed-loop proportional coefficient in SM V/F control | When the SM VF control mode is enabled, the function code is used to set the proportional coefficient of reactive current closed-loop control.<br>Setting range: 0–3000 | 50 | ○ |
| P04.38 | Reactive current closed-loop integral time in SM V/F control | When the SM VF control mode is enabled, the function code is used to set the integral coefficient of reactive current closed-loop control.<br>Setting range: 0–3000 | 30 | ○ |
| P04.39 | Reactive current closed-loop output limit in SM VF control | When the SM VF control mode is enabled, the function code is used to set the output limit of the reactive current closed-loop control. A greater value indicates a higher reactive closed-loop compensation voltage and higher output power of the motor. In general, you do not need to modify the function code.<br>Setting range: 0–16000 | 8000 | ○ |
| P04.40 | Enabling IF mode for AM 1 | 0: Invalid<br>1: Enable | 0 | ◎ |
| P04.41 | Current setting in IF mode for AM 1 | When IF control is adopted for AM 1, the function code is used to set the output current. The value is a percentage in relative to the rated current of the motor.<br>Setting range: 0.0–200.0% | 120.0% | ○ |
| P04.42 | Proportional coefficient in IF mode for AM 1 | When IF control is adopted for AM 1, the function code is used to set the proportional coefficient of the output current closed-loop control.<br>Setting range: 0–5000 | 350 | ○ |
| P04.43 | Integral coefficient | When IF control is adopted for AM 1, the | 150 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | in IF mode for AM 1 | function code is used to set the integral coefficient of the output current closed-loop control.<br>Setting range: 0–5000 | | |
| P04.44 | Starting frequency point for motor 1 switching off IMVF mode | 0.00–P04.50 | 10.00Hz | ○ |
| P04.45 | Enabling IF mode for AM 2 | 0: Invalid<br>1: Enable | 0 | ◎ |
| P04.46 | IMVF current setting | Setting range: 0.0–200.0% (of the motor rated current) | 120.0% | ○ |
| P04.47 | Proportional coefficient in IF mode for AM 2 | When IF control is adopted for AM 2, the function code is used to set the proportional coefficient of output current closed-loop control.<br>Setting range: 0–5000 | 350 | ○ |
| P04.48 | Integral coefficient in IF mode for AM 2 | When IF control is adopted for AM 2, the function code is used to set the integral coefficient of output current closed-loop control.<br>Setting range: 0–5000 | 150 | ○ |
| P04.49 | Starting frequency point for motor 2 switching off IMVF mode | 0.00–P04.51 | 10.00Hz | ○ |
| P04.50 | End frequency point for motor 1 switching off IMVF mode | P04.44–P00.03 | 25.00Hz | ○ |
| P04.51 | End frequency point for motor 2 switching off IMVF mode | P04.49–P00.03 | 25.00Hz | ○ |
| P04.52 | VF energy-saving mode selection | 0–2<br>0: Max. efficiency (default)<br>1: Optimal power factor<br>2: MTPA | 0 | ○ |

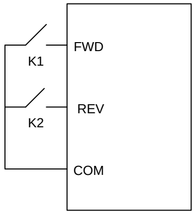
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P04.53 | VF energy-saving gain coefficient | 0.0%–400.0% | 100.0 | ○ |
| P04.54 | VF energy-saving power angle gain coefficient | 0.0%–200.0%<br>**Note:** A small value of this parameter increases energy saving control effect, but this also reduces the load carrying capability for sudden load. | 80.0% | ○ |

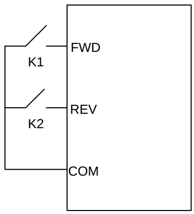
**Group P05—Input terminals**

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td>P05.00</td><td>HDI input type</td><td>0x00–0x11<br>Ones place: HDIA input type<br>0: HDIA is high-speed pulse input<br>1: HDIA is digital input<br>Tens place: HDIB input type (reserved)<br>0: HDIB is high-speed pulse input (reserved)<br>1: HDIB is digital input (reserved)</td><td>0x00</td><td>◎</td></tr>
<tr><td>P05.01</td><td>Function of S1</td><td rowspan="7">0–111<br>0: No function<br>1: Run forward<br>2: Run reversely<br>3: Three-wire running control<br>4: Jog forward<br>5: Jog reversely<br>6: Coast to stop<br>7: Fault reset<br>8: Pause running<br>9: External fault input<br>10: Increase frequency setting (UP)<br>11: Decrease frequency setting (DOWN)<br>12: Clear the frequency increase/decrease setting<br>13: Switch between A setting and B setting<br>14: Switch between combination setting and A setting<br>15: Switch between combination setting and B setting</td><td>1</td><td>◎</td></tr>
<tr><td>P05.02</td><td>Function of S2</td><td>4</td><td>◎</td></tr>
<tr><td>P05.03</td><td>Function of S3</td><td>7</td><td>◎</td></tr>
<tr><td>P05.04</td><td>Function of S4</td><td>0</td><td>◎</td></tr>
<tr><td>P05.05</td><td>Function of HDIA</td><td>0</td><td>◎</td></tr>
<tr><td>P05.06</td><td>Reserved</td><td>-</td><td>-</td></tr>
<tr><td>P05.07</td><td>Reserved</td><td>-</td><td>-</td></tr>
</table>

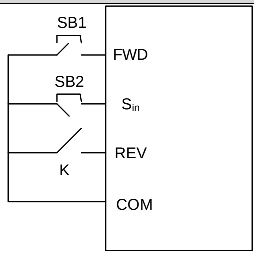
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 16: Multi-step speed terminal 1<br>17: Multi-step speed terminal 2<br>18: Multi-step speed terminal 3<br>19: Multi-step speed terminal 4<br>20: Pause multi-step speed running<br>21: ACC/DEC time selection 1<br>22: ACC/DEC time selection 2<br>23: Simple PLC stop reset<br>24: Pause simple PLC<br>25: Pause PID control<br>26: Pause wobbling frequency<br>27: Reset wobbling frequency<br>28: Counter reset<br>29: Switch between speed control and torque control<br>30: Disable ACC/DEC<br>31: Trigger the counter<br>32: Reserved<br>33: Clear the frequency increase/decrease setting temporarily<br>34: DC braking<br>35: Switch from motor 1 to motor 2<br>36: Switch the running command channel to keypad<br>37: Switch the running command channel to terminal<br>38: Switch the running command channel to communication<br>39: Pre-exciting command<br>40: Clear electricity consumption<br>41: Keep electricity consumption<br>42: Switch the setting source of braking torque upper limit to keypad<br>43–72: Reserved<br>73: PID2 start<br>74: PID2 stop<br>75: Pause PID2 integral<br>76: Pause PID2 control | | |

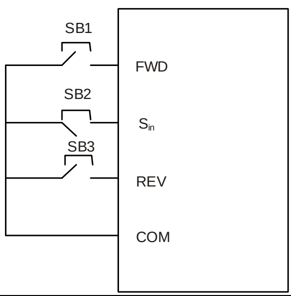
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>77: Switch PID2 polarities<br>78: Disable HVAC (only in stopped state)<br>79: Trigger fire signal<br>80: Pause PID1 control<br>81: Pause PID1 integral<br>82: Switch PID1 polarities<br>83: Trigger sleep mode<br>84: Trigger wakeup mode<br>85: Manual alternation<br>86: Pump cleaning signal<br>87: Water level upper limit of inlet pool<br>88: Water level lower limit of inlet pool<br>89: Water shortage level of inlet pool<br>90–103: Reserved<br>104: Disable motor A<br>105: Disable motor B<br>106: Disable motor C<br>107: Disable motor D<br>108: Disable motor E<br>109: Disable motor F<br>110: Disable motor G<br>111: Disable motor H<br>Note: The output of S4 and Y1 is mutually exclusive, meaning only one can be selected.</td><td></td><td></td></tr>
<tr><td>P05.08</td><td>Input terminal polarity selection</td><td>The function code is used to set the polarity of input terminals.<br>When a bit is 0, the input terminal is positive; when a bit is 1, the input terminal is negative.<br>0x00–0x3F<table><tr><td>Bit0</td><td>Bit1</td><td>Bit2</td><td>Bit3</td><td>Bit4</td><td>Bit5</td></tr><tr><td>S1</td><td>S2</td><td>S3</td><td>S4</td><td>HDIA</td><td>Reserved</td></tr></table></td><td>0x00</td><td>○</td></tr>
<tr><td>P05.09</td><td>Digital input filter time</td><td>Used to specify the sampling filter time of the S1–S4, and HDIA terminals. In strong interference cases, increase the value to avoid maloperation.<br>0.000–1.000s</td><td>0.010s</td><td>○</td></tr>
<tr><td>P05.10</td><td>Virtual terminal setting</td><td>0x00–0x3F (0: disable, 1: enable)<table><tr><td>Bit0</td><td>Bit1</td><td>Bit2</td><td>Bit3</td><td>Bit4</td><td>Bit5</td></tr></table></td><td>0x00</td><td>◎</td></tr>
</table>

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td><table><tr><td>S1</td><td>S2</td><td>S3</td><td>S4</td><td>HDIA</td><td>Reserved</td></tr></table></td><td></td><td></td></tr>
<tr><td>P05.11</td><td>Terminal control mode</td><td>The function code is used to set the mode of terminal control.<br>0: Two-wire control 1, the enabling consistent with the direction. This mode is widely used. The defined FWD/REV terminal command determines the motor rotation direction.<br>

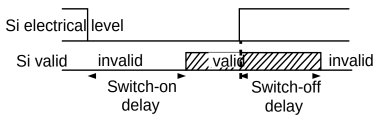
<table><tr><th>FWD</th><th>REV</th><th>Running command</th></tr><tr><td>OFF</td><td>OFF</td><td>Stop</td></tr><tr><td>ON</td><td>OFF</td><td>Forward running</td></tr><tr><td>OFF</td><td>ON</td><td>Reverse running</td></tr><tr><td>ON</td><td>ON</td><td>Hold</td></tr></table>
1: Two-wire control 2, the enabling separated from the direction. In this mode, FWD is the enabling terminal. The direction depends on the defined REV state.<br>

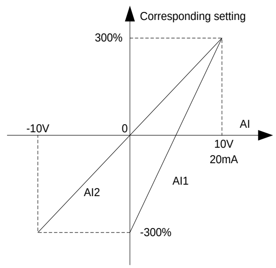
<table><tr><th>FWD</th><th>REV</th><th>Running command</th></tr><tr><td>OFF</td><td>OFF</td><td>Stop</td></tr><tr><td>ON</td><td>OFF</td><td>Forward running</td></tr><tr><td>OFF</td><td>ON</td><td>Stop</td></tr><tr><td>ON</td><td>ON</td><td>Reverse running</td></tr></table>
2: Three-wire control 1. This mode defines $S_{In}$ as the enabling terminal, and the running command is generated by FWD, while the direction is controlled by REV. During running, the $S_{in}$ terminal needs to be closed, and when terminal FWD generates a rising edge signal, the VFD starts to run in the direction set by the state of terminal REV; the VFD needs to be stopped by disconnecting terminal $S_{in}$.</td><td>0</td><td>◎</td></tr>
</table>

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>


The direction control is as follows during running:
<table>
<tr><th>$S_{in}$</th><th>REV</th><th>Previous direction</th><th>Present direction</th></tr>
<tr><td rowspan="2">ON</td><td rowspan="2">OFF→ON</td><td>FWD run</td><td>REV run</td></tr>
<tr><td>REV run</td><td>FWD run</td></tr>
<tr><td rowspan="2">ON</td><td rowspan="2">ON→OFF</td><td>REV run</td><td>FWD run</td></tr>
<tr><td>FWD run</td><td>REV run</td></tr>
<tr><td rowspan="2">ON→OFF</td><td>ON</td><td rowspan="2" colspan="2">Decelerate to stop</td></tr>
<tr><td>OFF</td></tr>
</table>
$S_{in}$: Three-wire control; FWD: Forward running; REV: Reverse running<br>
3: Three-wire control 2. This mode defines $S_{In}$ as the enabling terminal, and the running command is generated by FWD or REV, but the direction is controlled by both FWD and REV. During running, the $S_{in}$ terminal needs to be closed, and terminal FWD or REV generates a rising edge signal to control the running and direction of the VFD; the VFD needs to be stopped by disconnecting terminal $S_{in}$.


</td><td></td><td></td></tr>
</table>

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>
<table>
<tr><th>$S_{in}$</th><th>FWD</th><th>REV</th><th>Running direction</th></tr>
<tr><td rowspan="2">ON</td><td rowspan="2">OFF→ON</td><td>ON</td><td>FWD run</td></tr>
<tr><td>OFF</td><td>FWD run</td></tr>
<tr><td rowspan="2">ON</td><td>ON</td><td rowspan="2">OFF→ON</td><td>REV run</td></tr>
<tr><td>OFF</td><td>REV run</td></tr>
<tr><td>ON→OFF</td><td></td><td></td><td>Decelerate to stop</td></tr>
</table>
$S_{in}$: Three-wire control; FWD: Forward running; REV: Reverse running<br>
Note: For two-wire controlled running mode, when the FWD/REV terminal is valid, if the VFD stops due to a stop command given by another source, the VFD does not run again after the stop command disappears even if the control terminal FWD/REV is still valid. To make the VFD run, you need to trigger FWD/REV again, for example, PLC single-cycle stop, fixed-length stop, and valid STOP/RST stop during terminal control. (See P07.04.)</td><td></td><td></td></tr>
<tr><td>P05.12</td><td>S1 switch-on delay</td><td rowspan="12">These function codes specify the delay time corresponding to the electrical level changes when the programmable input terminals switch on or switch off.<br>
<br>Setting range: 0.000–50.000s<br>Note: After a virtual terminal is enabled, the state of the terminal can be changed only in communication mode. The communication address is 0x200A.</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.13</td><td>S1 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.14</td><td>S2 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.15</td><td>S2 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.16</td><td>S3 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.17</td><td>S3 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.18</td><td>S4 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.19</td><td>S4 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.20</td><td>HDIA switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.21</td><td>HDIA switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.22</td><td>HDIB switch-on delay (reserved)</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.23</td><td>HDIB switch-off delay (reserved)</td><td>0.000s</td><td>○</td></tr>
<tr><td>P05.24</td><td>AI1 lower limit</td><td rowspan="2">Used to define the relationship between the analog input voltage and its corresponding</td><td>0.00V</td><td>○</td></tr>
<tr><td>P05.25</td><td>Corresponding</td><td>0.0%</td><td>○</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | setting of AI1 lower limit | setting. When the analog input voltage exceeds the range from the upper limit to the | | |
| P05.26 | AI1 upper limit | lower limit, the upper limit or lower limit is | 10.00V | ○ |
| P05.27 | Corresponding setting of AI1 upper limit | used.<br>When the analog input is current input, 0mA–20mA current corresponds to 0V–10V | 100.0% | ○ |
| P05.28 | AI1 input filter time | voltage. | 0.030s | ○ |
| P05.29 | AI2 lower limit | In different applications, 100.0% of the analog | -10.00V | ○ |
| P05.30 | Corresponding setting of AI2 lower limit | setting corresponds to different nominal values. See the descriptions of each application section for details. | -100.0% | ○ |
| P05.31 | AI2 middle value 1 | The following figure illustrates the cases of | 0.00V | ○ |
| P05.32 | Corresponding setting of AI2 middle value 1 | several settings: | 0.0% | ○ |
| P05.33 | AI2 middle value 2 |  | 0.00V | ○ |
| P05.34 | Corresponding setting of AI2 middle value 2 | | 0.0% | ○ |
| P05.35 | AI2 upper limit | | 10.00V | ○ |
| P05.36 | Corresponding setting of AI2 upper limit | Input filter time: to adjust the sensitivity of | 100.0% | ○ |
| P05.37 | AI2 input filter time | analog input. Increasing the value properly can enhance analog input anti-interference but may reduce the sensitivity of analog input.<br>Note: AI1 supports the 0–10V/0–20mA input. When AI1 selects the 0–20mA input, the corresponding voltage of 20mA is 10V. AI2 supports the -10–+10V input.<br>See section 5.5.9 Analog input for function description.<br>Setting range of P05.24: 0.00V–P05.26<br>Setting range of P05.25: -300.0% –300.0%<br>Setting range of P05.26: P05.24–10.00V<br>Setting range of P05.27: -300.0%–300.0%<br>Setting range of P05.28: 0.000s–10.000s<br>Setting range of P05.29: -10.00V–P05.31<br>Setting range of P05.30: -300.0%–300.0% | 0.030s | ○ |

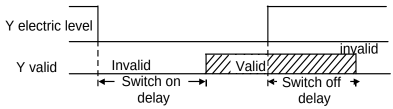
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Setting range of P05.31: P05.29 –P05.33<br>Setting range of P05.32: -300.0% –300.0%<br>Setting range of P05.33: P05.31 –P05.35<br>Setting range of P05.34: -300.0%–300.0%<br>Setting range of P05.35: P05.33–10.00V<br>Setting range of P05.36: -300.0% –300.0%<br>Setting range of P05.37: 0.000s–10.000s | | |
| P05.38 | HDIA high-speed pulse input function selection | 0–2<br>0: Input set through frequency<br>1–2: Reserved | 0 | ◎ |
| P05.39 | HDIA frequency lower limit | 0.000 kHz–P05.41 | 0.000kHz | ○ |
| P05.40 | Corresponding setting of HDIA frequency lower limit | -300.0%–300.0% | 0.0% | ○ |
| P05.41 | HDIA frequency upper limit | P05.39–50.000kHz | 50.000kHz | ○ |
| P05.42 | Corresponding setting of HDIA upper limit frequency | -300.0%–300.0% | 100.0% | ○ |
| P05.43 | HDIA frequency input filter time | 0.000s–10.000s | 0.030s | ○ |
| P05.44 | HDIB high-speed pulse input function selection (reserved) | 0–2<br>0: Input set through frequency<br>1–2: Reserved | 0 | ◎ |
| P05.45 | HDIB frequency lower limit (Reserved) | 0.000kHz–P05.47 | 0.000kHz | ○ |
| P05.46 | Corresponding setting of HDIB frequency lower limit (reserved) | -300.0%–300.0% | 0.0% | ○ |
| P05.47 | HDIB frequency upper limit (reserved) | P05.45–50.000kHz | 50.000 kHz | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P05.48 | Corresponding setting of HDIB upper limit frequency (reserved) | -300.0%–300.0% | 100.0% | ○ |
| P05.49 | HDIB frequency input filter time (reserved) | 0.000–10.000s | 0.030s | ○ |
| P05.50 | AI1 input signal type | 0x00–0x11<br>Ones place: Input signal type<br>0: Voltage<br>1: Current<br>Tens place: Input value unit selection<br>0: All voltage type<br>1: Voltage for voltage-type input, current for current-type input<br>**Note:** After selecting voltage and current inputs for the function code, you also need to install the jumper on the control board in the correct position. | 0 | ◎ |
| P05.51–P05.52 | Reserved | - | - | - |
| P05.53 | Keypad analog lower limit | 0.00V–P05.54 | 0.00V | ○ |
| P05.54 | Corresponding setting of keypad analog lower limit | -300.0%–300.0% | 0.0% | ○ |
| P05.55 | Keypad analog upper limit | P05.56–10.00V | 10.00V | ○ |
| P05.56 | Corresponding setting of keypad analog upper limit | -300.0%–300.0% | 100.0% | ○ |
| P05.57 | Keypad analog input filter time | 0.000s–10.000s | 0.030s | ○ |

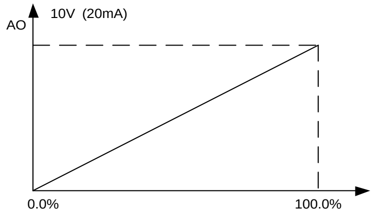
**Group P06—Output terminals**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P06.00 | HDO output type (reserved) | 0–1<br>0: Open collector high-speed pulse output<br>1: Open collector output | 0 | ◎ |
| P06.01 | Y1 output | 0–68<br>0: Invalid<br>1: Running<br>2: Running forward<br>3: Running reversely<br>4: Jogging<br>5: VFD in fault<br>6: Frequency level detection FDT1<br>7: Frequency level detection FDT2<br>8: Frequency reached<br>9: Running in zero speed<br>10: Upper limit frequency reached<br>11: Frequency lower limit reached<br>12: Ready for running<br>13: Pre-exciting<br>14: Overload pre-alarm<br>15: Underload pre-alarm<br>16: Simple PLC stage completed<br>17: Simple PLC cycle completed<br>18: Set counting value reached<br>19: Designated counting value reached<br>20: External fault is valid<br>21: Reserved<br>22: Running time reached<br>23: MODBUS communication virtual terminal output<br>24: PROFIBUS/CANopen/BACnet MSTP communication virtual terminal output<br>25: Ethernet communication virtual terminal output<br>26: DC bus voltage established<br>27–32: Reserved<br>33: In speed limit<br>34: PROFINET/EtherNet IP communication virtual terminal output | 0 | ○ |
| P06.02 | HDO output selection | | 0 | ○ |
| P06.03 | RO1 output selection | | 1 | ○ |
| P06.04 | RO2 output | | 5 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 35: Reserved<br>36: Speed/position control switchover completed<br>37: Any frequency reached<br>38–47: Reserved<br>48: Fire mode activated<br>49: Pre-alarm of PID1 feedback too low<br>50: Pre-alarm of PID1 feedback too high<br>51: PID1 in sleep<br>52: PID2 in startup<br>53: PID2 stopped<br>54: Indication of run with backup pressure<br>55: Water shortage indication of inlet pool<br>56: Pre-alarm output<br>57: Control variable-frequency circulation motor A<br>58: Control variable-frequency circulation motor B<br>59: Control variable-frequency circulation motor C<br>60: Control variable-frequency circulation motor D<br>61: Control variable-frequency circulation motor E<br>62: Control variable-frequency circulation motor F<br>63: Control variable-frequency circulation motor G<br>64: Control variable-frequency circulation motor H<br>65: Low-temperature pre-alarm<br>66: Stalling pre-alarm<br>67: Dry-pumping pre-alarm<br>68: PTC overtemperature pre-alarm | | |
| P06.05 | Output terminal polarity selection | The function code is used to set the polarity of output terminals.<br>When a bit is 0, the output terminal is positive.<br>When a bit is 1, the output terminal is negative. | 0x00 | ○ |

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td><table><tr><td>Bit3</td><td>Bit2</td><td>Bit1</td><td>Bit0</td></tr><tr><td>Reserved</td><td>RO1</td><td>Reserved</td><td>Y1</td></tr></table>Setting range: 0x0 –0xF</td><td></td><td></td></tr>
<tr><td>P06.06</td><td>Y1 switch-on delay</td><td rowspan="8">The function codes specify the delay time corresponding to the electrical level changes when the programmable output terminals switch on or switch off.<br><br><br>Setting range: 0.000–50.000s<br>Note: P06.08 and P06.09 are valid only when P06.00=1.</td><td>0.000s</td><td>○</td></tr>
<tr><td>P06.07</td><td>Y1 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P06.08</td><td>Reserved</td><td>-</td><td>-</td></tr>
<tr><td>P06.09</td><td>Reserved</td><td>-</td><td>-</td></tr>
<tr><td>P06.10</td><td>RO1 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P06.11</td><td>RO1 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P06.12</td><td>Reserved</td><td>-</td><td>-</td></tr>
<tr><td>P06.13</td><td>Reserved</td><td>-</td><td>-</td></tr>
<tr><td>P06.14</td><td>AO1 output</td><td rowspan="3">0: Running frequency<br>1: Set frequency<br>2: Ramp reference frequency<br>3: Rotational speed (10V corresponds to the speed corresponding to the max. output frequency)<br>4: Output current (10V corresponds to twice the VFD rated current)<br>5: Output current (10V corresponds to twice the motor rated current)<br>6: Output voltage (10V corresponds to 1.5 times the inverter unit rated voltage)<br>7: Output power (10V corresponds to twice the motor rated power)<br>8: Set torque (10V corresponds to twice the motor rated torque)<br>9: Output torque (Absolute value, 10V corresponds to twice the motor rated torque)<br>10: AI1 input (0–10V/0–20mA)<br>11: AI2 input (0–10V)<br>12: AI3 input (0–10V/0–20mA)<br>13: HDIA input (0.00–50.00kHz)<br>14: Value 1 set through Modbus communication (0–1000)<br>15: Value 2 set through Modbus communication (0–1000)</td><td>0</td><td>○</td></tr>
<tr><td>P06.15</td><td>AO0 output</td><td>0</td><td>○</td></tr>
<tr><td>P06.16</td><td>HDO high-speed pulse output (reserved)</td><td>0</td><td>○</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 16: Value 1 set through PROFIBUS/CANopen/BACnet MSTP communication (0–1000)<br>17: Value 2 set through PROFIBUS/CANopen communication (0–1000)<br>18: Value 1 set through Ethernet communication (0–1000)<br>19: Value 2 set through Ethernet communication (0–1000)<br>20: HDIB input value<br>21: Value 1 set through PROFINET/EtherNet IP (0–1000)<br>22: Torque current (bipolar, 100% corresponding to 10V)<br>23: Exciting current (100% corresponding to 10V)<br>24: Set frequency (bipolar)<br>25: Ramp reference frequency (bipolar)<br>26: Rotational speed (bipolar)<br>27: Value 2 set through PROFINET communication (0–1000)<br>28: C_AO1 (Reserved)<br>29: C_AO2 (Reserved)<br>30: Rotational speed (10V corresponds to the speed corresponding to twice the motor rated frequency)<br>31: Output torque<br>32: PID1 output<br>33: PID2 output<br>34: PID1 reference value<br>35: PID1 feedback value<br>36: PID2 reference value<br>37: PID2 feedback value<br>38–39: Reserved<br>40: Value 0 set through PROFIBUS/CANopen /BACnet MSTP communication<br>41: Value 0 set through PROFINET/EtherNet IP communication<br>42–47: Reserved | | |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P06.17 | AO1 output lower limit | The function codes define the relationship between the output value and analog output. When the output value exceeds the allowed range, the output uses the lower limit or upper limit.<br>When the analog output is current output, 1mA equals 0.5V.<br>In different cases, the corresponding analog output of 100% of the output value is different.<br><br>Setting range of P06.17: -300.0%–P06.19<br>Setting range of P06.18: 0.00V–10.00V<br>Setting range of P06.19: P06.17–300.0%<br>Setting range of P06.20: 0.00V–10.00V<br>Setting range of P06.21: 0.000s–10.000s | 0.0% | ○ |
| P06.18 | AO1 output corresponding to lower limit | | 0.00V | ○ |
| P06.19 | AO1 output upper limit | | 100.0% | ○ |
| P06.20 | AO1 output corresponding to upper limit | | 10.00V | ○ |
| P06.21 | AO1 output filter time | | 0.000s | ○ |
| P06.22 | AO0 output lower limit | -300.0%–P06.23 | 0.0% | ○ |
| P06.23 | AO0 output corresponding to lower limit | 0.00V–10.00V | 0.00V | ○ |
| P06.24 | AO0 output upper limit | P06.35–300.0% | 100.0% | ○ |
| P06.25 | AO0 output corresponding to upper limit | 0.00V–10.00V | 10.00V | ○ |
| P06.26 | AO0 output filter time | 0.000s–10.000s | 0.000s | ○ |
| P06.27–P06.32 | Reserved | - | - | - |
| P06.33 | Detection value for frequency being reached | 0.00–P00.03 | 1.00Hz | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P06.34 | Frequency reaching detection time | 0.0–3600.0s | 0.5s | ○ |

**Group P07—Human-machine interface**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P07.00 | User password | 0–65535<br>When you set the function code to a non-zero number, password protection is enabled.<br>If you set the function code to 00000, the previous user password is cleared and password protection is disabled.<br>After the user password is set and takes effect, you cannot enter the parameter menu if you enter an incorrect password. Please remember your password and save it in a secure place.<br>After you exit the function code editing interface, the password protection function is enabled within 1 minute. If password protection is enabled, "0.0.0.0.0" is displayed when you press the PRG/ESC key again to enter the function code editing interface. You need to enter the correct user password to enter the interface.<br>**Note:** Restoring the default values may delete the user password. Exercise caution when using this function. | 0 | ○ |
| P07.01 | Parameter copy | Used to set the parameter copy mode.<br>0: No operation<br>1: Parameter upload to keypad<br>2: Download all parameters (including motor parameters)<br>3: Download non-motor parameters<br>4: Download motor parameters<br>**Note:** After any operation among 1–4 is completed, the parameter restores to 0. The | 0 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | upload and download functions are not applicable to group P29. | | |
| P07.02 | Key function selection | Range: 0x00–0x28<br>Ones place: Function of QUICK/JOG<br>0: No function<br>1: Jog<br>2: Reserved<br>3: Switch between forward and reverse rotating<br>4: Clear the UP/DOWN setting<br>5: Coast to stop<br>6: Switch command channels in sequence<br>7: Quick commissioning mode<br>8: Sequential switching of the run command reference modes + frequency switching<br>**Note:** When switching to keypad control, the frequency is determined by the setting of P00.10; in other cases, it is determined by P00.06.<br>Tens place: Reserved | 0x01 | ◎ |
| P07.03 | Sequence of switching running-command channels by pressing QUICK | When P07.02=6, set the sequence of switching running-command channels by pressing this key.<br>0: Keypad→Terminal→Communication<br>1: Keypad←→Terminal<br>2: Keypad←→Communication<br>3: Terminal←→Communication | 0 | ○ |
| P07.04 | Stop function validity of STOP/RST | Used to specify the stop function validity of STOP/RST. For fault reset, STOP/RST is valid in any conditions.<br>0: Valid only for keypad control<br>1: Valid both for keypad and terminal control<br>2: Valid both for keypad and communication control<br>3: Valid for all control modes | 0 | ○ |
| P07.05 | Selection 1 of parameters displayed in running state | 0x0000–0xFFFF<br>Bit 0: Running frequency (HZ on)<br>Bit 1: Set frequency (HZ blinking)<br>Bit2: Bus voltage (V on) | 0x03FF | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Bit3: Output voltage (V on)<br>Bit4: Output current (A on)<br>Bit 5: Running speed (RPM on)<br>Bit6: Output power (% on)<br>Bit7: Output torque (% on)<br>Bit8: PID reference value (% blinking)<br>Bit9: PID feedback value (% on)<br>Bit10: Input terminal status<br>Bit11: Output terminal status<br>Bit12: Set torque (% on)<br>Bit13: Pulse count value<br>Bit14: Motor overload percentage (% on)<br>Bit15: PLC and actual step of multi-step speed | | |
| P07.06 | Selection 2 of parameters displayed in running state | 0x0000–0xFFFF<br>Bit0: AI1 (V on)<br>Bit 1: AI2 (V on)<br>Bit 2: AI3 (V on)<br>Bit 3: High-speed pulse HDIA frequency<br>Bit 4: Reserved<br>Bit5: VFD overload percentage (% on)<br>Bit 6: Ramp frequency reference (HZ on)<br>Bit7: Linear speed<br>Bit 8: AC incoming current<br>Bit 9: Frequency upper limit<br>Bit 10: AI0 (V on)<br>Bit11–Bit15: Reserved | 0x0000 | ○ |
| P07.07 | Selection of parameters displayed in stopped state | 0x0000–0xFFFF<br>Bit0: Set frequency (Hz on, blinking slowly)<br>Bit1: Bus voltage (V on)<br>Bit2: Input terminal state<br>Bit3: Output terminal state<br>Bit4: PID reference value (% blinking)<br>Bit5: PID feedback value (% on)<br>Bit6: Set torque (% on)<br>Bit7: AI1 (V on)<br>Bit 8: AI2 (V on)<br>Bit 9: AI3 (V on) | 0x00FF | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Bit 10: High-speed pulse HDIA frequency<br>Bit 11: High-speed pulse HDIB frequency<br>Bit 12: Counting value<br>Bit 13: PLC and current step number of multi-step speed<br>Bit 14: Frequency upper limit<br>Bit 15: AI0 (V on) | | |
| P07.08 | Frequency display coefficient | 0.01–10.00<br>Display frequency = Running frequency× P07.08 | 1.00 | ○ |
| P07.09 | Rotational speed display coefficient | 0.1–999.9%<br>Mechanical rotation speed = 120× (Displayed running frequency) × P07.09/(Number of motor pole pairs) | 100.0% | ○ |
| P07.10 | Linear speed display coefficient | 0.1–999.9%<br>Linear speed = (Mechanical rotation speed) × P07.10 | 1.0% | ○ |
| P07.11 | Rectifier bridge temperature | -20.0–120.0°C | 0.0°C | ● |
| P07.12 | Inverter module temperature | -20.0–120.0°C | 0.0°C | ● |
| P07.13 | Control board software version | 1.00–655.35 | Version depended | ● |
| P07.14 | Local accumulative running time | 0–65535h | 0h | ● |
| P07.15 | VFD electricity consumption MSB | Used to display the electricity consumption of the VFD.<br>VFD electricity consumption = P07.15 × 1000 + P07.16<br>Setting range of P07.15: 0–65535kWh (×1000)<br>Setting range of P07.16: 0.0–999.9 kWh | 0kWh | ● |
| P07.16 | VFD electricity consumption LSB | | 0.0kWh | ● |
| P07.17 | VFD model | 0x0000–0xFFF1<br>Bit0–bit3: G type or P type<br>0X0: G type<br>0x1: P type<br>Bit4–bit11: Chip type and manufacturer<br>0x00: DSP(TI) | 0x0000 | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 0x01–0x20: Reserved<br>0x21: MCU(ST)<br>0x22–0xFF: Reserved<br>Bit 12–Bit 15: Reserved | | |
| P07.18 | VFD rated power | 0.4–3000.0kW | 0.4kW | ● |
| P07.19 | VFD rated voltage | 50–1200V | 380V | ● |
| P07.20 | VFD rated current | 0.1–6000.0A | 0.1A | ● |
| P07.21 | Factory bar code 1 | 0x0000–0xFFFF | 0xFFFF | ● |
| P07.22 | Factory bar code 2 | 0x0000–0xFFFF | 0xFFFF | ● |
| P07.23 | Factory bar code 3 | 0x0000–0xFFFF | 0xFFFF | ● |
| P07.24 | Factory bar code 4 | 0x0000–0xFFFF | 0xFFFF | ● |
| P07.25 | Factory bar code 5 | 0x0000–0xFFFF | 0xFFFF | ● |
| P07.26 | Factory bar code 6 | 0x0000–0xFFFF | 0xFFFF | ● |
| P07.27 | Present fault type | 0: No fault<br>1: Inverter unit U-phase protection (OUt1)<br>2: Inverter unit V-phase protection (OUt2)<br>3: Inverter unit W-phase protection (OUt3)<br>4: Overcurrent during acceleration (OC1)<br>5: Overcurrent during deceleration (OC2)<br>6: Overcurrent during constant speed running (OC3)<br>7: Overvoltage during acceleration (OV1)<br>8: Overvoltage during deceleration (OV2)<br>9: Overvoltage during constant speed running (OV3)<br>10: Bus undervoltage fault (UV)<br>11: Motor overload (OL1)<br>12: VFD overload (OL2)<br>13: Phase loss on input side (SPI)<br>14: Phase loss on output side (SPO)<br>15: Rectifier module overheat (OH1)<br>16: Inverter module overheat (OH2)<br>17: External fault (EF)<br>18: Modbus/Modbus TCP communication fault (CE)<br>19: Current detection fault (ItE)<br>20: Motor autotuning fault (tE)<br>21: EEPROM operation error (EEP) | 0 | ● |
| P07.28 | Last fault type | | 0 | ● |
| P07.29 | 2nd-last fault type | | 0 | ● |
| P07.30 | 3rd-last fault type | | 0 | ● |
| P07.31 | 4th-last fault type | | 0 | ● |
| P07.32 | 5th-last fault type | | 0 | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 22: PID feedback offline fault (PIDE)<br>23: Braking unit fault (bCE)<br>24: Running time reached (END)<br>25: Electronic overload (OL3)<br>26: Keypad communication error (PCE)<br>27: Parameter upload error (UPE)<br>28: Parameter download error (DNE)<br>29: PROFIBUS communication fault (E-DP)<br>30: Ethernet communication fault (E-NET)<br>31: CANopen communication fault (E-CAN)<br>32: To-ground short-circuit fault 1 (ETH1)<br>33: To-ground short-circuit fault 2 (ETH2)<br>34: Speed deviation fault (dEu)<br>35: Mal-adjustment fault (STo)<br>36: Underload fault (LL)<br>37–39: Reserved<br>40: Safe torque off (STO)<br>41: Exception to safety circuit of channel 1 (STL1)<br>42: Exception to safety circuit of channel 2 (STL2)<br>43: Exception to both channels 1 and 2 (STL3)<br>44–54: Reserved<br>55: Duplicate expansion card type (E-Err)<br>56: Reserved<br>57: PROFINET communication fault (E_PN)<br>58: CAN communication timeout (ESCAN)<br>59: Motor overtemperature fault (OT)<br>60: Failure to identify the card in slot 1 (F1-Er)<br>61: Failure to identify the card in slot 2 (F2-Er)<br>62: Reserved<br>63: Communication timeout of the card in slot 1 (C1-Er)<br>64: Communication timeout of the card in slot 2 (C2-Er)<br>65–66: Reserved<br>67: BACnet MSTP communication timeout | | |

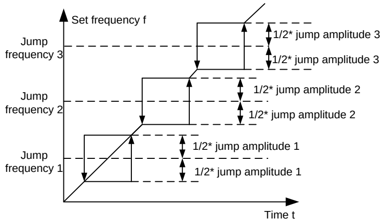
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | fault (E-BAC)<br>68: DeviceNet communication timeout fault (E-DEV)<br>69: CAN slave fault in master/slave synchronization (S-Err)<br>70: EtherNet IP communication timeout fault (E-EIP)<br>71: Braking pipe overcurrent fault (bOC)<br>72:Brake pipe overload (boL)<br>73:Frost fault (FrOSt)<br>74:Stalling fault (Block)<br>75:Dry pumping fault (Dry)<br>76: AI1 disconnection (E-AI1)<br>77: AI2 disconnection (E-AI2)<br>78: AI3 disconnection (E-AI3)<br>77: Water pipe breaking fault (pbd)<br>78: Power underload (E-LLP) | | |
| P07.33 | Running frequency at present fault | 0.00Hz–P00.03 | 0.00Hz | ● |
| P07.34 | Ramp reference frequency at present fault | 0.00Hz–P00.03 | 0.00Hz | ● |
| P07.35 | Output voltage at present fault | 0–1200V | 0V | ● |
| P07.36 | Output current at present fault | 0.0–6300.0A | 0.0A | ● |
| P07.37 | Bus voltage at present fault | 0.0–2000.0V | 0.0V | ● |
| P07.38 | Temperature at present fault | -20.0–120.0°C | 0.0°C | ● |
| P07.39 | Input terminal status at present fault | 0x0000–0xFFFF | 0x0000 | ● |
| P07.40 | Output terminal status at present fault | 0x0000–0xFFFF | 0x0000 | ● |
| P07.41 | Running frequency at last fault | 0.00Hz–P00.03 | 0.00Hz | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P07.42 | Ramp reference frequency at last fault | 0.00Hz–P00.03 | 0.00Hz | ● |
| P07.43 | Output voltage at last fault | 0–1200V | 0V | ● |
| P07.44 | Output current at last fault | 0.0–6300.0A | 0.0A | ● |
| P07.45 | Bus voltage at last fault | 0.0–2000.0V | 0.0V | ● |
| P07.46 | Temperature at last fault | -20.0–120.0°C | 0.0°C | ● |
| P07.47 | Input terminal status at last fault | 0x0000–0xFFFF | 0x0000 | ● |
| P07.48 | Output terminal state at last fault | 0x0000–0xFFFF | 0x0000 | ● |
| P07.49 | Running frequency at 2nd-last fault | 0.00Hz–P00.03 | 0.00Hz | ● |
| P07.50 | Ramp reference frequency at 2nd-last fault | 0.00Hz–P00.03 | 0.00Hz | ● |
| P07.51 | Output voltage at 2nd-last fault | 0–1200V | 0V | ● |
| P07.52 | Output current at 2nd-last fault | 0.0–6300.0A | 0.0A | ● |
| P07.53 | Bus voltage at 2nd-last fault | 0.0–2000.0V | 0.0V | ● |
| P07.54 | Temperature at 2nd-last fault | -20.0–120.0°C | 0.0°C | ● |
| P07.55 | Input terminal status at 2nd-last fault | 0x0000–0xFFFF | 0x0000 | ● |
| P07.56 | Output terminal state at 2nd-last fault | 0x0000–0xFFFF | 0x0000 | ● |

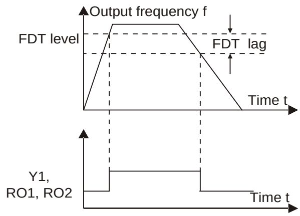
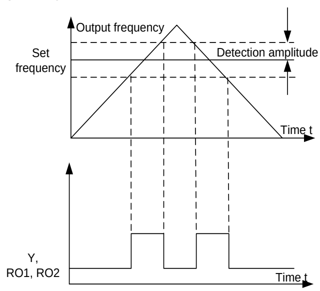
**Group P08—Enhanced functions**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P08.00 | ACC time 2 | For details, see P00.11 and P00.12. | Model | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | The VFD has four groups of ACC/DEC time, which can be selected by P05.<br>The factory default ACC/DEC time of the VFD is the first group.<br>Setting range: 0.0–3600.0s | depended (20.0s) | |
| P08.01 | DEC time 2 | | Model depended (20.0s) | ○ |
| P08.02 | ACC time 3 | | Model depended (20.0s) | ○ |
| P08.03 | DEC time 3 | | Model depended (20.0s) | ○ |
| P08.04 | ACC time 4 | | Model depended (20.0s) | ○ |
| P08.05 | DEC time 4 | | Model depended (20.0s) | ○ |
| P08.06 | Running frequency of jog | The function code is used to define the reference frequency during jogging.<br>Setting range: 0.00Hz–P00.03 (Max. output frequency) | 5.00Hz | ○ |
| P08.07 | ACC time for jogging | ACC time for jogging means the time needed for the VFD to accelerate from 0Hz to the max. output frequency (P00.03).<br>DEC time for jogging means the time needed for the VFD to decelerate from the max. output frequency (P00.03) to 0Hz.<br>Setting range: 0.0–3600.0s | Model depended (20.0s) | ○ |
| P08.08 | DEC time for jogging | | Model depended (20.0s) | ○ |
| P08.09 | Jump frequency 1 | When the set frequency is within the range of jump frequency, the VFD runs at the boundary of jump frequency.<br>The VFD can avoid mechanical resonance points by setting jump frequencies. The VFD supports the setting of three jump frequencies. If the jump frequency points are set to 0, this function is invalid. | 0.00Hz | ○ |
| P08.10 | Jump frequency amplitude 1 | | 0.00Hz | ○ |
| P08.11 | Jump frequency 2 | | 0.00Hz | ○ |
| P08.12 | Jump frequency amplitude 2 | | 0.00Hz | ○ |
| P08.13 | Jump frequency 3 | | 0.00Hz | ○ |
| P08.14 | Jump frequency amplitude 3 | | 0.00Hz | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | <br>Setting range: 0.00Hz–P00.03 (Max. output frequency) | | |
| P08.15 | Wobbling frequency amplitude percentage | 0.0–100.0% (of the set frequency) | 0.0% | ○ |
| P08.16 | Amplitude of sudden jump frequency | 0.0–50.0% (of the amplitude of wobbling frequency) | 0.0% | ○ |
| P08.17 | Rise time of wobbling frequency | 0.1–3600.0s | 5.0s | ○ |
| P08.18 | Fall time of wobbling frequency | 0.1–3600.0s | 5.0s | ○ |
| P08.19 | Switching frequency of ACC/DEC time | 0.00Hz–P00.03 (Max. output frequency)<br>0.00: no switchover.<br>If the running frequency is greater than P08.19, switch to ACC/DEC time 2. | 0.00Hz | ○ |
| P08.20 | Frequency threshold of the start of drop control | 0.00–50.00Hz | 2.00Hz | ○ |
| P08.21 | Reference frequency of ACC/DEC time | 0: Max. output frequency<br>1: Set frequency<br>2: 100Hz<br>Note: Valid only for straight-line ACC/DEC | 0 | ◎ |
| P08.22 | Output torque calculation method | 0: Based on torque current<br>1: Based on output power | 0 | ○ |
| P08.23 | Number of decimal points of frequency | 0: Two<br>1: One | 0 | ○ |
| P08.24 | Number of decimal places of linear | 0: No decimal place<br>1: One | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | speed | 2: Two<br>3: Three | | |
| P08.25 | Set counting value | P08.26–65535 | 0 | ○ |
| P08.26 | Designated counting value | 0–P08.25 | 0 | ○ |
| P08.27 | Set running time | 0–65535min | 0min | ○ |
| P08.28 | Auto fault reset count | Auto fault reset count: When the VFD uses automatic fault reset, it is used to set the number of automatic fault reset times. When the number of continuous reset times exceeds the value, the VFD reports a fault and stops.<br>Auto fault reset interval: Time interval from when a fault occurred to when automatic fault reset takes effect.<br>After VFD starts, If no fault occurred within 600s after the VFD starts, the number of automatic fault reset times is cleared.<br>Setting range of P08.28: 0–10<br>Setting range of P08.29: 0.1–3600.0s | 0 | ○ |
| P08.29 | Auto fault reset interval | | 1.0s | ○ |
| P08.30 | Frequency decrease ratio in drop control | The output frequency of the VFD changes as the load changes. The function code is mainly used to balance the power when several motors drive a same load.<br>Setting range: 0.00–50.00Hz | 0.00Hz | ○ |
| P08.31 | Channel for switching between motor 1 and motor 2 | 0x00–0x14<br>Ones place: Switchover channel<br>0: Terminal<br>1: Modbus/Modbus TCP communication<br>2: PROFIBUS/CANopen /BACnet MSTP communication<br>3: Ethernet communication<br>4: PROFINET/EtherNet IP communication<br>Tens place: indicates whether to enable switchover during running<br>0: Disable<br>1: Enable | 0x00 | ◎ |
| P08.32 | FDT1 electrical | When the output frequency exceeds the | 50.00Hz | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | level detection value | corresponding frequency of FDT electrical level, the multifunction digital output terminal continuously outputs the signal of "Frequency level detection FDT". The signal is invalid only when the output frequency decreases to a value lower than the frequency corresponding to (FDT electrical level—FDT lagging detection value).<br><br>Setting range of P08.32: 0.00Hz–P00.03<br>Setting range of P08.33: 0.0–100.0% (relative to FDT1 electrical level)<br>Setting range of P08.34: 0.00Hz–P00.03<br>Setting range of P08.35: 0.0–100.0% (relative to FDT2 electrical level) | | |
| P08.33 | FDT1 lagging detection value | | 5.0% | ○ |
| P08.34 | FDT2 electrical level detection value | | 50.00Hz | ○ |
| P08.35 | FDT2 lagging detection value | | 5.0% | ○ |
| P08.36 | Detection value for frequency being reached | When the output frequency is within the detection range, the multifunction digital output terminal outputs the signal of "Frequency reached".<br><br>Setting range: 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz | ○ |
| P08.37–P08.38 | Reserved | - | - | - |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P08.39 | Fan operating mode | 0x0000–0x0161<br>Ones place: Run mode<br>0: Normal mode<br>1: Permanent running after power-on<br>Tens place: Set speed<br>0: 100%<br>1: 95%<br>2: 90%<br>3: 85%<br>4: 80%<br>5: 75%<br>6: 70%<br>**Note:** Setting this bit can reduce the fan speed, but it may cause the VFD to overheat. Please set it with caution.<br>Hundreds: Speed control method<br>0:Tens setting of P08.39<br>1: Automatic speed regulation | 0x0100 | ○ |
| P08.40 | PWM selection | 0x0000–0x1121<br>Ones place: PWM mode selection<br>0: PWM mode 1, 3PH modulation and 2PH modulation<br>1: PWM mode 2, 3PH modulation<br>Tens place: PWM carrier frequency limit<br>0: Low-speed carrier frequency limit mode 1<br>1: Low-speed carrier frequency limit mode 2<br>2: No limit on carrier frequency<br>Hundreds place: Deadzone compensation method<br>0: Compensation method 1<br>1: Compensation method 2<br>Thousands place: PWM loading mode selection<br>0: Interruptive loading<br>1: Normal loading<br>For carrier limit mode 1 and carrier limit mode 2 set in the tens place, the output frequency must be below 3.00 Hz. Mode 2 is limited to 4 | 0x1101 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | kHz.<br>In Mode 1 under open-loop vector control, if the output frequency is ≥ 0.40Hz, it is limited to 2kHz, and if < 0.40Hz, it is limited to 1kHz.<br>In Mode 1 under closed-loop vector control for motors over 45kW, if the current exceeds 110%, it is limited to 1kHz; if the current is less than 100%, it is limited to 2kHz. For power ratings between 11kW and 45kW, if the current exceeds 110%, it is limited to 2kHz, and if less than 100%, it is limited to 4kHz.<br>The compensation method for the hundreds place: Method 1 is rectangular compensation, and Method 2 is trapezoidal compensation. | | |
| P08.41 | Overmodulation selection | 0x0000–0x1111<br>Ones place:<br>0: Disable<br>1: Enable<br>Tens place:<br>0: Mild overmodulation<br>1: Deepened overmodulation<br>Hundreds place: Carrier frequency limit<br>0:Yes<br>1:No<br>Thousands place: Output voltage compensation<br>0: No<br>1: Yes | 0x1000 | ◎ |
| P08.42 | Keypad digital control setting | 0x0000–0x1223<br>Ones place:<br>0: Both the ∧/∨ key and digital potentiometer can be used for the control.<br>1: Only the ∧/∨ key can be used for the control.<br>2: Only the digital potentiometer can be used for the control.<br>3: Both the ∧/∨ key and digital potentiometer can be used for the control. | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Tens place: Frequency control selection<br>0: Valid only when P00.06=0 or P00.07=0<br>1: Valid for all frequency setting methods<br>2: Invalid for multi-step speed running when multi-step speed running has the priority<br>Hundreds place: Action selection for stop<br>0: Setting is valid.<br>1: Valid during running, cleared after stop<br>2: Valid during running, cleared after a stop command is received<br>Thousands place: Integral function of the ∧/∨ key and digital potentiometer<br>0: Disable the integral function<br>1: Enable the integral function | | |
| P08.43 | Keypad digital potentiometer integral rate | 0.01–10.00s | 0.10s | ○ |
| P08.44 | UP/DOWN terminal control setting | 0x000–0x221<br>Ones place: Frequency setting selection<br>0: The setting made through UP/DOWN is valid.<br>1: The setting made through UP/DOWN is invalid.<br>Tens place: Frequency control selection<br>0: Valid only when P00.06=0 or P00.07=0<br>1: Valid for all frequency setting methods<br>2: Invalid for multi-step speed running when multi-step speed running has the priority<br>Hundreds place: Action selection for stop<br>0: Setting is valid.<br>1: Valid during running, cleared after stop<br>2: Valid during running, cleared after a stop command is received | 0x000 | ○ |
| P08.45 | Frequency increment integral rate of the UP terminal | 0.01–50.00Hz/s<br>**Note:** The value is also used as the frequency increment or decrement that is made by pressing the UP/DOWN key on the LCD keypad. | 0.50Hz/s | ○ |
| P08.46 | Frequency integral | 0.01–50.00Hz/s | 0.50Hz/s | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | rate of the DOWN terminal | | | |
| P08.47 | Action selection at power-off during frequency setting | 0x0000–0x1111<br>Ones place: Action selection at power-off during frequency adjusting through digitals.<br>0: Save the setting at power-off.<br>1: Clear the setting at power-off.<br>Action selection at power-off during frequency adjusting through Modbus communication<br>0: Save the setting at power-off.<br>1: Clear the setting at power-off.<br>Hundreds place: Action selection at power-off during frequency adjusting through DP communication methods<br>0: Save the setting at power-off.<br>1: Clear the setting at power-off.<br>Thousands place: Frequency selection for superimposing when switching between A and B sources<br>0: Enable<br>1: Disable | 0x0000 | ○ |
| P08.48 | Initial electricity consumption high bit | Used to set the initial electricity consumption.<br>Initial electricity consumption = P08.48*1000 + P08.49<br>Setting range of P08.48: 0–59999kWh (k)<br>Setting range of P08.49: 0.0–999.9 kWh | 0kWh | ○ |
| P08.49 | Initial electricity consumption low bit | | 0.0kWh | ○ |
| P08.50 | Magnetic flux braking | 0–150 (Used to enable magnetic flux braking.)<br>0: Invalid<br>100–150: A larger coefficient indicates stronger braking.<br>The VFD can quickly slow down the motor by increasing the magnetic flux. The energy generated by the motor during braking can be transformed into heat energy by increasing the magnetic flux.<br>The VFD monitors the state of the motor continuously even during the magnetic flux period. Magnetic flux braking can be used for | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | motor stop, as well as for motor rotation speed change. The other advantages include: Braking is performed immediately after the stop command is given. The braking can be started without waiting for magnetic flux weakening.<br>The cooling is better. The current of the stator other than the rotor increases during magnetic flux braking, while the cooling of the stator is more effective than the rotor. | | |
| P08.51 | VFD input power factor | This function code is used to adjust the current display value on the AC input side.<br>0.00–1.00 | 0.56 | ○ |
| P08.52 | STO lock selection | 0–1<br>0: Lock upon STO alarm<br>1: No lock on STO alarm<br>**Note:** "Lock upon STO alarm" indicates resetting is required after state restoration if STO alarm occurs. "No lock on STO alarm" indicates STO alarm disappears automatically after state restoration. | 0 | ○ |
| P08.53 | Upper limit frequency bias value in torque control | 0.00Hz–P00.03 (Max. output frequency)<br>**Note:** Valid only for torque control. | 0.00Hz | ○ |
| P08.54 | Upper limit frequency ACC/DEC selection in torque control | 0: No limit on acceleration or deceleration<br>1: ACC/DEC time 1<br>2: ACC/DEC time 2<br>3: ACC/DEC time 3<br>4: ACC/DEC time 4 | 0 | ○ |
| P08.55 | Enabling auto carrier frequency reduction | 0: Disable<br>1: Enable<br>**Note:** Automatic carrier frequency reduction indicates that the VFD automatically reduces the carrier frequency when detecting the heat sink temperature exceeds the rated temperature. When the temperature decreases to a certain degree, the carrier frequency recovers. This function reduces the chance of VFD overheat alarm. | 1 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P08.56 | Temperature point of auto carrier frequency reduction | 40.0–85.0°C | 65.0°C | ○ |
| P08.57 | Interval of carrier frequency reduction | 0–30Min (Setting it to 0 means carrier frequency reduction is invalid.) | 10 | ○ |
| P08.58 | Output phase loss detection delay | 0.0–360.0s<br>**Note:** When the run time exceeds the delay, the VFD detects for output phase loss. | 5.0s | ○ |
| P08.59 | AI1 disconnection detection threshold | 0–100% (relative to 10V) | 0% | ○ |
| P08.60 | AI2 disconnection detection threshold | 0–100% (relative to 10V) | 0% | ○ |
| P08.61 | AI3 disconnection detection threshold | 0–100% (relative to 10V) | 0% | ○ |
| P08.62 | Grid voltage and frequency selection | 0x00–0x21<br>Ones place: Frequency selection<br>0: 50Hz<br>1: 60HzTens place: Voltage selection<br>0: Indicates the 220V range, suitable for a voltage range of 208–240.<br>1: Indicates the 380V range, suitable for a voltage range of 380–415.<br>2: Indicates the 460V range, suitable for a voltage range of 440–480.<br>When the VFD model is -2, the tens place of P08.62 automatically becomes 0. If changed to 1 or 2, it will not take effect.<br>When the VFD model is -4, the tens place of P08.62 defaults to 1. If changed to 0, it will not take effect. | 0x10 | ◎ |

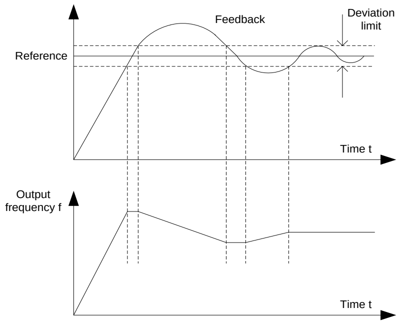
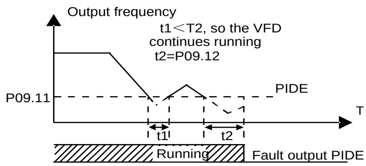
**Group P09— PID control**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P09.00 | PID reference source | When P00.06 or P00.07 (Setting channel of A/B frequency command) is 7 or P04.27 | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | (Voltage setting channel) is 6, the VFD is process PID controlled.<br>The function code determines the target given channel during the PID process.<br>0–18<br>0: Keypad (P09.01)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: High-speed pulse HDIA<br>5: Multi-step running<br>6: Modbus/Modbus TCP communication<br>7: PROFIBUS/CANopen /BACnet MSTP communication<br>8: Ethernet communication<br>9: High-speed pulse HDIB<br>10: PROFINET/EtherNet IP communication<br>11: Programmable card<br>12–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>The set target of process PID is a relative value, for which 100% equals 100% of the feedback signal of the controlled system.<br>The system always performs calculation by using a relative value (0.0–100.0%). | | |
| P09.01 | PID digital setting | The function code is mandatory when P09.00=0. The base value of The function code is the feedback of the system.<br>Setting range: -100.0%–100.0% | 0.0% | ○ |
| P09.02 | PID feedback source | The function code is used to select the PID feedback channel.<br>0–18<br>0: AI1<br>1: AI2<br>2: AI3<br>3: High-speed pulse HDIA<br>4: Modbus/Modbus TCP communication | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 5: PROFIBUS/CANopen /BACnet MSTP communication<br>6: Ethernet communication<br>7: High-speed pulse HDIB<br>8: PROFINET/EtherNet IP communication<br>9: Programmable card<br>10–17: Reserved<br>18: Keypad analog (valid for 1.5–22kW models)<br>**Note:** The reference channel and feedback channel cannot be duplicated. Otherwise, effective PID control cannot be achieved. | | |
| P09.03 | PID output characteristics selection | 0: PID output is positive.<br>When the feedback signal is greater than the PID reference value, the output frequency of the VFD will decrease to balance the PID.<br>Example: PID control on tension during winding.<br>1: PID output is negative.<br>When the feedback signal is greater than the PID reference value, the output frequency of the VFD will increase to balance the PID.<br>Example: PID control on tension during unwinding | 0 | ○ |
| P09.04 | Proportional gain (Kp) | The function is applied to the proportional gain P of PID input.<br>P determines the strength of the whole PID adjuster. The value 100 indicates that when the difference between the PID feedback value and given value is 100%, the range within which the PID regulator can regulate the output frequency command is the max. frequency (ignoring integral function and differential function).<br>Setting range: 0.00–100.00 | 1.80 | ○ |
| P09.05 | Integral time (Ti) | Used to determine the speed of the integral adjustment on the deviation of PID feedback and reference from the PID regulator. | 0.90s | ○ |

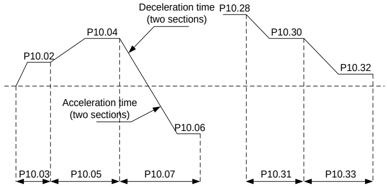
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | When the deviation of PID feedback and reference is 100%, the integral adjuster works continuously during the time (ignoring proportional and differential function) to achieve the max. output frequency (P00.03) or the max. voltage (P04.31). Shorter integral time indicates stronger adjustment.<br>Setting range: 0.00–10.00s | | |
| P09.06 | Differential time (Td) | Used to determine the strength of the change ratio adjustment on the deviation of PID feedback and reference from the PID regulator.<br>If the PID feedback changes 100% during the time, the adjustment of the differential regulator (ignoring proportional and integral function) is the max. output frequency (P00.03) or the max. voltage (P04.31). Longer differential time indicates stronger adjustment.<br>Setting range: 0.00–10.00s | 0.00s | ○ |
| P09.07 | Sampling cycle (T) | Used to indicate the sampling cycle of feedback. The regulator calculates in each sampling cycle. A longer sampling cycle indicates slower response.<br>Setting range: 0.001–10.000s | 0.001s | ○ |
| P09.08 | PID control deviation limit | The output of the PID system is relative to the max. deviation of the closed loop reference. As shown in the following figure, the PID regulator stops regulating in the range of deviation limit. Set the function parameter properly to adjust the accuracy and stability of the PID system. | 0.0% | ○ |

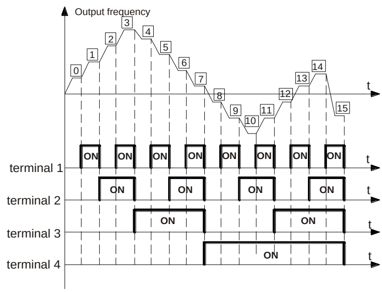
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | <br>Setting range: 0.0–100.0% | | |
| P09.09 | PID output upper limit | The function codes are used to set the upper and lower limits of PID regulator output values.<br>100.0% corresponds to the max. output frequency (P00.03) or max. voltage (P04.31).<br>Setting range of P09.09: P09.10–100.0%<br>Setting range of P09.10: 0.00Hz–P09.09 | 100.0% | ○ |
| P09.10 | PID output lower limit | | 0.0% | ○ |
| P09.11 | Feedback offline detection value | The function code is used to set the PID feedback offline detection value. When the feedback value is smaller than or equal to the feedback offline detection value, and the duration exceeds the value specified by P09.12, the VFD reports "PID feedback offline fault" and the keypad displays PIDE.<br><br>Setting range of P09.11: 0.0–100.0%<br>Setting range of P09.12: 0.0–3600.0s | 0.0% | ○ |
| P09.12 | Feedback offline detection time | | 1.0s | ○ |
| P09.13 | PID control selection | 0x0000–0x1111<br>Ones place:<br>0: Continue integral control after the frequency reaches upper/lower limit | 0x0001 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 1: Stop integral control after the frequency reaches upper/lower limit<br>Tens place:<br>0: Same as the main reference direction<br>1: Contrary to the main reference direction<br>Hundreds place:<br>0: Limit as per the max. frequency<br>1: Limit as per A frequency<br>Thousands place:<br>0: A+B frequency. Acceleration /deceleration of main reference A frequency source buffering is invalid.<br>1: A+B frequency. Acceleration /deceleration of main reference A frequency source buffering is valid.<br>**Note:** The ACC/DEC time is determined by P08.04. | | |
| P09.14 | Low frequency proportional gain (Kp) | 0.00–100.00<br>Low-frequency switching point: 5.00Hz, high-frequency switching point: 10.00Hz (P09.04 corresponds to high-frequency parameter), and the middle is the linear interpolation between these two points. | 1.00 | ○ |
| P09.15 | ACC/DEC time of PID command | 0.0–1000.0s | 0.0s | ○ |
| P09.16 | PID output filter time | 0.000–10.000s | 0.000s | ○ |
| P09.17 | Reserved | - | - | - |
| P09.18 | Low frequency integral time (Ti) | 0.00–10.00s | 0.90s | ○ |
| P09.19 | Low frequency differential time (Td) | 0.00–10.00s | 0.00s | ○ |
| P09.20 | Low frequency point for PID parameter switching | 0.00–P09.21 | 5.00Hz | ○ |
| P09.21 | High frequency point for PID parameter switching | P09.20–P00.04 | 10.00Hz | ○ |

**Group P10—Simple PLC and multi-step speed control**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P10.00 | Simple PLC mode | 0: Stop after running once<br>The VFD stops automatically after running for one cycle, and it can be started only after receiving the running command.<br>1: Keep running with the final value after running once<br>The VFD keeps the running frequency and direction of the last section after a single cycle.<br>2: Cyclic running<br>The VFD enters the next cycle after completing one cycle until receiving the stop command. | 0 | ○ |
| P10.01 | Simple PLC memory selection | 0: Do not memorize at power outage<br>1: Memory at power-off. The PLC memories its running stage and running frequency before power-off. | 0 | ○ |
| P10.02 | Multi-step speed 0 | Frequency setting range for steps from step 0 to step 15: -300.0% –300.0%. 300.0% corresponds to the max. output frequency P00.03.<br>Running time setting range for steps from step 0 to step 15: 0.0–6553.5s(min). The time unit is specified by P10.37 (s: P10.37=0, min: P10.37=1).<br>When simple PLC operation is selected, it is required to set P10.02–P10.33 to determine the running frequency and running time of each step.<br>**Note:** The symbol of multi-step speed determines the running direction of simple PLC, and the negative value means reverse running. | 0.0% | ○ |
| P10.03 | Running time of step 0 | | 0.0s (min) | ○ |
| P10.04 | Multi-step speed 1 | | 0.0% | ○ |
| P10.05 | Running time of step 1 | | 0.0s (min) | ○ |
| P10.06 | Multi-step speed 2 | | 0.0% | ○ |
| P10.07 | Running time of step 2 | | 0.0s (min) | ○ |
| P10.08 | Multi-step speed 3 | | 0.0% | ○ |
| P10.09 | Running time of step 3 | | 0.0s (min) | ○ |
| P10.10 | Multi-step speed 4 | | 0.0% | ○ |
| P10.11 | Running time of step 4 | | 0.0s (min) | ○ |
| P10.12 | Multi-step speed 5 | | 0.0% | ○ |
| P10.13 | Running time of step 5 | | 0.0s (min) | ○ |
| P10.14 | Multi-step speed 6 | | 0.0% | ○ |

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td>P10.15</td><td>Running time of step 6</td><td rowspan="19">

When selecting multi-step speed running, the multi-step speed is within the range of -fmax–fmax, and it can be set continuously.<br>The start-up and stop of multi-step speed is determined by the function code P00.01.<br>The VFD supports the setting of 16-step speed, which are set by combined codes of multi-step terminals 1–4 set by S terminals, corresponding to function code P05.01–P05.06) and correspond to multi-step speed 0 to multi-step speed 15.<br>

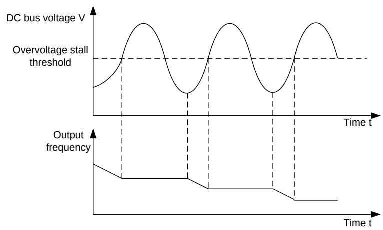
When terminal 1, terminal 2, terminal 3, and terminal 4 are off, the frequency input method is specified by P00.06 or P00.07. When terminal 1, terminal 2, terminal 3 and terminal 4 are not all OFF, the frequency set by multi-step speed will prevail, and the priority of multi-step setting is higher than that of the keypad, analog, high-speed pulse, PID, and communication settings.<br>The relation between terminal 1, terminal 2, terminal 3 and terminal 4 are shown in the following:<br><table><tr><td>Terminal 1</td><td>OFF</td><td>ON</td><td>OFF</td><td>ON</td><td>OFF</td><td>ON</td><td>OFF</td><td>ON</td></tr></table></td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.16</td><td>Multi-step speed 7</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.17</td><td>Running time of step 7</td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.18</td><td>Multi-step speed 8</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.19</td><td>Running time of step 8</td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.20</td><td>Multi-step speed 9</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.21</td><td>Running time of step 9</td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.22</td><td>Multi-step speed 10</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.23</td><td>Running time of step 10</td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.24</td><td>Multi-step speed 11</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.25</td><td>Running time of step 11</td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.26</td><td>Multi-step speed 12</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.27</td><td>Running time of step 12</td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.28</td><td>Multi-step speed 13</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.29</td><td>Running time of step 13</td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.30</td><td>Multi-step speed 14</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.31</td><td>Running time of step 14</td><td>0.0s (min)</td><td>○</td></tr>
<tr><td>P10.32</td><td>Multi-step speed 15</td><td>0.0%</td><td>○</td></tr>
<tr><td>P10.33</td><td>Running time of step 15</td><td>0.0s (min)</td><td>○</td></tr>
</table>

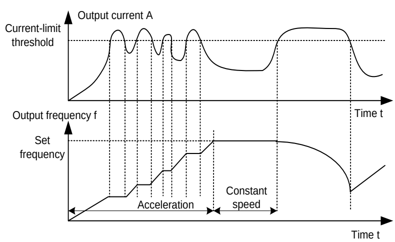
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>
<table>
<tr><td>Terminal 2</td><td>OFF</td><td>OFF</td><td>ON</td><td>ON</td><td>OFF</td><td>OFF</td><td>ON</td><td>ON</td></tr>
<tr><td>Terminal 3</td><td>OFF</td><td>OFF</td><td>OFF</td><td>OFF</td><td>ON</td><td>ON</td><td>ON</td><td>ON</td></tr>
<tr><td>Terminal 4</td><td>OFF</td><td>OFF</td><td>OFF</td><td>OFF</td><td>OFF</td><td>OFF</td><td>OFF</td><td>OFF</td></tr>
<tr><td>Step</td><td>0</td><td>1</td><td>2</td><td>3</td><td>4</td><td>5</td><td>6</td><td>7</td></tr>
<tr><td>Terminal 1</td><td>OFF</td><td>ON</td><td>OFF</td><td>ON</td><td>OFF</td><td>ON</td><td>OFF</td><td>ON</td></tr>
<tr><td>Terminal 2</td><td>OFF</td><td>OFF</td><td>ON</td><td>ON</td><td>OFF</td><td>OFF</td><td>ON</td><td>ON</td></tr>
<tr><td>Terminal 3</td><td>OFF</td><td>OFF</td><td>OFF</td><td>OFF</td><td>ON</td><td>ON</td><td>ON</td><td>ON</td></tr>
<tr><td>Terminal 4</td><td>ON</td><td>ON</td><td>ON</td><td>ON</td><td>ON</td><td>ON</td><td>ON</td><td>ON</td></tr>
<tr><td>Step</td><td>8</td><td>9</td><td>10</td><td>11</td><td>12</td><td>13</td><td>14</td><td>15</td></tr>
</table>
</td><td></td><td></td></tr>
<tr><td>P10.34</td><td>ACC/DEC time for steps 0–7</td><td>0x0000–0xFFFF. See the following table for details:</td><td>0x0000</td><td>○</td></tr>
<tr><td>P10.35</td><td>ACC/DEC time for steps 8–15</td><td>
<table>
<tr><th>Function code</th><th colspan="2">Binary</th><th>Step</th><th>ACC/ DEC time 1</th><th>ACC/ DEC time 2</th><th>ACC/ DEC time 3</th><th>ACC/ DEC time 4</th></tr>
<tr><td rowspan="8">P10.34</td><td>Bit1</td><td>Bit0</td><td>0</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit3</td><td>Bit2</td><td>1</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit5</td><td>Bit4</td><td>2</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit7</td><td>Bit6</td><td>3</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit9</td><td>Bit8</td><td>4</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit11</td><td>Bit10</td><td>5</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit13</td><td>Bit12</td><td>6</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit15</td><td>Bit14</td><td>7</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td rowspan="8">P10.35</td><td>Bit1</td><td>Bit0</td><td>8</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit3</td><td>Bit2</td><td>9</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit5</td><td>Bit4</td><td>10</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit7</td><td>Bit6</td><td>11</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit9</td><td>Bit8</td><td>12</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit11</td><td>Bit10</td><td>13</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit13</td><td>Bit12</td><td>14</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
<tr><td>Bit15</td><td>Bit14</td><td>15</td><td>00</td><td>01</td><td>10</td><td>11</td></tr>
</table>
Select corresponding acceleration/deceleration time, and then convert 16-bit binary number into hexadecimal number, finally, and then set corresponding function codes.<br>ACC/DEC time 1 is set by P00.11 and P00.12;<br>ACC/DEC time 2 is set by P08.00 and P08.01;<br>ACC/DEC time 3 is set by P08.02 and P08.03;<br>ACC/DEC time 4 is set by P08.04 and</td><td>0x0000</td><td>○</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | P08.05.<br>Setting range: 0x0000–0xFFFF | | |
| P10.36 | PLC restart mode | 0: Restart from multi-step speed 0.<br>Restart from the first step, namely if the VFD stops during running (caused by stop command, fault or power down), it will run from the first step after restart.<br>1: Resume from the paused step.<br>If the VFD stops during running (caused by stop command or fault), it records the running time of current step. It enters this step automatically after restart, and then continues running at the frequency defined by this step in the remaining time. | 0 | ◎ |
| P10.37 | Multi-step time unit | 0: second; the running time of each step is counted in seconds<br>1: minute; the running time of each step is counted in minutes | 0 | ◎ |
| P10.38 | Multi-step speed ACC/DEC time selection | 0–1<br>0:P00.11 and P00.12<br>1:According to P10.34 and P10.35 | 0 | ◎ |

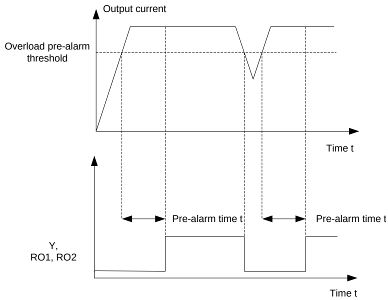
**Group P11—Protection parameters**

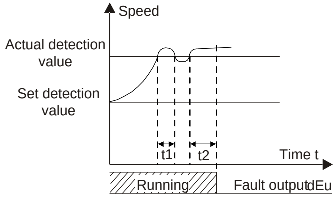
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P11.00 | Protection against phase loss | 0x000–0x111<br>Ones place:<br>0: Disable software input phase loss protection.<br>1: Enable software input phase loss protection.<br>Tens place:<br>0: Output phase loss protection disabled<br>1: Protection against output phrase loss enabled<br>Hundreds place: Reserved | 0x011 | ○ |
| P11.01 | Frequency drop at transient power-off | 0: Disable<br>1: Enable<br>If the bus voltage drops to the sudden | 0 | ○ |

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>frequency decreasing point due to power failure, the VFD decreases the running frequency by using the constant bus voltage control method, which makes the motor in power generation state. The regenerative power can maintain the bus voltage to ensure normal running of the VFD until the recovery of power.<br><table><tr><th>Voltage class</th><td>220V</td><td>380V</td><td>660V</td></tr><tr><th>Frequency decrease at sudden power failure</th><td>260V</td><td>460V</td><td>800V</td></tr></table><br>Note:<br>✧ This function can avoid VFD stop that is made for the purpose of protection in grid switchover.<br>✧ This function can be enabled only when the input phase loss protection function is disabled.</td><td></td><td></td></tr>
<tr><td>P11.02</td><td>Reserved</td><td>-</td><td>-</td><td>-</td></tr>
<tr><td>P11.03</td><td>Overvoltage stall protection</td><td>0: Disable<br>1: Enable<br><br><br>If the bus voltage exceeds the overvoltage stalling point, the motor is in power generation state, and the overvoltage stalling protection function takes effect to regulate output frequency (that is, consume unnecessary regenerative electricity).</td><td>1</td><td>○</td></tr>
<tr><td rowspan="2">P11.04</td><td rowspan="2">Overvoltage stalling protection voltage</td><td>380V: 120–150% (relative to standard bus voltage)</td><td>136%</td><td rowspan="2">○</td></tr>
<tr><td>220V: 120–150% (relative to standard bus</td><td>120%</td></tr>
</table>

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>voltage)</td><td></td><td></td></tr>
<tr><td>P11.05</td><td>Current limit mode</td><td>During accelerated running, as the load is too large, the actual acceleration rate of motor is lower than that of output frequency, if no measures are taken, the VFD may trip due to overcurrent during acceleration.<br>0x00–0x11<br>Ones place: Current limit action<br>0: Invalid<br>1: Always valid<br>Tens place: Hardware current limit overload alarm<br>0: Valid<br>1: Invalid</td><td>0x01</td><td>◎</td></tr>
<tr><td>P11.06</td><td>Automatic current limit threshold</td><td rowspan="2">The current-limit protection function detects output current during running, and compares it with the current-limit level specified by P11.06. If it exceeds the current-limit level, the VFD will run at stable frequency during accelerated running, or the VFD will run at decreased frequency during constant-speed running; if it exceeds the current-limit level continuously, the VFD output frequency will drop continuously until reaching the lower limit frequency. When the output current is detected to be lower than the current-limit level again, it will continue accelerated running.<br><br><br>Setting range of P11.06: 50.0–200.0%<br>(default value for G-type machine: 160.0%,</td><td>Model depended</td><td>◎</td></tr>
<tr><td>P11.07</td><td>Frequency drop rate during current limit</td><td>10.00 Hz/s</td><td>◎</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | default value for P-type machine: 120.0%)<br>Setting range of P11.07: 0.00–50.00Hz/s | | |
| P11.08 | VFD/motor OL/UL alarm selection | 0x000–0x1134<br>Ones place:<br>0:Motor OL/UL pre-alarm. The overload is relative to the motor's rated current, while the underload is also relative to the motor's rated current.<br>1:VFD OL/UL pre-alarm. The overload is relative to the VFD's rated current, while the underload is relative to the motor's rated current.<br>2:Motor output torque OL/UL pre-alarm. relative to the motor rated current. The overload is relative to the motor's rated torque, while the underload is relative to the motor's rated torque.<br>3: Motor OL/UL pre-alarm. The overload is relative to the motor rated current; while the underload is relative to the motor rated power.<br>4: VFD OL/UL pre-alarm. The overload is relative to the VFD rated current; while the underload is relative to the VFD rated power.<br>Tens place:<br>0: The VFD continues to work for an OL/UL alarm.<br>1: The VFD continues to work for a UL alarm but stops running for an OL fault<br>2: The VFD continues to work for an OL alarm but stops running for a UL fault<br>3. The VFD stops running for an OL/UL alarm<br>Hundreds place:<br>0: Detect all the time.<br>1: Detect during constant speed running.<br>Thousands place: VFD overload current reference selection<br>0: Related to current calibration coefficient | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 1: Irrelated to current calibration coefficient | | |
| P11.09 | Overload pre-alarm detection threshold | If the VFD or motor output current is larger than the overload pre-alarm detection level (P11.09), and the duration exceeds the overload pre-alarm detection time (P11.10), overload pre-alarm signal will be outputted. | Model depended | ○ |
| P11.10 | Overload pre-alarm detection time | <br>Setting range of P11.09: P11.11–200.0% (default value for G-type machine: 150%, default value for P-type machine: 120%)<br>P11.10 setting range: 0.1–3600.0s | 1.0s | ○ |
| P11.11 | Underload pre-alarm detection threshold | Underload pre-alarm signal will be outputted if the output current of the VFD or motor is lower than underload pre-alarm detection level (P11.11), and the duration exceeds underload pre-alarm detection time (P11.12).<br>Setting range of P11.11: 0%–P11.09<br>Setting range of P11.12: 0.1–3600.0s | 50% | ○ |
| P11.12 | Underload pre-alarm detection time | | 1.0s | ○ |
| P11.13 | Fault output terminal action upon fault occurring | Used to set the action of fault output terminals at undervoltage and fault reset.<br>0x00–0x11<br>Ones place:<br>0: Act at undervoltage<br>1: Do not act at undervoltage<br>Tens place:<br>0: Act during automatic reset period<br>1: Do not act during the automatic reset period | 0x00 | ○ |
| P11.14 | Speed deviation | 0.0–50.0% | 10.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | detection value | Used to set the speed deviation detection value. | | |
| P11.15 | Speed deviation detection time | 0.0–10.0s<br>**Note:** Speed deviation protection is invalid when P11.15=0.0.<br><br><br>t1<t2, so the VFD continues running<br>t2=P11.15 | 2.0s | ○ |
| P11.16 | Automatic frequency-reduction during voltage drop | 0–1<br>0: Invalid<br>1: Valid | 0 | ○ |
| P11.17 | Proportional coefficient of voltage regulator during undervoltage stall | This parameter is used to set the proportional coefficient of the bus voltage regulator during undervoltage stall.<br>Setting range: 0–1000 | 100 | ○ |
| P11.18 | Integral coefficient of voltage regulator during undervoltage stall | This parameter is used to set the integral coefficient of the bus voltage regulator during undervoltage stall.<br>Setting range: 0–1000 | 40 | ○ |
| P11.19 | Proportional coefficient of current regulator during undervoltage stall | This parameter is used to set the proportional coefficient of the active current regulator during undervoltage stall.<br>Setting range: 0–1000 | 25 | ○ |
| P11.20 | Integral coefficient of current regulator during undervoltage stall | This parameter is used to set the integral coefficient of the active current regulator during undervoltage stall.<br>Setting range: 0–2000 | 150 | ○ |
| P11.21 | Proportional coefficient of voltage regulator during overvoltage | This parameter is used to set the proportional coefficient of the bus voltage regulator during overvoltage stall.<br>Setting range: 0–1000 | 60 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | stall | | | |
| P11.22 | Integral coefficient of voltage regulator during overvoltage stall | This parameter is used to set the integral coefficient of the bus voltage regulator during overvoltage stall.<br>Setting range: 0–1000 | 10 | ○ |
| P11.23 | Proportional coefficient of current regulator during overvoltage stall | This parameter is used to set the proportional coefficient of the active current regulator during overvoltage stall.<br>Setting range: 0–1000 | 60 | ○ |
| P11.24 | Integral coefficient of current regulator during overvoltage stall | This parameter is used to set the integral coefficient of the active current regulator during overvoltage stall.<br>Setting range: 0–2000 | 250 | ○ |
| P11.25 | Enabling VFD overload integral | 0: Disable<br>1: Enable<br>When this parameter is set to 0, the overload timing value is reset to zero after the VFD is stopped. In this case, the determination of VFD overload takes more time, and therefore the effective protection over the VFD is weakened. When this parameter is set to 1, the overload timing value is not reset, and the overload timing value is accumulative. In this case, the determination of VFD overload takes less time, and therefore the protection over the VFD can be performed more quickly. | 1 | ◎ |
| P11.26 | Reserved | - | - | - |
| P11.27 | VF oscillation control method | 0x00–0x11<br>Ones place:<br>0: Method 1<br>1: Method 2<br>Tens place: Reserved | 0x11 | ◎ |
| P11.28 | Software input phase loss detection method | 0–1<br>0: Sine-wave detection<br>1: Square-wave detection<br>**Note:** Since phase loss detection is implemented through software, output phase loss cannot be detected when the VFD is running without a motor, and input phase loss | 1 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | cannot be detected during no-load or light-load operation. Input phase loss can only be detected normally when the load current is above 60% of the rated current. | | |
| P11.29 | Software input phase loss detection limit value | 0–200.0V<br>**Note:** Larger values are less likely to report a fault. | 40.0V | ○ |
| P11.30 | Software input phase loss detection time | 0–20.0s<br>**Note:** Larger values are less likely to report a fault. | 2.0s | ○ |
| P11.31 | Fault severity group 1 | 0x0000–0x3313<br>Ones place (fault 11=OL1):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Tens place (fault 12=OL2):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>Hundreds place (fault 13=SPI):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place (fault 14=SPO):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>**Note:** Different fault actions are taken for different fault severities. The first 10 faults are not grouped by severity, but each four of the subsequent faults are grouped by severity in ascending order from right to left in hexadecimal format. | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Group 1: Fault 11–14<br>Group 2: Fault 15–18<br>Group 3: Fault 19–22<br>Group 4: Fault 23–26<br>Group 5: Fault 27–30<br>Group 6: Fault 31–34<br>Group 7: Fault 35–38<br>Group 8: Fault 39–42<br>Group 9: Fault 43–46<br>Group 10: Fault 47–50<br>Group 11: Fault 51–54<br>Group 12: Fault 55–58<br>Group 13: Fault 59–62<br>Group 14: Fault 63–66<br>Group 15: Fault 67–70<br>Group 16: Fault 71–75<br>Group 17: Fault 75–78<br>Group 18: Fault 79–82<br>Group 19: Fault 83–86<br>Group 20: Fault 87–90 | | |
| P11.32 | Fault severity group 2 | 0x0000–0x3300<br>Ones place(fault 15=OH1):<br>0: Report a fault<br>Tens place(fault 16=OH2):<br>0: Report a fault<br>Hundreds place(fault 17=EF):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place(fault 18=CE):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | 0x0000 | ○ |
| P11.33 | Fault severity group | 0x0000–0x3000 | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | 3 | Ones place (fault 19=ItE):<br>0: Report a fault<br>Tens place (fault 20=tE):<br>0: Report a fault<br>Hundreds place (fault 21=EEP):<br>0: Report a fault<br>Thousands place (fault 22=PIDE):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | | |
| P11.34 | Fault severity group 4 | 0x0000–0x3301<br>Ones place (fault 23=bCE):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>Hundreds place (fault 24=END):<br>0: Report a fault<br>Hundreds place (fault 25=OL3):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place (fault 26=PCE):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | 0x0000 | ○ |
| P11.35 | Fault severity group 5 | 0x0000–0x0300<br>Ones place (fault 27=UPE):<br>0: Report a fault<br>Hundreds place (fault 28=DNE):<br>0: Report a fault<br>Hundreds place (fault 29=E-DP):<br>0: Report a fault<br>1: Report a fault after deceleration to stop | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place (fault 30=Reserved):<br>0: Reserved | | |
| P11.36 | Fault severity group 6 | 0x0000–0x3003<br>Ones place (fault 31=E-CAN):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Tens place (fault 32=ETH1):<br>0: Report a fault<br>Hundreds place (fault 33=ETH2):<br>0: Report a fault<br>Thousands place (fault 34=dEu):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | 0x0000 | ○ |
| P11.37 | Fault severity group 7 | 0x0000–0x0011<br>Ones place (fault 35= STo):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>Hundreds place (fault 36=LL):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>Hundreds place (fault 37=Reserved):<br>Thousands place (fault 38=Reserved): | 0x0000 | ○ |
| P11.38 | Fault severity group 8 | 0x0000–0x0000<br>Ones place (fault 39=Reserved):<br>Tens place (fault 40=Reserved):<br>Hundreds place (fault 41=Reserved):<br>Thousands place (fault 42=Reserved): | | |
| P11.39 | Fault severity group 9 | 0x0000–0x0000<br>Ones place (fault 43=Reserved): | | |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Tens place (fault 44=Reserved):<br>Hundreds place (fault 45=Reserved):<br>Thousands place (fault 46=Reserved): | | |
| P11.40 | Fault severity group 10 | 0x0000–0x0000<br>Ones place (fault 47=Reserved):<br>Tens place (fault 48=Reserved):<br>Hundreds place (fault 49=Reserved):<br>Thousands place (fault 50=Reserved): | | |
| P11.41 | Fault severity group 11 | 0x0000–0x0000<br>Ones place (fault 51=Reserved):<br>Tens place (fault 52=Reserved):<br>Hundreds place (fault 53=Reserved):<br>Thousands place (fault 54=Reserved): | | |
| P11.42 | Fault severity group 12 | 0x0000–0x3303<br>Ones place (fault 55=E-Err):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Tens place (fault 56=Reserved):<br>Hundreds place (fault 57=E-PN):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place (fault 58=SECAN):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | 0x0000 | ○ |
| P11.43 | Fault severity group 13 | 0x0000–0x0333<br>Ones place(fault 59=OT):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | according to P11.51<br>3: Screen out fault<br>Tens place (fault 60=F1-Er):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Hundreds place (fault 61=F2-Er):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place (fault 62=Reserved): | | |
| P11.44 | Fault severity group 14 | 0x0000–0x0033<br>Ones place (fault 63=C1-Er):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Tens place (fault 64=C2-Er):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Hundreds place (fault 65=Reserved):<br>Thousands place (fault 66=Reserved): | 0x0000 | ○ |
| P11.45 | Fault severity group 15 | 0x0000–0x0300<br>Ones place (fault 67=Reserved):<br>Tens place (fault 68=Reserved):<br>Hundreds place (fault 69= S-Err):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51 | 0x0000 | ○ |

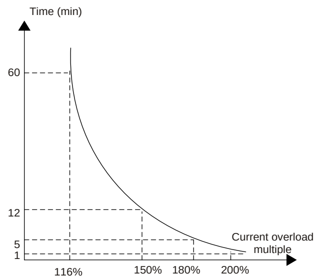
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 3: Screen out fault<br>Thousands place (fault 70=Reserved): | | |
| P11.46 | Fault severity group 16 | 0x0000–0x3300<br>Ones place (fault 71=Reserved):<br>Tens place (fault 72=Reserved):<br>Hundreds place (fault 73=Freezing fault):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands place (fault 74=Stalling):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | 0x0000 | ○ |
| P11.47 | Fault severity group 17 | 0x0000–0x3333<br>Ones place (fault 75=Dry pumping):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Tens place (fault 76=AI1 disconnection):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Tens (fault 77=AI2 disconnection)<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Thousands (fault 78=AI3 disconnection)<br>0: Report a fault | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault | | |
| P11.48 | Fault severity group 18 | 0x0000–0x0003<br>Ones place (fault 79=Water pipe breaking):<br>0: Report a fault<br>1: Report a fault after deceleration to stop<br>2: Pre-alarm, with the action executed according to P11.51<br>3: Screen out fault<br>Tens place (fault 80=Reserved):<br>0: Report a fault<br>Hundreds place (fault 81=Reserved):<br>0: Reserved<br>Thousands place (fault 82=Reserved):<br>0: Report a fault | 0x0000 | ○ |
| P11.49 | Fault severity group 19 | 0x0000–0x0000<br>Ones place (fault 83=Reserved):<br>Tens place (fault 84=Reserved):<br>Hundreds place (fault 85=Reserved):<br>Thousands place (fault 86=Reserved): | 0x0000 | ○ |
| P11.50 | Fault severity group 20 | 0x0000–0x0000<br>Ones place (fault 87=Reserved):<br>Tens place (fault 88=Reserved):<br>Hundreds place (fault 89=Reserved):<br>Thousands place (fault 90=Reserved): | 0x0000 | ○ |
| P11.51 | Action for fault pre-alarm | 0–4<br>0: Run at the set frequency<br>1: Run at the output frequency at the time of failure<br>2: Run at the upper limit frequency<br>3: Run at the lower limit frequency<br>4: Run at the backup frequency upon exceptions | 0x0000 | ○ |
| P11.52 | Backup frequency upon exceptions | 0.00Hz–P00.03 (Max. output frequency) | 0.00Hz | ○ |

**Group P12—Parameters of motor 2**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P12.00 | Type of motor 2 | 0: Asynchronous motor (AM)<br>1: Synchronous motor (SM) | 0 | ◎ |
| P12.01 | Rated power of AM 2 | 0.1–3000.0kW | Model depended (0.4) | ◎ |
| P12.02 | Rated frequency of AM 2 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz | ◎ |
| P12.03 | Rated speed of AM 2 | 1–60000rpm | Model depended (1400) | ◎ |
| P12.04 | Rated voltage of AM 2 | 0–1200V | Model depended (380) | ◎ |
| P12.05 | Rated current of AM 2 | 0.8–6000.0A | Model depended (1.0) | ◎ |
| P12.06 | Stator resistance of AM 2 | 0.001–65.535Ω | Model depended (0.001) | ○ |
| P12.07 | Rotor resistance of AM 2 | 0.001–65.535Ω | Model depended (0.001) | ○ |
| P12.08 | Leakage inductance of AM 2 | 0.1–6553.5mH | Model depended (0.1) | ○ |
| P12.09 | Mutual inductance of AM 2 | 0.1–6553.5mH | Model depended (0.1) | ○ |
| P12.10 | No-load current of AM 2 | 0.1–6553.5A | Model depended (0.1) | ○ |
| P12.11 | Magnetic saturation coefficient 1 of iron core of AM 2 | 0.0–100.0% | 80% | ○ |
| P12.12 | Magnetic saturation coefficient 2 of iron core of AM 2 | 0.0–100.0% | 68% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P12.13 | Magnetic saturation coefficient 3 of iron core of AM 2 | 0.0–100.0% | 57% | ○ |
| P12.14 | Magnetic saturation coefficient 4 of iron core of AM 2 | 0.0–100.0% | 40% | ○ |
| P12.15 | Rated power of SM 2 | 0.1–3000.0kW | Model depended (0.4) | ◎ |
| P12.16 | Rated frequency of SM 2 | 0.01Hz–P00.03 (Max. output frequency) | 50.00Hz | ◎ |
| P12.17 | Number of pole pairs of SM 2 | 1–128 | 2 | ◎ |
| P12.18 | Rated voltage of SM 2 | 0–1200V | Model depended (380) | ◎ |
| P12.19 | Rated current of SM 2 | 0.8–6000.0A | Model depended (1.0) | ◎ |
| P12.20 | Stator resistance of SM 2 | 0.001–65.535Ω | Model depended (0.001) | ○ |
| P12.21 | Direct-axis inductance of SM 2 | 0.01–655.35mH | Model depended (0.01) | ○ |
| P12.22 | Quadrature-axis inductance of SM 2 | 0.01–655.35mH | Model depended (0.01) | ○ |
| P12.23 | Counter-emf constant of SM 2 | 0–10000V | 300 | ○ |
| P12.24 | Initial pole position of SM 2 | 0x0000–0xFFFF | 0x0000 | ● |
| P12.25 | Identification current of SM 2 | 0–50% (of the motor rated current) | 10% | ● |
| P12.26 | Overload protection selection of motor 2 | 0: No protection<br>1: Common motor (with low-speed compensation)<br>2: Frequency-variable motor (without | 2 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | low-speed compensation) | | |
| P12.27 | Overload protection coefficient of motor 2 | Motor overload multiples $M=I_{out}/(In*K)$<br>$I_n$ indicates the rated motor current, $I_{out}$ indicates the VFD output current, and K indicates the motor overload protection coefficient.<br>A smaller value of "K" indicates a bigger value of "M".<br>When M=116%, protection is performed after motor overload lasts for 1 hour; when M=200%, protection is performed after motor overload lasts for 60 seconds; and when M≥400%, protection is performed immediately.<br><br>Setting range: 20.0%–150.0% | 100.0% | ○ |
| P12.28 | Power display calibration coefficient of motor 2 | 0.00–3.00 | 1.00 | ○ |
| P12.29 | Parameter display of motor 2 | 0: Display by motor type<br>In this mode, only parameters related to the present motor type are displayed.<br>1: Display all<br>In this mode, all the motor parameters are displayed. | 0 | ○ |
| P12.30 | System inertia of motor 2 | 0.000–30.000kg•m$^2$ | 0.000 kg•m$^2$ | ○ |

**Group P13—SM control**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P13.00 | SM injected-current decrease ratio | Used to set the reduction rate of the input reactive current. When the active current of the synchronous motor increases to some extent, the input reactive current can be reduced to improve the power factor of the motor.<br>Setting range: 0.0%–+100.0% (of the motor rated current) | 80.0% | ○ |
| P13.01 | Detection mode of initial pole | 0–2<br>0: Do not detect<br>1: High-frequency superposition<br>2: Pulse superposition | 0 | ◎ |
| P13.02 | Pull-in current 1 | Pull-in current is the pole position orientation current; pull-in current 1 is valid within the lower limit of pull-in current switch-over frequency threshold. If you need to increase the start torque, increase the value of this function parameter properly.<br>Setting range: -100.0%–100.0% (of the motor rated current) | 20.0% | ○ |
| P13.03 | Pull-in current 2 | Pull-in current is the pole position orientation current; pull-in current 2 is valid within the lower limit of pull-in current switch-over frequency threshold. You do not need to change the value in most cases.<br>Setting range: -100.0%–100.0% (of the motor rated current) | 10.0% | ○ |
| P13.04 | Pull-in current switchover frequency | 0.00Hz–P00.03 (Max. output frequency) | 10.00Hz | ○ |
| P13.05 | High frequency superimposed frequency | 200–1000Hz | 500Hz | ◎ |
| P13.06 | High-frequency superposition voltage | Used to set the pulse current threshold when the initial magnetic pole position is detected in the pulse mode, The value is a percentage in relative to the rated current of the motor. | 100.0% | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Setting range: 0.0–300.0% (of the motor rated voltage) | | |
| P13.07 | Control parameter 0 | 0.0–400.0 | 0.0 | ○ |
| P13.08 | Control parameter 1 | 0x0000–0xFFFF | 0x0000 | ○ |
| P13.09 | Control parameter 2 | Used to set the frequency threshold for enabling the counter-electromotive force phase-locked loop in SVC 0. When the running frequency is lower than the value of the function code, the phase-locked loop is disabled; and when the running frequency is higher than that, the phase-locked loop is enabled.<br>Setting range: 0–655.35 | 2.00 | ○ |
| P13.10 | Initial compensation angle of SM | 0.0–359.9° | 0.0° | ○ |
| P13.11 | Mal-adjustment detection time | Used to adjust the responsiveness of anti-maladjustment function. If the load inertia is large, increase the value of this parameter properly, however, the responsiveness may slow down accordingly.<br>Setting range: 0.0–10.0s | 0.5s | ○ |
| P13.12 | High-frequency compensation coefficient of SM | Valid when the motor speed exceeds the rated speed. If oscillation occurred to the motor, adjust this parameter properly.<br>Setting range: 0.0–100.0% | 0.0% | ○ |
| P13.13 | High-frequency pull-in current | 0.0–300.0% (of the VFD rated output current) | 20.0% | ◎ |

**Group P14—Serial communication**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P14.00 | Local communication address | Setting range: 1–247<br>When the master writes the slave communication address to 0 indicating a broadcast address in a frame, all the salves | 1 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | on the Modbus bus receive the frame but do not respond to it.<br>The communication addresses on the communication network are unique, which is the basis of the point-to-point communication.<br>**Note:** The slave address cannot be set to 0. | | |
| P14.01 | Communication baud rate setting | Used to set the rate of data transmission between the host controller and the VFD.<br>0: 1200bps<br>1: 2400 bps<br>2: 4800 bps<br>3: 9600 bps<br>4: 19200 bps<br>5: 38400 bps<br>6: 57600 bps<br>7: 115200 bps<br>**Note:** The baud rate set on the VFD must be consistent with that on the host controller. Otherwise, the communication fails. A greater baud rate indicates faster communication. | 4 | ○ |
| P14.02 | Data bit check | The data format set on the VFD must be consistent with that on the host controller. Otherwise, the communication fails.<br>0: No check (N, 8, 1) for RTU<br>1: Even check (E, 8, 1) for RTU<br>2: Odd check (O, 8, 1) for RTU<br>3: No check (N, 8, 2) for RTU<br>4: Even check (E, 8, 2) for RTU<br>5: Odd check (O, 8, 2) for RTU | 1 | ○ |
| P14.03 | Communication response delay | 0–200ms<br>Indicates the communication response delay, that is, the interval from when the VFD completes receiving data to when it sends response data to the host controller. If the response delay is shorter than the rectifier processing time, the rectifier sends response data to the host controller after processing data. If the delay is longer than the rectifier | 5ms | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | processing time, the rectifier does not send response data to the host controller until the delay is reached although data has been processed. | | |
| P14.04 | Communication timeout time | 0.0 (invalid); 0.1–60.0s<br>When the function code is set to 0.0, the communication timeout time is invalid. When the function code is set to a non-zero value, the system reports the "485 communication fault" (CE) if the communication interval exceeds the value.<br>In general, the function code is set to 0.0. When continuous communication is required, you can set the function code to monitor communication status. | 0.0s | ○ |
| P14.05 | Transmission fault processing | 0–3<br>0: Report an alarm and coast to stop<br>1: Keep running without reporting an alarm<br>2: Stop in enabled stop mode without reporting an alarm (applicable only to communication mode)<br>3: Stop in enabled stop mode without reporting an alarm (applicable to any mode) | 0 | ○ |
| P14.06 | Communication processing action | 0x000–0x111<br>Ones place:<br>0: Respond to write operations<br>1: Not respond to write operations<br>Tens place:<br>0: Communication password protection is invalid.<br>1: Communication password protection is valid.<br>Hundreds place:<br>0: Custom addresses of P14.07, P14.08 are invalid.<br>1: Custom addresses of P14.07, P14.08 are valid. | 0x000 | ○ |
| P14.07 | User-defined | 0x0000–0xFFFF | 0x2000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | running command address | | | |
| P14.08 | User-defined frequency setting address | 0x0000–0xFFFF | 0x2001 | ○ |
| P14.09 | Modbus TCP communication timeout time | 0.0–60.0s | 5.0s | ○ |
| P14.10 | Enabling 485 upgrade program | 0–1<br>0: Disable<br>1: Enable | 0 | ◎ |
| P14.11 | Bootload software version | 0.00–655.35 | 0.00 | ● |
| P14.12–P14.18 | Reserved | - | - | - |
| P14.19 | Address mapping function control | 0x00–0x11<br>Ones place: Read address mapping function<br>0: Invalid<br>1: Enabled<br>Tens place: Write address mapping function<br>0: Invalid<br>1: Enabled | 0x00 | ○ |
| P14.20 | 2200H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2200H. | 0x0000 | ○ |
| P14.21 | 2201H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2201H. | 0x0000 | ○ |
| P14.22 | 2202H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2202H. | 0x0000 | ○ |
| P14.23 | 2203H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2203H. | 0x0000 | ○ |
| P14.24 | 2204H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2204H. | 0x0000 | ○ |
| P14.25 | 2205H read | 0x0000–0xFFFF | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | mapped address | Used to set the register address mapped to 2205H. | | |
| P14.26 | 2206H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2206H. | 0x0000 | ○ |
| P14.27 | 2207H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2207H. | 0x0000 | ○ |
| P14.28 | 2208H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2208H. | 0x0000 | ○ |
| P14.29 | 2209H read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2209H. | 0x0000 | ○ |
| P14.30 | 220AH read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 220AH. | 0x0000 | ○ |
| P14.31 | 220BH read mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 220BH. | 0x0000 | ○ |
| P14.32 | 2300H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2300H. | 0x0000 | ○ |
| P14.33 | 2301H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2301H. | 0x0000 | ○ |
| P14.34 | 2302H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2302H. | 0x0000 | ○ |
| P14.35 | 2303H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2303H. | 0x0000 | ○ |
| P14.36 | 2304H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2304H. | 0x0000 | ○ |
| P14.37 | 2305H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2305H. | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P14.38 | 2306H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2306H. | 0x0000 | ○ |
| P14.39 | 2307H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2307H. | 0x0000 | ○ |
| P14.40 | 2308H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2308H. | 0x0000 | ○ |
| P14.41 | 2309H write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 2309H. | 0x0000 | ○ |
| P14.42 | 230AH write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 230AH. | 0x0000 | ○ |
| P14.43 | 230BH write mapped address | 0x0000–0xFFFF<br>Used to set the register address mapped to 230BH. | 0x0000 | ○ |

**Group P15—Communication expansion card 1 functions**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P15.00 | Reserved | 0–4 | 0 | ● |
| P15.01 | Module address | 0–127 | 2 | ◎ |
| P15.02 | Received PZD2 | 0–31<br>0: Invalid<br>1: Set frequency (0–Fmax, unit: 0.01Hz)<br>2: PID reference (-1000–1000, in which 1000 corresponds to 100.0%)<br>3: PID feedback (-1000–1000, in which 1000 corresponds to 100.0%)<br>4: Torque setting (-3000–+3000, in which 1000 corresponds to 100.0% of the motor rated current)<br>5: Setting of the upper limit of forward running frequency (0–Fmax, unit: 0.01Hz)<br>6: Setting of the upper limit of reverse running frequency (0–Fmax, unit: 0.01Hz) | 0 | ○ |
| P15.03 | Received PZD3 | | 0 | ○ |
| P15.04 | Received PZD4 | | 0 | ○ |
| P15.05 | Received PZD5 | | 0 | ○ |
| P15.06 | Received PZD6 | | 0 | ○ |
| P15.07 | Received PZD7 | | 0 | ○ |
| P15.08 | Received PZD8 | | 0 | ○ |
| P15.09 | Received PZD9 | | 0 | ○ |
| P15.10 | Received PZD10 | | 0 | ○ |
| P15.11 | Received PZD11 | | 0 | ○ |
| P15.12 | Received PZD12 | | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 7: Upper limit of the electromotive torque (0–3000, in which 1000 corresponds to 100.0% of the motor rated current)<br>8: Upper limit of braking torque (0–3000, in which 1000 corresponds to 100% of the motor rated current)<br>9: Virtual input terminal command. Range: 0x000–0x3FF<br>10: Virtual output terminal command. Range: 0x00–0x0F<br>11: Voltage setting (special for V/F separation) (0–1000, in which 1000 corresponds to 100% of the motor rated voltage)<br>12: AO1 output setting 1 (-1000–+1000, in which 1000 corresponds to 100.0%)<br>13: AO2 output setting 2 (-1000–+1000, in which 1000 corresponds to 100.0%)<br>14–18: Reserved<br>19: PID1 reference source 1 (0–1000, in which 1000 corresponds to 100.0%)<br>20: PID1 feedback source 1 (0–1000, in which 1000 corresponds to 100.0%)<br>21: PID1 reference source 2 (0–1000, in which 1000 corresponds to 100.0%)<br>22: PID1 feedback source 2 (0–1000, in which 1000 corresponds to 100.0%)<br>23: PID2 reference source (0–1000, in which 1000 corresponds to 100.0%)<br>24: PID2 feedback source (0–1000, in which 1000 corresponds to 100.0%)<br>25: Inlet water level (0–1000, in which 1000 corresponds to 100.0%)<br>26: AO0 output setting 0 (-1000–+1000, in which 1000 corresponds to 100.0%)<br>27–31: Reserved | | |
| P15.13 | Sent PZD2 | 0–37<br>0: Invalid | 0 | ○ |
| P15.14 | Sent PZD3 | | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P15.15 | Sent PZD4 | 1: Running frequency (×100, Hz) | 0 | ○ |
| P15.16 | Sent PZD5 | 2: Set frequency (×100, Hz) | 0 | ○ |
| P15.17 | Sent PZD6 | 3: Bus voltage (×10, V) | 0 | ○ |
| P15.18 | Sent PZD7 | 4: Output voltage (×1, V) | 0 | ○ |
| P15.19 | Sent PZD8 | 5: Output current (×10, A) | 0 | ○ |
| P15.20 | Sent PZD9 | 6: Actual output torque (×10, %) | 0 | ○ |
| P15.21 | Sent PZD10 | 7: Actual output power (×10, %) | 0 | ○ |
| P15.22 | Sent PZD11 | 8: Rotation speed of running (×1, RPM) | 0 | ○ |
| P15.23 | Sent PZD12 | 9: Linear speed of running (×1, m/s)<br>10: Ramp reference frequency<br>11: Fault code<br>12: AI1 input (×100, V)<br>13: AI2 input (×100, V)<br>14: AI3 input (×100, V)<br>15: HDIA frequency value (×1000, kHz)<br>16: Terminal input status<br>17: Terminal output status<br>18: PID reference (×100, %)<br>19: PID feedback (×100, %)<br>20: Motor rated torque<br>21–24: Reserved<br>25: Status word<br>26: HDIB frequency value (×1000, kHz) (reserved)<br>27: PID1 reference<br>28: PID1 feedback<br>29: PID1 output<br>30: PID2 reference value<br>31: PID2 feedback value<br>32: PID2 output<br>33–37: Reserved | 0 | ○ |
| P15.24 | Reserved | - | - | - |
| P15.25 | DP communication timeout period | 0.0–60.0s | 5.0s | ○ |
| P15.26 | CANopen communication timeout period | 0.0–60.0s | 5.0s | ○ |
| P15.27 | CANopen | 0–7 | 3 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | communication baud rate | 0: 1000kbps<br>1: 800kbps<br>2: 500kbps<br>3: 250kbps<br>4: 125kbps<br>5: 100kbps<br>6: 50kbps<br>7: 20kbps | | |
| P15.28 | CAN communication address | 0–127 | 1 | ◎ |
| P15.29 | Master/slave CAN communication baud rate | 0–5<br>0: 50kbps<br>1: 100kbps<br>2: 125kbps<br>3: 250kbps<br>4: 500kbps<br>5: 1Mbps | 2 | ◎ |
| P15.30 | Master/slave CAN communication timeout period | 0.0 (invalid)–60.0s | 5.0s | ○ |
| P15.31 | DeviceNET communication timeout period (reserved) | 0.0 (invalid)–60.0s | 5.0s | ○ |
| P15.32 | Display node baud rate (reserved) | 0–65535 | 0 | ● |
| P15.33 | Alternation enable (reserved) | 0–1 | 1 | ○ |
| P15.34 | Instance number of alternation output (Reserved) | 0–27<br>0–18: Reserved<br>19: INVT VFD output<br>20: ODVA basic speed control output<br>21: ODVA extended speed control output<br>22: ODVA speed and torque control output<br>23: ODVA extended speed and torque control output<br>24: INVT basic speed control output | 19 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 25: INVT extended speed control output<br>26: INVT speed and torque control output<br>27: INVT extended speed and torque control output | | |
| P15.35 | Instance number of alternation input (Reserved) | 0–77<br>0–68: Reserved<br>69: INVT VFD input<br>70: ODVA basic speed control input<br>71: ODVA extended speed control input<br>72: ODVA speed and torque control input<br>73: ODVA extended speed and torque control input<br>74: INVT basic speed control input<br>75: INVT extended speed control input<br>76: INVT speed and torque control input<br>77: INVT extended speed and torque control input | 69 | ○ |
| P15.36 | State change/cycle enable (reserved) | 0–1 | 0 | ○ |
| P15.37 | State change/cycle output instance (reserved) | 0–27<br>0–18: Reserved<br>19: INVT VFD output<br>20: ODVA basic speed control output<br>21: ODVA extended speed control output<br>22: ODVA speed and torque control output<br>23: ODVA extended speed and torque control output<br>24: INVT basic speed control output<br>25: INVT extended speed control output<br>26: INVT speed and torque control output<br>27: INVT extended speed and torque control output | 19 | ○ |
| P15.38 | State change/cycle input instance (reserved) | 0–77<br>0–68: Reserved<br>69: INVT VFD input<br>70: ODVA basic speed control input<br>71: ODVA extended speed control input<br>72: ODVA speed and torque control input | 69 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 73: ODVA extended speed and torque control input<br>74: INVT basic speed control input<br>75: INVT extended speed control input<br>76: INVT speed and torque control input<br>77: INVT extended speed and torque control input | | |
| P15.39 | Component 19 output length (reserved) | 8–32 | 32 | ○ |
| P15.40 | Component 19 input length (reserved) | 8–32 | 32 | ○ |
| P15.41 | BACnet communication mode | 0–1<br>0: P16.22 is enabled.<br>1: P15.42 is enabled. | 1 | ◎ |
| P15.42 | Baud rate of BACnet_MSTP | 0–5<br>0: 9600 bps<br>1: 19200 bps<br>2: 38400 bps<br>3: 57600 bps<br>4: 76800 bps<br>5: 115200 bps | 0 | ◎ |
| P15.43 | Communication control word expression format (reserved) | 0–1<br>0: Decimal format<br>1: Binary format | 0 | ● |
| P15.44 | BACnet device No. high bit | 0–4194 | 0 | ◎ |
| P15.45 | BACnet device No. low bit | 0–999 | 1 | ◎ |
| P15.46 | BACnet I-AM service selection | 0–1<br>0: Send at power-on<br>1: Send constantly | 0 | ◎ |
| P15.47 | BACnet communication timeout time | 0.0–60.0s | 5.0s | ○ |
| P15.48 | BACnet multi-card communication timeout time | 0.0s–P15.47 | 0.0s | ○ |

**Group P16—Functions of communication expansion card 2**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P16.00–P16.01 | Reserved | - | - | - |
| P16.02 | Ethernet monitoring card IP address 1 | 0–255 | 192 | ◎ |
| P16.03 | Ethernet monitoring card IP address 2 | 0–255 | 168 | ◎ |
| P16.04 | Ethernet monitoring card IP address 3 | 0–255 | 0 | ◎ |
| P16.05 | Ethernet monitoring card IP address 4 | 0–255 | 1 | ◎ |
| P16.06 | Ethernet monitoring card subnet mask 1 | 0–255 | 255 | ◎ |
| P16.07 | Ethernet monitoring card subnet mask 2 | 0–255 | 255 | ◎ |
| P16.08 | Ethernet monitoring card subnet mask 3 | 0–255 | 255 | ◎ |
| P16.09 | Ethernet monitoring card subnet mask 4 | 0–255 | 0 | ◎ |
| P16.10 | Ethernet monitoring card gateway 1 | 0–255 | 192 | ◎ |
| P16.11 | Ethernet monitoring card gateway 2 | 0–255 | 168 | ◎ |
| P16.12 | Ethernet monitoring card gateway 3 | 0–255 | 0 | ◎ |
| P16.13 | Ethernet monitoring card gateway 4 | 0–255 | 1 | ◎ |
| P16.14 | Ethernet card monitoring variable address 1 | 0x0000–0xFFFF | 0x0000 | ○ |
| P16.15 | Ethernet card monitoring variable address 2 | 0x0000–0xFFFF | 0x0000 | ○ |
| P16.16 | Ethernet card monitoring variable address 3 | 0x0000–0xFFFF | 0x0000 | ○ |
| P16.17 | Ethernet card | 0x0000–0xFFFF | 0x0000 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | monitoring variable address 4 | | | |
| P16.18 | Ethernet monitoring card communication timeout period (reserved) | 0.0 (invalid)–60.0s | 0.0s | ○ |
| P16.19 | Reserved | 0–4<br>0: 250μs<br>1: 500μs<br>2: 1ms<br>3: 2ms<br>4: Reserved | 2 | ○ |
| P16.20 | BACnet device No. MSB (reserved) | 0–4194<br>**Note:** BACnet device No. range is 0–4194303. | 0 | ◎ |
| P16.21 | BACnet device No. LSB (reserved) | 0–999<br>**Note:** BACnet device No. range is 0–4194303. | 1 | ◎ |
| P16.22 | BACnet "I-Am" service selection (reserved) | 0–1<br>0: Send at power-on<br>1: Send constantly | 0 | ○ |
| P16.23 | BACnet communication timeout period (reserved) | 0.0 (invalid)–60.0s | 5.0s | ○ |
| P16.24 | Time to identify expansion card in card slot 1 | 0.0 (invalid)–600.0s | 0.0s | ○ |
| P16.25 | Time to identify expansion card in card slot 2 | 0.0 (invalid)–600.0s | 0.0s | ○ |
| P16.26 | Time to identify expansion card in card slot 3 (reserved) | 0.0 (invalid)–600.0s | 0.0s | ● |
| P16.27 | Communication timeout period of | 0.0 (invalid)–600.0s | 0.0s | ○ |

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td>card in slot 1</td><td></td><td></td><td></td></tr>
<tr><td>P16.28</td><td>Communication timeout period of card in slot 2</td><td>0.0 (invalid)–600.0s</td><td>0.0s</td><td>○</td></tr>
<tr><td>P16.29</td><td>Communication timeout period of expansion card in card slot 3 (reserved)</td><td>0.0 (invalid)–600.0s</td><td>0.0s</td><td>●</td></tr>
<tr><td>P16.30</td><td>Reserved</td><td>-</td><td>-</td><td>-</td></tr>
<tr><td>P16.32</td><td>Received PZD2</td><td rowspan="12">0–31<br>0: Invalid<br>1: Set frequency (0–Fmax, unit: 0.01Hz)<br>2: PID reference source 1 (-1000–+1000, in which 1000 corresponds to 100.0%)<br>3: PID feedback source 1 (-1000–1000, in which 1000 corresponds to 100.0%)<br>4: Torque setting (-3000–+3000, in which 1000 corresponds to 100.0% of the motor rated current)<br>5: Setting of the upper limit of forward running frequency (0–Fmax, unit: 0.01Hz)<br>6: Setting of the upper limit of reverse running frequency (0–Fmax, unit: 0.01Hz)<br>7: Upper limit of the electromotive torque (0–3000, in which 1000 corresponds to 100.0% of the motor rated current)<br>8: Upper limit of braking torque (0–3000, in which 1000 corresponds to 100% of the motor rated current)<br>9: Virtual input terminal command (0x000–0x3FF)<br>10: Virtual output terminal command (0x00–0x0F)<br>11: Voltage setting (special for V/F separation) (0–1000, in which 1000 corresponds to 100% of the motor rated voltage)</td><td>0</td><td>○</td></tr>
<tr><td>P16.33</td><td>Received PZD3</td><td>0</td><td>○</td></tr>
<tr><td>P16.34</td><td>Received PZD4</td><td>0</td><td>○</td></tr>
<tr><td>P16.35</td><td>Received PZD5</td><td>0</td><td>○</td></tr>
<tr><td>P16.36</td><td>Received PZD6</td><td>0</td><td>○</td></tr>
<tr><td>P16.37</td><td>Received PZD7</td><td>0</td><td>○</td></tr>
<tr><td>P16.38</td><td>Received PZD8</td><td>0</td><td>○</td></tr>
<tr><td>P16.39</td><td>Received PZD9</td><td>0</td><td>○</td></tr>
<tr><td>P16.40</td><td>Received PZD10</td><td>0</td><td>○</td></tr>
<tr><td>P16.41</td><td>Received PZD11</td><td>0</td><td>○</td></tr>
<tr><td>P16.42</td><td>Received PZD12</td><td>0</td><td>○</td></tr>
<tr><td>P16.32</td><td>Received PZD2</td><td>0</td><td>○</td></tr>
</table>

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td></td><td>12: AO1 output setting 1 (-1000–+1000, in which 1000 corresponds to 100.0%)<br>13: AO2 output setting 2 (-1000–+1000, in which 1000 corresponds to 100.0%)<br>14–18: Reserved<br>19: PID1 reference source 1 (0–1000, in which 1000 corresponds to 100.0%)<br>20: PID1 feedback source 1 (0–1000, in which 1000 corresponds to 100.0%)<br>21: PID1 reference source 2 (0–1000, in which 1000 corresponds to 100.0%)<br>22: PID1 feedback source 2 (0–1000, in which 1000 corresponds to 100.0%)<br>23: PID2 reference source (0–1000, in which 1000 corresponds to 100.0%)<br>24: PID2 feedback source (0–1000, in which 1000 corresponds to 100.0%)<br>25: Inlet water level (0–1000, in which 1000 corresponds to 100.0%)<br>26: AO0 output setting 0 (-1000–+1000, in which 1000 corresponds to 100.0%)<br>27–31: Reserved</td><td></td><td></td></tr>
<tr><td>P16.43</td><td>Sent PZD2</td><td rowspan="11">0–37<br>0: Invalid<br>1: Running frequency (×100, Hz)<br>2: Set frequency (×100, Hz)<br>3: Bus voltage (×10, V)<br>4: Output voltage (×1, V)<br>5: Output current (×10, A)<br>6: Actual output torque (×10, %)<br>7: Actual output power (×10, %)<br>8: Rotation speed of running (×1, RPM)<br>9: Linear speed of running (×1, m/s)<br>10: Ramp reference frequency<br>11: Fault code<br>12: AI1 input (×100, V)<br>13: AI2 input (×100, V)<br>14: AI3 input (×100, V)</td><td>0</td><td>○</td></tr>
<tr><td>P16.44</td><td>Sent PZD3</td><td>0</td><td>○</td></tr>
<tr><td>P16.45</td><td>Sent PZD4</td><td>0</td><td>○</td></tr>
<tr><td>P16.46</td><td>Sent PZD5</td><td>0</td><td>○</td></tr>
<tr><td>P16.47</td><td>Sent PZD6</td><td>0</td><td>○</td></tr>
<tr><td>P16.48</td><td>Sent PZD7</td><td>0</td><td>○</td></tr>
<tr><td>P16.49</td><td>Sent PZD8</td><td>0</td><td>○</td></tr>
<tr><td>P16.50</td><td>Sent PZD9</td><td>0</td><td>○</td></tr>
<tr><td>P16.51</td><td>Sent PZD10</td><td>0</td><td>○</td></tr>
<tr><td>P16.52</td><td>Sent PZD11</td><td>0</td><td>○</td></tr>
<tr><td>P16.53</td><td>Sent PZD12</td><td>0</td><td>○</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 15: HDIA frequency value (×1000, kHz)<br>16: Terminal input status<br>17: Terminal output status<br>18: PID reference (×100, %)<br>19: PID feedback (×100, %)<br>20: Motor rated torque<br>21–24: Reserved<br>25: Status word<br>26: Reserved<br>27: PID1 reference<br>28: PID1 feedback<br>29: PID1 output<br>30: PID2 reference value<br>31: PID2 feedback value<br>32: PID2 output<br>33–37: Reserved | | |
| P16.54 | EtherNet IP communication timeout period | 0.0 (invalid)–60.0s<br>**Note:** When an EtherNet IP communication fault occurs, the VFD reports the EtherNet IP communication fault (E-EIP). | 5.0s | ○ |
| P16.55 | EtherNet IP communication rate (reserved) | 0–4<br>0: Self adaptive<br>1: 100M full duplex<br>2: 100M half duplex<br>3: 10M full duplex<br>4: 10M half duplex | 0 | ● |
| P16.56–P16.57 | Reserved | - | - | - |
| P16.58 | Industrial Ethernet communication card IP address 1 | 0–255 | 192 | ◎ |
| P16.59 | Industrial Ethernet communication card IP address 2 | 0–255 | 168 | ◎ |
| P16.60 | Industrial Ethernet communication card IP address 3 | 0–255 | 0 | ◎ |
| P16.61 | Industrial Ethernet | 0–255 | 20 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | communication card IP address 4 | | | |
| P16.62 | Industrial Ethernet communication card subnet mask 1 | 0–255 | 255 | ◎ |
| P16.63 | Industrial Ethernet communication card subnet mask 2 | 0–255 | 255 | ◎ |
| P16.64 | Industrial Ethernet communication card subnet mask 3 | 0–255 | 255 | ◎ |
| P16.65 | Industrial Ethernet communication card subnet mask 4 | 0–255 | 0 | ◎ |
| P16.66 | Industrial Ethernet communication card gateway 1 | 0–255 | 192 | ◎ |
| P16.67 | Industrial Ethernet communication card gateway 2 | 0–255 | 168 | ◎ |
| P16.68 | Industrial Ethernet communication card gateway 3 | 0–255 | 0 | ◎ |
| P16.69 | Industrial Ethernet communication card subnet mask 4 | 0–255 | 1 | ◎ |

**Group P17—Status viewing**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P17.00 | Set frequency | Displays the present set frequency of the VFD.<br>Range: 0.00Hz–P00.03 | 50.00Hz | ● |
| P17.01 | Output frequency | Displays the present output frequency of the VFD.<br>Range: 0.00Hz–P00.03 | 0.00Hz | ● |
| P17.02 | Ramp reference frequency | Displays the present ramp reference frequency of the VFD. | 0.00Hz | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Range: 0.00Hz–P00.03 | | |
| P17.03 | Output voltage | Displays the present output voltage of the VFD.<br>Range: 0–1200V | 0V | ● |
| P17.04 | Output current | Displays the valid value of current output current of the VFD.<br>Range: 0.0–5000.0A | 0.0A | ● |
| P17.05 | Motor rotation speed | Displays the present motor rotation speed.<br>Range: 0–65535RPM | 0 RPM | ● |
| P17.06 | Torque current | Displays the present torque current of the VFD.<br>Range: -3000.0–3000.0A | 0.0A | ● |
| P17.07 | Exciting current | Displays the present exciting current of the VFD.<br>Range: -3000.0–3000.0A | 0.0A | ● |
| P17.08 | Motor power | Displays the present motor power; 100% relative to the rated motor power. The positive value is the motoring state while the negative value is the generating state.<br>Setting range: -300.0%–300.0% (of the motor rated power) | 0.0% | ● |
| P17.09 | Motor output torque | Displays the present output torque of the VFD; 100% relative to the rated motor torque. During forward running, the positive value is the motoring state while the negative value is generating state. During reverse running, the positive value is the generating state while the negative value is the motoring state.<br>Range: -250.0%–250.0% | 0.0% | ● |
| P17.10 | Estimated motor frequency | Displays the estimated motor rotor frequency under the open-loop vector condition.<br>Range: 0.00–P00.03 | 0.00Hz | ● |
| P17.11 | DC bus voltage | Displays the present DC bus voltage of the VFD.<br>Range: 0.0–2000.0 V | 0V | ● |
| P17.12 | Digital input terminal state | Displays the present digital input terminal state of the VFD.<br>0x0000–0x003F | 0x0000 | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | Corresponds to Reserved, HDIA, S4, S3, S2 and S1 respectively. | | |
| P17.13 | Digital output terminal status | Displays the present digital output terminal state of the VFD.<br>0x0000–0x000F<br>The bits correspond to reserved, RO1, reserved, and Y1 respectively. | 0x0000 | ● |
| P17.14 | Digital adjustment value | Displays the adjustment on the VFD through the UP/DOWN terminal.<br>Range: 0.00Hz–P00.03 | 0.00Hz | ● |
| P17.15 | Torque reference value | Relative to the percentage of the rated torque of the present motor, displaying the torque reference.<br>Range: -300.0%–300.0% | 0.0% | ● |
| P17.16 | Linear speed | 0–65535 | 0 | ● |
| P17.17 | Reserved | - | - | - |
| P17.18 | Count value | 0–65535 | 0 | ● |
| P17.19 | AI1 input voltage | Displays the AI1 input signal.<br>Range: 0.00–10.00V<br>**Note:** When P05.50=0x11, P17.19 will display without units, with a range of 0.00 to 20.00. | 0.00V | ● |
| P17.20 | AI2 input voltage | Displays the AI2 input signal.<br>Range: -10.00V–10.00V | 0.00V | ● |
| P17.21 | HDIA input frequency | Display HDIA input frequency.<br>Range: 0.000–50.000kHz | 0.000kHz | ● |
| P17.22 | HDIB input frequency (Reserved) | Range: 0.000–50.000kHz | 0.000kHz | ● |
| P17.23 | PID reference value | Displays the PID reference value.<br>Range: -100.0%–100.0% | 0.0% | ● |
| P17.24 | PID feedback value | Displays the PID feedback value.<br>Range: -100.0%–100.0% | 0.0% | ● |
| P17.25 | Motor power factor | Displays the power factor of the current motor.<br>Range: -1.00–1.00 | 1.00 | ● |
| P17.26 | Duration of this run | Displays the duration of this run of the VFD.<br>Range: 0–65535min | 0min | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P17.27 | Present step of simple PLC | Used to display the present step of the simple PLC function.<br>Range: 0–15 | 0 | ● |
| P17.28 | Motor ASR controller output | Displays the ASR controller output value under the vector control mode.<br>Range: -300.0%–300.0% (of the motor rated current) | 0.0% | ● |
| P17.29 | Open-loop SM pole angle | Displays the initial identification angle of SM.<br>Range: 0.0–360.0° | 0.0° | ● |
| P17.30 | Phase compensation of SM | Displays the phase compensation of SM.<br>Range: -180.0–180.0 | 0.0 | ● |
| P17.31 | High-frequency superposition current of SM | 0.0%–200.0% (of the motor rated current) | 0.0% | ● |
| P17.32 | Motor flux linkage | 0.0%–200.0% | 0.0% | ● |
| P17.33 | Exciting current reference | Displays the exciting current reference value under the vector control mode.<br>Range: -3000.0–3000.0A | 0.0A | ● |
| P17.34 | Torque current reference | Displays the torque current reference value under the vector control mode.<br>Range: -3000.0–3000.0A | 0.0A | ● |
| P17.35 | AC incoming current | Displays the valid value of incoming current on AC side.<br>Range: 0.0–5000.0A | 0.0A | ● |
| P17.36 | Actual output torque | Displays the actual output torque value of the VFD. During forward running, the positive value is the motoring state while the negative value is generating state. During reverse running, the positive value is the generating state while the negative value is the motoring state.<br>Range: -3000.0N·m–3000.0N·m | 0.0N·m | ● |
| P17.37 | Motor overload count value | 0–65535 | 0 | ● |
| P17.38 | Process PID output | -100.0%–100.0% | 0.00% | ● |
| P17.39 | Function codes in parameter | 0.00–99.99 | 0.00 | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | download error | | | |
| P17.40 | Motor control mode | 0x000–0x123<br>Ones place: Control mode<br>0: Vector 0<br>1: Vector 1<br>2: VF control<br>3: Reserved<br>Tens place: Control status<br>0: Speed control<br>1: Torque control<br>2: Reserved<br>Hundreds place: Motor number<br>0: Motor 1<br>1: Motor 2 | 0x000 | ● |
| P17.41 | Electromotive torque upper limit | 0.0%–300.0% (of the motor rated current) | 0.0% | ● |
| P17.42 | Braking torque upper limit | 0.0%–300.0% (of the motor rated current) | 0.0% | ● |
| P17.43 | Forward rotation upper-limit frequency in torque control | 0.00Hz–P00.03 | 0.00Hz | ● |
| P17.44 | Reverse rotation upper-limit frequency in torque control | 0.00Hz–P00.03 | 0.00Hz | ● |
| P17.45 | Inertia compensation torque | -100.0%–100.0% | 0.0% | ● |
| P17.46 | Friction compensation torque | -100.0%–100.0% | 0.0% | ● |
| P17.47 | Motor pole pairs | 0–65535 | 0 | ● |
| P17.48 | VFD overload count value | 0–65535 | 0 | ● |
| P17.49 | Frequency set by A source | 0.00Hz–P00.03 | 0.00Hz | ● |
| P17.50 | Frequency set by B | 0.00Hz–P00.03 | 0.00Hz | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | source | | | |
| P17.51 | PID1 proportional output | -100.0%–100.0% | 0.00% | ● |
| P17.52 | PID1 integral output | -100.0%–100.0% | 0.00% | ● |
| P17.53 | PID1 differential output | -100.0%–100.0% | 0.00% | ● |
| P17.54 | Present proportional gain | 0.00–100.00% | 0.00% | ● |
| P17.55 | Present integral time | 0.00–10.00s | 0.00s | ● |
| P17.56 | Present differential time | 0.00–10.00s | 0.00s | ● |
| P17.57 | Actual steps of multi-step speed | 0–15 | 0 | ● |
| P17.58 | 100Hz component peak value (square waves quadrature) | 0.0–300.0V<br>**Note:** Peak-to-peak value of bus voltage fluctuation at 100Hz frequency component, which is detected by using a square-wave orthogonal function. | 0.0V | ● |
| P17.59 | 100Hz component peak value (sin quadrature) | 0.0–300.0V<br>Note: The peak-to-peak value of bus voltage fluctuation at 100Hz frequency component, is detected by using a sin-wave orthogonal function. | 0.0V | ● |
| P17.60 | Keypad analog voltage | 0.00–10.00 | 0.00 | ● |

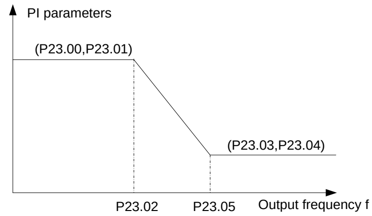
**Group P19—Expansion card status viewing**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P19.00 | Type of expansion card in slot 1 | 0–80<br>0: No card<br>1: Reserved<br>2: I/O card<br>3–4: Reserved<br>5: Ethernet<br>6: DP communication card | 0 | ● |
| P19.01 | Type of expansion card in slot 2 | | 0 | ● |
| P19.02 | Reserved | | - | - |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 7–8: Reserved<br>9: CANopen Communication card<br>10: Reserved<br>11: PROFINET communication card<br>12–14: Reserved<br>15: CAN master/slave communication card<br>16: Modbus TCP Communication card<br>17: Reserved<br>18: BACnet MSTP communication card<br>19–20: Reserved<br>21: Ethernet/IP communication card<br>22–24: Reserved<br>25: Water supply card<br>26–80: Reserved | | |
| P19.03 | Software version of expansion card in slot 1 | 0.00–655.35 | 0.00 | ● |
| P19.04 | Software version of expansion card in slot 2 | 0.00–655.35 | 0.00 | ● |
| P19.05 | Reserved | - | - | - |
| P19.06 | Terminal input status of I/O card | 0–0xFFFF | 0 | ● |
| P19.07 | Terminal output status of I/O card | 0–0xFFFF | 0 | ● |
| P19.08 | Reserved | - | - | - |
| P19.09 | AI3 input voltage of I/O card | 0.00–10.00V | 0.00V | ● |

**Group P23—Vector control of motor 2**

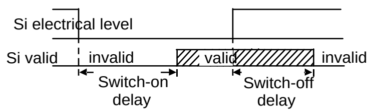
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P23.00 | Speed-loop proportional gain 1 | P23.00–P23.05 are applicable only to vector control mode. When switching frequency 1 (P23.02) is not reached, the speed-loop PI parameters are: P23.00 and P23.01. When switching frequency 2 (P23.05) is exceeded, the speed-loop PI parameters are: P23.03 | 20.0 | ○ |
| P23.01 | Speed-loop integral time 1 | | 0.200s | ○ |
| P23.02 | Low-point frequency for | | 5.00Hz | ○ |

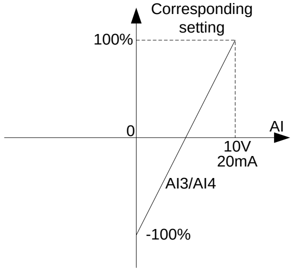
| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | switching | and P23.04. PI parameters are obtained | | |
| P23.03 | Speed-loop proportional gain 2 | according to the linear change of two groups of parameters. See the following figure: | 20.0 | ○ |
| P23.04 | Speed-loop integral time 2 |   | 0.200s | ○ |
| P23.05 | High-point frequency for switching | The speed loop dynamic response characteristics of vector control can be adjusted by setting the proportional coefficient and integral time of speed regulator. Increasing proportional gain or reducing integral time can accelerate dynamic response of speed loop; however, if the proportional gain is too large or integral time is too small, system oscillation and overshoot may occur; if proportional gain is too small, stable oscillation or speed offset may occur.<br>PI parameters have a close relationship with the inertia of the system. Adjust PI parameters depending on different loads to meet various demands.<br>Setting range of P23.00: 0.0–200.0<br>Setting range of P23.01: 0.000–10.000s<br>Setting range of P23.02: 0.00Hz –P23.05<br>Setting range of P23.03: 0.0–200.0<br>Setting range of P23.04: 0.000–10.000s<br>Setting range of P23.05: P23.02–P00.03 | 10.00Hz | ○ |
| P23.06 | Speed-loop output filter | 0–8 (corresponding to 0–$2^8$/10ms) | 0 | ○ |
| P23.07 | Electromotive slip compensation coefficient of vector control | Slip compensation coefficient is used to adjust the slip frequency of the vector control and improve the speed control accuracy of the system. Adjusting the parameter properly | 100% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P23.08 | Power-generation slip compensation coefficient of vector control | can control the speed steady-state error.<br>Setting range: 50–200% | 100% | ○ |
| P23.09 | Current-loop proportional coefficient P | **Note:**<br>✧ The two function codes impact the dynamic response speed and control accuracy of the system. Generally, you do not need to modify the two function codes.<br>✧ Applicable to SVC mode 0 (P00.00=0) only.<br>✧ The values of the two function codes are updated automatically after SM parameter autotuning is completed.<br>Setting range: 0–65535 | 1000 | ○ |
| P23.10 | Current-loop integral coefficient I | | 1000 | ○ |
| P23.11 | Speed-loop differential gain | 0.00–10.00s | 0.00s | ○ |
| P23.12 | Proportional coefficient of high-frequency current loop | In the vector control mode (P00.00=3), when the frequency is lower than the current-loop high-frequency switching threshold (P23.14), the current-loop PI parameters are P23.09 and P23.10; and when the frequency is higher than the current-loop high-frequency switching threshold, the current-loop PI parameters are P23.12 and P23.13.<br>Setting range of P23.12: 0–65535<br>Setting range of P23.13: 0–65535<br>Setting range of P23.14: 0.0–100.0% (of the max. frequency) | 1000 | ○ |
| P23.13 | Integral coefficient of high-frequency current loop | | 1000 | ○ |
| P23.14 | Current-loop high-frequency switching threshold | | 100.0% | ○ |

**Group P25—I/O card input functions**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P25.00 | HDI3 input type | 0–1<br>0: HDI3 is high-speed pulse input<br>1: HDI3 is digital input | 0 | ◎ |
| P25.01 | Function of S5 | Same as Group P05 | 0 | ◎ |
| P25.02 | Function of S6 | | 0 | ◎ |

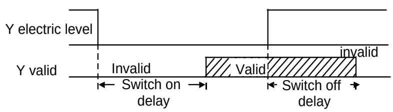
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td>P25.03</td><td>Function of S7</td><td rowspan="5"></td><td>0</td><td>◎</td></tr>
<tr><td>P25.04</td><td>Function of S8</td><td>0</td><td>◎</td></tr>
<tr><td>P25.05</td><td>Function of S9</td><td>0</td><td>◎</td></tr>
<tr><td>P25.06</td><td>Function of S10</td><td>0</td><td>◎</td></tr>
<tr><td>P25.07</td><td>Function of HDI3</td><td>0</td><td>◎</td></tr>
<tr><td>P25.08</td><td>Expansion card input terminal polarity</td><td>0x00–0x7F<br>When a bit is 0, the input terminal is positive.<br>when a bit is 1, the input terminal is negative.<table><tr><td>Bit0</td><td>Bit1</td><td>Bit2</td><td>Bit3</td><td>Bit4</td><td>Bit5</td><td>Bit6</td></tr><tr><td>S5</td><td>S6</td><td>S7</td><td>S8</td><td>S9</td><td>S10</td><td>HDI3</td></tr></table></td><td>0x00</td><td>○</td></tr>
<tr><td>P25.09</td><td>Expansion card virtual terminal setting</td><td>0x000–0x7F (0: disable; 1: enable)<table><tr><td>Bit0</td><td>Bit1</td><td>Bit2</td><td>Bit3</td><td>Bit4</td><td>Bit5</td><td>Bit6</td></tr><tr><td>S5</td><td>S6</td><td>S7</td><td>S8</td><td>S9</td><td>S10</td><td>HDI3</td></tr></table></td><td>0x00</td><td>◎</td></tr>
<tr><td>P25.10</td><td>HDI3 switch-on delay</td><td rowspan="14">These function codes specify the delay time corresponding to the electrical level changes when the programmable input terminals switch on or switch off.<br><br><br>Setting range: 0.000–50.000s</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.11</td><td>HDI3 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.12</td><td>S5 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.13</td><td>S5 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.14</td><td>S6 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.15</td><td>S6 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.16</td><td>S7 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.17</td><td>S7 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.18</td><td>S8 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.19</td><td>S8 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.20</td><td>S9 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.21</td><td>S9 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.22</td><td>S10 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.23</td><td>S10 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P25.24</td><td>AI3 lower limit</td><td rowspan="4">Used to define the relationship between the analog input voltage and its corresponding setting. When the analog input voltage exceeds the range from the upper limit to the lower limit, the upper limit or lower limit is used.</td><td>0.00V</td><td>○</td></tr>
<tr><td>P25.25</td><td>Corresponding setting of AI3 lower limit</td><td>0.0%</td><td>○</td></tr>
<tr><td>P25.26</td><td>AI3 upper limit</td><td>10.00V</td><td>○</td></tr>
<tr><td>P25.27</td><td>Corresponding</td><td>100.0%</td><td>○</td></tr>
</table>

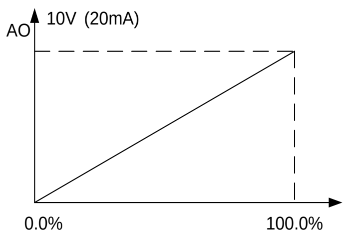
<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td></td><td>setting of AI3 upper limit</td><td rowspan="2">When the analog input is current input, 0mA–20mA current corresponds to 0V–10V voltage.<br>In different applications, 100.0% of the analog setting corresponds to different nominal values. See the descriptions of each application section for details.<br>The following figure illustrates the cases of several settings:<br><br><br>Input filter time: to adjust the sensitivity of analog input. Increasing the value properly can enhance analog input anti-interference but may reduce the sensitivity of analog input.<br>Note: AI3 can support 0–10V/0–20mA input. When AI3 selects 0–20mA input, the corresponding voltage of 20mA is 10V.<br>Setting range of P25.24: 0.00V–P25.26<br>Setting range of P25.25: -300.0% –300.0%<br>Setting range of P25.26: P25.24–10.00V<br>Setting range of P25.27: -300.0% –300.0%<br>Setting range of P25.28: 0.000s–10.000s</td><td></td><td></td></tr>
<tr><td>P25.28</td><td>AI3 input filter time</td><td>0.030s</td><td>○</td></tr>
<tr><td>P25.29</td><td>AI4 lower limit</td><td>0.00V–P25.31</td><td>0.00V</td><td>○</td></tr>
<tr><td>P25.30</td><td>Corresponding setting of AI4 lower limit</td><td>-300.0%–300.0%</td><td>0.0%</td><td>○</td></tr>
<tr><td>P25.31</td><td>AI4 upper limit</td><td>P25.29–10.00V</td><td>10.00V</td><td>○</td></tr>
<tr><td>P25.32</td><td>Corresponding setting of AI4 upper limit</td><td>-300.0%–300.0%</td><td>100.0%</td><td>○</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P25.33 | AI4 input filter time | 0.000–10.000s | 0.030s | ○ |
| P25.34 | HDI3 high-speed pulse input function selection | 0–1<br>0: Input set through frequency<br>1: Counting function | 0 | ◎ |
| P25.35 | HDI3 lower limit frequency | 0.000kHz–P25.37 | 0.000kHz | ○ |
| P25.36 | Corresponding setting of HDI3 lower limit frequency | -300.0%–300.0% | 0.0% | ○ |
| P25.37 | HDI3 upper limit frequency | P25.35–50.000kHz | 50.000 kHz | ○ |
| P25.38 | Corresponding setting of HDI3 upper limit frequency | -300.0%–300.0% | 100.0% | ○ |
| P25.39 | HDI3 frequency input filter time | 0.000–10.000s | 0.030s | ○ |
| P25.40 | AI3 input signal type | 0–1<br>0: Voltage<br>1: Current | 0 | ○ |
| P25.41 | AI4 input signal type | 0–1<br>0: Voltage<br>1: Current | 0 | ○ |

**Group P26—I/O card output functions**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P26.00 | HDO2 output type | 0–1<br>0: Open collector high-speed pulse output<br>1: Open collector output | 0 | ◎ |
| P26.01 | HDO2 output | Same as the description for P06.01 | 0 | ○ |
| P26.02 | Y2 output | | 0 | ○ |
| P26.03 | Y3 output | | 0 | ○ |
| P26.04 | RO3 output | | 0 | ○ |
| P26.05 | RO4 output | | 0 | ○ |
| P26.06 | RO5 output | | 0 | ○ |
| P26.07 | RO6 output | | 0 | ○ |

<table>
<tr><th>Function code</th><th>Name</th><th>Description</th><th>Default</th><th>Modify</th></tr>
<tr><td>P26.08</td><td>RO7 output</td><td rowspan="4"></td><td>0</td><td>○</td></tr>
<tr><td>P26.09</td><td>RO8 output</td><td>0</td><td>○</td></tr>
<tr><td>P26.10</td><td>RO9 output</td><td>0</td><td>○</td></tr>
<tr><td>P26.11</td><td>RO10 output</td><td>0</td><td>○</td></tr>
<tr><td>P26.12</td><td>Expansion card output terminal polarity</td><td>0x0000–0x1FFF<br>When a bit is 0, the output terminal is positive.<br>When a bit is 1, the output terminal is negative.<table><tr><td>Bit0</td><td>Bit1</td><td>Bit2</td><td>Bit3</td><td>Bit4</td><td>Bit5</td><td>Bit6</td></tr><tr><td>Y2</td><td>Y3</td><td>HDO2</td><td>RO3</td><td>RO4</td><td>RO5</td><td>RO6</td></tr><tr><td>Bit7</td><td>Bit8</td><td>Bit9</td><td>Bit10</td><td>Bit11</td><td>Bit12</td><td>-</td></tr><tr><td>RO7</td><td>RO8</td><td>RO9</td><td>RO10</td><td>RO11</td><td>RO12</td><td>-</td></tr></table></td><td>0x0000</td><td>○</td></tr>
<tr><td>P26.13</td><td>HDO2 switch-on delay</td><td rowspan="15">Used to specify the delay time corresponding to the electrical level changes when the programmable output terminals switch on or switch off.<br><br><br>Setting range: 0.000–50.000s</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.14</td><td>HDO2 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.15</td><td>Y2 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.16</td><td>Y2 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.17</td><td>Y3 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.18</td><td>Y3 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.19</td><td>RO3 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.20</td><td>RO3 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.21</td><td>RO4 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.22</td><td>RO4 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.23</td><td>RO5 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.24</td><td>RO5 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.25</td><td>RO6 switch-on delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.26</td><td>RO6 switch-off delay</td><td>0.000s</td><td>○</td></tr>
<tr><td>P26.27</td><td>RO7 switch-on</td><td>0.000s</td><td>○</td></tr>
</table>

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | delay | | | |
| P26.28 | RO7 switch-off delay | | 0.000s | ○ |
| P26.29 | RO8 switch-on delay | | 0.000s | ○ |
| P26.30 | RO8 switch-off delay | | 0.000s | ○ |
| P26.31 | RO9 switch-on delay | | 0.000s | ○ |
| P26.32 | RO9 switch-off delay | | 0.000s | ○ |
| P26.33 | RO10 switch-on delay | | 0.000s | ○ |
| P26.34 | RO10 switch-off delay | | 0.000s | ○ |
| P26.35 | AO2 output | Same as the description for P06.14 | 0 | ○ |
| P26.36 | AO3 output | | 0 | ○ |
| P26.37 | Reserved | | - | - |
| P26.38 | AO2 output lower limit | The function codes define the relationship between the output value and analog output. When the output value exceeds the allowed range, the output uses the lower limit or upper limit.<br>When the analog output is current output, 1mA equals 0.5V.<br>In different cases, the corresponding analog output of 100% of the output value is different.<br><br><br>Setting range of P26.38: -300.0%–P26.40<br>Setting range of P26.39: 0.00V–10.00V<br>Setting range of P26.40: P26.38–100.0%<br>Setting range of P26.41: 0.00V–10.00V | 0.0% | ○ |
| P26.39 | AO2 output corresponding to lower limit | | 0.00V | ○ |
| P26.40 | AO2 output upper limit | | 100.0% | ○ |
| P26.41 | AO2 output corresponding to upper limit | | 10.00V | ○ |
| P26.42 | AO2 output filter time | | 0.000s | ○ |
| P26.43 | AO3 output lower limit | | 0.0% | ○ |
| P26.44 | AO3 output corresponding to lower limit | | 0.00V | ○ |
| P26.45 | AO3 output upper limit | | 100.0% | ○ |
| P26.46 | AO3 output | | 10.00V | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | corresponding to upper limit | Setting range of P26.42: 0.000s–10.000s<br>Setting range of P26.43: -300.0%–P26.45<br>Setting range of P26.44: 0.00V–10.00V<br>Setting range of P26.45: P26.43–300.0%<br>Setting range of P26.46: 0.00V–10.00V<br>Setting range of P26.47: 0.000s–10.000s | | |
| P26.47 | AO3 output filter time | | 0.000s | ○ |

**Group P28—Master/slave control**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P28.00 | Master/slave mode | 0: Master/slave control is invalid.<br>1: The local device is the master.<br>2: The local device is the slave. | 0 | ◎ |
| P28.01 | Master/slave communication data selection | 0: CAN<br>1: Reserved | 0 | ◎ |
| P28.02 | Master/slave control mode | 0x000–0x112<br>Ones place: Master/slave running mode<br>0: Master/slave mode 0<br>The master and slave use speed control, with power balanced through droop control.<br>1: Master/slave mode 1<br>The master and slave must be in the same type of vector control. When the master is in speed control, the slave is forced into torque control.<br>2: Master/slave mode 2<br>The slave switches from speed mode (master/slave mode 0) to torque mode (master/slave mode 1) at a frequency point.<br>Tens place: Slave start command source<br>0: Master<br>1: Determined by P00.01<br>Hundreds place: Whether to enable master/slave to send/receive data<br>0: Enable<br>1: Disable | 0x001 | ◎ |
| P28.03 | Slave speed gain | 0.0–500.0% | 100.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P28.04 | Slave torque gain | 0.0–500.0% | 100.0% | ○ |
| P28.05 | Frequency point for switching between speed mode and torque mode | 0.00–10.00Hz<br>**Note:** Valid in master-slave mode 2. | 5.00Hz | ○ |
| P28.06 | Number of slaves | 0–15 | 1 | ◎ |

**Group P89—HVAC status viewing**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P89.00 | HVAC function status | 0: Invalid<br>1: Valid | 0 | ● |
| P89.01 | Variable-frequency motor run sequence | 1–8<br>The sequences 1–8 correspond to motors A–F. For fixed variable-frequency motors, the value is 255. | 1 | ● |
| P89.02 | Multi-motor validity status | 0x00–0xFF<br>Bit 0–Bit 7 correspond to motor A–motor H.<br>0: The corresponding motor is invalid and cannot be put into service.<br>1: The corresponding motor is valid and can be put into service. | 0x00 | ● |
| P89.03 | Power-frequency motor run status | 0x00–0xFF<br>Bit 0–Bit 7 correspond to motor A–motor H.<br>0: The corresponding motor stops.<br>1: The corresponding motor is running. | 0x00 | ● |
| P89.04 | SN of power-frequency motor to be polled | 1–8 | 1 | ● |
| P89.05 | Left time of power-frequency motor to be polled | 0.00–600.00h | 0.00h | ● |
| P89.06 | SN of variable-frequency motor to be polled | 1–8 | 1 | ● |
| P89.07 | Left time of variable-frequency motor to be polled | 0.00–600.00h | 0.00h | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P89.08 | PID1 status | Bit0: Stop<br>Bit1: Pause<br>Bit2: Deviation deadzone<br>Bit3: Polarity reversal | 0x0 | ● |
| P89.09 | Present reference value of PID1 | -100.0%–100.0% | 0.0% | ● |
| P89.10 | PID1 feedback value | -100.0%–100.0% | 0.0% | ● |
| P89.11 | PID1 deviation input | -100.0%–100.0% | 0.0% | ● |
| P89.12 | Proportional output value of PID1 | -1000.0%–1000.0% | 0.0% | ● |
| P89.13 | Integral output value of PID1 | -100.00%–100.00% | 0.00% | ● |
| P89.14 | PID1 differential output | -1000.0%–1000.0% | 0.0% | ● |
| P89.15 | Comprehensive output of PID1 | -100.00%–100.00% | 0.00% | ● |
| P89.16 | PID2 status | Bit0: Stop<br>Bit1: Pause<br>Bit2: Deviation deadzone<br>Bit3: Polarity reversal | 0x0 | ● |
| P89.17 | Present reference value of PID2 | -100.0%–100.0% | 0.0% | ● |
| P89.18 | PID2 feedback value | -100.0%–100.0% | 0.0% | ● |
| P89.19 | PID2 deviation input | -100.0%–100.0% | 0.0% | ● |
| P89.20 | Proportional output value of PID2 | -1000.0%–1000.0% | 0.0% | ● |
| P89.21 | Integral output value of PID2 | -100.00%–100.00% | 0.00% | ● |
| P89.22 | PID2 differential output | -1000.0%–1000.0% | 0.0% | ● |
| P89.23 | Comprehensive output of PID2 | -100.0%–100.0% | 0.0% | ● |
| P89.24 | Accumulative run | 0–65535h | 0h | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | time of motor A | | | |
| P89.25 | Accumulative run time of motor B | 0–65535h | 0h | ● |
| P89.26 | Accumulative run time of motor C | 0–65535h | 0h | ● |
| P89.27 | Accumulative run time of motor D | 0–65535h | 0h | ● |
| P89.28 | Accumulative run time of motor E | 0–65535h | 0h | ● |
| P89.29 | Accumulative run time of motor F | 0–65535h | 0h | ● |
| P89.30 | Accumulative run time of motor G | 0–65535h | 0h | ● |
| P89.31 | Accumulative run time of motor H | 0–65535h | 0h | ● |
| P89.32 | AI/AO measured temperature | -20.0–200.0℃ | 0℃ | ● |

**Group P90—PID1 control**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P90.00 | Unit selection | 0–21<br>0: MPa<br>1: kPa<br>2: Pa<br>3: A<br>4: V<br>5: %<br>6: m/s<br>7: m/min<br>8: m/h<br>9: $m^3$/s<br>10: $m^3$/min<br>11: $m^3$/h<br>12: kg/s<br>13: kg/min<br>14: kg/h<br>15: °C | 0 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 16: °F<br>17: bar<br>18: mbar<br>19: L/s<br>20: L/min<br>21: L/h | | |
| P90.01 | Number of decimal places | 0–3 | 2 | ◎ |
| P90.02 | PID1 given max. value | 0.00–30.00<br>It is displayed with two decimal places by default. If P90.01 is changed, the number of decimal places changes. | 10.00 | ○ |
| P90.03 | PID1 reference upper limit | P90.04–P90.02 | 10.00 | ○ |
| P90.04 | PID1 reference lower limit | 0.00–P90.03 | 0.00 | ○ |
| P90.05 | ACC/DEC time of PID1 reference value | 0.0–1000.0s | 0.0s | ○ |
| P90.06 | PID1 reference source 1 | 0–6<br>0: Keypad (P90.07)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: HDIA<br>5: Reserved<br>6: Communication card | 0 | ○ |
| P90.07 | PID1 reference value 1 through keypad | P90.04–P90.03 | 0.100 | ○ |
| P90.08 | PID1 feedback source 1 | 0–6<br>0: Keypad (P90.09)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: HDIA<br>5: Reserved<br>6: Communication card | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P90.09 | PID1 feedback value 1 through keypad | P90.04–P90.03 | 0.100 | ○ |
| P90.10 | Gain of PID1 feedback source 1 | 0.000–3.000 | 1.000 | ○ |
| P90.11 | PID1 reference source 2 | 0–6<br>0: Keypad (P90.12)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: HDIA<br>5: Reserved<br>6: Communication card | 0 | ○ |
| P90.12 | PID1 reference value 2 through keypad | P90.04–P90.03 | 0.100 | ○ |
| P90.13 | PID1 feedback source 2 | 0–6<br>0: Keypad (P90.14)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: HDIA<br>5: Reserved<br>6: Communication card | 0 | ○ |
| P90.14 | PID1 feedback value 2 through keypad | P90.04–P90.03 | 0.100 | ○ |
| P90.15 | Gain of PID1 feedback source 2 | 0.000–3.000 | 1.000 | ○ |
| P90.16 | Feedback function combination | 0–7<br>0: No combination, feedback source 1<br>1: Sum of feedback sources 1 and 2<br>1: Difference between feedback sources 1 and 2<br>3: Average of feedback sources 1 and 2<br>4: Minimum of feedback sources 1 and 2<br>5: Maximum of feedback sources 1 and 2<br>6: Min. positive difference or max. negative | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | difference among multiple reference values<br>When calculating the difference between reference source 1 and feedback source 1 and the difference between reference source 2 and feedback source 2, give priority to the condition in which the feedback is greater than the reference.<br>If there are some feedback values that are greater than the reference values, select the group with the max. negative difference as the PID reference and feedback. If all feedback values are less than the reference values, select the group with the min. positive difference as the PID reference and feedback.<br>7: Max. positive difference or min. negative difference among multiple reference values<br>When calculating the difference between reference source 1 and feedback source 1 and the difference between reference source 2 and feedback source 2, give priority to the condition in which the feedback is less than the reference.<br>If there are some feedback values that are less than the reference values, select the group with the max. positive difference as the PID reference and feedback. If all feedback values are greater than the reference values, select the group with the min. negative difference as the PID reference and feedback. | | |
| P90.17 | Feedback upper limit detection value | 0–100.0% | 100.0% | ○ |
| P90.18 | Feedback lower limit detection value | 0–100.0% | 0.0% | ○ |
| P90.19 | Feedback out-of-range detection time | 0.0–3600.0s | 1.0s | ○ |
| P90.20 | PID1 feedback filter time | 0.000–60.000s | 0.000s | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P90.21 | PID1 deviation input limit value | 0.0–100.0% | 100.0% | ○ |
| P90.22 | Output characteristics selection | 0: PID output is positive.<br>1: PID output is negative. | 0 | ○ |
| P90.23 | PID1 output gain | 0.000–3.000 | 1.000 | ○ |
| P90.24 | PID1 output filter time | 0.000–60.000s | 0.100s | ○ |
| P90.25 | PID1 output upper limit | P90.26–100.0% | 100.0% | ○ |
| P90.26 | PID1 output lower limit | -100.0%–P90.25 | 0.0% | ○ |
| P90.27 | Proportional gain | 0.000–60.000 | 1.000 | ○ |
| P90.28 | Integral time | 0.000–60.000s | 5.000s | ○ |
| P90.29 | Differential time | 0.000–60.000s | 0.000s | ○ |
| P90.30 | Sampling period | 0.001–60.000s | 0.100s | ○ |
| P90.31 | PID1 control deadzone | 0.0–100.0% | 0.0% | ◎ |
| P90.32 | Deadzone delay | 0.0–300.0s<br>The PID suspends the regulation when the PID input deviation is kept for the deadzone retaining delay time. | 1.0s | ● |
| P90.33 | Integral separation threshold | 0.0–100.0% | 100.0% | ○ |
| P90.34 | Differential filter times | 0–40 | 10 | ○ |
| P90.35 | Prior differential processing | 0: Perform differential processing on feedback with priority<br>1: Perform differential processing on deviation with priority | 0 | ○ |

**Group P91—PID2 control**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P91.00 | Unit selection | 0–21<br>0: MPa<br>1: kPa<br>2: Pa | 0 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 3: A<br>4: V<br>5: %<br>6: m/s<br>7: m/min<br>8: m/h<br>9: $m^3$/s<br>10: $m^3$/min<br>11: $m^3$/h<br>12: kg/s<br>13: kg/min<br>14: kg/h<br>15: °C<br>16:°F<br>17: bar<br>18: mbar<br>19: L/s<br>20: L/min<br>21: L/h | | |
| P91.01 | Number of decimal places | 0–3 | 2 | ◎ |
| P91.02 | PID2 given max. value | 0.00–30.00<br>It is displayed with two decimal places by default. If P90.01 is changed, the number of decimal places changes. | 10.00 | ○ |
| P91.03 | PID2 reference upper limit | P91.04–P91.02 | 10.00 | ○ |
| P91.04 | PID2 reference lower limit | 0.000–P91.03 | 0 | ○ |
| P91.05 | ACC/DEC time of PID2 reference value | 0.0–1000.0s | 0.0s | ○ |
| P91.06 | PID2 reference source 1 | 0: Keypad (P91.07)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: HDIA<br>5: Reserved | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 6: Communication card | | |
| P91.07 | PID2 reference value 1 through keypad | P91.04–P91.03 | 0.100 | ○ |
| P91.08 | PID2 feedback source 1 | 0: Keypad (P91.09)<br>1: AI1<br>2: AI2<br>3: AI3<br>4: HDIA<br>5: Reserved<br>6: Communication card | 0 | ○ |
| P91.09 | PID2 feedback value 1 through keypad | P91.04–P91.03 | 0.100 | ○ |
| P91.10 | Gain of PID2 feedback source 1 | 0.000–3.000 | 1.000 | ○ |
| P91.11 | PID2 startup feedback value | 0.00–P91.02<br>It is displayed with two decimal places by default. If P90.01 is changed, the number of decimal places changes.<br>When P91.15 is set to 1 or the enabling terminal is valid, if the output is positive, the feedback is less than the value of this function code; if the output is negative, the feedback is greater than the value of this function code. After the situation lasts for the time specified by P91.12, PID2 automatically starts. | 10.00 | ○ |
| P91.12 | PID2 startup delay | 0.0–300.0s | 1.0s | ○ |
| P91.13 | PID2 stop feedback value | 0.00–P91.02<br>It is displayed with two decimal places by default. If P90.01 is changed, the number of decimal places changes. | 10.00 | ○ |
| P91.14 | PID2 stop delay | 0.0–300.0s | 1.0s | ○ |
| P91.15 | Enabling PID2 | 0: Invalid<br>1: Valid | 0 | ○ |
| P91.16 | Reserved | - | - | - |
| P91.17 | Feedback upper limit detection | 0–100.0% | 100.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | value | | | |
| P91.18 | Feedback lower limit detection value | 0–100.0% | 0.0% | ○ |
| P91.19 | Feedback out-of-range detection time | 0.0–3600.0s | 1.0s | ○ |
| P91.20 | PID2 feedback filter time | 0.000–60.000s | 0.000s | ○ |
| P91.21 | PID2 deviation input limit value | 0.0–100.0% | 100.0% | ○ |
| P91.22 | Output characteristics selection | 0: PID output is positive.<br>1: PID output is negative. | 0 | ○ |
| P91.23 | PID2 output gain | 0.000–3.000 | 1.000 | ○ |
| P91.24 | PID2 output filter time | 0.000–60.000s | 0.000s | ○ |
| P91.25 | PID2 output upper limit | P91.26–100.0% | 100.0% | ○ |
| P91.26 | PID2 output lower limit | -100.0–P91.25 | 0.0% | ○ |
| P91.27 | Proportional gain | 0.000–60.000 | 1.000 | ○ |
| P91.28 | Integral time | 0.000–60.000s | 5.000s | ○ |
| P91.29 | Differential time | 0.000–60.000s | 0.000s | ○ |
| P91.30 | Sampling period | 0.001–60.000s | 0.100s | ○ |
| P91.31 | PID2 control deadzone | 0.0–100.0% | 0.0% | ◎ |
| P91.32 | Deadzone delay | 0.0–300.0s<br>The PID suspends the regulation when the PID input deviation is kept for the deadzone retaining delay time. | 1.0s | ○ |
| P91.33 | Integral separation threshold | 0.0–200.0% | 200.0% | ○ |
| P91.34 | Differential filter times | 0–40 | 10 | ○ |
| P91.35 | Prior differential processing | 0: Perform differential processing on feedback with priority | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 1: Perform differential processing on deviation with priority | | |

**Group P92—Real-time clock and timer (available at use of LCD keypad)**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P92.00 | Displaying year | 2020–2099 YY | 2020 YY | ● |
| P92.01 | Displaying month and date | 01.01–12.31 MMDD | 01.01 MMDD | ● |
| P92.02 | Displaying day of a week | 1–7 (Corresponding to Monday through Sunday) | 1 | ● |
| P92.03 | Displaying hour and minute | 00.00–23.59 HHMM<br>00.00 is the earliest hour and time of a day, while 23.59 is the latest hour and time of a day. | 00.00 HHMM | ● |
| P92.04 | Setting working days | Bit 0–bit 6 correspond to Monday–Sunday.<br>Setting instances:<br>Monday: 0x01<br>Wednesday: 0x04<br>From Monday to Friday: 0x1F<br>From Saturday to Sunday: 0x60 | 0 | ○ |
| P92.05 | VFD startup hour and minute | 00.00–23.59 HH.MM | 00.00 HH.MM | ○ |
| P92.06 | VFD startup second | 0–59s | 0s | ○ |
| P92.07 | VFD stop hour and minute | 00.00–23.59 HH.MM | 00.00 HH.MM | ○ |
| P92.08 | VFD stop second | 0–59s | 0s | ○ |
| P92.09 | Clock fault | 0: Disable<br>1: Enable | 0 | ○ |
| P92.10 | Actual second | 0–59s | 0s | ● |

**Group P93—Fire control**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P93.00 | Fire mode | 0–2<br>0: Invalid | 0 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 1: Fire mode 1<br>2: Fire mode 2<br>When P93.00=0, the fire mode is invalid, the VFD runs in normal mode and it stops if suffering a fault. When P93.00 is a non-zero value and the fire signal is activated, the fire mode is valid, and the VFD runs at the speed specified by P93.01.<br>If fire mode 1 is selected, the VFD always runs except it is damaged. If fire mode 2 is selected, the VFD always runs except it stops upon the following faults: OUT1, OUT2, OUT3, OC1, OC2, OC3, OV1, OV2, OV3, and SPO. | | |
| P93.01 | Running frequency in fire mode | 0.00Hz–P00.03 (Max. output frequency) | 50.00Hz | ○ |
| P93.02 | Motor running direction in fire mode | 0: Run at the default direction.<br>1: Run at the opposite direction. | 0 | ○ |
| P93.03 | Fire mode flag | 0–1<br>If the fire mode duration reaches 5 minutes, this flag is set to 1, and no warranty repair is granted. | 0 | ● |
| P93.04 | Actual month and date when fire activated | 01.01–12.31 | 00.00 | ● |
| P93.05 | Actual time when fire activated | 00.00–23.59 | 00.00 | ● |
| P93.06–P93.09 | Reserved | - | - | - |

**Group P94—Multi-pump and fan control functions**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P94.00 | Multi-pump and fan control function enabling | 0–1<br>0: Invalid<br>1: Valid | 0 | ◎ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P94.01 | Sleep method selection | 0–2<br>0:Sleep according to terminal input<br>1:Sleep according to run frequency<br>2:Sleep according to deviation | 0 | ○ |
| P94.02 | Sleep start frequency | P00.05–P00.04 (Upper limit frequency)<br>When the running frequency is less than or equal to the value and this situation lasts the time longer than P94.04, sleep is allowed. | 5.00Hz | ○ |
| P94.03 | Sleep starting deviation | 0.0–30.0% (relative to PID1 max. value)<br>When output is positive, if the feedback is greater than the reference, sleep is allowed only when the absolute difference is greater than the value of this function code and the situation lasts the time longer than P94.04.<br>When output is negative, if the feedback is less than the reference, sleep is allowed only when the absolute difference is greater than the value of this function code and this situation lasts the time longer than P94.04. | 5.0% | ○ |
| P94.04 | Sleep delay | P94.49–3600.0s | 60.0s | ○ |
| P94.05 | PID1 reference boost value | -100.0–100.0% (relative to the reference value of PID1) | 10.0% | ○ |
| P94.06 | Longest boost time | 0.0–6000.0s<br>This function is used for continuous VFD running when the running frequency reaches the upper limit frequency but the feedback value cannot reach the setting after boost. In this situation, the VFD enters the sleep mode at once after the boost time. | 10.0s | ○ |
| P94.07 | Sleep wakeup frequency | P00.05–P00.04 (Upper limit frequency)<br>In closed-loop PID, the PID output is superimposed directly from the corresponding value of this frequency when the VFD is woken up. | 5.00Hz | ○ |
| P94.08 | Wake-up-from-sleep deviation | 0.0–30.0% (relative to PID1 max. value)<br>In closed-loop PID, when output is positive, if the feedback is less than the reference, wakeup is allowed only when the actual | 5.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | difference is greater than the value of this function code and this situation lasts the time longer than P94.09.<br>When output is negative, if the feedback is greater than the reference, wakeup is allowed only when the actual difference is greater than the value of this function code and this situation lasts the time longer than P94.09. | | |
| P94.09 | Wake-up-from-sleep delay | 0.0–3600.0s<br>Min. sleep time | 5.0s | ○ |
| P94.10 | Variable-frequency motor run mode | 0: Fixed<br>Motor A is a variable-frequency motor. The other motors are power-frequency motors. When a fixed VF motor is selected, if motors A to D are set as VF motors, this setting becomes invalid. If multiple motors are used, the corresponding motors can only be set as power frequency motors. At this time, the GD270 can form a system with a maximum of 1 fixed VF motor and 4 power frequency motors.<br>1: Circular<br>According to the wiring method in the appendix, use the relays and motors with the same quantity to achieve cyclic power/variable frequency switchover.<br>When set as a cyclic VF motor, at least two of the motors A to D must be set as VF motors. In this case, the GD270 can form a system with a maximum of 4 VF motors. | 1 | ◎ |
| P94.11 | Total number of motors | 0–8, corresponding to motors A–H. The sequence numbers must be successive. | 1 | ◎ |
| P94.12–P94.18 | Reserved | - | - | - |
| P94.19 | Pressure tolerance for motor adding | 0.0–30.0% (relative to PID1 max. value) | 5.0% | ○ |
| P94.20 | Running frequency for motor adding | P94.25 (Running frequency for motor reducing)–P00.03 | 50.00Hz | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P94.21 | Motor adding delay | 0.0–3600.0s | 10.0s | ○ |
| P94.22 | Switching frequency for variable-frequency motor adding | P00.05 (Lower limit frequency)–P00.03 | 50.00Hz | ○ |
| P94.23 | Variable-frequency motor DEC time for power-frequency motor adding | 0.0–300.0s | 10.0s | ○ |
| P94.24 | Pressure tolerance for motor reducing | 0.0–30.0% (relative to PID1 max. value) | 4.0% | ○ |
| P94.25 | Running frequency for motor reducing | P00.05–P94.20 (Running frequency for motor adding) | 5.00Hz | ○ |
| P94.26 | Motor reducing delay | 0.0–3600.0s | 10.0s | ○ |
| P94.27 | Variable-frequency motor action for motor reducing | 0: Keep the frequency unchanged<br>1: Accelerate to the motor running frequency | 1 | ○ |
| P94.28 | Variable-frequency motor ACC time for motor reducing | 0.0–300.0s | 10.0s | ○ |
| P94.29 | Multi-motor pressure loss compensation | 0: No<br>1: Yes | 0 | ○ |
| P94.30 | Pressure reference boost value for one auxiliary motor | 0.0–100.0% (relative to PID1 reference value) | 5.0% | ○ |
| P94.31 | Pressure reference boost value for two auxiliary motors | 0.0–100.0% (relative to PID1 reference value) | 10.0% | ○ |
| P94.32 | Pressure reference boost value for three auxiliary motors | 0.0–100.0% (relative to PID1 reference value) | 15.0% | ○ |
| P94.33 | Reserved | - | - | - |
| P94.34 | Motor alternation cycle | 0.0–6000.0h<br>Automatic alternation is targeted at idle variable-frequency motors. The value 0 | 0.0h | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | indicates no alternation. | | |
| P94.35 | Alternation frequency threshold | P00.05–P00.03<br>When the running frequency is greater than the value of this function code, variable-frequency motor polling is not performed. Otherwise, great water pressure change impacts water supply. | 45.00Hz | ○ |
| P94.36 | Contactor closing delay | 0.2–100.0s<br>The delay starts after the contactor closing command is given. The VFD startup command is given after the delay since actual contactor closing also takes some time. | 0.5s | ○ |
| P94.37 | Contactor opening delay | 0.2–100.0s<br>Some time is taken from giving the contactor opening command to actual contactor opening. After the delay, the VFD controls the motor to switch to power frequency. | 0.5s | ○ |
| P94.38 | Manual soft startup switching frequency | 0.00Hz–P00.03<br>Used to check whether a motor can run properly. | 50.00Hz | ○ |
| P94.39 | Water level signal input selection of inlet pool | 0: None<br>1: Digital<br>2: AI1<br>3: AI2<br>4: AI3<br>5: HDIA<br>6: Reserved<br>7: Communication card | 0 | ○ |
| P94.40 | Water level upper limit of inlet pool | 0.0–100.0% | 60.0% | ○ |
| P94.41 | Water level lower limit of inlet pool | 0.0%–P94.40 | 40.0% | ○ |
| P94.42 | Water shortage level of inlet pool | 0.0%–P94.41 | 20.0% | ○ |
| P94.43 | Backup pressure upon exceptions | 0.0–100.0% (relative to PID1 max. value) | 0.0% | ○ |
| P94.44 | Protection value for PID1 feedback too | 0.0–100.0% (relative to PID1 max. value) | 10.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | low | | | |
| P94.45 | Delay of PID1 feedback too low | 0.0–3600.0s<br>Corresponding terminal output that is set when PID1 feedback value is less than P94.44 and this situation lasts the time longer than P94.45. | 500.0s | ○ |
| P94.46 | Protection value for PID1 feedback too high | 0.0–100.0% (relative to PID1 max. value) | 80.0% | ○ |
| P94.47 | Delay of PID1 feedback too high | 0.0–3600.0s<br>Corresponding terminal output that is set when PID1 feedback value is greater than P94.46 and this situation lasts the time longer than P94.47. | 500.0s | ○ |
| P94.48 | DEC time of emergency stop | 0.0–600.0s | 2.0s | ○ |
| P94.49 | ACC time with water pump frequency | 0.0s–P94.04 | Model depended (2.0s) | ○ |
| P94.50 | DEC time with water pump frequency | 0.0s–P94.04 | Model depended (2.0s) | ○ |

**Group P95—Multi-section water pressure function (LCD keypad required)**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P95.00 | Actual time | 00.00–23.59<br>Set the clock date and time in group P92. | 00.00 | ● |
| P95.01 | Number of pressure segments | 0–8 (0 indicates that this function is disabled.) | 0 | ○ |
| P95.02 | Start time of T1 | After the Tx moment, the water pressure will become the pressure of the Tx period. The water pressure before T1 is set to 0.<br>You need to set the end time segment. The segment selection in P95.01 indicates the number of valid segments. Settings beyond the selected segments will be invalid.<br>If the start time of Tx is later than the start | 00.00 | ○ |
| P95.03 | Pressure at T1 | | 0.0% | ○ |
| P95.04 | Start time of T2 | | 23.00 | ○ |
| P95.05 | Pressure at T2 | | 0.0% | ○ |
| P95.06 | Start time of T3 | | 23.00 | ○ |
| P95.07 | Pressure at T3 | | 0.0% | ○ |
| P95.08 | Start time of T4 | | 23.00 | ○ |
| P95.09 | Pressure at T4 | | 0.0% | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P95.10 | Start time of T5 | time of T(x+1), T(x+1) automatically changes to Tx.<br>Start time range of Tx: 00.00–23.59<br>Pressure range of Tx period: 0.0–100.0% | 23.00 | ○ |
| P95.11 | Pressure at T5 | | 0.0% | ○ |
| P95.12 | Start time of T6 | | 23.00 | ○ |
| P95.13 | Pressure at T6 | | 0.0% | ○ |
| P95.14 | Start time of T7 | | 23.00 | ○ |
| P95.15 | Pressure at T7 | | 0.0% | ○ |
| P95.16 | Start time of T8 | | 23.59 | ○ |
| P95.17 | Pressure at T8 | | 0.0% | ○ |

**Group P96—Multi-pump and fan protection function**

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.00 | Action upon water pipe break | 0–1<br>0: Disable<br>1: Report a fault | 0 | ○ |
| P96.01 | Detection level of water pipe break | After water pipe break, the VFD running frequency boosts up to the upper limit or the PID output upper limit frequency. When it is set to 0, the water pipe break detection function is invalid.<br>Range: 0.0–100.0% | 10.0% | ○ |
| P96.02 | Detection time of water pipe break | Used to check the detection time of water pipe break.<br>Range: 0.0–6000.0s | 120.0s | ○ |
| P96.03 | Water pipe soft padding function | 0: Disable<br>1: Enable | 0 | ○ |
| P96.04 | Reference frequency for soft padding | 0.00Hz–P00.03 | 30.00Hz | ○ |
| P96.05 | Duration of reference frequency for soft padding | 0.0–6000.0s | 10.0s | ○ |
| P96.06 | Soft padding cutoff detection level | The PID function is valid when the feedback value is greater than the value of this function code.<br>Range: 0.0–100.0% | 30.0% | ○ |
| P96.07– | Reserved | - | - | - |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.09 | | | | |
| P96.10 | Enabling freezing protection | 0–1<br>0: Disable<br>1: Enable<br>Freezing protection: The freezing protection signal is activated when the detected temperature is lower than the protection threshold; this signal is ignored if the VFD is running.<br>If the run command is received after the protection has been activated, the protection is terminated and the run command is executed.<br>If a stop command is received after the protection has been activated, the motor is stopped and automatic protection is disabled. Automatic protection can be enabled only when the temperature is higher than the protection threshold. | 0 | ○ |
| P96.11 | Temperature sensor type | 0–6<br>0: Invalid<br>1: PT100<br>2: PT1000<br>3: KTY84<br>4: PTC (AO+AI terminal combination)<br>5: PTC (AI1+10V terminal combination)<br>6: PTC (AI2+10V terminal combination)<br>Usage of functions 1–4: To select current-type output for AO, connect one end of the temperature resistor to AI1 (voltage-type) and AO1 (current-type), and the other end to GND.<br>Usage of functions 5–6: Connect the PTC sensor between the +10V terminal and AI1 or AI2. | 0 | ○ |
| P96.12 | Freezing protection threshold | -20.0–20.0°C | -5.0°C | ○ |
| P96.13 | Low temperature | -20.0–20.0°C | 0.0°C | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | pre-alarm threshold | When the temperature is lower than the value of this function code, the pre-alarm terminal outputs a signal. | | |
| P96.14 | Freezing protection frequency | 0.00–45.00 | 0.00Hz | ○ |
| P96.15 | Current of triggering condensation protection | 0.0–100.0%<br>When an external terminal triggers the condensation protection signal, the VFD transfers DC current and stops the transfer if the duration reaches 40s. The condensation protection signal needs to be triggered again. | 30.0% | ○ |
| P96.16–P96.19 | Reserved | - | - | - |
| P96.20 | Forward run frequency for pump cleaning | 0.00Hz–P00.04 | 50.00Hz | ○ |
| P96.21 | Reverse run frequency for pump cleaning | 0.00Hz–P00.04 | 50.00Hz | ○ |
| P96.22 | Forward run ACC time for pump cleaning | 0.0–3600.0s | 5.0s | ○ |
| P96.23 | Reverse run ACC time for pump cleaning | 0.0–3600.0s | 5.0s | ○ |
| P96.24 | Forward run duration for pump cleaning | 0.0–3600.0s | 5.0s | ○ |
| P96.25 | Reverse run duration for pump cleaning | 0.0–3600.0s | 5.0s | ○ |
| P96.26 | Forward/reverse run interval for pump cleaning | 0.0–3600.0s | 1.0s | ○ |
| P96.27 | Number of pump cleaning cycles | 1–1000 | 1 | ○ |
| P96.28 | Motor stalling function selection | 0–2<br>0: Disable | 0 | ○ |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| | | 1: Pre-alarm<br>2: Faulty<br>Prerequisite for selecting the function: The VFD exceeds the stalling current limit, the output frequency is lower than the stalling frequency upper limit, and the duration of this situation exceeds the stalling time. | | |
| P96.29 | Stalling current limit | 0.0–300.0% (100.0% corresponds to the motor rated current.) | 200.0% | ○ |
| P96.30 | Stalling frequency upper limit | 0.00Hz–P00.04<br>**Note:** It cannot be lower than 10Hz. | 15.00Hz | ○ |
| P96.31 | Stalling detection time | 0.0–3600.0s | 2.0s | ○ |
| P96.32 | Motor dry pumping function selection | 0–2<br>0: Disable<br>1: Pre-alarm<br>2: Faulty | 0 | ○ |
| P96.33 | Current limit for motor dry pumping | 0.0–100.0% (100.0% corresponds to the motor rated current.) | 0.0% | ○ |
| P96.34 | Detection time for motor dry pumping | 0.0–3600.0s | 2.0s | ○ |
| P96.35 | Motor overtemperature protection threshold | -20.0–200.0 | 110.0 | ○ |
| P96.36 | AI/AO detected temperature offset value | -40.0–40.0 | 0.0 | ○ |
| P96.37 | PTC constant output current setting | 0.000–20.000mA | 4.000mA | ○ |
| P96.38 | PTC resistance alarm threshold | 0–60000Ω | 750Ω | ○ |
| P96.39 | PTC resistance alarm recovery threshold | 0–60000Ω | 150Ω | ○ |
| P96.40 | Actual PTC resistance | 0–60000Ω | 0Ω | ● |

| Function code | Name | Description | Default | Modify |
|---|---|---|---|---|
| P96.41 | PTC AI1 temperature compensation coefficient | 0–100 | 50 | ○ |
| P96.42 | PTC AI2 temperature compensation coefficient | 0–100 | 50 | ○ |

# 7 Troubleshooting

## 7.1 What this chapter contains

The chapter tells you how to reset faults and check faults history. A complete list of alarms and fault information as well as possible causes and corrective measures are presented in this chapter.

| | |
|---|---|
| | Only trained and qualified professionals are allowed to carry out the operations mentioned in this chapter. Please carry out operations according to instructions presented in chapter 1 Safety precautions. |

## 7.2 Indications of alarms and faults

The fault is indicated by indicators. For details, see section 5.3 LED keypad (BOP-270) display and operation. When the TRIP indicator is on, the alarm or fault code displayed on the keypad indicates the VFD is in abnormal state. This chapter covers most of the alarms and faults, and their possible causes and corrective measures. If you cannot find out the causes of alarms or faults, contact local INVT office.

## 7.3 Fault reset

The VFD can be reset by pressing the keypad key STOP/RST, digital inputs, or by cutting off the VFD power. After faults are removed, the motor can be started again.

## 7.4 Fault history

The function codes from P07.27 to P07.32 record the types of the last six faults. The function codes P07.33–P07.40, P07.41–P07.48, P07.49–P07.56 record the running data of VFD at the last three faults.

## 7.5 Faults and solutions

When a fault occurred, handle the fault as follows:

Step 1 Check whether keypad display is improper. If yes, contact the local INVT office.

Step 2 If keypad works properly, check the function codes in P07 group to check the fault record parameters to determine the real state when the fault occurred.

Step 3 See the following table for a detailed solution and check for exceptions.

Step 4 Rectify the fault or ask for help.

Step 5 After confirming the fault is removed, perform fault reset, and start running.

### 7.5.1 Faults and solutions

**Note:** The numbers enclosed in square brackets such as [1], [2] and [3] in the Fault type column in the following table indicate the VFD fault type codes read through communication.

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| OUt1 | [1] Inverter unit | ACC is too fast. | Increase ACC time. |

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| | U-phase protection | IGBT module is damaged.<br>Misoperation caused by interference.<br>Drive wires connected poorly.<br>To-ground short circuit occurred. | Replace the power unit.<br>Check drive wires.<br>Check whether there is strong interference surrounding the peripheral device. |
| OUt2 | [2] Inverter unit V-phase protection | | |
| OUt3 | [3] Inverter unit W-phase protection | | |
| OV1 | [7] Overvoltage during ACC | DEC time too short.<br>Input voltage exception.<br>Large energy feedback.<br>No braking components.<br>Energy-consumption braking is not enabled. | Check the input power.<br>Check whether load DEC time is too short or the motor starts during rotating.<br>Install dynamic braking components.<br>Check the settings of related function codes. |
| OV2 | [8] Overvoltage during DEC | | |
| OV3 | [9] Overvoltage during constant speed running | | |
| OC1 | [4] Overcurrent during ACC | ACC/DEC is too fast.<br>Grid voltage too low.<br>VFD power too small.<br>Load transient or exception occurred.<br>To-ground short circuit or output phase loss occurred.<br>Strong external interference sources.<br>The overcurrent stall protection is not enabled. | Increase ACC/DEC time.<br>Check the input power.<br>Select a VFD with larger power.<br>Check whether the load is short circuited (to-ground short circuit or line-to-line short circuit) or the rotation is not smooth.<br>Check the output wiring.<br>Check whether there is strong interference.<br>Check the settings of related function codes. |
| OC2 | [5] Overcurrent during DEC | | |
| OC3 | [6] Overcurrent during constant speed running | | |
| UV | [10] Bus undervoltage | Grid voltage too low.<br>The overvoltage stall protection is not enabled. | Check the grid input power.<br>Check the settings of related function codes. |
| OL1 | [11] Motor overload | The grid voltage is too low.<br>Motor rated current set incorrectly.<br>The motor stall occurs or the load transient is too large. | Check the grid voltage.<br>Reset the rated current of the motor.<br>Check the load and adjust the torque boost quantity. |
| OL2 | [12] VFD overload | ACC is too fast.<br>The motor in rotating is | Increase ACC time.<br>Avoid restart after stop. |

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| | | restarted.<br>The grid voltage is too low.<br>Load is too large.<br>Power is too small. | Check the grid voltage.<br>Select a VFD with larger power.<br>Select a proper motor. |
| SPI | [13] Phase loss on input side | Phase loss or violent fluctuation occurred on input R, S, T. | Check the input power.<br>Check the installation wiring. |
| SPO | [14] Phase loss on output side | Phase loss occurred to U, V, W output (or the three phases of motor is asymmetrical). | Check the output wiring.<br>Check the motor and cables. |
| OH1 | [15] Rectifier module overheating | Air duct blocked or fan damaged.<br>Ambient temperature is too high.<br>Long-time overload running. | Ventilate the air duct or replace the fan.<br>Lower the ambient temperature. |
| OH2 | [16] Inverter module overheat | | |
| EF | [17] External fault | SI external faulty input terminal action. | Check external device input. |
| CE | [18] RS485 communication fault | Baud rate set improperly.<br>Communication line fault.<br>Incorrect communication address.<br>Communication suffers from strong interference. | Set a proper baud rate.<br>Check the wiring of communication interfaces.<br>Set the communication address correctly.<br>Change or replace the wire or improve the anti-interference capability. |
| ItE | [19] Current detection fault | Poor contact of the connector of control board.<br>Hall component damaged.<br>Exception occurred to amplification circuit. | Check the connector and re-plug.<br>Replace the hall component.<br>Replace the main control board. |
| tE | [20] Motor autotuning fault | Motor capacity does not match with the VFD capacity, this fault may occur easily if the difference between them is exceeds five power | Change the VFD model, or adopt V/F mode for control.<br>Set the proper motor type and nameplate parameters.<br>Empty the motor load and carry out autotuning again. |

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| | | classes.<br>Incorrect motor parameter settings.<br>The parameters gained from autotuning deviate sharply from the standard parameters.<br>Autotuning timeout. | Check the motor wiring and parameter settings.<br>Check whether the upper limit frequency is larger than 2/3 of the rated frequency. |
| EEP | [21] EEPROM operation fault | Error in reading or writing control parameters.<br>EEPROM damaged. | Press STOP/RST to reset.<br>Replace the main control board. |
| PIDE | [22] PID feedback offline fault | PID feedback offline.<br>PID feedback source disappears. | Check PID feedback signal wires.<br>Check PID feedback source. |
| End | [24] Running time reached | The actual running time of the VFD is longer than the internal set running time. | Ask for the supplier and adjust the set running time. |
| OL3 | [25] Electronic overload fault | The VFD reports overload pre-alarm according to the setting. | Check the load and the overload pre-alarm points. |
| PCE | [26] Keypad communication fault | Keypad cable connected improperly or disconnected.<br>Keypad cable too long, causing strong interference.<br>Circuit fault occurred to the keypad or communication part of the main board. | Check the keypad cable to determine whether a fault occurs.<br>Check for and remove the external interference source.<br>Replace the hardware and seek maintenance services. |
| UPE | [27] Parameter upload error | Keypad cable connected improperly or disconnected.<br>Keypad cable too long, causing strong interference.<br>Circuit fault occurred to the keypad or communication part of the main board. | Check for and remove the external interference source.<br>Replace the hardware and seek maintenance services.<br>Replace the hardware and seek maintenance services. |

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| DNE | [28] Parameter download error | Keypad cable connected improperly or disconnected.<br>Keypad cable too long, causing strong interference.<br>Data storage error occurred to the keypad. | Check for and remove the external interference source.<br>Replace the hardware and seek maintenance services.<br>Re-back up the data on the keypad. |
| ETH1 | [32] To-ground short-circuit fault 1 | VFD output is short connected to the ground.<br>There is a fault in the current detection circuit.<br>Actual motor power setup deviates sharply from the VFD power.. | Check whether the motor wiring is normal.<br>Replace the hall component.<br>Replace the main control board.<br>Reset the motor parameters properly. |
| ETH2 | [33] To-ground short-circuit fault 2 | VFD output is short connected to the ground.<br>There is a fault in the current detection circuit.<br>Actual motor power setup deviates sharply from the VFD power.. | Check whether the motor wiring is normal.<br>Replace the hall component.<br>Replace the main control board.<br>Reset the motor parameters properly. |
| dEu | [34] Speed deviation fault | The load is too heavy or stalled. | Check and ensure the load is proper, and increase the detection time.<br>Check whether the control parameters are set properly. |
| STo | [35] Mal-adjustment fault | Incorrect SM control parameter settings.<br>Autotuned parameters are not accurate.<br>The VFD is not connected to the motor. | Check the load and ensure the load is normal.<br>Check whether control parameters are set correctly.<br>Increase the mal-adjustment detection time. |
| LL | [36] Electronic underload fault | The VFD reports underload pre-alarm according to the setting. | Check the load and the underload pre-alarm points. |
| OT | [59] Motor overtemperature fault | Motor overtemperature input terminal is valid. | Check the wiring of the motor overtemperature input terminal |

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| | | The temperature detection resistance is abnormal.<br>Long-time overload running or exception occurred. | (terminal function 57).<br>Check whether the temperature sensor is proper.<br>Check the motor, and perform maintenance on the motor. |
| E-Err | [55] Duplicate expansion card type | The two inserted expansion cards are of the same type. | You should not insert two cards with the same type. Check the type of expansion card, and remove one card after power-off. |
| F1-Er | [60] Failed to identify the expansion card in card slot 1 | There is data transmission in the interface of card slot 1, but it cannot read the card type. | Check whether the expansion card in this slot is supported.<br>Secure the expansion card interface after power-off, and check whether the fault persists at next power-on.<br>Check whether the insertion port is damaged, if yes, replace the insertion port after power-off. |
| F2-Er | [61] Failed to identify the expansion card in card slot 2 | There is data transmission in interfaces of card slot 2, however, it cannot read the card type. | Check whether the expansion card at this slot is supported.<br>Secure the expansion card interface after power-off, and check whether the fault persists at next power-on.<br>Check whether the insertion port is damaged, if yes, replace the insertion port after power-off. |
| C1-Er | [63] Communication timeout of expansion card in slot 1 | There is no data transmission in interfaces of card slot 1. | Check whether the expansion card at this slot is supported.<br>Secure the expansion card interface after power-off, and check whether the fault persists at next power-on.<br>Check whether the insertion port is damaged, if yes, replace the insertion port after power-off. |
| C2-Er | [64] Communication timeout of expansion | There is no data transmission in interfaces | Check whether the expansion card at this slot is supported. |

| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| | card in slot 2 | of card slot 2. | Secure the expansion card interface after power-off, and check whether the fault persists at next power-on.<br>Check whether the insertion port is damaged, if yes, replace the insertion port after power-off. |
| E-DP | [29] PROFIBUS card communication timeout fault | There is no data transmission between the communication card and the host controller (or PLC). | Check whether the communication card wiring is loose or dropped. |
| E-NET | [30] Ethernet card communication timeout fault | There is no data transmission between the communication card and the host controller. | Check whether the communication card wiring is loose or disconnected. |
| E-CAN | [31] CANopen card communication timeout fault | There is no data transmission between the communication card and the host controller (or PLC). | Check whether the communication card wiring is loose or dropped. |
| E-PN | [57] PROFINET card communication timeout fault | There is no data transmission between the communication card and the host controller (or PLC). | Check whether the communication card wiring is loose or dropped. |
| E-BAC | [67] BACnet card communication timeout fault | There is no data transmission between the communication card and the host controller (or PLC). | Check whether the communication card wiring is loose or dropped. |
| ESCAN | [58] CAN master/slave card communication timeout fault | There is no data transmission between the CAN master and slave communication cards. | Check whether the communication card wiring is loose or dropped. |
| S-Err | [69] CAN slave fault in master/slave synchronization | Fault occurred to one of the CAN slave VFDs. | Detect the CAN slave VFD and analyze the corresponding fault cause of the VFD. |

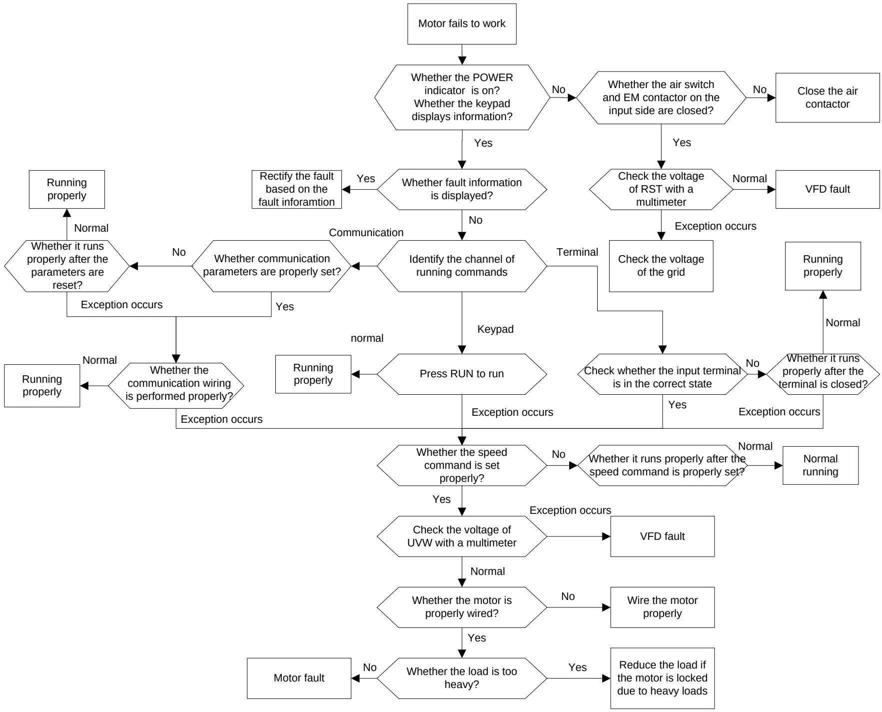
| Fault code | Fault type | Possible cause | Solution |
|---|---|---|---|
| FrOST | [73] Freezing fault | The temperature is lower than the freezing protection threshold. | Check the temperature. |
| BLOCK | [74] Stalling fault | The current is greater than the stalling current. | Check for stalling. |
| Dr | [75] Dry pumping fault | The current is lower than the current limit for motor dry pumping. | Check for dry pumping. |
| STO | Safe torque off | Safe torque off function is enabled by external forces. | - |
| STL1 | Exception occurred to safety circuit of channel 1 | The wiring of STO is improper;<br>Fault occurred to external switch of STO;<br>Hardware fault occurred to safety circuit of channel. | Check whether terminal wiring of STO is proper and firm enough;<br>Check whether the external switch of STO can work properly;<br>Replace the control board.<br>**Note:** Re-power on is required to remove the fault. |
| STL2 | Exception occurred to safety circuit of channel 2 | | |
| STL3 | Exception occurred to channel 1 and channel 2 | Hardware fault occurred to STO circuit. | Replace the control board. |

### 7.5.2 Other status

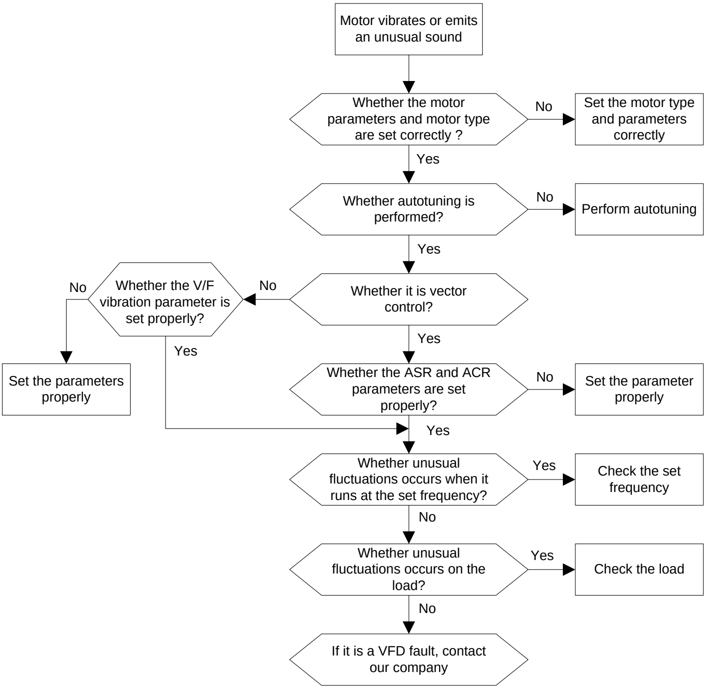
| Displayed code | Status type | Possible cause | Solution |
|---|---|---|---|
| PoFF | System power failure | The system is powered off or the bus voltage is too low. | Check the grid conditions. |

## 7.6 Analysis on common faults

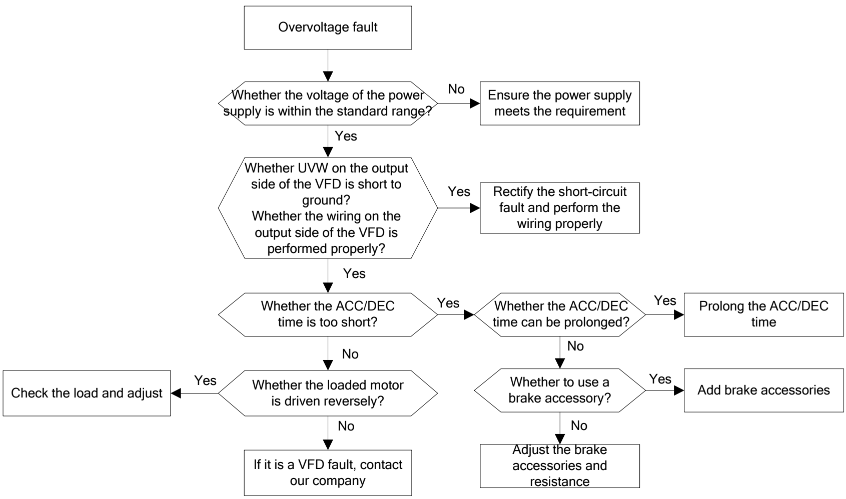
### 7.6.1 Motor fails to work



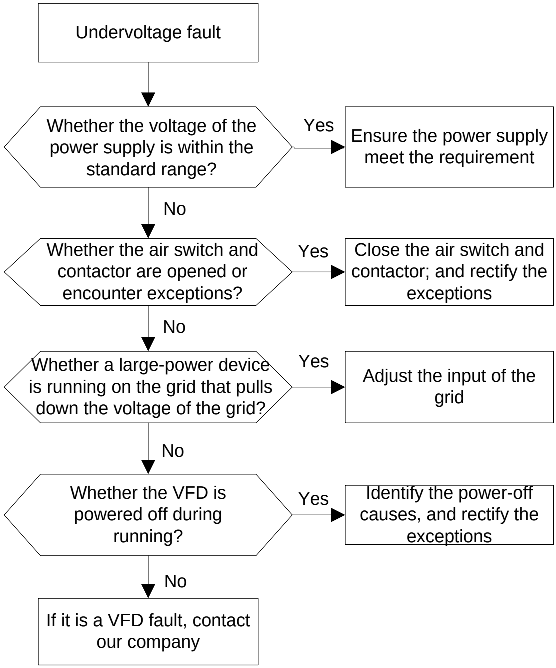
### 7.6.2 Motor vibrates



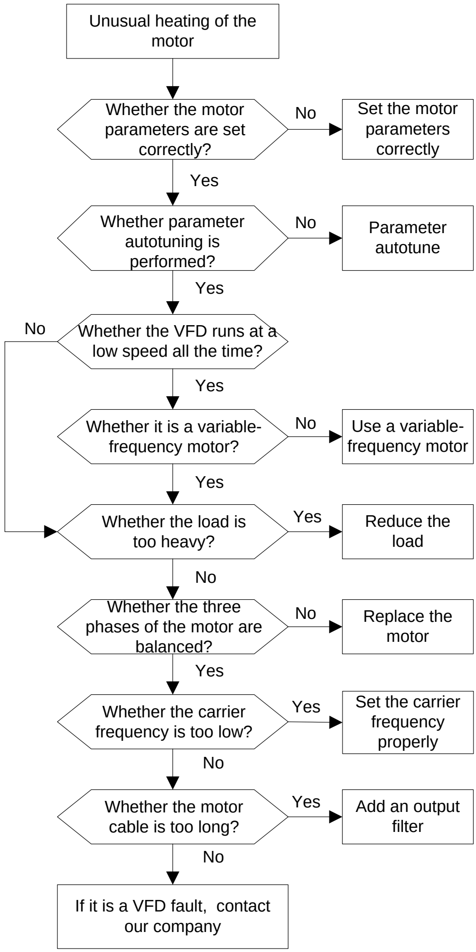

### 7.6.3 Overvoltage



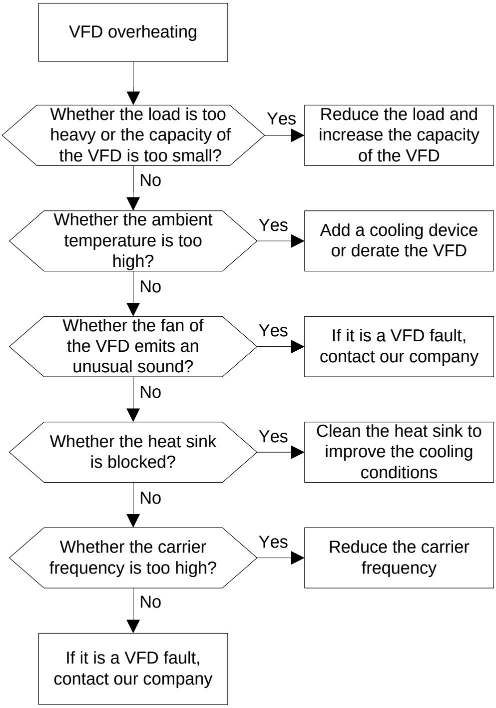
### 7.6.4 Undervoltage



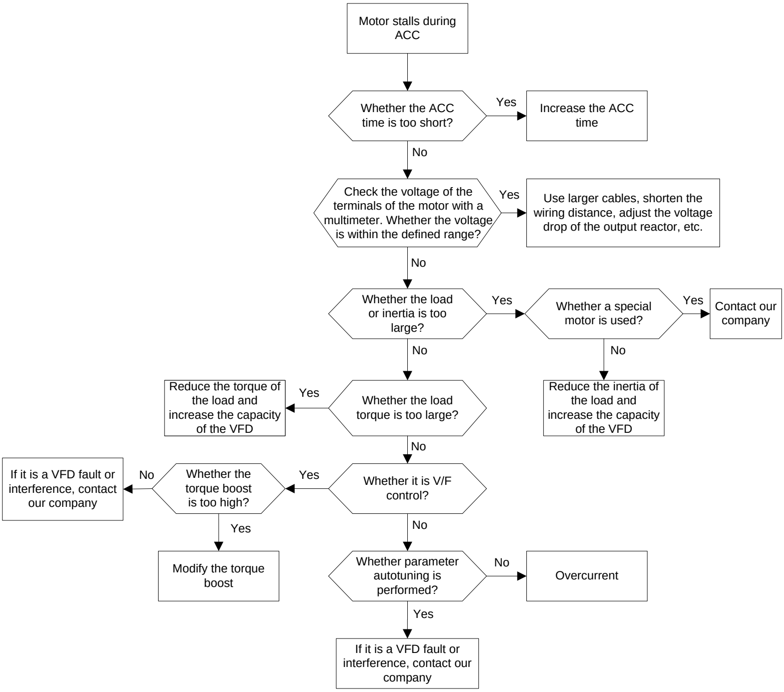
### 7.6.5 Motor overheating



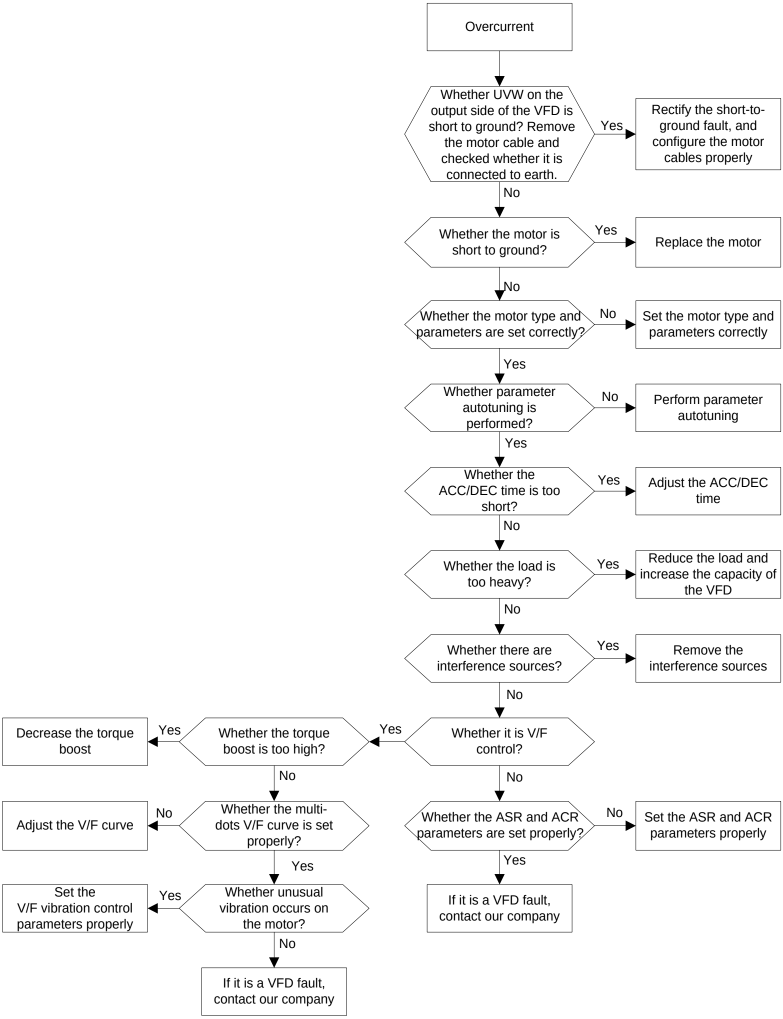
### 7.6.6 VFD overheating



### 7.6.7 Motor stalls during ACC



### 7.6.8 Overcurrent




## 7.7 Countermeasures on common interference

### 7.7.1 Interference on meter switches and sensors

#### Interference phenomenon

Pressure, temperature, displacement, and other signals of a sensor are collected and displayed by a human-machine interaction device. The values are incorrectly displayed as follows after the VFD is started:

1. The upper or lower limit is wrongly displayed, for example, 999 or -999.
2. The display of values jumps (usually occurring on pressure transmitters).
3. The display of values is stable, but there is a large deviation, for example, the temperature is dozens of degrees higher than the common temperature (usually occurring on thermocouples).
4. A signal collected by a sensor is not displayed but functions as a drive system running feedback signal. For example, the VFD is expected to decelerate when the upper pressure limit of the compressor is reached, but in actual running, it starts to decelerate before the upper pressure limit is reached.
5. After the VFD is started, the display of all kinds of meters (such as frequency meter and current meter) that are connected to the analog output (AO) terminal of the VFD is severely affected, displaying the values incorrectly.
6. Proximity switches are used in the system. After the VFD is started, the indicator of a proximity switch flickers, and the output level flips.

**Solution**

1. Check and ensure that the feedback cable of the sensor is 20 cm or farther away from the motor cable.
2. Check and ensure that the ground wire of the motor is connected to the PE terminal of the VFD (if the ground wire of the motor has been connected to the ground block, you need to use a multimeter to measure and ensure that the resistance between the ground block and PE terminal is lower than 1.5 Ω).
3. Try to add a safety capacitor of 0.1μF to the signal end of the feedback signal terminal of the sensor.
4. Try to add a safety capacitor of 0.1μF to the power end of the sensor meter (pay attention to the voltage of the power supply and the voltage endurance of the capacitor).
5. For interference on meters connected to the AO terminal of the VFD, If AO uses 0–20mA current signal, add a capacitor of 0.47μF between the AO and GND terminals; if AO uses 0–10V voltage signal, add a capacitor of 0.1μF between the AO and GND terminals.

**Note:**

✧ When a decoupling capacitor is required, add it to the terminal of the device connected to the sensor. For example, if a thermocouple is to transmit signals of 0 to 20 mA to a temperature meter, the capacitor needs to be added on the terminal of the temperature meter; if an electronic ruler is to transmit signals of 0 to 30 V to a PLC signal terminal, the capacitor needs to be added on the terminal of the PLC.

✧ If a large number of meters or sensors are disturbed, it is recommended that you configure an external C2 filter on the VFD input power end. For details, see section D.5 Harmonic filters.

### 7.7.2 Interference on RS485 communication

The interference described in this section on RS485 communication mainly includes communication delay, out of synchronization, occasional power-off, or complete power-off that occurs after the VFD is started.

If the communication cannot be implemented properly, regardless of whether the VFD is running, the exception is not necessarily caused by interference. You can find out the causes as follows:

1. Check whether the RS485 communication bus is disconnected or in poor contact.
2. Check whether the two ends of line A or B are connected reversely.
3. Check whether the communication protocol of the VFD is consistent with that of the host controller. Check whether the communication protocol (such as the baud rate, data bits, and check bit) of the VFD is consistent with that of the host computer.

**If you are sure that communication exceptions are caused by interference, you can resolve the problem through the following measures:**

1. Simple inspection**:**
2. Arrange the communication cables and motor cables in different cable trays.
3. In multi-VFD application scenarios, adopt the chrysanthemum connection mode to connect the communication cables between VFDs, which can improve the anti-interference capability.
4. In multi-VFD application scenarios, check and ensure that the driving capacity of the master is sufficient.
5. In the connection of multiple VFDs, you need to configure one 120 Ω terminal resistor on each end.

**Solution**

1. Check and ensure that the ground wire of the motor is connected to the PE terminal of the VFD (if the ground wire of the motor has been connected to the ground block, you need to use a multimeter to measure and ensure that the resistance between the ground block and PE terminal is lower than 1.5 Ω).
2. Do not connect the VFD and motor to the same ground terminal as the host controller (PLC, HMI, and touch screen). It is recommended that you connect the VFD and motor to the power ground, and connect the host controller separately to a ground stud.
3. Try to short the signal reference ground terminal (GND) of the VFD with that of the host controller controller to ensure that ground potential of the communication chip on the control board of the VFD is consistent with that of the communication chip of the host controller.
4. Try to change the short-connection cap of jumper J9 on the VFD control board from 1/2 pins to 2/3 pins.
5. Try to add a safety capacitor of 0.1 μF on the power terminal of the host controller (PLC, HMI,

and touch screen). During this process, pay attention to the voltage of the power supply and the voltage endurance capability of the capacitor. Alternatively, you can use a magnet ring (Fe-based nanocrystalline magnet rings are recommended). Put the power L/N line or +/- line of the host controller through the magnet ring in the same direction and wind 8 coils around the magnet ring.

### 7.7.3 Failure to stop and indicator shimmering due to motor cable coupling

**Interference phenomenon**

1. Failure to stop

   In a VFD system where an S terminal is used to control the start and stop, the motor cable and control cable are arranged in the same cable tray. After the system is started properly, the S terminal cannot be used to stop the inverter.

2. Indicator shimmering

   After the VFD is started, the relay indicator, power distribution box indicator, PLC indicator, and indication buzzer shimmer, blink, or emit unusual sounds unexpectedly.

**Solution**

1. Check and ensure that the exception signal cable is arranged 20 cm or farther away from the motor cable.
2. Add a safety capacitor of 0.1μF between the digital input terminal (S) and the COM terminal.
3. Connect the digital input terminal (S) that controls the start and stop to other idle digital input terminals in parallel. For example, if S1 is used to control the start and stop and S4 is idle, you can try to short connect S1 to S4 in parallel.

**Note:** If the controller (such as PLC) in the system controls more than 5 VFDs at the same time through digital input terminals (S), this scheme is not applicable.

### 7.7.4 Leakage current and interference on RCD

VFDs output high-frequency PWM voltage to drive motors. In this process, the distributed capacitance between the internal IGBT of a VFD and the heat sink and that between the stator and rotor of a motor may inevitably cause the VFD to generate high-frequency leakage current to the ground. A residual current operated protective device (RCD) is used to detect the power-frequency leakage current when a grounding fault occurs on a circuit. The application of a VFD may cause misoperation of a RCD.

1. Rules for selecting RCDs

(1) VFD systems are special. In these systems, it is required that the rated residual current of common RCDs at all levels is larger than 200 mA, and the VFDs are grounded reliably.

(2) For RCDs, the time limit of an action needs to be longer than that of a next action, and the time difference between two actions need to be longer than 20ms. For example, 1s, 0.5s, and 0.2s.

(3) For circuits in VFD systems, electromagnetic RCDs are recommended. Electromagnetic RCDs have strong anti-interference capability, and thus can prevent the impact of high-frequency leakage current.

| Electronic RCD | Electromagnetic RCD |
|---|---|
| Low cost, high sensitivity, small in volume, susceptible to voltage fluctuation of the grid and ambient temperature, and weak anti-interference capability | Requiring highly sensitive, accurate, and stable zero-phase sequence current transformer, using permalloy high-permeability materials, complex process, high cost, not susceptible to voltage fluctuation of the power supply and ambient temperature, strong anti- interference capability |

2. Solution to RCD misoperation (handling the VFD)

(1) Try to remove the EMC/VDR screw or J10 jumper at "EMC/VDR" of the VFD. The location of the screw or jumper is as shown in Figure 7-1 – Figure 7-8.

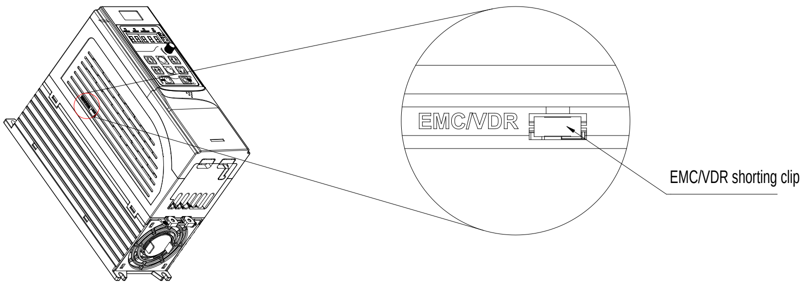



Figure 7-1 Shorting clip for 1.5–7.5kW

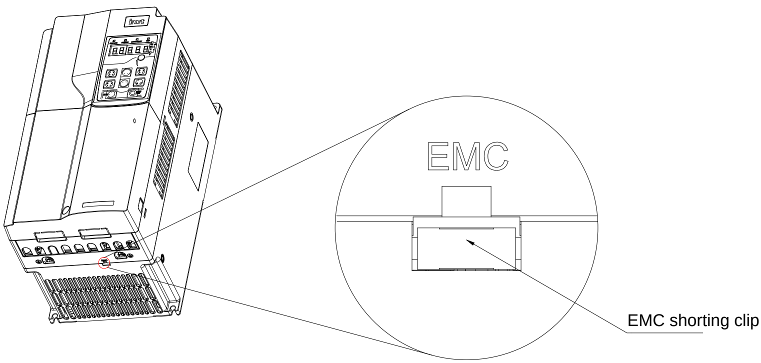



Figure 7-2 Shorting clip for 11–22kW

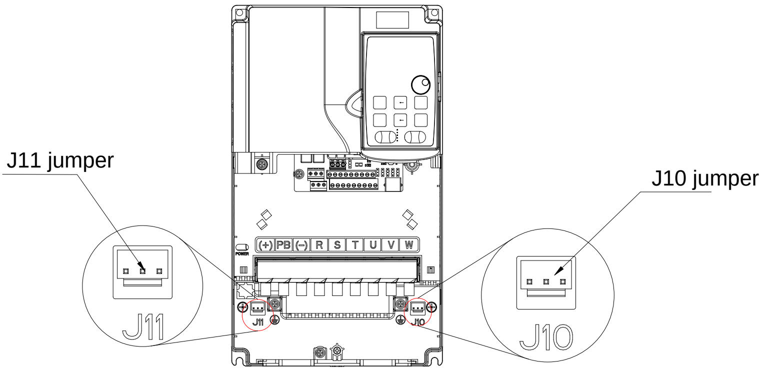



Figure 7-3 Jumper for 30–37kW (J10 for EMC; J11 for VDR)

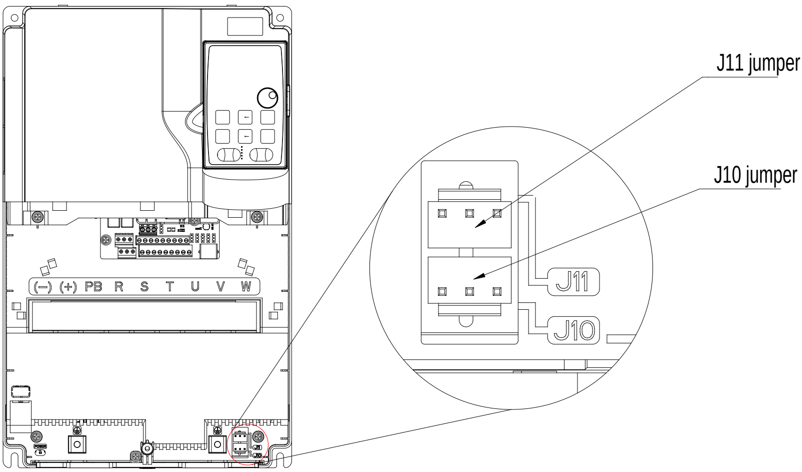



Figure 7-4 Jumper for 45kW (J10 for EMC; J11 for VDR)

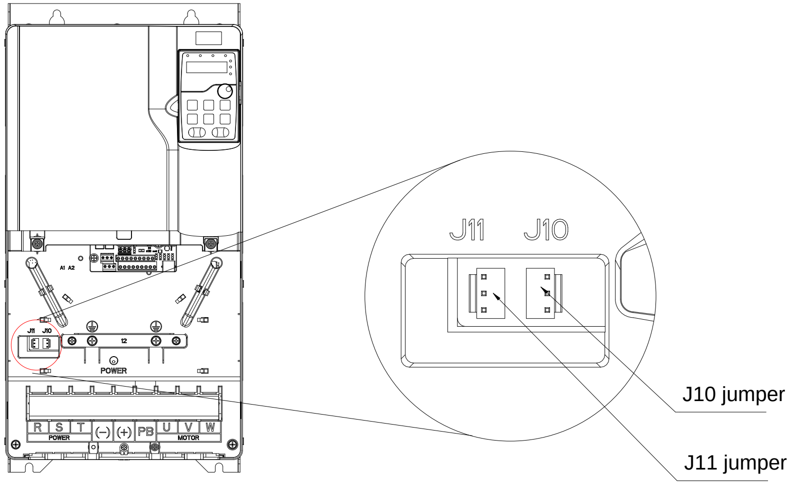



Figure 7-5 Jumper for 55–90kW (J10 for EMC; J11 for VDR)

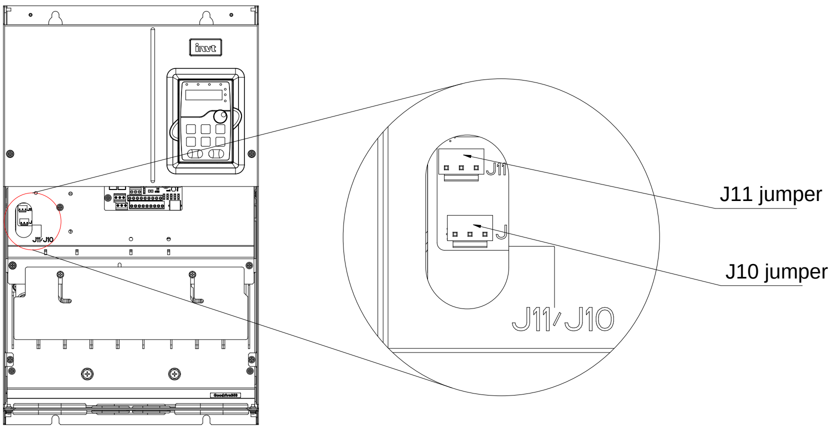



Figure 7-6 Jumper for 110–132kW (J10 for EMC; J11 for VDR)

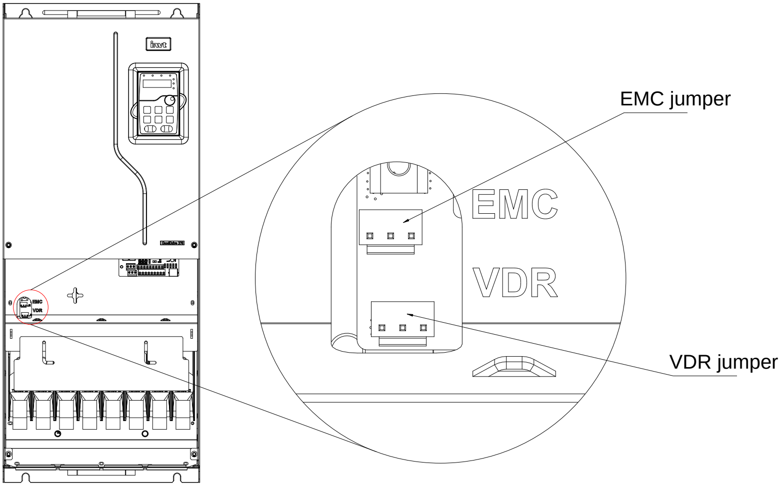



Figure 7-7 Jumper for 160–200kW

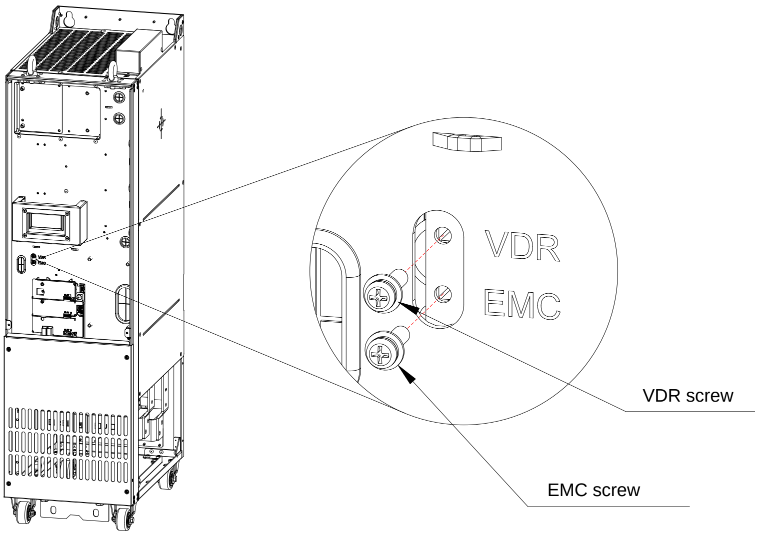



Figure 7-8 Screw positions for 220–630kW

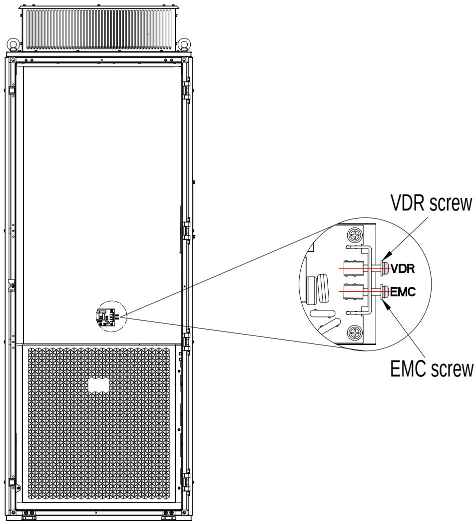



Figure 7-9 Screw positions for 710–800kW

(2) Try to decrease the carrier frequency to 1.5kHz (P00.14=1.5).

(3) Try to modify the modulation method to "3PH modulation and 2PH modulation" (P08.40=00).

3. Solution to mal-operation of RCD (on the part of system distribution)

(1) Check and ensure that the power cable is not soaking in water.

(2) Check and ensure that the cables are not damaged or spliced.

(3) Check and ensure that no secondary grounding is performed on the neutral wire.

(4) Check and ensure that the main power cable terminal is in good contact with the air switch or contactor (all screws are tightened).

(5) Check 1PH powered devices, and ensure that no earth lines are used as neutral wires by these devices.

(6) Do not use shielded cables as VFD power cables and motor cables.

**7.7.5 Live device chassis**

After the VFD is started, there is sensible voltage on the chassis, and you may feel an electric shock when touching the chassis. The chassis, however, is not live (or the voltage is far lower than the human safety voltage) when the VFD is powered on but not running.

Solution

1. If there is power distribution grounding or ground stud on the site, ground the cabinet chassis of the VFD through the power ground or stud.
2. If there is no grounding on the site, you need to connect the motor casing to the VFD grounding terminal PE, and ensure that the jumper at "EMC/VDR" of the VFD is shorted.

# 8 Maintenance

## 8.1 What this chapter contains

This chapter describes how to carry out preventive maintenance on the VFD.

## 8.2 Periodical maintenance

Little maintenance is required when the VFD is installed in an environment that meets requirements. The following table describes the routine maintenance periods recommended by INVT. The following table describes the routine maintenance periods recommended by INVT.

<table>
<tr><th colspan="2">Check scope</th><th>Check item</th><th>Method</th><th>Expected result</th></tr>
<tr><td colspan="2" rowspan="2">Ambient environment</td><td>Check the temperature, and humidity, and whether there is vibration, dust, gas, oil spray, and water droplets in the environment.</td><td>Visual inspection and instrument measurement</td><td>The requirements stated in this manual are met.</td></tr>
<tr><td>Check whether there are foreign matters, such as tools, or dangerous substances placed nearby.</td><td>Visual inspection</td><td>There are no tools or dangerous substances placed nearby.</td></tr>
<tr><td colspan="2">Voltage</td><td>Check the voltage of the main circuit and control circuit.</td><td>Use multimeters or other instruments for measurement.</td><td>The requirements stated in this manual are met.</td></tr>
<tr><td colspan="2" rowspan="2">Keypad</td><td>Check the display of information.</td><td>Visual inspection</td><td>The characters are displayed properly.</td></tr>
<tr><td>Check whether characters are not completely displayed.</td><td>Visual inspection</td><td>The requirements stated in this manual are met.</td></tr>
<tr><td rowspan="3">Main circuit</td><td rowspan="3">Common</td><td>Check whether bolts are loose or fall off.</td><td>Screw them up.</td><td>No exception occurs.</td></tr>
<tr><td>Check whether the machine is deformed, cracked, or damaged, or their color changes due to overheating and aging.</td><td>Visual inspection</td><td>No exception occurs.</td></tr>
<tr><td>Check whether there are stains and dust attached.</td><td>Visual inspection</td><td>No exception occurs.<br>Note: Discoloration of copper bars does not mean that they cannot work properly.</td></tr>
</table>

| Check scope | | Check item | Method | Expected result |
|---|---|---|---|---|
| | Conductor and wire | Check whether conductors are deformed or color change for overheat. | Visual inspection | No exception occurs. |
| | | Check whether the wire sheaths are cracked or their color changes. | Visual inspection | No exception occurs. |
| | Terminal block | Check whether there is damage. | Visual inspection | No exception occurs. |
| | Filter capacitor | Check whether there is electrolyte leakage, discoloration, cracks, and chassis expansion. | Visual inspection | No exception occurs. |
| | | Check whether the safety valves are released. | Determine the service life based on the maintenance information, or measure them through electrostatic capacity. | No exception occurs. |
| | | Check whether the electrostatic capacity is measured as required. | Use instruments to measure the capacity. | Electrostatic capacity ≥ (Initial value × 0.85) |
| | Resistor | Check whether there is displacement caused due to overheat. | Olfactory and visual inspection | No exception occurs. |
| | | Check whether the resistors are disconnected. | Visual inspection, or remove one end of the connection cable and use a multimeter for measurement. | Resistance range: ±10% (of the standard resistance) |
| | Transformer, Reactor | Check whether there is unusual vibration sounds or smells. | Auditory, olfactory, and visual inspection | No exception occurs. |

| Check scope | | Check item | Method | Expected result |
|---|---|---|---|---|
| | Electromagnetic contactor and Relay | Check whether there are vibration sounds in the workshop. | Auditory inspection | No exception occurs. |
| | | Check whether the contacts are in good contact. | Visual inspection | No exception occurs. |
| Control circuit | Control PCB and connector | Check whether the screws and connectors are loose. | Screw them up. | No exception occurs. |
| | | Check whether there is unusual smell or discoloration. | Olfactory and visual inspection | No exception occurs. |
| | | Check whether there are cracks, damage, deformation, or rust. | Visual inspection | No exception occurs. |
| | | Check whether there is electrolyte leakage or deformation. | Visual inspection, and determine the service life based on the maintenance information. | No exception occurs. |
| Cooling system | Cooling fan | Check whether there are unusual sounds or vibration. | Auditory and visual inspection, and turn the fan blades with your hand. | The rotation is smooth. |
| | | Check whether the bolts loose. | Screw them up. | No exception occurs. |
| | | Check whether there is decoloration caused due to overheat. | Visual inspection, and determine the service life based on the maintenance information. | No exception occurs. |
| | Ventilation duct | Check whether there are foreign matters blocking or attached to the cooling fan, air inlets, or air outlets.<br>Check whether there are foreign objects attached. | Visual inspection | No exception occurs. |

For more details about maintenance, contact the local INVT office, or visit our website www.invt.com, and choose **Support** > **Services**.

## 8.3 Cooling fan

The service life of the cooling fan of the VFD is more than 25,000 hours. The actual service life of the cooling fan is related to the use of the VFD and the temperature in the ambient environment.

You can view the running duration of the VFD through P07.14 (Accumulated running time).

The increase of the bearing noise indicates a fan fault. If the VFD is applied in a key position, replace the fan once the fan starts to generate unusual noise. You can purchase spares of fans from INVT.

| | |
|---|---|
| ⚠ | Read chapter 1 Safety precautions carefully and follow the instructions to perform operations. Ignoring these safety precautions may lead to physical injury or death, or device damage. |

To replace the cooling fan for 2.2–630kW models:

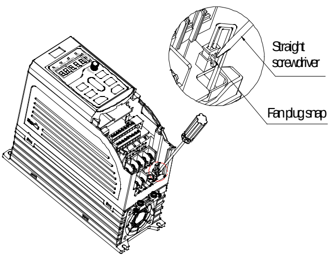
Step 1 Stop the VFD, disconnect the AC power supply, and wait for a time no shorter than the waiting time designated on the VFD.

Step 2 Open the cable clamp to loose the fan cable.

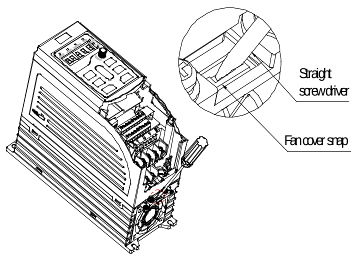
Step 3 Disconnect the fan cable.

Step 4 Remove the fan with a screwdriver.

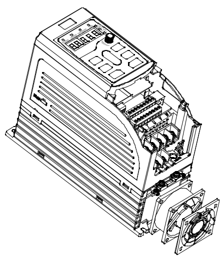
Step 5 Install a new fan in the VFD in the reverse steps. Assemble the VFD. Ensure that the air direction of the fan is consistent with that of the VFD, as shown in the following figure.




1. Remove the fan cable through the straight screwdriver.




2. Remove the fan cover through the straight screwdriver.



3. Take out of the fan and replace it.

Figure 8-1 Fan maintenance for 2.2–7.5kW VFD models (disassembly with tools)

**Note:** The GD270-1R5-4 model is a fanless natural cooling design that requires no fan maintenance.

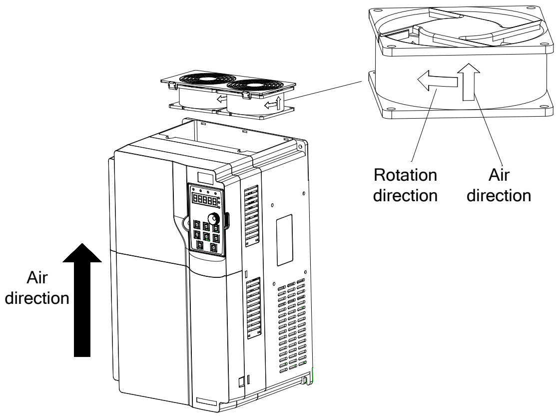



Figure 8-2 Fan maintenance for 11–200kW VFD models

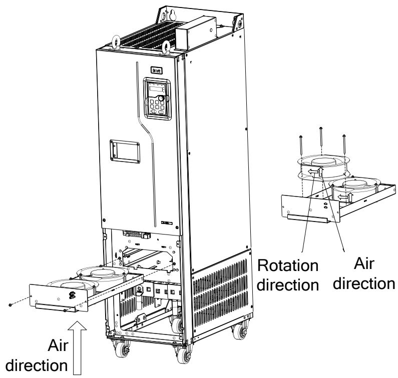



Figure 8-3 Fan maintenance for the 220–630kW VFD models

Step 6 Connect to the power supply.

The 710–800kW cabinet unit features two types of cooling fans: top-mounted fans and phase unit internal fans. The replacement procedures for each are described below.

To replace the top cooling fan:

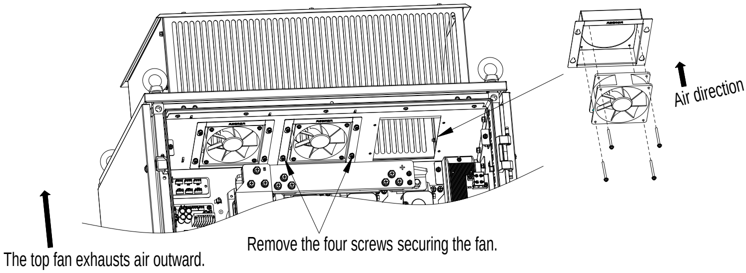
Step 1 Stop the VFD, disconnect the AC power supply, and wait for a time no shorter than the waiting time designated on the VFD.

Step 2 Open the cable clamp to lose the fan cable.

Step 3 Use a screwdriver to remove the four screws securing the fan box, and then take out the fan box assembly.

Step 4 Use a screwdriver to remove the four screws securing the fan, and then remove the fan.

Step 5 Install a new fan in the VFD in the reverse steps. Assemble the VFD. Ensure that the air direction of the fan is consistent with that of the VFD, as shown in the following figure.



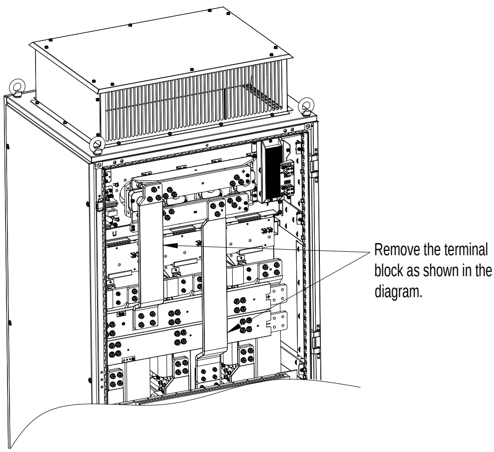

Step 6 Connect the power supply.

To replace the phase unit internal fan:

Step 1 Stop the VFD, disconnect the AC power supply, and wait for a time no shorter than the waiting time designated on the VFD.

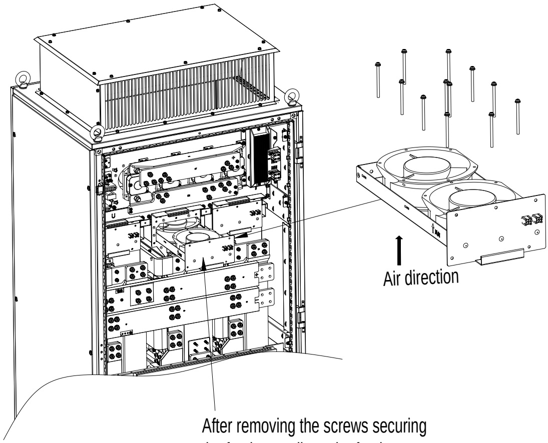
Step 2 Open the cable clamp to loose the fan cable.

Step 3 Use a screwdriver to remove the front connector bar from the fan box (see figure below).




Step 4 Use a screwdriver to remove the five screws securing the fan box, then take out the fan box assembly.

Step 5 Use a screwdriver to remove the eight screws securing the fan, then remove the fan as shown in the following figure.




Step 6 Install a new fan in the VFD in the reverse steps. Assemble the VFD. Ensure that the air direction of the fan is consistent with that of the VFD.

Step 7 Connect the power supply.

## 8.4 Capacitor

### 8.4.1 Capacitor reforming

If the VFD has been left unused for a long time, you need to follow the instructions to reform the DC bus capacitor before using it. The storage time is calculated from the date the VFD is delivered.

| Storage time | Operation principle |
|---|---|
| Less than 1 year | No charging operation is required. |
| 1 to 2 years | The VFD needs to be powered on for 1 hour before the first running command. |
| 2 to 3 years | Use a voltage controlled power supply to charge the VFD:<br>● Charge the VFD at 25% of the rated voltage for 30 minutes,<br>● and then charge it at 50% of the rated voltage for 30 minutes,<br>● at 75% for another 30 minutes,<br>● and finally charge it at 100% of the rated voltage for 30 minutes. |
| More than 3 years | Use a voltage controlled power supply to charge the VFD:<br>● Charge the VFD at 25% of the rated voltage for 2 hours,<br>● and then charge it at 50% of the rated voltage for 2 hours,<br>● at 75% for another 2 hours,<br>● and finally charge it at 100% of the rated voltage for 2 hours. |

The method for using a voltage controlled power supply to charge the VFD is described as follows:

The selection of a voltage controlled power supply depends on the power supply of the VFD. For VFDs with an incoming voltage of 1PH/3PH 230V AC, you can use a 1PH 230V AC/2 A voltage regulator. Both 1PH and 3PH VFDs can be charged with a 1PH voltage controlled power supply (connect L+ to R, and N to S or T). All the DC bus capacitors share one rectifier, and therefore they are all charged.

For VFDs of a high voltage class, ensure that the voltage requirement (for example, 380 V) is met during charging. Capacitor changing requires little current, and therefore you can use a small-capacity power supply (2 A is sufficient).

The method for using a resistor (incandescent lamp) to charge the drive is described as follows:

If you directly connect the drive device to a power supply to charge the DC bus capacitor, it needs to be charged for a minimum of 60 minutes. The charging operation must be performed at a normal indoor temperature without load, and you must connect a resistor in series mode in the 3PH circuit of the power supply.

For a 380 V drive device, use a resistor of 1 kΩ/100W. If the voltage of the power supply is no higher than 380 V, you can also use an incandescent lamp of 100W. If an incandescent lamp is used, it may go off or the light may become very weak.

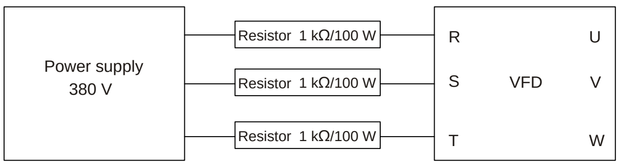



Figure 8-4 380V drive device charging circuit example

### 8.4.2 Electrolytic capacitor replacement

| | |
|---|---|
| ⚠ | Read chapter 1 Safety precautions carefully and follow the instructions to perform operations. Ignoring these safety precautions may lead to physical injury or death, or device damage. |

The electrolytic capacitor of a VFD must be replaced if it has been used for more than 35,000 hours. For details about the replacement, contact the local INVT office.

## 8.5 Power cable

| | |
|---|---|
| ⚠ | Read chapter 1 Safety precautions carefully and follow the instructions to perform operations. Ignoring these safety precautions may lead to physical injury or death, or device damage. |

1. Stop the VFD, disconnect the power supply, and wait for a time no shorter than the waiting time designated on the VFD.
2. Check the connection of the power cables. Ensure that they are firmly connected.
3. Connect to the power.

# 9 Communication protocol

## 9.1 What this chapter contains

This chapter describes the communication of the VFD.

The VFD provides RS485 communication interfaces and adopts the master-slave communication based on the international standard Modbus communication protocol. You can implement centralized control (setting commands for controlling the VFD, modifying the running frequency and related function code parameters, and monitoring the working state and fault information of the VFD) through PC/PLC, upper control computer, or other devices to meet specific application requirements.

## 9.2 Modbus protocol introduction

Modbus is a communication protocol for use with electronic controllers. By using this protocol, a controller can communicate with other devices through transmission lines. It is a general industrial standard. With this standard, control devices produced by different manufacturers can be connected to form an industrial network and be monitored in a centralized way.

The Modbus protocol provides two transmission modes, namely American Standard Code for Information Interchange (ASCII) and remote terminal units (RTU). On one Modbus network, all the device transmission modes, baud rates, data bits, check bits, stop bits, and other basic parameters must be set consistently.

A Modbus network is a control network with one master and multiple slaves, that is, on one Modbus network, there is only one device serving as the master, and other devices are the slaves. The master can communicate with any single slave or with all slaves. For separate access commands, a slave needs to return a response. For broadcasted information, slaves do not need to return responses.

## 9.3 Application of Modbus

The VFD uses the Modbus RTU mode and communicates through RS485 interfaces.

### 9.3.1 RS485

RS485 interfaces work in half-duplex mode and transmit data signals in the differential transmission way, which is also referred to as balanced transmission. An RS485 interface uses a twisted pair, where one wire is defined as A (+), and the other B (-). Generally, if the positive electrical level between the transmission drives A and B ranges from +2V to +6V, the logic is "1"; and if it ranges from -6V to -2V, the logic is "0".

The 485+ terminal on the terminal block of the VFD corresponds to A, and 485- corresponds to B.

The communication baud rate (P14.01) indicates the number of bits sent in a second, and the unit Bit/s(bps). A higher baud rate indicates faster transmission and poorer anti-interference capability. When a twisted pair of 0.56mm (24 AWG) is used, the maximum transmission distance varies according to the baud rate, as described in the following table.

| Baud rate | Max. transmission distance | Baud rate | Max. transmission distance |
|---|---|---|---|
| 2400bps | 1800m | 9600bps | 800m |
| 4800bps | 1200m | 19200bps | 600m |

In long-distance RS485 communication, it is recommended that you use shielded cables, and use the shielding layer as the ground wire.

When there are fewer devices and the transmission distance is short, the whole network works well without terminal load resistors. The performance, however, degrades as the distance increases. Therefore, it is recommended that you use a 120Ω terminal resistor when the transmission distance is long.

#### 9.3.1.1 Application to one VFD

Figure 9-1 is the Modbus wiring diagram of one VFD and a PC. Generally, PCs do not provide RS485 interfaces, so you need to convert an RS232 or USB interface of a PC to an RS485 interface through an adapter. Connect end A of the RS485 interface to the 485+ port on the terminal block of the VFD, and connect end B to the 485- port. It is recommended that you use shielded twisted pairs. When an RS232-RS485 adapter is used, the cable used to connect the RS232 interface of the PC and the adapter cannot be longer than 15m. Use a short cable when possible. It is recommended that you insert the adapter directly into the PC. Similarly, when a USB-RS485 converter is used, use a short cable when possible.

After wiring, select the correct port (such as COM1 to connect the RS232-RS485 converter) on the host controller, and set the basic parameters such as baud rate and data bit check consistent with those of the VFD.

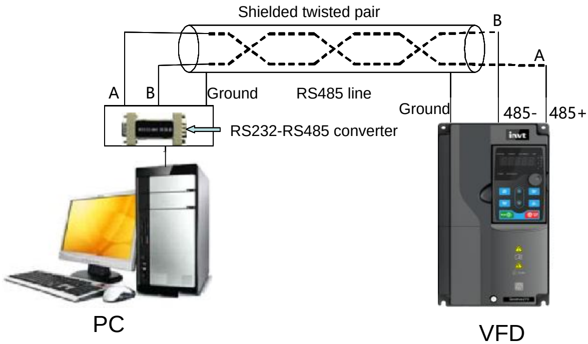



Figure 9-1 RS485 wiring of one VFD

#### 9.3.1.2 Application to multiple VFDs

In practical application to multiple VFDs, chrysanthemum connection and star connection are commonly used.

According to the requirements of the RS485 industrial bus standards, all the devices need to be connected in chrysanthemum mode with one 120Ω terminal resistor on each end, as shown in Figure 9-2. Figure 9-3 is the simplified wiring diagram, and Figure 9-4 is the practical application diagram.

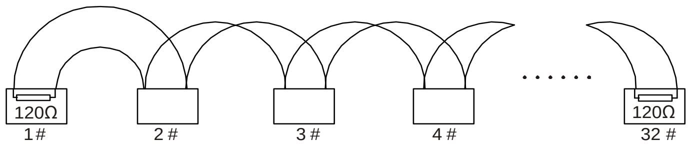



Figure 9-2 Onsite chrysanthemum connection

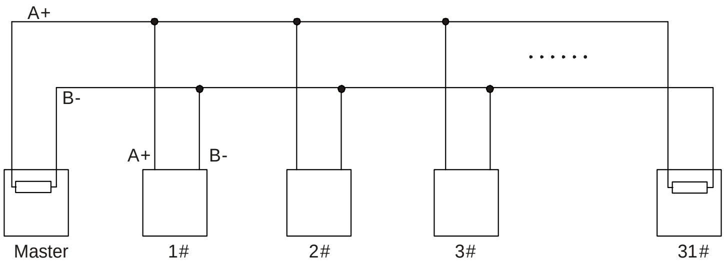



Figure 9-3 Simplified chrysanthemum connection

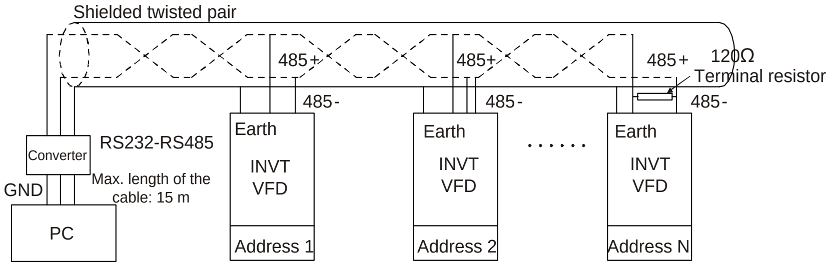



Figure 9-4 Practical chrysanthemum connection application

Figure 9-5 shows the start connection diagram. When this connection mode is adopted, each of the two devices that are farthest away from each other on the line must be configured with a terminal resistor (in Figure 9-5, the two devices are devices 1# and 15#).

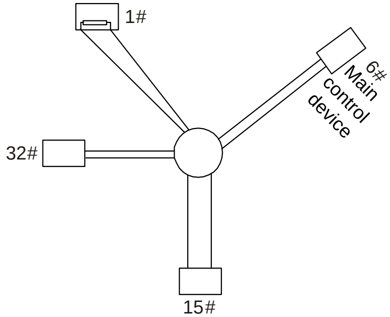



Figure 9-5 Star connection

Use shielded cables, if possible, in multi-device connection. The baud rates, data bit check settings, and other basic parameters of all the devices on the RS485 line must be set consistently, and addresses cannot be repeated.

### 9.3.2 RTU mode

#### 9.3.2.1 RTU communication frame structure

When a controller is set to use the RTU communication mode on a Modbus network, every byte (8 bits) in the message includes 2 hexadecimal characters (each includes 4 bits). Compared with the ASCII mode, the RTU mode achieves transmission of more data at the same baud rate.

**Code system**

• 1 start bit

• 7 or 8 data bits; the minimum valid bit is transmitted first. Each frame domain of 8 bits includes 2 hexadecimal characters (0–9, A–F).

• 1 odd/even check bit; this bit is not provided if no check is needed.

• 1 stop bit (with check performed), 2 bits (without check)

**Error detection domain**

• Cyclic redundancy check (CRC)

The following table describes the data format.

11-bit frame (bits 1 to 8 are data bits):

| | | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|---|
| Start bit | Bit1 | Bit2 | Bit3 | Bit4 | Bit5 | Bit6 | Bit7 | Bit8 | Check bit | Stop bit |

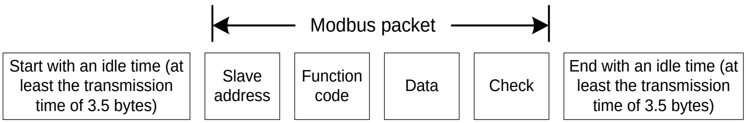
10-bit character frame (bits 1 to 7 are data bits):

| | | | | | | | | | |
|---|---|---|---|---|---|---|---|---|---|
| Start bit | Bit1 | Bit2 | Bit3 | Bit4 | Bit5 | Bit6 | Bit7 | Check bit | Stop bit |

In a character frame, only the data bits carry information. The start bit, check bit, and end bit are used to facilitate the transmission of the data bits to the destination device. In practical applications, you must set the data bits, parity check bits, and stop bits consistently.

In RTU mode, the transmission of a new frame always starts from an idle time (the transmission time of 3.5 bytes). On a network where the transmission rate is calculated based on the baud rate, the transmission time of 3.5 bytes can be easily obtained. After the idle time ends, the data domains are transmitted in the following sequence: slave address, operation command code, data, and CRC check character. Each byte sent in each domain includes 2 hexadecimal characters (0–9, A–F). The network devices always monitor the communication bus. After receiving the first domain (address information), each network device identifies the byte. After the last byte is sent, a similar transmission interval (with a minimum transmission time of 3.5 bytes) is used to indicate that the frame transmission ends. Then, the transmission of a new frame starts.

RTU data frame format




The information of a frame must be transmitted in a continuous data flow. If there is an interval greater than the transmission time of 1.5 bytes before the transmission of the entire frame is complete, the receiving device deletes the incomplete information, and mistakes the subsequent byte for the address domain of a new frame. Similarly, if the transmission interval between two frames is shorter than the transmission time of 3.5 bytes, the receiving device mistakes it for the data of the last frame. The CRC check value is incorrect due to the disorder of the frames, and thus a communication fault occurs.

The following table describes the standard structure of an RTU frame.

| | |
|---|---|
| START (frame header) | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |
| ADDR (slave address domain) | Communication address: 0–247 (decimal system) (0 is the broadcast address) |
| CMD (function domain) | 03H: read slave parameters<br>06H: write slave parameters |
| Data domain<br>DATA（N-1）…DATA（0） | Data of 2*N bytes, main content of the communication as well as the core of data exchanging. |
| CRC CHK LSB | Detection value: CRC verification value (16 bits) |
| CRC CHK MSB | |
| END (frame tail) | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |

#### 9.3.2.2 RTU communication frame error check modes

During the transmission of data, errors may occur due to various factors. Without error check, the data receiving device cannot identify data errors and may make an incorrect response. The incorrect response may cause severe problems. Therefore, the data must be checked.

The check is implemented as follows: The transmitter calculates the to-be-transmitted data based on a specific algorithm to obtain a result, adds the result to the rear of the message, and transmits them together. After receiving the message, the receiver calculates the data based on the same algorithm to obtain a result, and compares the result with that transmitted by the transmitter. If the results are the same, the message is correct. Otherwise, the message is considered incorrect.

The error check of a frame includes two parts, namely, bit check on individual bytes (that is, odd/even check using the check bit in the character frame), and whole data check (CRC check).

**Bit check on individual bytes (odd/even check)**

You can select the bit check mode as required, or you can choose not to perform the check, which will affect the check bit setting of each byte.

Definition of even check: Before the data is transmitted, an even check bit is added to indicate whether the number of "1" in the to-be-transmitted data is odd or even. If it is even, the check bit is set to "0"; and if it is odd, the check bit is set to "1".

Definition of odd check: Before the data is transmitted, an odd check bit is added to indicate whether the number of "1" in the to-be-transmitted data is odd or even. If it is odd, the check bit is set to "0"; and if it is even, the check bit is set to "1".

For example, the data bits to be sent are "11001110", including five "1". If the even check is applied, the even check bit is set to "1"; and if the odd check is applied, the odd check bit is set to "0". During the transmission of the data, the odd/even check bit is calculated and placed in the check bit of the frame. The receiving device performs the odd/even check after receiving the data. If it finds that the odd/even parity of the data is inconsistent with the preset information, it determines that a communication error occurs.

**CRC**

A frame in the RTU format includes an error detection domain based on the CRC calculation. The CRC domain checks all the content of the frame. The CRC domain consists of two bytes, including 16 binary bits. It is calculated by the transmitter and added to the frame. The receiver calculates the CRC of the received frame, and compares the result with the value in the received CRC domain. If the two CRC values are not equal to each other, errors occur in the transmission.

During CRC, 0xFFFF is stored first, and then a process is invoked to process a minimum of 6 contiguous bytes in the frame based on the content in the current register. CRC is valid only for the 8-bit data in each character. It is invalid for the start, stop, and check bits.

During the generation of the CRC values, the "exclusive or" (XOR) operation is performed on the each 8-bit character and the content in the register. The result is placed in the bits from the least significant bit (LSB) to the most significant bit (MSB), and 0 is placed in the MSB. Then, LSB is detected. If LSB is 1, the XOR operation is performed on the current value in the register and the preset value. If LSB is 0, no operation is performed. This process is repeated 8 times. After the last bit (8th bit) is detected and processed, the XOR operation is performed on the next 8-bit byte and the current content in the register. The final values in the register are the CRC values obtained after operations are performed on all the bytes in the frame.

The calculation adopts the international standard CRC check rule. You can refer to the related standard CRC algorithm to compile the CRC calculation program as required.

The following example is a simple CRC calculation function for your reference (using the C programming language):

```
unsigned int crc_cal_value（unsigned char*data_value,unsigned char data_length）
{
     int i;
     unsigned int crc_value=0xffff;
     while（data_length--）
     {
          crc_value^=*data_value++;
          for（i=0;i<8;i++）
          {
               if（crc_value&0x0001）
                    crc_value=（crc_value>>1）^0xa001;
               else
                    crc_value=crc_value>>1;
          }
     }
     Return（crc_value）;
}
```

In the ladder logic, CKSM uses the table look-up method to calculate the CRC value according to the content in the frame. The program of this method is simple, and the calculation is fast, but the ROM space occupied is large. Use this program with caution in scenarios where there are space occupation requirements on programs.

## 9.4 RTU command codes and communication data

### 9.4.1 Command code 03H, reading N words (continuously up to 16 words)

The command code 03H is used by the master to read data from the VFD. The count of data to be read depends on the "data count" in the command. A maximum of 16 pieces of data can be read. The addresses of the read parameters must be contiguous. Each piece of data occupies 2 bytes, that is, one word. The command format is presented using the hexadecimal system (a number followed by "H" indicates a hexadecimal value). One hexadecimal value occupies one byte.

The 03H command is used to read information including the parameters and running status of the VFD.

For example, to read two contiguous data content pieces from 0004H from the VFD with the address of 01H (that is, to read content from data addresses 0004H and 0005H), the frame structure is as follows:

RTU master command (from the master to the VFD)

| | |
|---|---|
| START | T1-T2-T3-T4 (transmission time of 3.5 bytes) |
| ADDR (address) | 01H |
| CMD (command code) | 03H |
| Start address MSB | 00H |
| Start address LSB | 04H |
| Data count MSB | 00H |
| Data count LSB | 02H |
| CRC LSB | 85H |
| CRC MSB | CAH |
| End | T1-T2-T3-T4 (transmission time of 3.5 bytes) |

The value in START and END is "T1-T2-T3-T4 (transmission time of 3.5 bytes)", indicating that the RS485 needs to stay idle for at least the transmission time of 3.5 bytes. An idle time is required to distinguish on message from another to ensure that the two messages are not regarded as one.

"ADDR" is "01H", indicating that the command is sent to the VFD whose address is 01 H. "ADDR" occupies one byte.

"CMD" is "03H", indicating that the command is used to read data from the VFD. The CMD information occupies one byte.

"Start address" means the address from which data reading starts. and it occupies two bytes with the MSB on the left and LSB on the right.

"Data count" indicates the count of data to be read (unit: word). "Start address" is "0004H" and "Data count" is 0002H, indicating that data is to be read from the data addresses of 0004H and 0005H.

CRC check occupies two bytes, with the LSB on the left, and MSB on the right.

RTU slave response (from the VFD to the master)

| | |
|---|---|
| START | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |
| ADDR | 01H |
| CMD | 03H |
| Number of bytes | 04H |
| Address 0004H data MSB | 13H |
| Address 0004H data LSB | 88H |
| Address 0005H data MSB | 00H |
| Address 0005H data LSB | 00H |
| CRC LSB | 7EH |
| CRC MSB | 9DH |
| End | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |

The definition of the response information is described as follows:

"ADDR" is "01H", indicating that the message is sent by the VFD whose address is 01H. The ADDR information occupies one byte.

"CMD" is "03H", indicating that the message is a response of the VFD to the 03H command of the master for reading data. The CMD information occupies one byte.

"Number of bytes" indicates the number of bytes between a byte (not included) and the CRC byte (not included). The value "04" indicates that there are four bytes of data between "Number of bytes" and "CRC LSB", that is, "MSB of data in 0004H", "LSB of data in 0004H", "MSB of data in 0005H", and "LSB of data in 0005H".

A piece of data contains two bytes, with the MSB on the left and LSB on the right. From the response, the data in 0004H is 1388H, and that in 0005H is 0000H.

CRC check occupies two bytes, with the LSB on the left, and MSB on the right.

### 9.4.2 Command code 06H, writing a word

This command is used by the master to write data to the VFD. One command can be used to write only one piece of data. It is used to modify the parameters and running mode of the VFD.

For example, if the master writes 5000 (1388H) to 0004H of the VFD whose address is 02H, the frame structure is as follows.

RTU master command (from the master to the VFD)

| | |
|---|---|
| START | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |
| ADDR | 02H |
| CMD | 06H |
| MSB of data writing address | 00H |
| LSB of data writing address | 04H |
| Data content MSB | 13H |
| Data content LSB | 88H |
| CRC LSB | C5H |
| CRC MSB | 6EH |
| End | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |

RTU slave response (from the VFD to the master)

| | |
|---|---|
| START | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |
| ADDR | 02H |
| CMD | 06H |
| MSB of data writing address | 00H |
| LSB of data writing address | 04H |
| Data content MSB | 13H |
| Data content LSB | 88H |
| CRC LSB | C5H |
| CRC MSB | 6EH |
| End | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |

**Note:** The sections 9.4.1 and 9.4.2 mainly describe the command formats. For the detailed application, see the examples in section 9.4.7.

### 9.4.3 Command code 10H, continuous writing

The command code 10H is used by the master to write data to the VFD. The quantity of data to be written is determined by "Data quantity", and a maximum of 16 pieces of data can be written.

For example, to write 5000 (1388H) and 50 (0032H) respectively to 0004H and 0005H of the VFD whose slave address is 02H, the frame structure is as follows.

RTU master command (from the master to the VFD)

| | |
|---|---|
| START | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |
| ADDR | 02H |
| CMD | 10H |
| MSB of data writing address | 00H |
| LSB of data writing address | 04H |
| Data count MSB | 00H |
| Data count LSB | 02H |
| Number of bytes | 04H |
| MSB of data to be written to 0004H | 13H |
| LSB of data to be written to 0004H | 88H |
| MSB of data to be written to 0005H | 00H |
| LSB of data to be written to 0005H | 32H |
| CRC LSB | C5H |
| CRC MSB | 6EH |
| End | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |

RTU slave response (from the VFD to the master)

| | |
|---|---|
| START | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |
| ADDR | 02H |
| CMD | 10H |
| MSB of data writing address | 00H |
| LSB of data writing address | 04H |
| Data count MSB | 00H |
| Data count LSB | 02H |
| CRC LSB | C5H |
| CRC MSB | 6EH |
| End | T1-T2-T3-T4 (time gap with a min. length of 3.5 bytes) |

### 9.4.4 Data address definition

This section describes the address definition of communication data. The addresses are used for controlling the running, obtaining the state information, and setting related function parameters of the VFD.

#### 9.4.4.1 Function code address format rules

The address of a function code consists of two bytes, with the MSB on the left and LSB on the right. The MSB ranges from 00 to ffH, and the LSB also ranges from 00 to ffH. The MSB is the hexadecimal form of the group number before the dot mark, and LSB is that of the number behind the dot mark. Take P05.06 as an example: The group number is 05, that is, the MSB of the parameter address is the hexadecimal form of 05; and the number behind the dot mark is 06, that is, the LSB is the hexadecimal form of 05. Therefore, the function code address is 0506H in the hexadecimal form. For example, the parameter address of P10.01 is 0A01H.

| Function code | Name | Description | Setting range | Default | Modify |
|---|---|---|---|---|---|
| P10.00 | Simple PLC mode | 0: Stop after running once<br>1: Keep running with the final value after running once<br>2: Cyclic running | 0–2 | 0 | ○ |
| P10.01 | Simple PLC memory selection | 0: Do not memorize at power outage<br>1: Memorize at power outage | 0–1 | 0 | ○ |

**Note:**

✧ The parameters in the P99 group are set by the manufacturer and cannot be read or modified. Some parameters cannot be modified when the VFD is running; some cannot be modified regardless of the VFD status. Pay attention to the setting range, unit, and description of a parameter when modifying it.

✧ The service life of the Electrically Erasable Programmable Read-Only Memory (EEPROM) may be reduced if it is frequently used for storage. Some function codes do not need to be stored during communication. The application requirements can be met by modifying the value of the on-chip RAM, that is, modifying the MSB of the corresponding function code address from 0 to 1. For example, if P00.07 is not to be stored in the EEPROM, you need only to modify the value of the RAM, that is, set the address to 8007H. The address can be used only for writing data to the on-chip RAM, and it is invalid when used for reading data.

#### 9.4.4.2 Addresses of other Modbus functions

In addition to modifying the parameters of the VFD, the master can also control the VFD, such as starting and stopping it, and monitoring the operation status of the VFD.

Table 9-1 Addresses of other function parameters

| Function description | Address definition | Data description | R/W |
|---|---|---|---|
| Communication-based control command | 2000H | 0001H: Run forward | R/W |
| | | 0002H: Run reversely | |
| | | 0003H: Jog forward | |

| Function description | Address definition | Data description | R/W |
|---|---|---|---|
| | | 0004H: Jog reversely | |
| | | 0005H: Stop | |
| | | 0006H: Coast to stop | |
| | | 0007H: Fault reset | |
| | | 0008H: Jogging stop | |
| Communication-based setting address | 2001H | Communication-based frequency setting (0–Fmax, unit: 0.01Hz) | R/W |
| | 2002H | PID reference (0–1000, in which 1000 corresponds to 100.0%) | |
| | 2003H | PID feedback (0–1000, in which 1000 corresponds to 100.0%) | R/W |
| | 2004H | Torque setting (-3000–3000, in which 1000 corresponds to 100.0% of the motor rated current) | R/W |
| | 2005H | Upper limit setting of forward running frequency (0–Fmax; unit: 0.01Hz) | R/W |
| | 2006H | Upper limit setting of reverse running frequency (0–Fmax; unit: 0.01Hz) | R/W |
| | 2007H | Upper limit of the electromotive torque (0–3000, in which 1000 corresponds to 100.0% of the motor rated current) | R/W |
| | 2008H | Upper limit of the braking torque (0–3000, in which 1000 corresponds to 100.0% of the motor rated current) | R/W |
| | 2009H | Special control command word<br>Bit1–bit0=00: Motor 1 =01: Motor 2<br>Bit2=1: Enable speed/torque control switchover<br>=0: Disable speed/torque control switchover<br>Bit3=1: Clear electricity consumption data<br>=0: Keep electricity consumption data<br>Bit4=1: Enable pre-excitation =0: Disable pre-excitation<br>Bit5=1: Enable DC braking =0: Disable DC braking | R/W |
| | 200AH | Virtual input terminal command (0x000–0x3FF)<br>Corresponding to S8/ S7/ S6/ S5/Reserved/HDIA/S4/S3/S2/S1 in sequence. | R/W |
| | 200BH | Virtual output terminal command, range: 0x00–0x0F | R/W |

<table>
<tr><th>Function description</th><th>Address definition</th><th colspan="2">Data description</th><th>R/W</th></tr>
<tr><td rowspan="4"></td><td></td><td colspan="2">The bits correspond to the local terminals: RO2/RO1/Reserved/Y1 in sequence.</td><td></td></tr>
<tr><td>200CH</td><td colspan="2">Voltage setting (used when V/F separation is implemented)<br>(0–1000, in which 1000 corresponds to 100.0% of the motor rated voltage)</td><td>R/W</td></tr>
<tr><td>200DH</td><td colspan="2">AO setting 1 (-1000–+1000, in which 1000 corresponding to 100.0%)</td><td>R/W</td></tr>
<tr><td>200EH</td><td colspan="2">AO setting 2 (-1000–+1000, in which 1000 corresponding to 100.0%)</td><td>R/W</td></tr>
<tr><td rowspan="6">VFD status word 1</td><td rowspan="6">2100H</td><td colspan="2">0001H: Forward running</td><td rowspan="6">R</td></tr>
<tr><td colspan="2">0002H: Reverse running</td></tr>
<tr><td colspan="2">0003H: Stopped</td></tr>
<tr><td colspan="2">0004H: VFD in fault</td></tr>
<tr><td colspan="2">0005H: POFF</td></tr>
<tr><td colspan="2">0006H: Pre-exciting</td></tr>
<tr><td>VFD status word 2</td><td>2101H</td><td colspan="2">Bit0=0: Not ready to run =1: Ready to run<br>Bit2–bit1=00: Motor 1 =01: Motor 2<br>Bit3=0: Asynchronous motor<br>=1: Synchronous motor<br>Bit4=0: No overload pre-alarm<br>=1: Overload pre-alarm<br>bit5–Bit6=0: Keypad-based control<br>=1: Terminal-based control<br>=2: Communication-based control<br>Bit 7: Reserved<br>Bit8=0: Speed control =1: Torque control<br>Bit9=0: Non position control<br>=1: Position control<br>Bit11–Bit10: =00: Vector 0 =01: Vector 1<br>=10: Closed-loop vector<br>=11: Space voltage vector</td><td>R</td></tr>
<tr><td>VFD fault code</td><td>2102H</td><td colspan="2">See the description of fault types.</td><td>R</td></tr>
<tr><td>VFD identification code</td><td>2103H</td><td colspan="2">GD270-----0x01c0</td><td>R</td></tr>
<tr><td>Running frequency</td><td>3000H</td><td>0–Fmax (Unit: 0.01Hz)</td><td rowspan="4">Compatible with CHF100A and CHV100 communication</td><td>R</td></tr>
<tr><td>Set frequency</td><td>3001H</td><td>0–Fmax (Unit: 0.01Hz)</td><td>R</td></tr>
<tr><td>Bus voltage</td><td>3002H</td><td>0.0–2000.0V (Unit: 0.1V)</td><td>R</td></tr>
<tr><td>Output voltage</td><td>3003H</td><td>0–1200V (Unit: 1V)</td><td>R</td></tr>
</table>

| Function description | Address definition | Data description | | R/W |
|---|---|---|---|---|
| Output current | 3004H | 0.0–3000.0A (Unit: 0.1A) | addresses | R |
| Rotational speed | 3005H | 0–65535 (Unit: 1RPM) | | R |
| Output power | 3006H | -300.0%–300.0% (Unit: 0.1%) | | R |
| Output torque | 3007H | -250.0–250.0% (Unit: 0.1%) | | R |
| Closed-loop setting | 3008H | -100.0–100.0% (Unit: 0.1%) | | R |
| Closed-loop feedback | 3009H | -100.0–100.0% (Unit: 0.1%) | | R |
| Input I/O status | 300AH | 00–3F<br>Corresponding to the local Reserved/HDIA/S4/S3/S2/S1 | | R |
| Output I/O status | 300BH | 00–0F<br>The bits correspond to the local terminals: RO2/RO1/Reserved/Y1 in sequence. | | R |
| Analog input 1 | 300CH | 0.00–10.00V (Unit: 0.01V) | | R |
| Analog input 2 | 300DH | 0.00–10.00V (Unit: 0.01V) | | R |
| Analog input 3 | 300EH | -10.00–10.00V (Unit: 0.01V) | | R |
| Analog input 4 | 300FH | / | | R |
| Read input of HDIA high-speed pulse | 3010H | 0.00–50.00kHz (Unit: 0.01Hz) | | R |
| Reserved | 3011H | / | | R |
| Read the actual step of multi-step speed | 3012H | 0–15 | | R |
| External length value | 3013H | 0–65535 | | R |
| External counting value | 3014H | 0–65535 | | R |
| Torque setting | 3015H | -300.0%–300.0% (Unit: 0.1%) | | R |
| VFD identification code | 3016H | / | | R |
| Fault code | 5000H | / | | R |

The Read/Write (R/W) characteristics indicate whether a function parameter can be read and written. For example, "Communication-based control command" can be written, and therefore the command code 06H is used to control the VFD. The R characteristic indicates that a function parameter can only be read, and W indicates that a function parameter can only be written.

**Note:** Some parameters in the preceding table are valid only after they are enabled. Take the running and stop operations as examples, you need to set "Running command channel" (P00.01) to "Communication", and set "Communication mode of running commands" (P00.02) to Modbus. For another example, when modifying "PID reference", you need to set "PID reference source" (P09.00) to Modbus communication.

The following table describes the encoding rules of device codes (corresponding to the identification code 2103H of the VFD).

| 8 MSBs | Meaning | 8 LSBs | Meaning |
|---|---|---|---|
| 0x01 | Goodrive | 0xc0 | GD270 vector VFD |

### 9.4.5 Fieldbus scale

In practical applications, communication data is represented in the hexadecimal form, but hexadecimal values cannot represent decimals. For example, 50.12 Hz cannot be represented in the hexadecimal form. In such cases, multiply 50.12 by 100 to obtain an integer 5012, and then 50.12 can be represented as 1394H in the hexadecimal form (5012 in the decimal form).

In the process of multiplying a non-integer by a multiple to obtain an integer, the multiple is referred to as a fieldbus scale.

The fieldbus scale depends on the number of decimal places in the value specified in "Setting range" or "Default". If there are *n* (for example, 1) decimal places in the value, the fieldbus scale *m* (then *m*=10) is the result of 10 to the power of *n*. Take the following table as an example.

| Function code | Name | Description | Setting range | Default | Modify |
|---|---|---|---|---|---|
| P01.20 | Wake-up-from-sleep delay | 0.0–3600.0s (valid only when P01.19=2) | 0.0–3600.0 | 0.0s | ○ |
| P01.21 | Power-off restart selection | 0: Disable<br>1: Enable | 0–1 | 0 | ○ |

If "Setting range" or "Default value" contains one decimal, the fieldbus scale is 10. If the value received by the host controller is 50, "Delay of auto fault reset" of the rectifier is 5.0 (5.0=50/10).

To set "Wake-up-from-sleep delay" to 5.0s through Modbus communication, you need first to multiply 5.0 by 10 according to the scale to obtain an integer 50, that is, 32H in the hexadecimal form,

| **01** | **06** | **01 14** | **00 32** | **49 E7** |
|---|---|---|---|---|
| VFD address | Write command | Parameter address | Parameter data | CRC |

After receiving the command, the VFD converts 50 into 5.0 based on the fieldbus scale, and then sets "Wake-up-from-sleep delay" to 5.0s.

For another example, after the host controller sends the "Wake-up-from-sleep delay" parameter read command, the master receives the following response from the VFD:

| **01** | **03** | **02** | **00 32** | **39 91** |
|---|---|---|---|---|
| VFD address | Read command | 2-byte data | Parameter data | CRC |

The parameter data is 0032H, that is, 50, and therefore 5.0 is obtained based on the fieldbus scale (50/10=5.0). In this case, the master identifies that "Wake-up-from-sleep delay" is 5.0s.

### 9.4.6 Error message response

Operation errors may occur in communication-based control. For example, some parameters can only be read, but a write command is sent. In this case, the VFD returns an error message response.

Error message responses are sent from the VFD to the master. The following table lists the codes and definitions of the error message responses.

| Code | Name | Meaning |
|---|---|---|
| 01H | Invalid command | The command code received by the host controller is not allowed to be executed. The possible causes are as follows:<br>• The function code is applicable only on new devices and is not implemented on this device.<br>• The slave is in faulty state when processing this request. |
| 02H | Invalid data address | For the VFD, the data address in the request of the host controller is not allowed. In particular, the combination of the register address and the number of the to-be-sent bytes is invalid. |
| 03H | Invalid data value | The received data domain contains a value that is not allowed. The value indicates the error of the remaining structure in the combined request.<br>**Note:** It does not mean that the data item submitted for storage in the register includes a value unexpected by the program. |
| 04H | Operation failure | The parameter setting is invalid in the write operation. For example, a function input terminal cannot be set repeatedly. |
| 05H | Incorrect password | The password entered in the password verification address is different from that is specified by P07.00. |
| 06H | Incorrect data frame | The data frame sent from the host controller is incorrect in the length, or in the RTU format, the value of the CRC check bit is inconsistent with the CRC value calculated by the downstream device. |
| 07H | Parameter read-only | The parameter to be modified in the write operation of the host controller is a read-only parameter. |
| 08H | Parameter cannot be modified in running | The parameter to be modified in the write operation of the host controller cannot be modified during the running of the VFD. |
| 09H | Password protection | If the host controller does not provide the correct password to unlock the system to perform a read or write operation, the error of “system being locked” is reported. |

When returning a response, the slave uses a function code domain and fault address to indicate whether it is a normal response (no error) or exception response (an error occurs). In a normal response, the slave returns the corresponding function code and data address or sub-function code.

In an exception response, the slave returns a code that is equal to a normal code, but the first bit is logic 1.

For example, if the master sends a request message to a slave for reading a group of function code address data, the following code is generated:

0 0 0 0 0 0 1 1 (03H in the hexadecimal form)

In a normal response, the slave returns the same function code. In an exception response, the slave returns the following code:

1 0 0 0 0 0 1 1 (83H in the hexadecimal form)

In addition to the modification of the code, the slave returns a byte of exception code that describes the cause of the exception. After receiving the exception response, the typical processing of the master is to send the request message again or modify the command based on the fault information.

For example, to set the "Channel of running commands" (P00.01, the parameter address is 0001H) to 03 for the VFD whose address is 01H, the command is as follows:

| **01** | **06** | **00 01** | **00 03** | **98 0B** |
|---|---|---|---|---|
| VFD address | Write command | Parameter address | Parameter data | CRC |

However, the "Running command channel" ranges from 0 to 2. The value 3 is out of the setting range. In this case, the VFD returns an error message response.

| **01** | **86** | **04** | **43 A3** |
|---|---|---|---|
| VFD address | Exception response code | Error code | CRC |

The exception response code 86H (generated based on the MSB "1" of the write command 06H) indicates that it is an exception response to the write command (06H). The error code is 04H that indicates the error "Operation failure", which means "The parameter is set to an invalid value in the write operation".

### 9.4.7 Reading and writing examples

For the formats of the read and write commands, see sections 9.4.1 and 9.4.2.

#### 9.4.7.1 Example of reading command 03H

Example 1: Read state word 1 of the VFD whose address is 01H. According to the table of other Modbus function addresses in Table 9-1, the parameter address of status word 1 of the VFD is 2100H,

The read command transmitted to the VFD is as follows:

| **01** | **03** | **21 00** | **00 01** | **8E 36** |
|---|---|---|---|---|
| VFD address | Read command | Parameter address | Data quantity | CRC |

Assume that the following response is returned:

| **01** | **03** | **02** | **00 03** | **F8 45** |
|---|---|---|---|---|
| VFD address | Read command | Number of bytes | Data content | CRC |

The data content returned by the VFD is 0003H, which indicates that the VFD is in the stopped state.

Example 2: View information about the VFD whose address is 03H, including "Present fault type" (P07.27) to "5th-last fault type" (P07.32) of which the parameter addresses are 071BH to 0720H (contiguous 6 parameter addresses starting from 071BH).

The command transmitted to the VFD is as follows:

| **03** | **03** | **07 1B** | **00 06** | **B5 59** |
|---|---|---|---|---|
| VFD address | Read command | Start address | 6 parameters in total | CRC |

Assume that the following response is returned:

| **03** | **03** | **0C** | **00 23** | **00 23** | **00 23** | **00 23** | **00 23** | **00 23** | **5F D2** |
|---|---|---|---|---|---|---|---|---|---|
| VFD address | Read command | Number of bytes | Most recent fault type | Last fault type | 2nd-last fault type | 3rd-last fault type | 4th-last fault type | 5th-last fault type | CRC |

From the returned data, we can see that all the fault types are 0023H, that is, 35 in the decimal form, which means the maladjustment fault (STo).

**9.4.7.2 Write command 06H examples**

Example 1: Set the VFD whose address is 03H to be forward running. According to Table 9-1 other function parameters, the address of "Communication-based control command" is 2000H, and 0001H indicates forward running.

| Function description | Address definition | Data description | R/W |
|---|---|---|---|
| Communication-based control command | 2000H | 0001H: Run forward | R/W |
| | | 0002H: Run reversely | |
| | | 0003H: Jog forward | |
| | | 0004H: Jog reversely | |
| | | 0005H: Stop | |
| | | 0006H: Coast to stop | |
| | | 0007H: Fault reset | |
| | | 0008H: Jogging stop | |

The command transmitted from the master is as follows:

| 03 | 06 | 20 00 | 00 01 | 42 28 |
|---|---|---|---|---|
| VFD address | Write command | Parameter address | Forward running | CRC |

If the operation is successful, the following response (same as the command transmitted from the master) is returned:

| 03 | 06 | 20 00 | 00 01 | 42 28 |
|---|---|---|---|---|
| VFD address | Write command | Parameter address | Forward running | CRC |

Example 2: Set the max. output frequency to 100 Hz for the VFD with the address of 03H.

| Function code | Name | Description | Setting range | Default | Modify |
|---|---|---|---|---|---|
| P00.03 | Max. output frequency | P00.04–400Hz | 100.00–400.00 | 50.00Hz | ◎ |

According to the number of decimal places, the fieldbus scale of max. output frequency (P00.03) is 100. 100Hz timed by 100 is 10000 and the corresponding hex is 2710H.

The command transmitted from the master is as follows:

| 03 | 06 | 00 03 | 27 10 | 62 14 |
|---|---|---|---|---|
| VFD address | Write command | Parameter address | Parameter data | CRC |

If the operation is successful, the following response (same as the command transmitted from the master) is returned:

| 03 | 06 | 00 03 | 27 10 | 62 14 |
|---|---|---|---|---|
| VFD address | Write command | Parameter address | Parameter data | CRC |

**Note:** In the preceding command description, spaces are added to a command just for explanatory purposes. In practical applications, no space is required in the commands.

#### 9.4.7.3 Example of continuously writing command 10H

Example 1: Set the VFD whose address is 01H to be forward running at the frequency of 10Hz. According to Table 9-1 other Modbus function addresses, the address of "Communication-based control command" is 2000H, and 0001H indicates forward running. and the address of "Communication-based value setting" is 2001H, as shown in the following figure. 10 Hz is 03E8H in the hexadecimal form.

| Function description | Address definition | Data description | R/W |
|---|---|---|---|
| Communication-based | 2000H | 0001H: Run forward | R/W |

| **Function description** | **Address definition** | **Data description** | **R/W** |
|---|---|---|---|
| control command | | 0002H: Run reversely | |
| | | 0003H: Jog forward | |
| | | 0004H: Jog reversely | |
| | | 0005H: Stop | |
| | | 0006H: Coast to stop | |
| | | 0007H: Fault reset | |
| | | 0008H: Jogging stop | |
| Communication-based setting address | 2001H | Communication-based frequency setting (0–Fmax, unit: 0.01Hz) | R/W |
| | 2002H | PID reference (0–1000, in which 1000 corresponds to 100.0%) | |

In the actual operation, set P00.01 to 2 and P00.06 to 8.

The command sent from the master is as follows:

| **01** | **10** | **20 00** | **00 02** | **04** | **00 01** | **03 E8** | **3B 10** |
|---|---|---|---|---|---|---|---|
| VFD address | Continuous write command | Parameter address | Parameter quantity | Number of bytes | Froward running | 10 Hz | CRC |

If the operation is successful, the following response is returned:

| **01** | **10** | **20 00** | **00 02** | **4A 08** |
|---|---|---|---|---|
| VFD address | Continuous write command | Parameter address | Parameter quantity | CRC |

Example 2: Set "Acceleration time" of the VFD whose address is 01H to 10s, and "Deceleration time" to 20s.

| **Function code** | **Name** | **Description** | **Default** | **Modify** |
|---|---|---|---|---|
| P00.11 | ACC time 1 | P00.11 and P00.12 setting range: 0.0–3600.0s | Model depended | ○ |
| P00.12 | DEC time 1 | | Model depended | ○ |

The address of P00.11 is 000B, 10s is 0064H in the hexadecimal form, and 20s is 00C8H in the hexadecimal form.

The command sent from the master is as follows:

| **01** | **10** | **00 0B** | **00 02** | **04** | **00 64** | **00 C8** | **F2 55** |
|---|---|---|---|---|---|---|---|
| VFD address | Continuous write command | Parameter address | Parameter quantity | Number of bytes | 10s | 20s | CRC |

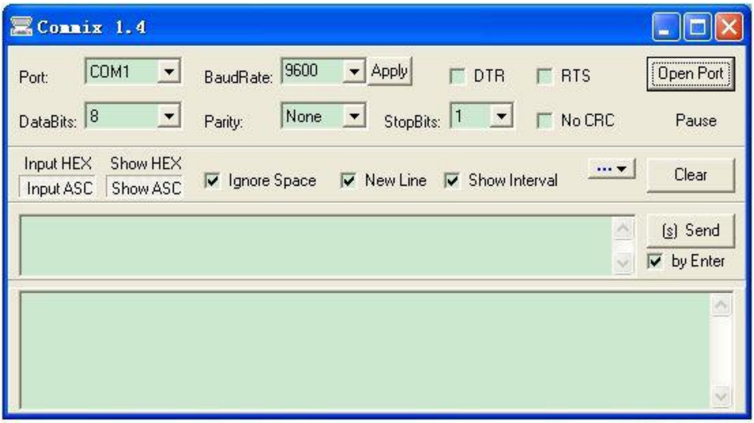
If the operation is successful, the following response is returned:

| 01 | 10 | 00 0B | 00 02 | 30 0A |
|---|---|---|---|---|
| VFD address | Continuous write command | Parameter address | Parameter quantity | CRC |

Note: In the preceding command description, spaces are added to a command just for explanatory purposes. In practical applications, no space is required in the commands.

### 9.4.7.4 Example of Modbus communication commissioning

A PC is used as the host, an RS232-RS485 converter is used for signal conversion, and the PC serial port used by the converter is COM1 (an RS232 port). The host controller commissioning software is the serial port commissioning assistant Commix, which can be downloaded from the Internet. Download a version that can automatically execute the CRC check function. The following figure shows the interface of Commix.




First, set the serial port to **COM1**. Then, set the baud rate consistently with P14.01. The data bits, check bits, and stop bits must be set consistently with P14.02. If the RTU mode is selected, you need to select the hexadecimal form **Input HEX**. To set the software to automatically execute the CRC function, you need to select ModbusRTU, select **CRC16 (Modbus RTU)**, and set the start byte to **1**. After the auto CRC check function is enabled, do not enter CRC information in commands. Otherwise, command errors may occur due to repeated CRC check.

The commissioning command to set the VFD whose address is 03H to run forward is as follows:

| 03 | 06 | 20 00 | 00 01 | 42 28 |
|---|---|---|---|---|
| VFD address | Write command | Parameter address | Forward running | CRC |

**Note:**

1. Set the address (P14.00) of the VFD to 03.

2. Set "Channel of running commands" (P00.01) to "Communication", and set "Communication channel of running commands" (P00.02) to the Modbus communication channel.
3. After you click **Send**, if the line configuration and settings are correct, a response transmitted by the VFD is received.

## 9.5 Common communication faults

Common communication faults include the following:

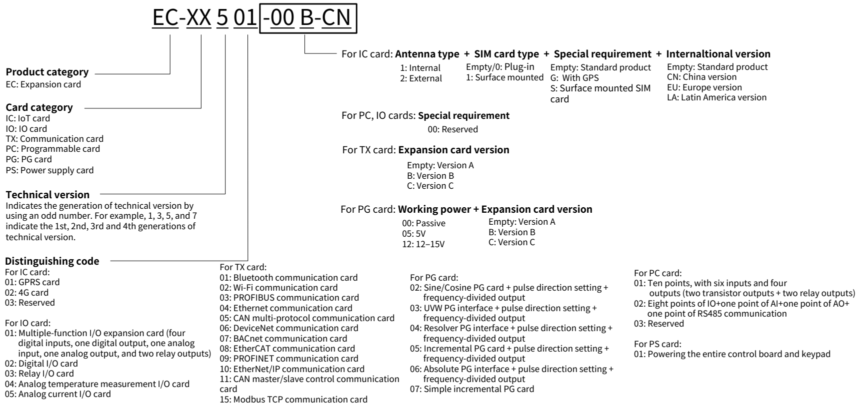
• No response is returned.
• The VFD returns an exception response.

Possible causes of no response include the following:

1. The serial port is set incorrectly. For example, the adapter uses the serial port COM1, but COM2 is selected for the communication.
2. The settings of the baud rates, data bits, end bits, and check bits are inconsistent with those set on the VFD.
3. The positive pole (+) and negative pole (-) of the RS485 bus are connected reversely.
4. The resistor connected to 485 terminals on the terminal block of the VFD is set incorrectly.

# Appendix A Expansion card

## A.1 Model definition




The following table describes expansion cards that the VFD supports. The expansion cards are optional and need to be purchased separately.

| Name | Model | Specification | Ordering information |
|---|---|---|---|
| I/O expansion card | EC-IO501-00 | ● Four digital inputs<br>● One digital output<br>● One analog input<br>● One analog output<br>● Two relay outputs: one double-contact output and one single-contact output | 11023–00083 |
| | EC-IO503-00 | ● Two digital inputs<br>● Six relay outputs | 11023-00136 |
| PROFIBUS-DP communication card | EC-TX503D | ● Supporting the PROFIBUS-DP protocol | 11023-00151 |
| CAN multi-protocol communication card | EC-TX505D | ● Based on the CAN2.0A physical layer<br>● Supporting the CANopen protocol<br>● Adopting INVT master-slave control proprietary protocol | 11023-00164 |
| PROFINET communication card | EC-TX509C | ● Supporting the PROFINET protocol | 11023-00149 |
| BACnet MSTP | EC-TX507B | ● Supporting the BACnet protocol and BACnet | 11023-00163 |

| Name | Model | Specification | Ordering information |
|---|---|---|---|
| communication card | | MSTP devices.<br>● Providing one BACnet MSTP port and supports half-duplex operations of 115.2kbps.<br>● Adopting the shielded twisted-pair cable and supporting the daisy chain connection network topologies, with the number of slave nodes up to 31.<br>● Supporting timeout detection. | |
| EtherNet IP/ Modbus TCP protocol communication card | EC-TX510B | When the switch selects EtherNet IP:<br>● Supporting the EtherNet IP protocol and EtherNet IP<br>● Equipped with two EtherNet IP ports, supporting 10M/100M half/full duplex operating.<br>● Equipped with two RJ45 interfaces, which do not distinguish the direction and can be swappable<br>● Supporting star and line IP network topologies<br>When the switch selects Modbus TCP:<br>● Supporting the Modbus TCP protocol and Modbus TCP secondary nodes<br>● Equipped with two Modbus TCP ports, supporting 10M/100M half/full duplex operating<br>● Supporting star and line TCP network topologies<br>When the switch selects Ethernet:<br>● Supporting INVT Ethernet protocol<br>● Supporting the connection to INVT's host controller monitoring software INVT Workshop for monitoring and oscillography, allowing multi-card networking monitoring | 11023-00197 |
| 24V power supply expansion card | EC-PS501-24 | ● Input voltage range: DC18–30V(Rated 24Vdc)/2A<br>● Three channels of output voltage: +5V/1A (±5%), +15V/0.2A (±10%), -15V/0.2A (±10%) | 11023-00135 |

## A.2 Dimensions and installation

All expansion cards are of the same dimensions (108× 39mm) and can be installed in the same way.

All the VFD models provide two expansion card slots. Note the following when installing or uninstalling an expansion card:

1. Ensure that no power is applied before installing the expansion card.
2. To ease wiring, comply with the following although any supported expansion card at either slot can be identified:

| Cabinet power range | Installation precautions |
|---|---|
| 1.5–7.5kW | Install a communication card in SLOT2. Before installing a DP communication card, remove the middle casing and lower casing. |
| 11–800kW | It is recommended to install a DP communication card in SLOT1. |

The following figure shows the installation diagram and a VFD with expansion cards installed.

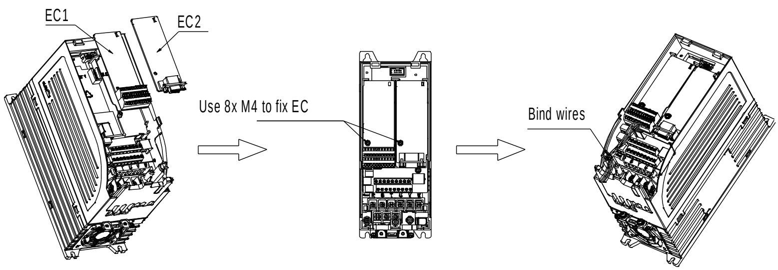



Figure A-1 1.5–7.5kW VFDs with expansion cards installed

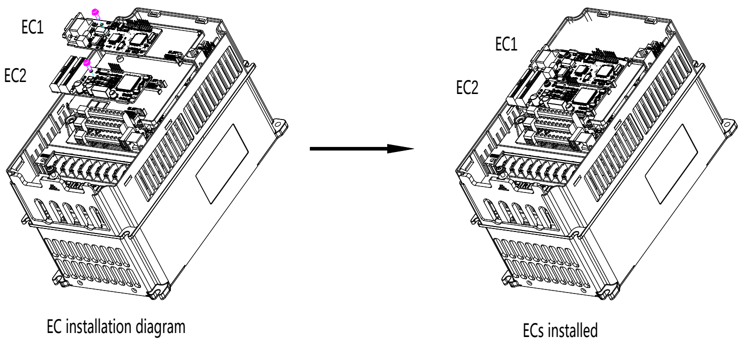



Figure A-2 11–800kW VFDs with expansion cards installed

Figure A-3 shows the expansion card installation procedure.

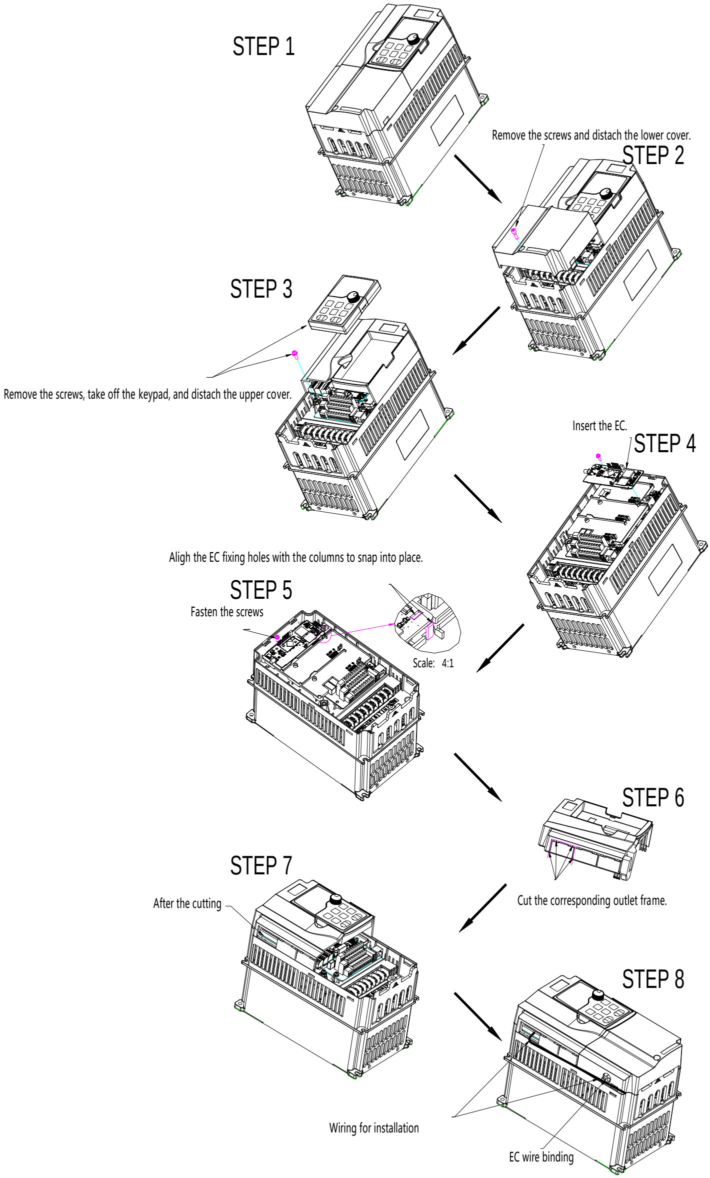



Figure A-3 Expansion card installation procedure

## A.3 Wiring

1. Ground a shielded cable as follows.

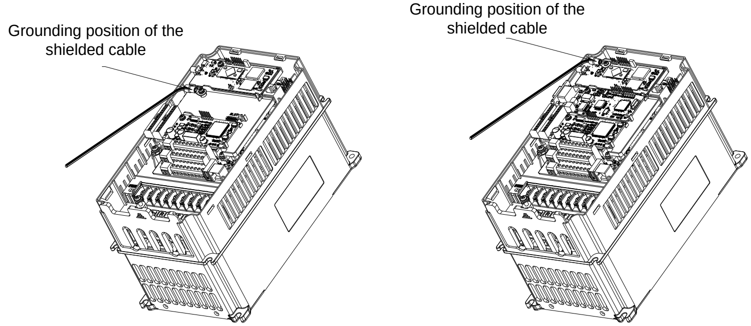



Figure A-4 Expansion card grounding

2. Wire an expansion card as follows:

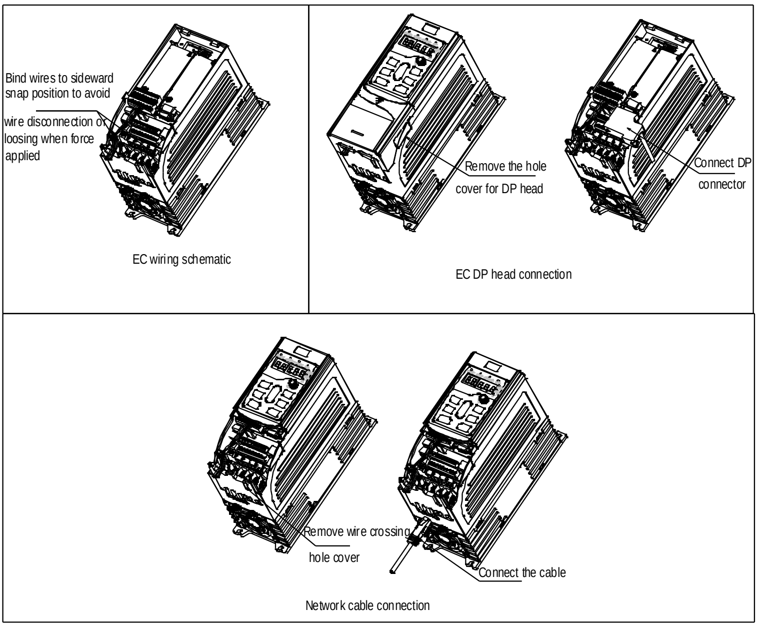



Figure A-5 Expansion card wiring for 1.5–7.5kW VFDs

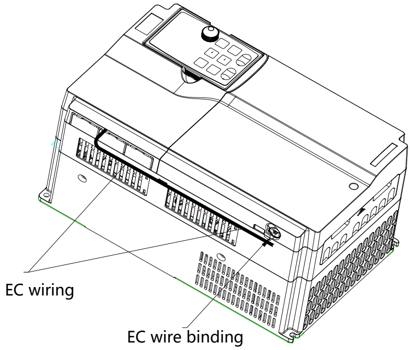
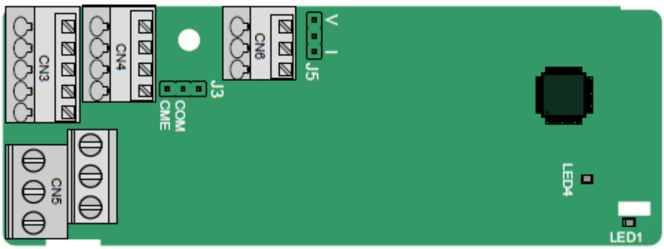



Figure A-6 Expansion card wiring for 11–630kW VFDs

## A.4 I/O expansion cards

### A.4.1 EC-IO501-00




The terminals are arranged as follows:

CME and COM are shorted through J3 before delivery, and J5 is the jumper for selecting the output type (voltage or current) of AO2.

| | | |
|---|---|---|
| AI3 | AO2 | GND |

| | | | | |
|---|---|---|---|---|
| COM | CME | Y2 | S5 | |
| PW | +24V | S6 | S7 | S8 |

| | | | |
|---|---|---|---|
| RO3A | RO3B | RO3C | |
| | RO4A | | RO4C |

Indicator definition:

| Indicator | Definition | Function |
|---|---|---|
| LED1 | Status indicator | On: The expansion card is connecting with the control board.<br>Blinking (On: 500ms; Off: 500ms): The expansion card is connected with the control board.<br>Off: The expansion card is disconnected from the control board. |

| Indicator | Definition | Function |
|---|---|---|
| LED4 | Power indicator | On: The expansion card is powered on.<br>Off: The expansion card is not powered on. |

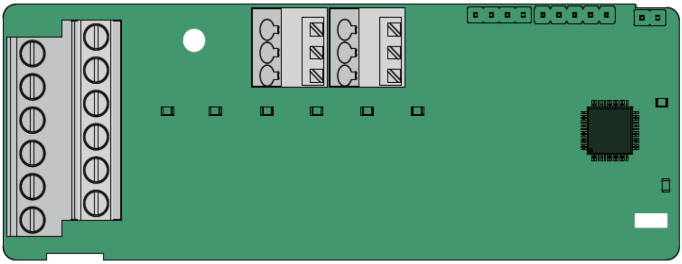
EC-IO501-00 can be used in scenarios where the I/O interfaces of VFD cannot meet the application requirements. It can provide 4 digital inputs, 1 digital output, 1 analog input, 1 analog output, and two relay outputs. It is user-friendly, providing relay outputs through European-type screw terminals and other inputs and outputs through spring terminals.

EC-IO501-00 terminal functions:

| Category | Terminal symbol | Terminal name | Description |
|---|---|---|---|
| Power supply | PW | External power | Used to provide input digital working power from the external to the internal<br>Voltage range: 12–24V<br>PW and +24V have been short connected before delivery. |
| Analog input and output | AI3—GND | Analog input 1 | ● Input range: For AI3, 0(2)–10V or 0(4)–20mA<br>● Input impedance: 20kΩ for voltage input or 250Ω for current input<br>● Whether voltage or current is used for input is set through the corresponding function code.<br>● Resolution: 5mV when 10V corresponds to 50Hz<br>● Error: ±0.5% when input is above 5V or 10mA at 25°C |
| | AO2—GND | Analog output 1 | ● Output range: 0(2)–10V or 0(4)–20mA<br>● Whether voltage or current is used for output is set through the jumper J5.<br>● Error: ±0.5% when output is above 5V or 10mA at 25°C |
| Digital input and output | S5—COM | Digital input 1 | ● Internal impedance: 3.3kΩ<br>● 12–30V voltage input is acceptable<br>● Bi-direction input terminal<br>● Max. input frequency: 1kHz |
| | S6—COM | Digital input 2 | |
| | S7—COM | Digital input 3 | |
| | S8—COM | Digital input 4 | |
| | Y2—CME | Digital output | ● Switch capacity: 200mA/30V<br>● Output frequency range: 0–1kHz<br>● The terminals CME and COM are shorted through J3 before delivery. |

| Category | Terminal symbol | Terminal name | Description |
|---|---|---|---|
| Relay output | RO3A | NO contact of relay 3 | ● Contact capacity: 3A/AC250V, 1A/DC30V<br>● Cannot be used as high frequency digital output. |
| | RO3B | NC contact of relay 3 | |
| | RO3C | Common contact of relay 3 | |
| | RO4A | NO contact of relay 4 | |
| | RO4C | Common contact of relay 4 | |

### A.4.2 EC-IO503-00



The terminals of EC-IO503-00 are arranged as follows:

| | | |
|---|---|---|
| COM | S9 | S10 |

| | | |
|---|---|---|
| COM | PW | +24V |

| | | | | | |
|---|---|---|---|---|---|
| RO5A | RO5C | RO6A | RO6C | RO7A | RO7C |
| RO8A | RO8C | RO9A | RO9C | RO10A | RO10C |

Indicator definition:

| Indicator | Definition | Function |
|---|---|---|
| LED1 | Status indicator | On: RO5 is switched on.<br>Off: RO5 is switched off. |
| LED2 | Status indicator | On: RO6 is switched on.<br>Off: RO6 is switched off. |
| LED3 | Status indicator | On: RO7 is switched on.<br>Off: RO7 is switched off. |
| LED4 | Status indicator | On: RO8 is switched on.<br>Off: RO8 is switched off. |
| LED5 | Status indicator | On: RO9 is switched on.<br>Off: RO9 is switched off. |

| Indicator | Definition | Function |
|---|---|---|
| LED6 | Status indicator | On: RO10 is switched on.<br>Off: RO10 is switched off. |
| LED7 | Power indicator | On: The expansion card is powered on.<br>Off: The expansion card is not powered on. |
| LED8 | Status indicator | On: The expansion card is connecting with the control board.<br>Blinking (On: 500ms; Off: 500ms): The expansion card is connected with the control board.<br>Off: The expansion card is disconnected from the control board. |

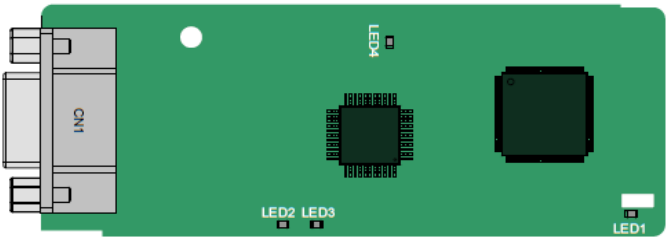
EC-IO503-00 can be used in scenarios where the I/O interfaces of VFD cannot meet the application requirements. It can provide 2 analog inputs and 6 analog outputs. It is user-friendly, providing relay outputs through European-type screw terminals and other inputs and outputs through spring terminals.

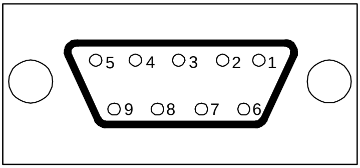
EC-IO503-00 terminal function description

<table>
<tr><th>Category</th><th>Terminal symbol</th><th>Terminal name</th><th>Description</th></tr>
<tr><td rowspan="3">Power supply</td><td>COM</td><td rowspan="3">External power</td><td rowspan="3">Used to provide I/O expansion card working power from the external to the internal<br>Voltage: +24V<br>PW and +24V are shorted during use</td></tr>
<tr><td>PW</td></tr>
<tr><td>+24V</td></tr>
<tr><td rowspan="2">Digital input</td><td>S9—COM</td><td>Digital input 1</td><td rowspan="2">● Internal impedance: 3.3kΩ<br>● 12–30V voltage input is acceptable.<br>● Max. input frequency: 1kHz</td></tr>
<tr><td>S10—COM</td><td>Digital input 2</td></tr>
<tr><td rowspan="12">Relay output</td><td>RO5A</td><td>NO contact of relay 5</td><td rowspan="12">● Contact capacity: 3A/AC250V, 1A/DC30V<br>● Cannot be used as high frequency digital output</td></tr>
<tr><td>RO5C</td><td>NO contact of relay 5</td></tr>
<tr><td>RO6A</td><td>NO contact of relay 6</td></tr>
<tr><td>RO6C</td><td>NO contact of relay 6</td></tr>
<tr><td>RO7A</td><td>NO contact of relay 7</td></tr>
<tr><td>RO7C</td><td>NO contact of relay 7</td></tr>
<tr><td>RO8A</td><td>NO contact of relay 8</td></tr>
<tr><td>RO8C</td><td>NO contact of relay 8</td></tr>
<tr><td>RO9A</td><td>NO contact of relay 9</td></tr>
<tr><td>RO9C</td><td>NO contact of relay 9</td></tr>
<tr><td>RO10A</td><td>NO contact of relay 10</td></tr>
<tr><td>RO10C</td><td>NO contact of relay 10</td></tr>
</table>

## A.5 Communication cards

### A.5.1 PROFIBUS-DP communication card (EC-TX503D)




CN1 is a 9-pin D-type connector, as shown in the following figure.

| Connector pin | | Description |
|---|---|---|
| 1 | - | Unused |
| 2 | - | Unused |
| 3 | B-Line | Data+ (twisted pair 1) |
| 4 | RTS | Request sending |
| 5 | GND_BUS | Isolation ground |
| 6 | +5V BUS | Isolated power supply of 5 V DC |
| 7 | - | Unused |
| 8 | A-Line | Data- (twisted pair 2) |
| 9 | - | Unused |
| Housing | SHLD | PROFIBUS cable shielding line |

+5V and GND_BUS are bus terminators. Some devices, such as the optical transceiver (RS485), may need to obtain power through these pins.

On some devices, the transmission and receiving directions are determined by RTS. In normal applications, only A-Line, B-Line, and the shield layer need to be used.

Indicator definition:

| Indicator | Definition | Function |
|---|---|---|
| LED1 | Status indicator | On: The expansion card is connecting with the control board.<br>Blinking (On: 500ms; Off: 500ms): The expansion card is connected with the control board.<br>Off: The expansion card is disconnected from the control board. |
| LED2 | Online indicator | On: The communication card is online and data exchange can be |

| Indicator | Definition | Function |
|---|---|---|
| | | performed.<br>Off: The communication card is not in the online state. |
| LED3 | Offline/Fault indicator | On: The communication card is offline and data exchange cannot be performed.<br>Blinking: The communication card is not in the offline state.<br>Blinking at the frequency of 1 Hz: A configuration error occurs. The length of the user parameter data set during the initialization of the communication card is different from that during the network configuration.<br>Blinking at the frequency of 2 Hz: User parameter data is incorrect. The length or content of the user parameter data set during the initialization of the communication card is different from that during the network configuration.<br>It blinks at the frequency of 4Hz when an error occurs in the ASIC initialization of PROFIBUS communication.<br>Off: The diagnosis function is disabled. |
| LED4 | Power indicator | On: The expansion card is powered on.<br>Off: The expansion card is not powered on. |

**Note:** For details, see the communication card manual.

### A.5.2 CAN multi-protocol communication card (EC-TX505D)

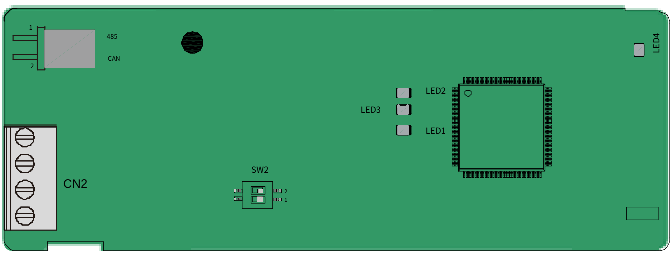



Table A-1 Parts on the EC-TX505D expansion card

| Symbol | Name | Description |
|---|---|---|
| PGND | Isolation ground | Isolation ground |
| PE | Shielded cable | CAN bus shielding |
| CANH | CAN positive input | CAN bus high level signal |
| CANL | CAN negative input | CAN bus low level signal |
| 485 | RS485 terminal resistor switch | No terminal resistor is connected between RS485+ and RS485-. |
| | | A 120 Ω terminal resistor is connected between RS485+ and RS485-. |

| Symbol | Name | Description |
|---|---|---|
| CAN | CAN terminal resistor switch | No terminal resistor is connected between CAN_H and CAN_L. |
| | | A 120 Ω terminal resistor is connected between CAN_H and CAN_L. |

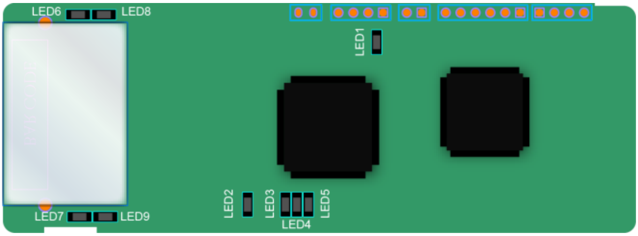
**Note:** To select the protocol of this expansion card, please set the switch SW2 according to the following relationship before power on.

| SW2 | | |
|---|---|---|
| **1** | **2** | **Protocol type** |
| OFF | OFF | CANopen |
| ON | OFF | CAN master/slave |

| Indicator | Definition | Function |
|---|---|---|
| LED1 | Status indicator | On: The expansion card is connecting with the control board.<br>Blinking (On: 500ms; Off: 500ms): The expansion card is connected with the control board.<br>Off: The expansion card is disconnected from the control board. |
| LED2 | Run indicator | On: The communication card is in the operating state.<br>Blinking (On: 250 ms; Off: 250 ms): The communication card is in the pre-operation state.<br>Off: A fault occurs; the reset pin of the communication card and the power supply are not properly connected; the expansion card is in a stopped state. |
| LED3 | Fault indicator | On: The CAN controller bus is off; a fault occurs on the VFD; received frame lost or incorrect.<br>Off: The communication card is in the working state. |
| LED4 | Power indicator | On: The expansion card is powered on.<br>Off: The expansion card is not powered on. |

**Note:** For details, see the communication card manual.

### A.5.3 PROFINET communication card (EC-TX509C)




The terminal CN2 adopts standard RJ45 interfaces, which are in the dual design, and the two RJ45 interfaces are not distinguished from each other and can be interchangeably inserted. They are arranged as follows:

| Pin | Name | Description |
|---|---|---|
| 1 | TX+ | Transmit Data+ |
| 2 | TX- | Transmit Data- |
| 3 | RX+ | Receive Data+ |
| 4 | n/c | Not connected |
| 5 | n/c | Not connected |
| 6 | RX- | Receive Data- |
| 7 | n/c | Not connected |
| 8 | n/c | Not connected |

Indicator definition:

The PROFINET communication card has 9 indicators, among which LED1 is the power indicator, LED2–5 are the communication status indicators of the communication card, and LED6–9 are the status indicators of the network port.

| Indicator | Color | Status | Description |
|---|---|---|---|
| LED1 | Green | / | 3.3V power indicator |
| LED2 (Bus status indicator) | Red | On | No network connection |
| | | Blinking | The connection to the network cable between the PROFINET controller is OK, but the communication is not established. |
| | | Off | Communication with the PROFINET controller has been established. |
| LED3 (System fault indicator) | Green | On | PROFINET diagnosis exists. |
| | | Off | No PROFINET diagnosis. |
| LED4 (Slave ready indicator) | Green | On | TPS-1 protocol stack has started. |
| | | Blinking | TPS-1 waits for MCU initialization. |
| | | Off | TPS-1 protocol stack does not start. |

| Indicator | Color | Status | Description |
|---|---|---|---|
| LED5 (Maintenance status indicator) | Green | / | Manufacturer-specific, depending on the characteristics of the device. |
| LED6/7 (Network port status indicator) | Green | On | The PROFINET communication card and PC/PLC have been connected by using a network cable. |
| | | Off | The connection between the PROFINET communication card and PC/PLC has not been established. |
| LED8/9 (Network port communication indicator) | Green | On | The PROFINET communication card and PC/PLC are communicating. |
| | | Off | The PROFINET communication card and PC/PLC have no communication yet. |

Electrical connection:

The PROFINET communication card adopts standard RJ45 interfaces, which can be used in a linear network topology and a star network topology. The linear network topology electrical connection diagram is shown in Figure A-7.

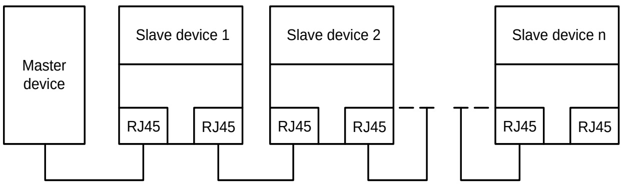



Figure A-7 Linear network topology electrical connection

**Note:** For the star network topology, you need to prepare PROFINET switches.

The star network topology electrical connection diagram is shown in Figure A-8.

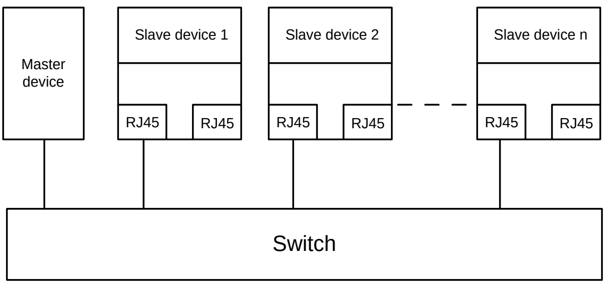
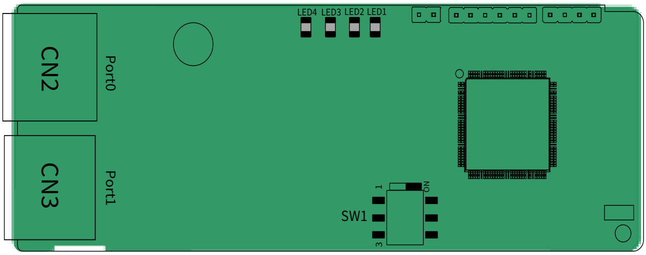



Figure A-8 Star network topology electrical connection

### A.5.4 EtherNet IP and Modbus TCP protocol communication card (EC-TX510B)




The expansion card has two communication ports, both of which adopt standard RJ45 interfaces and can be interchangeably inserted. It supports selecting the protocol via the DIP switch before power-on. The default selection is EtherNet IP, with Modbus TCP and INVT's own Ethernet UDP protocol as optional choices.

**Note:** For this card, before power-on, set the SW2 switch according to the mapping between protocols and positions.

Table A-2 Switch definition

| **SW1** | **Protocol type** | **1** | **2** | **3** |
|---|---|---|---|---|
| | EtherNet IP | ON | ON | ON |
| | EtherNet UDP | OFF | ON | ON |
| | Modbus TCP | ON | OFF | ON |
| | Reserved | Other | Other | Other |

Table A-3 EtherNet IP indicator description

| **Indicator** | **Color** | **Definition** | **Function** |
|---|---|---|---|
| LED1 | Green | On | The expansion card is shaking hands with the VFD. |
| | | Blinking (1Hz) | The expansion card and VFD communicate normally. |
| | | Off | The expansion card and VFD communicate improperly. |
| LED2 | Green | On | The communication between the expansion card and the PLC is online and data exchange is allowed. |
| | | Off | The communication between the expansion card and PLC is offline. |
| LED3 | Red | On | Failed to set up I/O between the expansion card and the PLC. |
| | | Blinking (1Hz) | Incorrect PLC configuration. |
| | | Blinking (2Hz) | The expansion card failed to send data to the PLC. |
| | | Blinking (4Hz) | The connection between the expansion card and PLC timed out. |
| | | Off | No fault |
| LED4 | Red | On | 3.3V power indicator |

Table A-4 Modbus TCP indicator description

| Indicator | Color | Definition | Function |
|---|---|---|---|
| LED1 | Green | On | The expansion card is shaking hands with the VFD. |
| | | Blinking (1Hz) | The expansion card and VFD communicate normally. |
| | | Off | The expansion card and VFD communicate improperly. |
| LED2 | Green | On | The communication between the expansion card and the PLC is online and data exchange is allowed. |
| | | Off | The communication between the expansion card and PLC is offline. |
| LED3 | Red | On | Expansion card has no valid data received. |
| | | Blinking (1Hz) | The message function code is not used or defined |
| | | Blinking (8Hz) | Message address error |
| | | Off | No fault |
| LED4 | Red | On | 3.3V power indicator |

Table A-5 Ethernet indicator description

| Indicator | Color | Definition | Function |
|---|---|---|---|
| LED1 | Green | On | The expansion card is shaking hands with the VFD. |
| | | Blinking (1Hz) | The expansion card and VFD communicate normally (handshake successful). |
| | | Off | The expansion card and VFD communicate improperly. |
| LED2 | Green | On | The connection between the expansion card and PC is successful. |
| | | Off | The expansion card fails to connect with PC (abnormal network cable). |
| LED3 | Red | Blinking (4Hz) | The expansion card is successfully connected to the PC but communication fails (abnormal IP address). |
| | | Off | No fault |
| LED4 | Red | On | 3.3V power indicator |

Electrical connection:

The communication card adopts standard RJ45 interfaces, which can be used in a linear, star, and ring network topologies. The electrical connection diagram is shown as follows.

Use CAT5, CAT5e, and CAT6 network cables for electrical wiring. When the communication distance is greater than 50m, use high-quality network cables that meet the high-quality standards.

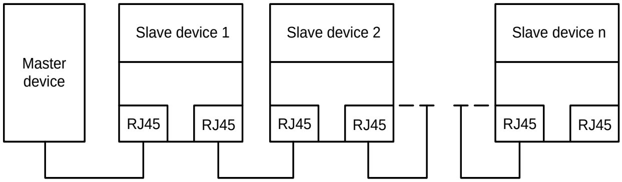



Figure A-9 Linear network topology electrical connection

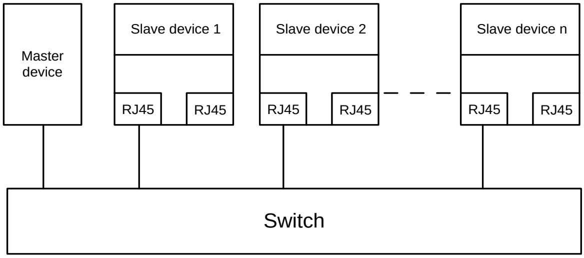



Figure A-10 Star network topology electrical connection

**Note:** For the star network topology, you need to prepare Ethernet switches.

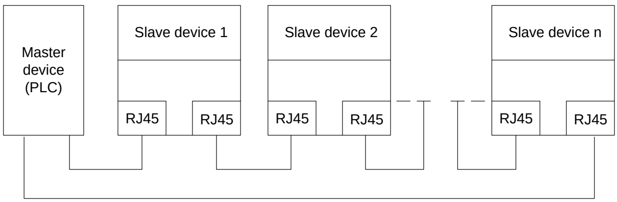



Figure A-11 Ring network topology electrical connection

**A.5.5 BACnet MSTP communication card (EC-TX507B)**

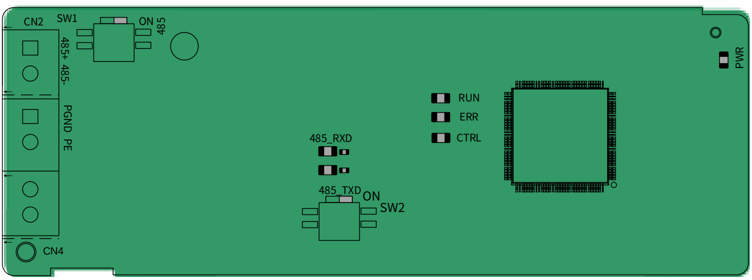


Table A-6 Terminal function definition

| Signal | Port | Description |
|---|---|---|
| 485+ | RS485 | Positive differential signal |
| 485- | | Negative differential signal |
| PGND | / | Signal ground |
| PE | / | Earth |
| 485 | Switch | OFF: Do not connect the terminal resistor<br>ON: Connect the terminal resistor |

Table A-7 Function description

| Function description | | Specifications |
|---|---|---|
| Main functions | Features | 1. Supporting the BACnet protocol and BACnet MSTP devices.<br>2. Providing one BACnet MSTP port and supports half-duplex operations of 115.2kbps.<br>3. Adopting the shielded twisted-pair cable and supporting the daisy chain connection network topologies, with the number of slave nodes up to 31.<br>4. Supporting timeout detection. |
| | Service | 1. Single-property reading service<br>2. Multi-property reading service<br>3. Single-property writing service<br>4. Multi-property writing service<br>5. I-Am service<br>6. I-Have service<br>7. Device communication control service<br>8. Device re-initialization service |
| | Function | 1. Supporting the setting of 32 analog objects.<br>2. Supporting the reading and writing of VFD process data and function codes, reading of VFD status words, and writing of VFD control words.<br>3. Supporting the Yet Another BACnet Explorer (YABE) host controller and PLC controller |

Table A-8 Indicator functions

| Indicator | Definition | Function |
|---|---|---|
| CTRL | Status indicator | On: The expansion card is connecting with the control board.<br>Blinking periodically (the period is 1s, on for 0.5s, and off for the other 0.5s): The expansion card is properly connected to the control board.<br>Off: The expansion card is disconnected from the control board. |
| RUN | Run indicator (green) | On: BACnet communication state. Received BACnet data frames.<br>Blinking periodically (on-off at a 0.5s interval): Online. Waiting to receive BACnet data frames.<br>Off: Not powered or in fault state |

| Indicator | Definition | Function |
|---|---|---|
| ERR | Fault indicator (red) | Off: No fault<br>Blinking periodically (on-off at a 0.5s interval for twice and 2s off): Fault state. Duplicate address. The VFD keypad reports E-bAC.<br>Blinking periodically (on-off at a 0.5s interval for three times and 2s off): Fault state. No BACnet data frames received in specified time. (Timeout detection must be enabled, that is, the timeout time cannot be 0.) The VFD keypad reports an E-bAC fault. |
| PWR | Power indicator | It is on once the control board feeds power to the BACnet MSTP card. |
| 485_TXD | Transmission indicator (green) | On: Transmitting. The device is transmitting data fast on the RS485 network.<br>Blinking: Transmitting. The device is transmitting data on the RS485 network.<br>Off: Not transmitting. The device does not transmit data on the RS485 network. |
| 485_RXD | Reception indicator (red) | On: Receiving. The device is receiving data fast on the RS485 network.<br>Blinking: Receiving. The device is receiving data on the RS485 network.<br>Off: Not receiving. The device does not receive data on the RS485 network. |

### A.5.6 24V power supply expansion card (EC-PS501-24)


Indicator definition:

| Indicator | Definition | Function |
|---|---|---|
| LED1 | 24V power indicator | Indicator for the external 24V power. |
| LED2 | 5V power indicator | Indicator for the 5V power that is provided for the control board after the switch power converts external power. |

The 24V power supply card is mainly used to connect to external 24V power to power the control board, avoiding to apply electricity for independent control board commissioning. During wiring, connect to +24V and COM according to the CN2 sign.

# Appendix B Technical data

## B.1 What this chapter contains

This chapter describes the technical data of the VFD and its compliance to CE and other quality certification systems.

## B.2 Derated application

### B.2.1 Capacity

Choose a VFD model based on the rated current and power of the motor. To ensure the rated power of the motor, the rated output current of the VFD must be larger or equal to the rated current of the motor. The rated power of the VFD must be higher or equal to that of the motor.

**Note:**

✧ The rated capacity is the capacity at the ambient temperature of 40°C.

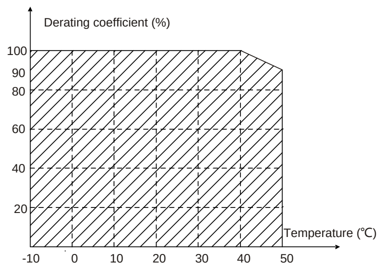
✧ You need to check and ensure that the power flowing through the common DC connection in the common DC system does not exceed the rated power of the motor.

### B.2.2 Derating

If the ambient temperature at the VFD installation site exceeds 40°C, the VFD installation site altitude exceeds 1000m, a cover with heat dissipation vents is used, or the carrier frequency is higher than the recommended (for the recommended frequency, see P00.14), the VFD needs to be derated.

#### B.2.2.1 Derating due to temperature

When the temperature ranges from 40°C to 50°C, the rated output current is derated by 1% for each increased 1°C. For the actual derating, see the following figure.




**Note:** It is not recommended to use the VFD at an environment with the temperature higher than 50°C. If you do, you shall be held accountable for the consequences caused.

#### B.2.2.2 Derating due to altitude

The VFD does not need to be derated when it is used below an altitude of 1000m. When it is used in the altitude range of 1000–4800m, the capacity is reduced by 1% for every increase of 100m.

**Note:** When the VFD is used at altitudes above 2000m and employs a corner grounding device, special considerations apply. For more information, please contact your local INVT representative.

#### B.2.2.3 Derating due to carrier frequency

The carrier frequency of the VFD varies with power class. The VFD rated power is defined based on the carrier frequency factory setting. If the carrier frequency exceeds the factory setting, the VFD power is derated by 10% for each increased 1 kHz.

## B.3 Grid specifications

| | |
|---|---|
| Grid voltage | AC 3PH 380V–480V |
| Short-circuit capacity | According to the definition in IEC 61439-1, the maximum allowable short-circuit current at the incoming end is 100 kA. Therefore, the VFD is applicable to scenarios where the transmitted current in the circuit is no larger than 100kA when the VFD runs at the maximum rated voltage. |
| Frequency | 50/60Hz±5%, with a maximum change rate of 20%/s |

## B.4 Motor connection data

| | |
|---|---|
| Motor type | Asynchronous induction motor or permanent-magnet synchronous motor |
| Voltage | 0–U1 (motor rated voltage), 3PH symmetrical, $U_{max}$ (VFD rated voltage) at the field-weakening point |
| Short-circuit protection | The motor output short-circuit protection meets the requirements of IEC 61800-5-1. |
| Frequency | 0–400Hz |
| Frequency resolution | 0.01Hz |
| Current | See section 3.6 "Product ratings". |
| Power limit | 1.1 times of the motor rated power |
| Field-weakening point | 10–400Hz |
| Carrier frequency | 2, 4, 8, 12, or 15kHz |

### B.4.1 EMC compatibility and motor cable length

To meet IEC/EN61800-3 C3 and C2 electromagnetic environment requirements, GD270 series offers models with built-in filters. The allowable motor cable lengths (with shielding) under a 2kHz carrier frequency condition are shown in the following table.

| **Power range** | **Length of supported motor cable (with shield) (unit: m)** | |
|---|---|---|
| | **Environment category II (C3)** | **Environment category II (C2)** |
| 1.5–22kW (built-in C2 filter) | 50 | 20 |
| 30–37kW (built-in C3 filter) | 30 | Not met |
| 45–800kW (built-in C3 filter) | 50 | Not met |

For details about the C3 and C2 EMC environment categories, see section B.6 EMC regulations.

**Note:** For 5.5–7.5kW models, an additional magnetic ring needs to be installed on the motor output side for the VFD to achieve the motor cable length specifications listed in the table above. The magnetic ring is included as a standard accessory with the VFD.

## B.5 Application standards

The following table describes the standards that VFDs comply with.

| | |
|---|---|
| EN/ISO 13849-1 | Safety of machinery—Safety-related parts of control systems—Part 1: General principles for design |
| IEC/EN 60204-1 | Safety of machinery. Electrical equipment of machines. Part 1: General requirements |
| IEC/EN 62061 | Safety of machinery—Safety-related functional safety of electrical, electronic, and programmable electronic control systems |
| IEC/EN 61800-3 | Adjustable speed electrical power drive systems. Part 3: EMC requirements and specific test methods |
| IEC/EN 61800-5-1 | Adjustable speed electrical power drive systems—Part 5-1: Safety requirements—Electrical, thermal and energy |

### B.5.1 CE marking

The CE marking on the VFD nameplate indicates that the VFD is CE-compliant, meeting the regulations of the European low-voltage directive (2014/35/EU) and EMC directive (2014/30/EU).

### B.5.2 EMC compliance declaration

European union (EU) stipulates that the electric and electrical devices sold in Europe cannot generate electromagnetic disturbance that exceeds the limits stipulated in related standards, and can work properly in environments with certain electromagnetic interference. The EMC product standard (EN 61800-3) describes the EMC standards and specific test methods for adjustable speed electrical power drive systems. Our products have been compliant with these EMC regulations.

## B.6 EMC regulations

The EMC product standard (EN 61800-3) describes the EMC requirements on VFDs.

Application environment categories:

First environment: Civilian environment, including application scenarios where VFDs are directly connected to the civil power supply low-voltage grids without intermediate transformers.

Second environment: All environments other than those directly connected to low-voltage power supply networks serving civilian applications.

VFD categories:

Category C1: VFD of rated voltage lower than 1000V, applied to the first environment.

Category C2: VFD of rated voltage lower than 1000V, which is neither a non-plug, socket, nor mobile devices and must be installed and commissioned by a professional person when used in the first environment.

**Note:** The EMC standard IEC/EN 61800-3 no longer restricts the power distribution of the VFD, but defines the use, installation, and commissioning of the VFD. Specialized personnel or organizations must have the necessary skills (including the EMC-related knowledge) for installing and/or performing commissioning on the electrical drive systems.

Category C3: VFD of rated voltage lower than 1000V, applied to the second environment. They cannot be applied to the first environment.

Category C4: VFD of rated voltage higher than 1000 V, or rated current higher or equal to 400 A, applied to complex systems in the second environment.

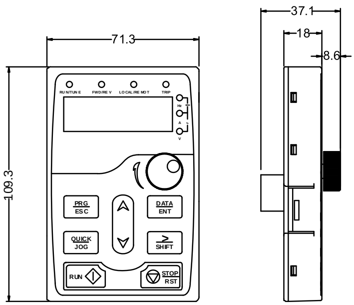
# Appendix C Dimension drawings

## C.1 What this chapter contains

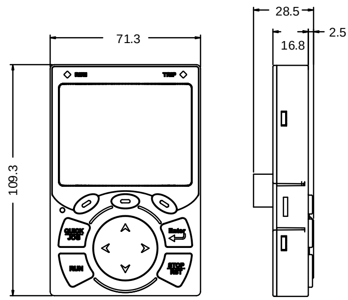
This chapter provides the dimension drawings of the VFD. which use millimeter (mm) as the unit.

## C.2 Keypad structure

### C.2.1 Structure diagram




BOP-270

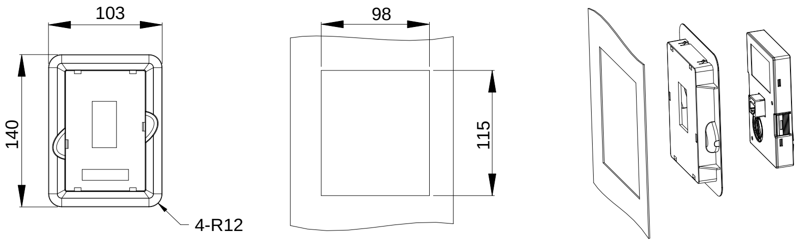



SOP-270

### C.2.2 External installation of keypad

When users need to externally install the optional LED and LCD keypads of GD270 on the cabinet door, there are two installation methods are available.

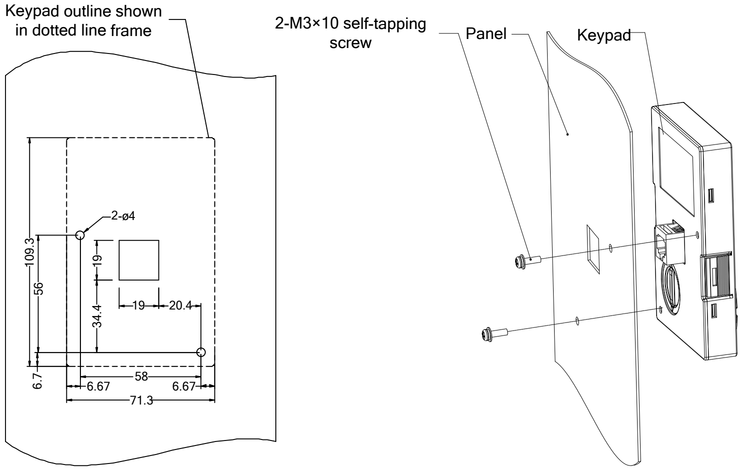
Method 1: As shown in Figure C-1, cut a hole on the cabinet door according to the specified dimensions, purchase an external mounting bracket (model: GD350-JPZJ) for embedded installation, and then install the keypad into the bracket.




Keypad adapter bracket Installation dimensions

Figure C-1 (Optional) Keypad installation bracket

Method 2: According to Figure C-2, cut the fixing holes and keypad hole, and use the two M3 self-tapping screws provided to directly mounting.




Dimension and hole sizes for mounting keypad without a bracket

Figure C-2 Keypad hole dimensions without bracket

**Note:**

✧ When the local keypad of the 30–630kW models is externally installed, the keypad port on the VFD is prone to dust and foreign objects. It is recommended to purchase a keypad protective cover (model: GD270-JPFH) for sealing, as shown in Figure C-3.

✧ The network port outlet hole designed for the GD270 series protective cover will not be used. For details, see the external keypad wiring requirements in section 4.3.6 External optional keypad wiring.

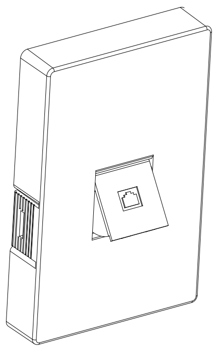


Figure C-3 Keypad protective cover

## C.3 VFD structure

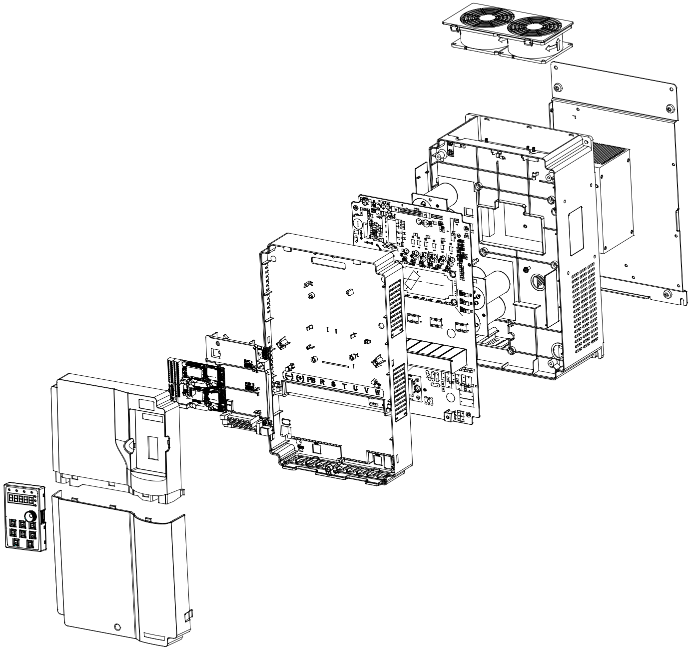


Figure C-4 VFD structure of 630kW and below models

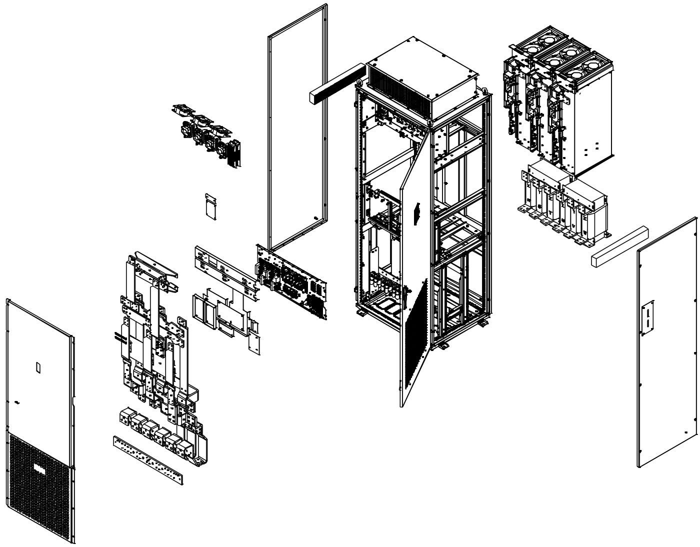


Figure C-5 VFD structure of 710–800kW models

## C.4 Product dimensions

### C.4.1 Wall-mounting dimensions

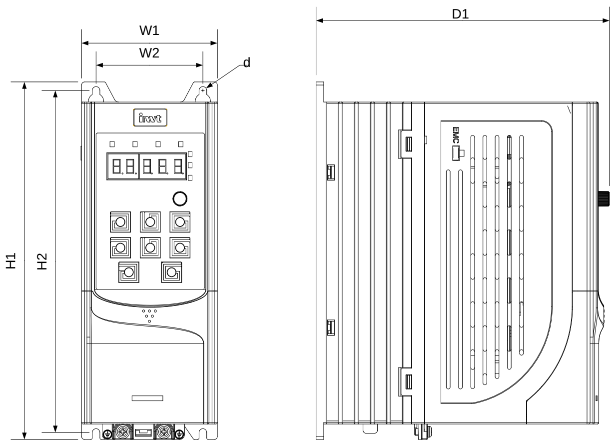



Figure C-6 Wall mounting diagram for 1.5–7.5kW VFD models

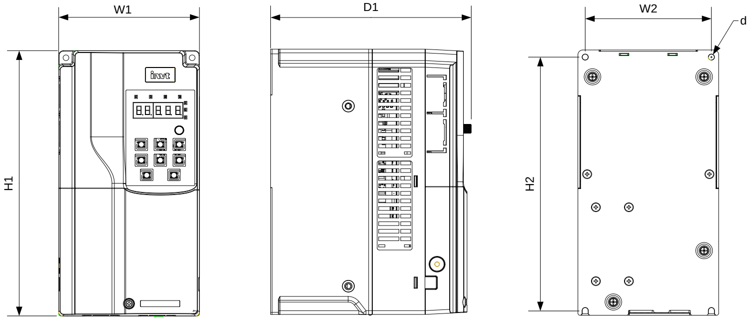



Figure C-7 Wall mounting diagram for 11–45kW VFD models

Table C-1 Wall mounting dimensions for 1.5–45kW VFD models

| VFD power | Outline dimensions (mm) | | | Mounting hole distance (mm) | | | Hole diameter | Fixing screw |
|---|---|---|---|---|---|---|---|---|
| | W1 | H1 | D1 | H2 | W2 | D2 | | |
| 1.5–4kW | 89 | 231 | 193 | 221 | 70 | - | ø5 | M4 |
| 5.5–7.5kW | 89 | 259 | 211.5 | 248 | 70 | - | ø6 | M5 |
| 11–15kW | 145 | 280 | 207 | 268 | 130 | - | ø6 | M5 |
| 18.5–22kW | 169 | 320 | 214 | 308 | 154 | - | ø6 | M5 |
| 30–37kW | 200 | 341 | 214 | 328.5 | 185 | - | ø6 | M5 |
| 45kW | 250 | 400 | 228 | 380 | 230 | - | ø6 | M5 |

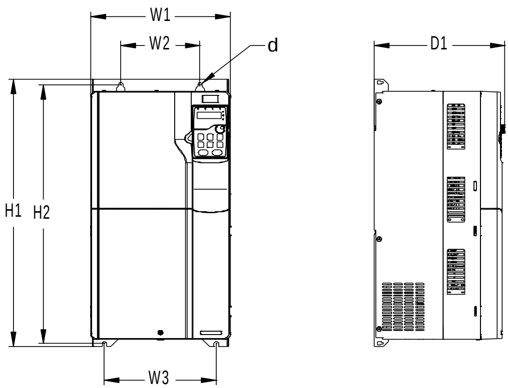



Figure C-8 Wall mounting for 380V 55–90kW VFD models

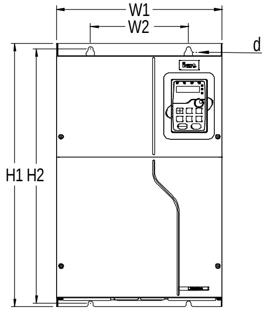



Figure C-9 Wall-mounting diagram for 380V 110–200kW VFD models

Table C-2 Wall mounting dimensions for 380V 55–200kW VFD models

| VFD power | Outline dimensions (mm) | | | Mounting hole distance (mm) | | | Hole diameter | Fixing screw |
|---|---|---|---|---|---|---|---|---|
| | W1 | H1 | D1 | H2 | W2 | W3 | | |
| 55–90kW | 282 | 560 | 264 | 542 | 160 | 226 | ø9 | M8 |
| 110–132kW | 338 | 554 | 338 | 534 | 200 | - | ø9.5 | M8 |
| 160–200kW | 338 | 825 | 398 | 800 | 260 | - | ø11 | M10 |

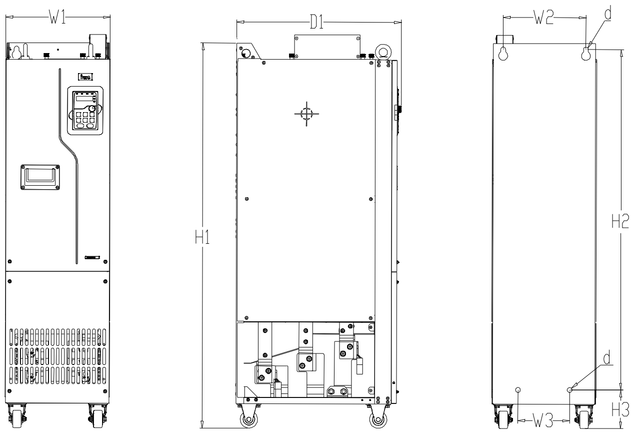



Figure 10-C Wall mounting for 380V 220–250kW VFD models

Table C-3 Wall mounting dimensions for 380V 220–250kW VFD models

| VFD power | Outline dimensions (mm) | | | Mounting hole distance (mm) | | | Hole diameter | Fixing screw |
|---|---|---|---|---|---|---|---|---|
| | W1 | H1 | D1 | H2 | W2 | W3 | | |
| 220–250kW | 303 | 1108 | 477 | 980 | 240 | 150 | ø14 | M12 |

### C.4.2 Flange installation dimensions

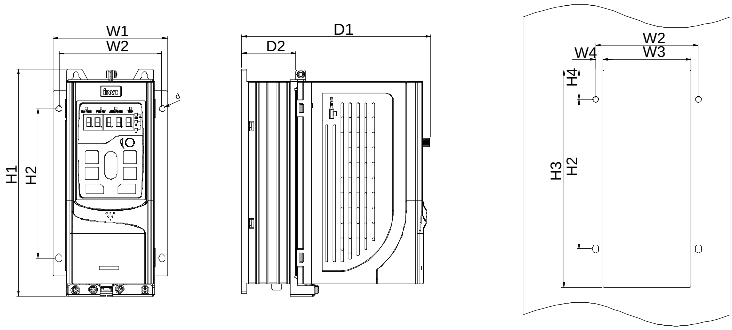



Figure C-11 Flange mounting for 380V 1.5–7.5kW VFD models

Table C-4 Flange mounting dimensions for 380V 1.5–7.5kW VFD models

| VFD power | Outline dimensions (mm) | | | Mounting hole distance (mm) | | | | | | | Hole diameter | Fixing screw |
|---|---|---|---|---|---|---|---|---|---|---|---|---|
| | W1 | H1 | D1 | H2 | H3 | H4 | W2 | W3 | W4 | D2 | | |
| 1.5–4kW | 117 | 233.5 | 193 | 153.5 | 225 | 30 | 105 | 92.5 | 6.5 | 55 | ø6 | M5 |
| 5.5–7.5kW | 117 | 261 | 211.5 | 180 | 250 | 30 | 105 | 92.5 | 6.5 | 75 | ø6 | M5 |

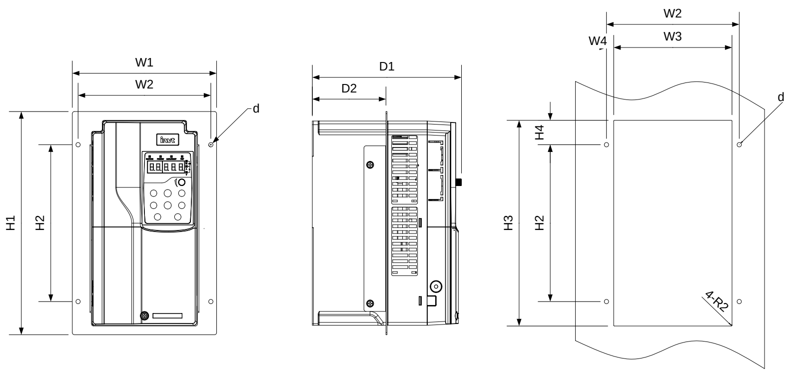



Figure C-12 Flange mounting for 380V 11–22kW VFD models

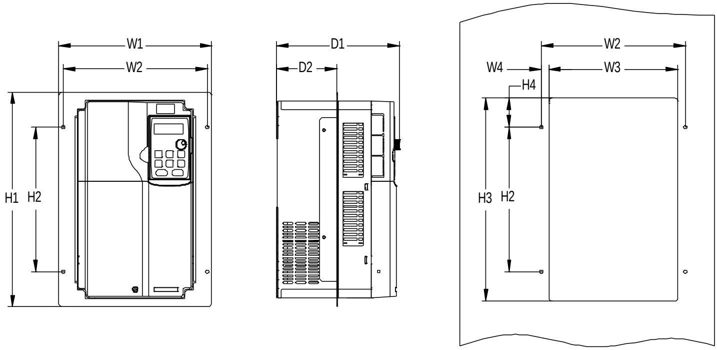



Figure C-13 Flange mounting for 380V 30–90kW VFD models

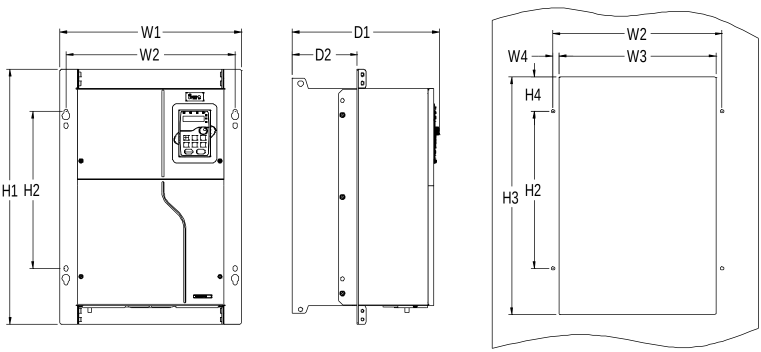
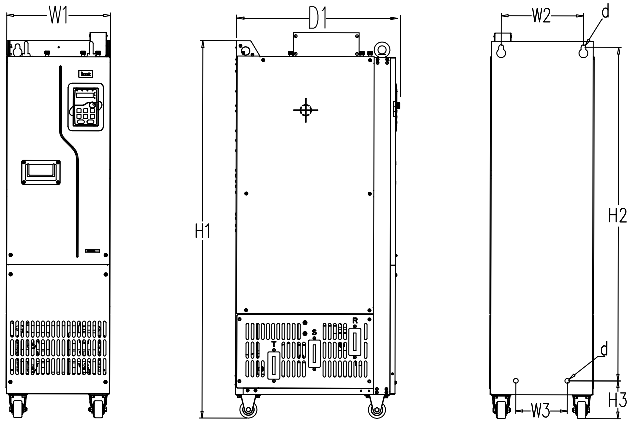


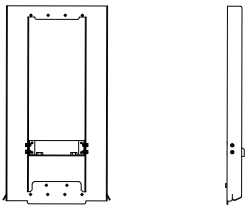

Figure C-14 Flange mounting for 380V 110–200kW VFD models

Table C-5 Flange mounting dimensions for 380V 11–200kW VFD models

| VFD power | Outline dimensions (mm) | | | Mounting hole distance (mm) | | | | | | | Hole diameter | Fixing screw |
|---|---|---|---|---|---|---|---|---|---|---|---|---|
| | W1 | H1 | D1 | H2 | H3 | H4 | W2 | W3 | W4 | D2 | | |
| 11–15kW | 200 | 306 | 207 | 215 | 282 | 33.5 | 184 | 164 | 10 | 102 | ø6 | M5 |
| 18.5–22kW | 224 | 346 | 214 | 255 | 322 | 33.5 | 208 | 189 | 9.5 | 108 | ø6 | M5 |
| 30–37kW | 266 | 371 | 214 | 250 | 350.5 | 50.5 | 250 | 224 | 13 | 104 | ø6 | M5 |
| 45kW | 316 | 430 | 228 | 300 | 410 | 55 | 300 | 274 | 13 | 118.5 | ø6 | M5 |
| 55–90kW | 352 | 580 | 264 | 400 | 570 | 90 | 332 | 306 | 13 | 134 | ø9 | M8 |
| 110–132kW | 418.5 | 600 | 338 | 370 | 559 | 80.5 | 389.5 | 361 | 14 | 149.5 | ø10 | M8 |
| 160–200kW | 428 | 868 | 398.5 | 625 | 830 | 80 | 394 | 345 | 24.5 | 183 | ø11 | M10 |

### C.4.3 Floor installation dimensions



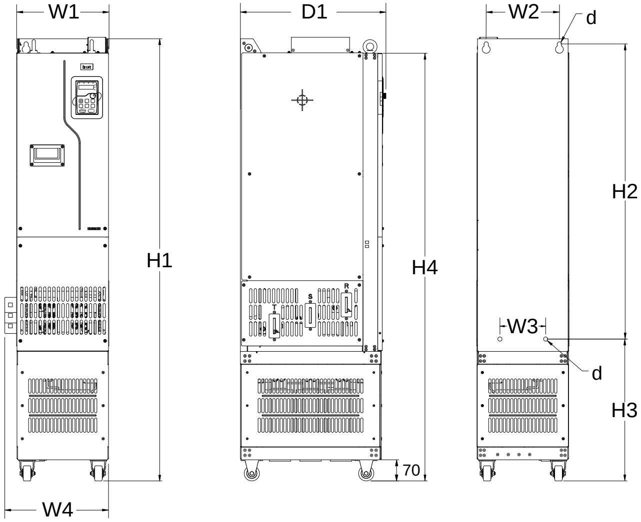
Base mounting bracket

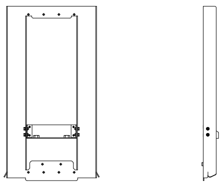
Figure C-15 Floor mounting for 380V 220–630kW VFD models

Table C-6 380V 220–630kW VFD floor mounting dimensions

| VFD power | Outline dimensions (mm) | | | Mounting hole distance (mm) | | | | Hole diameter (d) | Fixing screw |
|---|---|---|---|---|---|---|---|---|---|
| | W1 | H1 | D1 | H2 | H3 | W2 | W3 | | |
| 220–250kW | 303 | 1108 | 477 | 980 | 111 | 240 | 150 | ø14 | M12 |
| 280–355kW | 330 | 1288 | 552 | 1150 | 122 | 225 | 185 | ø13 | M10 |
| 400–500kW | 330 | 1398 | 552 | 1280 | 101 | 240 | 200 | ø13 | M10 |
| 560–630kW | 380 | 1450 | 582 | 1320 | 112 | 240 | 200 | ø14 | M12 |

**Note:** For details about the base mounting bracket, see Figure C-17 and Table C-8.



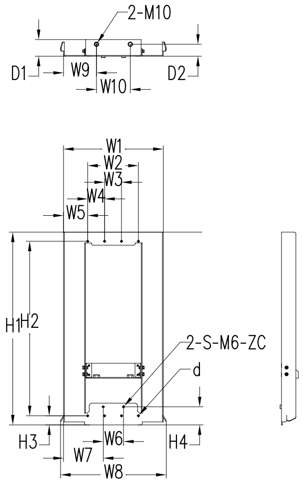
Base mounting bracket

Figure C-16 Mounting diagram for 380V 220–630kW VFDs with output reactors

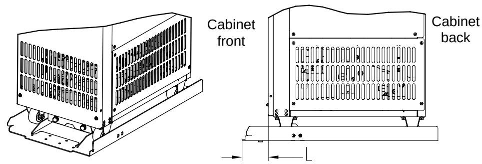
Table C-7 Floor mounting dimensions for 380V 220–630kW VFDs with output reactors

| VFD power | Outline dimensions (mm) | | | | Mounting hole distance (mm) | | | | | Hole diameter (d) | Fixing screw |
|---|---|---|---|---|---|---|---|---|---|---|---|
| | W1 | W4 | H1 | D1 | H2 | H3 | H4 | W2 | W3 | | |
| 220kW–250kW | 303 | 350 | 1470 | 477 | 980 | 471 | 1420 | 240 | 150 | ø14 | M12 |
| 280kW–355kW | 330 | 429 | 1619 | 552 | 1150 | 453 | 1571 | 225 | 185 | ø13 | M10 |
| 400kW–500kW | 330 | 430 | 1729 | 552 | 1280 | 432 | 1681 | 240 | 200 | ø13 | M10 |
| 560kW–630kW | 380 | 480 | 1780 | 582 | 1320 | 442 | 1730 | 240 | 200 | ø14 | M12 |

**Note:** For details about the base mounting bracket, see Figure C-17 and Table C-8.




Base dimensions




Place of base for supporting the VFD cabinet

Figure C-17 380V 220–630kW VFD base bracket dimensions and mounting dimensions

Table C-8 380V 220–630kW VFD base bracket dimensions

| VFD power | W1 | W2 | W3 | W4 | W5 | W6 | W7 | W8 | W9 | W10 | H1 | H2 | H3 | H4 | D1 | D2 | d | Screw | L |
|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|---|
| 220–250kW | 295 | 150 | 50 | 50 | 71.5 | 60 | 117.5 | 313 | 97.5 | 100 | 580 | 525 | 27.5 | 54.5 | 50 | 36 | ø6 | M5 self-tapping screw | 77.5 |
| 280–315kW | 321 | 150 | 50 | 50 | 84.5 | 60 | 130.5 | 339 | 110.5 | 100 | 580 | 525 | 27.5 | 54.5 | 46 | 33.5 | ø6 | | 25.5 |
| 355–500kW | | | | | | | | | | | | | | | | | | | 25 |
| 560–630kW | 380 | 150 | 50 | 50 | 115 | 60 | 160 | 398 | 140 | 100 | 615 | 575 | 25 | 55 | 48.5 | 32.5 | ø6 | | 19 |

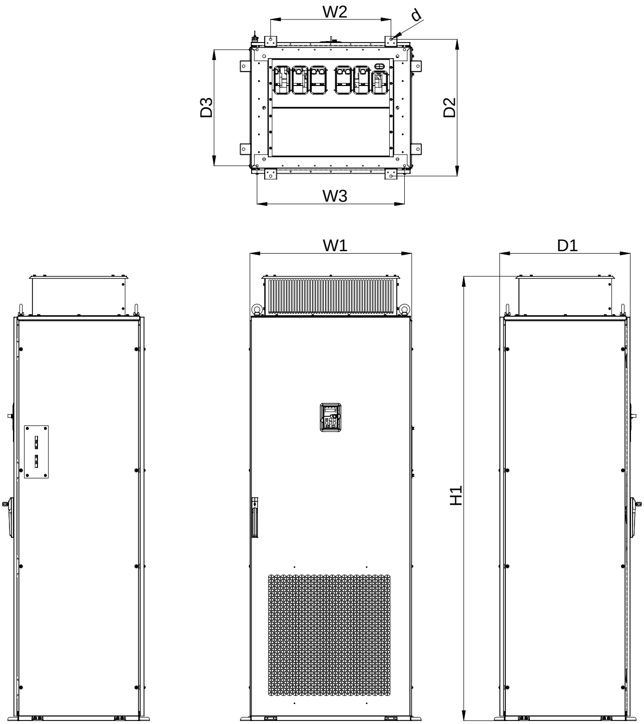



Figure C-18 Mounting diagram for 380V 710–800kW cabinets

Table C-9 Floor mounting dimensions for 380V 710–800kW cabinets

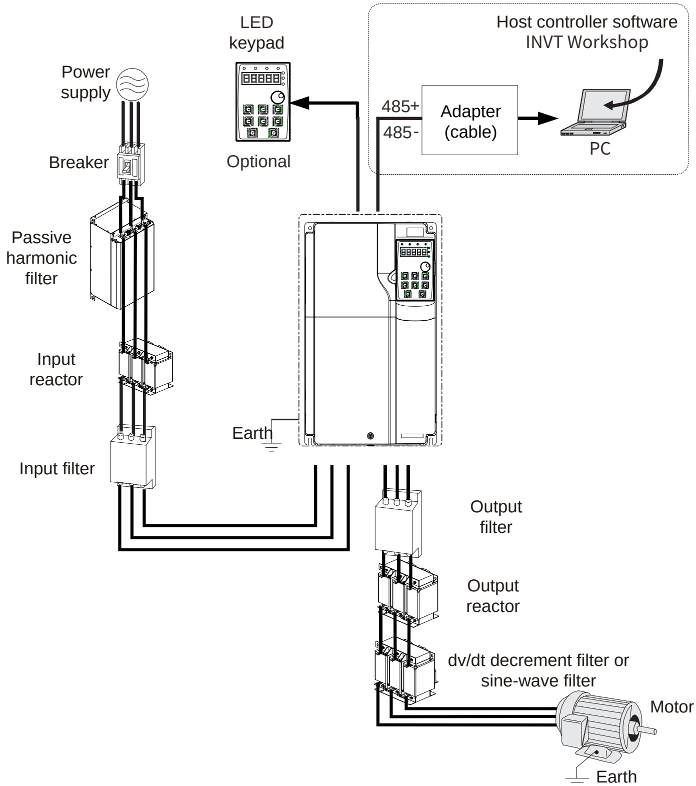
| VFD power | Outline dimensions (mm) | | | Mounting hole distance (mm) | | | | Hole diameter | Fixing screw |
|---|---|---|---|---|---|---|---|---|---|
| | W1 | H1 | D1 | W2 | W3 | D2 | D3 | | |
| 710–800kW | 806 | 2200 | 650 | 600 | 735 | 677 | 575 | ø13 | M12 |

# Appendix D Optional peripheral accessories

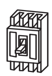
This chapter describes how to select optional accessories for the VFD.

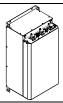
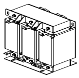
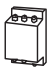
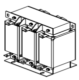
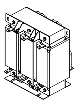
## D.1 Wiring of peripheral accessories

The following figure shows the external wiring of the VFD.




**Note:** You can choose the optional built-in DC reactor, which will be installed at the factory before delivery.

| Image | Name | Description |
|---|---|---|
|  | Cable | Accessory for signal transmission. |
|  | Breaker | Device for electric shock prevention and protection against short-to-ground that may cause current leakage and fire. Select residual-current circuit breakers (RCCBs) that are applicable to VFDs and can restrict high-order harmonics, and |

| Image | Name | Description |
|---|---|---|
| | | of which the rated sensitive current for one VFD is larger than 30mA. |
|  | Passive harmonic filters | Device used to reduce the current distortion rate and harmonic content, thereby improving the power factor. |
|  | Input reactor | Device used to prevent instantaneous high currents from flowing into the input power circuit and damaging rectifier components when high voltage is input from the power grid. Additionally, it can improve the power factor on the input side. |
|  | Input filter | Device that restricts the electromagnetic interference generated by the VFD and transmitted to the public grid through the power cable. Install as close to the input terminal of the VFD as possible. |
|  | Output filter | Device used to suppress interference generated from the wiring on the output side of the VFD. Install as close to the output terminal of the VFD as possible. |
|  | Output reactor | Device used to extend the effective transmission distance of the VFD and effectively suppress instantaneous high voltage generated when the IGBT module of the VFD switches. |
|  | dv/dt decrement filters | Device used to suppress voltage spikes, reduce traveling waves in long cables, and reflect dv/dt transient voltages, thereby reducing motor eddy current losses and noise, and providing motor insulation protection. |
| | Sine filters | Device used to suppress and absorb high-order harmonic currents derived from switching frequency ripple currents, correcting the waveform to approximate a sine wave, significantly extending the length of the output cable, reducing motor eddy current losses and noise, and protecting motor insulation. |

## D.2 Power supply

See chapter 4 Installation guidelines.

| | |
|---|---|
|  | Ensure that the voltage class of the VFD is consistent with that of the grid. |

## D.3 Cable

### D.3.1 Power cable

The sizes of the input power cables and motor cables must comply with local regulations.

✧ The input power cables and motor cables must be able to carry the corresponding load currents.

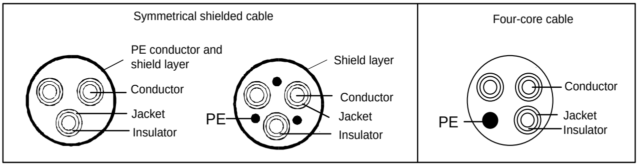
✧ The maximum temperature margin of the motor cables in continuous operation cannot be lower than 70°C.

✧ The conductivity of the PE grounding conductor is the same as that of the phase conductor, that is, the cross-sectional areas are the same.

✧ For details about the EMC requirements, see Appendix B Technical data.

To meet the EMC requirements stipulated in the CE standards, you must use symmetrical shielded cables as motor cables (as shown in the following figure).

Four-core cables can be used as input cables, but symmetrical shielded cables are recommended. Compared with four-core cables, symmetrical shielded cables can reduce electromagnetic radiation as well as the current and loss of the motor cables.




**Note:** If the electrical conductivity of the motor cable shield layer does not meet the requirements, a separate PE conductor must be used.

To protect the conductors, the cross-sectional area of the shielded cables must be the same as that of the phase conductors if the cable and conductor are made of materials of the same type. This reduces grounding resistance, and thus improves impedance continuity.

To effectively restrict the emission and conduction of radio frequency (RF) interference, the conductivity of the shielded cable must be at least 1/10 of the conductivity of the phase conductor. This requirement can be well met by a copper or aluminum shield layer. Figure D-1 shows the min. requirement on motor cables of VFD. The cable must consist of a layer of spiral-shaped copper strips. The denser the shield layer is, the more effectively the electromagnetic interference is restricted.

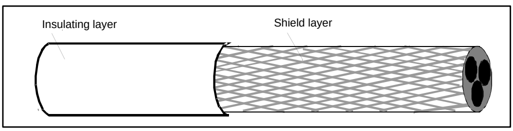



Figure D-1 Cable cross section

### D.3.2 Control cable

All analog control cables and cables used for frequency input must be shielded cables. Analog signal cables need to be double-shielded twisted-pair cables (as shown in figure a in Figure D-2). Use one separate shielded twisted pair for each signal. Do not use the same ground wire for different analog signals.

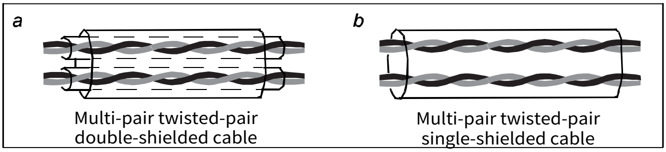



Figure D-2 Power cable arrangement

For low-voltage digital signals, double-shielded cables are recommended, but shielded or unshielded twisted pairs (as shown in figure b in Figure D-2) also can be used. For frequency signals, however, only shielded cables can be used.

Relay cables need to be those with metal braided shield layers.

Keypads need to be connected by using network cables. In complicated electromagnetic environments, shielded network cables are recommended.

**Note:** Analog signals and digital signals cannot use the same cables, and their cables must be arranged separately.

Dielectric withstand tests have been performed between the main circuit and housing of each VFD before delivery. In addition, the VFD has the internal voltage limiting circuit, which can automatically cut off the test voltage. Do not perform any voltage withstand or insulation resistance tests, such as high-voltage insulation tests or using a megameter to measure the insulation resistance, on the VFD or its components.

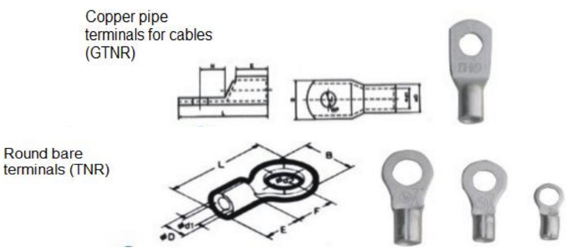
**Note:** Before connecting the input power cable of the VFD, check the insulation conditions of the cable according to local regulations.

### D.3.3 Recommended cable size

Table D-1 Recommended cable size

| Rated power (kW) | R, S, T / U, V, W / (+), (-) | | PE | | Fastening torque (N·m) |
|---|---|---|---|---|---|
| | Recommended cable (BVR) $mm^2$ | Recommended connection terminal model | Recommended cable (BVR) $mm^2$ | Recommended connection terminal model | |
| 1.5 | 1 | TNR1.25-4 | 1 | TNR1.25-4 | 1.2–1.5 |
| 2.2 | 1 | TNR1.25-4 | 1 | TNR1.25-4 | 1.2–1.5 |
| 4 | 1.5 | TNR1.25-4 | 1.5 | TNR1.25-4 | 1.2–1.5 |
| 5.5 | 2.5 | TNR2-4 | 2.5 | TNR2-4 | 1.2–1.5 |
| 7.5 | 2.5 | TNR2-4 | 2.5 | TNR2-4 | 1.2–1.5 |
| 11 | 4 | TNR3.5-5 | 4 | TNR3.5-5 | 2–2.5 |
| 15 | 6 | TNR5.5-5 | 6 | TNR5.5-5 | 2–2.5 |
| 18.5 | 10 | TNR8-5 | 10 | TNR8-5 | 2–2.5 |
| 22 | 16 | TNR14-5 | 16 | TNR14-5 | 2–2.5 |
| 30 | 16 | GTNR16-6 | 16 | GTNR16-5 | 3.5 |

| Rated power (kW) | R, S, T / U, V, W / (+), (-) | | PE | | Fastening torque (N·m) |
|---|---|---|---|---|---|
| | Recommended cable (BVR) $mm^2$ | Recommended connection terminal model | Recommended cable (BVR) $mm^2$ | Recommended connection terminal model | |
| 37 | 25 | GTNR25-6 | 16 | GTNR16-5 | 3.5 |
| 45 | 25 | GTNR25-6 | 16 | GTNR16-5 | 3.5 |
| 55 | 35 | GTNR35-8 | 16 | GTNR16-6 | 9–11 |
| 75 | 50 | GTNR50-8 | 25 | GTNR25-6 | 9–11 |
| 90 | 70 | GTNR70-8 | 35 | GTNR35-6 | 9–11 |
| 110 | 95 | GTNR95-12 | 50 | GTNR50-8 | 31–40 |
| 132 | 95 | GTNR95-12 | 50 | GTNR50-8 | 31–40 |
| 160 | 150 | GTNR150-12 | 70 | GTNR70-8 | 31–40 |
| 185 | 185 | GTNR185-12 | 95 | GTNR95-8 | 31–40 |
| 200 | 185 | GTNR185-12 | 95 | GTNR95-8 | 31–40 |
| 220 | 2×95 | GTNR95-12 | 95 | GTNR95-12 | 31–40 |
| 250 | 2×95 | GTNR95-12 | 95 | GTNR95-12 | 31–40 |
| 280 | 2×150 | GTNR150-12 | 150 | GTNR150-12 | 31–40 |
| 315 | 2×150 | GTNR150-12 | 150 | GTNR150-12 | 31–40 |
| 355 | 2×185 | GTNR185-12 | 185 | GTNR185-12 | 31–40 |
| 400 | 2×185 | GTNR185-16 | 2×120 | GTNR120-12 | 92–100 |
| 450 | 2×240 | GTNR240-16 | 2×150 | GTNR150-12 | 92–100 |
| 500 | 2×300 | GTNR300-16 | 2×150 | GTNR150-12 | 92–100 |
| 560 | 4×150 | GTNR150-12 | 2×150 | GTNR150-12 | 31–40 |
| 630 | 4×150 | GTNR150-12 | 2×150 | GTNR150-12 | 31–40 |
| 710 | 4×150 | GTNR150-12 | 2×150 | GTNR150-12 | 31–40 |
| 800 | 4×150 | GTNR150-12 | 2×150 | GTNR150-12 | 31–40 |




GTNR terminal brand: Suzhou Yuanli (The model varies with the brand.)

TNR terminal brand: Suzhou Yuanli (The model varies with the brand.)

Table D-2 Recommended cable size (Compliant with UL standards)

| Rated power (kW) | R, S, T / U, V, W / (+), (-) | | PE | | Fastening torque (N·m) |
|---|---|---|---|---|---|
| | Recommended cable size (UL) AWG/Kcmil | Recommended connection terminal model | Recommended cable size (UL) AWG/Kcmil | Recommended connection terminal model | |
| 1.5 | 16 | TLK1.5-4 | 16 | TLK1.5-4 | 1.2–1.5 |
| 2.2 | 16 | TLK1.5-4 | 16 | TLK1.5-4 | 1.2–1.5 |
| 4 | 14 | TLK2.5-4 | 14 | TLK2.5-4 | 1.2–1.5 |
| 5.5 | 14 | TLK2.5-4 | 14 | TLK2.5-4 | 1.2–1.5 |
| 7.5 | 12 | TLK4-4 | 12 | TLK4-4 | 1.2–1.5 |
| 11 | 10 | TLK6-5 | 10 | TLK6-5 | 2–2.5 |
| 15 | 8 | TLK10-5 | 8 | TLK10-5 | 2–2.5 |
| 18.5 | 6 | TLK16-5 | 6 | TLK16-5 | 2–2.5 |
| 22 | 4 | TLK25-5 | 4 | TLK25-5 | 2–2.5 |
| 30 | 4 | TLK25-6 | 4 | TLK25-5 | 3.5 |
| 37 | 3 | TLK25-6 | 4 | TLK25-5 | 3.5 |
| 45 | 3 | TLK25-6 | 4 | TLK25-5 | 3.5 |
| 55 | 2 | TLK35-8 | 4 | TLK25-6 | 9–11 |
| 75 | 1/0 | TLK50-8 | 3 | TLK25-6 | 9–11 |
| 90 | 3/0 | TLK95-8 | 2 | TLK35-6 | 9–11 |
| 110 | 4/0 | TLK120-12 | 1/0 | TLK50-8 | 31–40 |
| 132 | 4/0 | TLK120-12 | 1/0 | TLK50-8 | 31–40 |
| 160 | 300 | TLK150-12 | 3/0 | TLK95-8 | 31–40 |
| 185 | 400 | TLK240-12 | 4/0 | TLK120-8 | 31–40 |
| 200 | 400 | TLK240-12 | 4/0 | TLK120-8 | 31–40 |
| 220 | 2×4/0 | TLK120-12 | 4/0 | TLK120-12 | 31–40 |
| 250 | 2×4/0 | TLK120-12 | 4/0 | TLK120-12 | 31–40 |
| 280 | 2×300 | TLK150-12 | 300 | TLK150-12 | 31–40 |
| 315 | 2×300 | TLK150-12 | 300 | TLK150-12 | 31–40 |
| 355 | 2×400 | TLK240-12 | 400 | TLK240-12 | 31–40 |
| 400 | 2×400 | SQNBS200-16 | 2×250 | TLK150-12 | 96 |
| 450 | 2×500 | SQNBS250-16 | 2×300 | TLK150-12 | 96 |
| 500 | 2×600 | SQNBS325-16 | 2×300 | TLK150-12 | 96 |
| 560 | 4×300 | TLK150-12 | 2×300 | TLK150-12 | 31–40 |
| 630 | 4×300 | TLK150-12 | 2×300 | TLK150-12 | 31–40 |
| 710 | 4×400 | TLK240-12 | 2×400 | TLK150-12 | 31–40 |
| 800 | 4×400 | TLK240-12 | 2×400 | TLK150-12 | 31–40 |

TLK terminal

SQNBS narrow-head terminal

TLK terminal brand: KST (The model varies with the brand.)

SQNBS narrow-head terminal brand: KST (The model varies with the brand.)

**Note:**

✧ If you select a cable model larger than a recommended model in the table, check whether the wiring terminal width exceeds the allowed width in 4.3.2 Main circuit terminals.

✧ If yes, select an SG narrow-head terminal and matching cable since an SG narrow-head terminal has smaller width.

✧ The cables recommended for the main circuit can be used in scenarios where the ambient temperature is lower than 40°C, the wiring distance is shorter than 100m, and the current is the rated current.

✧ The terminals (+) and (-) are used by multiple VFDs to share the DC bus.

### D.3.4 Cable arrangement

Motor cables must be arranged away from other cables. The motor cables of several inverters can be arranged in parallel. It is recommended that you arrange the motor cables, input power cables, and control cables separately in different trays. The output dv/dt of the inverters may increase electromagnetic interference on other cables. Do not arrange other cables and the motor cables in parallel.

If a control cable and power cable must cross each other, ensure that the angle between them is 90°.

The cable trays must be connected properly and well grounded. Aluminum trays can implement local equipotential.

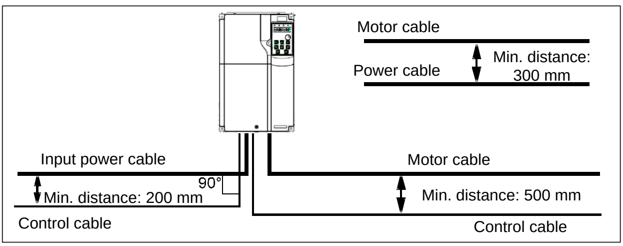



Figure D-3 Cable routing distance

#### D.3.5 Insulation inspection

Check the motor and the insulation conditions of the motor cable before running the motor.

1. Ensure that the motor cable is connected to the motor, and then remove the motor cable from the U, V, and W output terminals of the VFD.
2. Use a megohmmeter of 500V DC to measure the insulation resistance between each phase conductor and the protection grounding conductor. For details about the insulation resistance of the motor, see the description provided by the manufacturer.

**Note:** The insulation resistance is reduced if it is damp inside the motor. If it may be damp, you need to dry the motor and then measure the insulation resistance again.

## D.4 Breaker and electromagnetic contactor

The circuit breaker is mainly used to prevent electric shock accidents and short circuits to the ground that may cause leakage current fire. The electromagnetic contactor is mainly used to control the main circuit power on and off, which can effectively cut off the input power of the VFD in case of system failure to ensure safety.

| | |
|---|---|
| | According to the working principle and structure of breakers, if the manufacturer's regulation is not followed, hot ionized gases may escape from the breaker enclosure when a short-circuit occurs. To ensure safe use, exercise extra caution when installing and placing the breaker. Follow the manufacturer's instructions. |

Table D-3 Ratings for AC 3PH 380V VFD models

| Rated power (kW) | Breaker rated current (A) | Fast-acting fuse rated current (A) | Contactor rated current (A) |
|---|---|---|---|
| 1.5 | 6 | 10 | 9 |
| 2.2 | 10 | 10 | 9 |
| 4 | 20 | 20 | 18 |
| 5.5 | 25 | 32 | 25 |
| 7.5 | 32 | 40 | 32 |
| 11 | 50 | 50 | 38 |
| 15 | 50 | 63 | 50 |
| 18.5 | 63 | 80 | 65 |
| 22 | 80 | 80 | 80 |
| 30 | 100 | 125 | 80 |
| 37 | 125 | 125 | 98 |
| 45 | 140 | 150 | 115 |
| 55 | 180 | 200 | 150 |
| 75 | 225 | 250 | 185 |
| 90 | 250 | 300 | 225 |
| 110 | 315 | 350 | 265 |

| Rated power (kW) | Breaker rated current (A) | Fast-acting fuse rated current (A) | Contactor rated current (A) |
|---|---|---|---|
| 132 | 400 | 400 | 330 |
| 160 | 500 | 500 | 400 |
| 185 | 500 | 600 | 400 |
| 200 | 630 | 600 | 500 |
| 220 | 630 | 700 | 500 |
| 250 | 700 | 800 | 630 |
| 280 | 800 | 1000 | 630 |
| 315 | 1000 | 1000 | 800 |
| 355 | 1000 | 1000 | 800 |
| 400 | 1000 | 1200 | 1000 |
| 450 | 1250 | 1200 | 1000 |
| 500 | 1250 | 1400 | 1000 |
| 560 | 1250 | 1600 | 1200 |
| 630 | 1250 | 1600 | 1200 |
| 710 | 1600 | 2000 | 1600 |
| 800 | 1600 | 2000 | 1600 |

**Note:** The accessory specifications described in the preceding table are ideal values. You can select accessories based on the actual market conditions, but try not to use those with lower values.

## D.5 Harmonic filters

To enhance grid protection, reduce harmonic interference from the VFD to the grid, and improve input power factor, consider configuring external DC reactors, input reactors, or passive harmonic filters based on your specific application needs.

If you want to use long cables between the VFD and the motor, select external output reactors, dv/dt attenuation filters, or sine-wave filters based on the motor cable length. This helps mitigate excessive dv/dt, reducing voltage stress on the motor windings as well as protecting them, and extending the motor's lifespan. Refer to the following table for recommended output filter selections according to motor cable length.

Table D-4 Reactor model selection

| Rated power (kW) | Input reactor | Output reactor |
|---|---|---|
| 1.5 | GDL-ACL0005-4CU | GDL-OCL0005-4CU |
| 2.2 | GDL-ACL0006-4CU | GDL-OCL0006-4CU |
| 4 | GDL-ACL0014-4CU | GDL-OCL0010-4CU |
| 5.5 | GDL-ACL0020-4CU | GDL-OCL0014-4CU |
| 7.5 | GDL-ACL0025-4CU | GDL-OCL0020-4CU |
| 11 | GDL-ACL0035-4AL | GDL-OCL0025-4CU |
| 15 | GDL-ACL0040-4AL | GDL-OCL0035-4AL |

| Rated power (kW) | Input reactor | Output reactor |
|---|---|---|
| 18.5 | GDL-ACL0051-4AL | GDL-OCL0040-4AL |
| 22 | GDL-ACL0051-4AL | GDL-OCL0050-4AL |
| 30 | GDL-ACL0070-4AL | GDL-OCL0060-4AL |
| 37 | GDL-ACL0090-4AL | GDL-OCL0075-4AL |
| 45 | GDL-ACL0110-4AL | GDL-OCL0092-4AL |
| 55 | GDL-ACL0150-4AL | GDL-OCL0115-4AL |
| 75 | GDL-ACL0150-4AL | GDL-OCL0150-4AL |
| 90 | GDL-ACL0220-4AL | GDL-OCL0220-4AL |
| 110 | GDL-ACL0220-4AL | GDL-OCL0220-4AL |
| 132 | GDL-ACL0265-4AL | GDL-OCL0265-4AL |
| 160 | GDL-ACL0330-4AL | GDL-OCL0330-4AL |
| 185 | GDL-ACL0390-4AL | GDL-OCL0400-4AL |
| 200 | GDL-ACL0390-4AL | GDL-OCL0400-4AL |
| 220 | GDL-ACL0450-4AL | GDL-OCL0450-4AL |
| 250 | GDL-ACL0500-4AL | GDL-OCL0500-4AL |
| 280 | GDL-ACL0500-4AL | GDL-OCL0560-4AL |
| 315 | GDL-ACL0580-4AL | GDL-OCL0660-4AL |
| 355 | GDL-ACL0660-4AL | GDL-OCL0660-4AL |
| 400 | GDL-ACL0715-4AL | GDL-OCL0720-4AL |
| 450 | GDL-ACL0840-4AL | GDL-OCL0820-4AL |
| 500 | GDL-ACL1000-4AL | GDL-OCL1000-4AL |
| 560 | 2×GDL-ACL0500-4AL | 2×GDL-OCL0560-4AL |
| 630 | 2×GDL-ACL0580-4AL | 2×GDL-OCL0660-4AL |
| 710 | 2×GDL-ACL0660-4AL | 2×GDL-OCL0660-4AL |
| 800 | 2×GDL-ACL0715-4AL | 2×GDL-OCL0720-4AL |

**Note:**

✧ The rated input voltage drop of input reactor is designed to ≥ 1.5%.

✧ The rated output voltage drop of output reactor is designed to 1%.

✧ The preceding table lists only external accessories. You need to specify whether external or built-in accessories are needed in your purchase order.

✧ For the selection of accessories with different material requirements than those listed above, please refer to the low-voltage VFD GDL series filter option brochure.

Table D-5 Filter model selection

| Rated power (kW) | Input filter | Output filter | |
|---|---|---|---|
| | Passive harmonic filters | dv/dt decrement filters | Sine filters |
| 1.5 | GDL-H0006-4AL | GDL-DUL0005-4CU | GDL-OSF0005-4AL |
| 2.2 | GDL-H0006-4AL | GDL-DUL0005-4CU | GDL-OSF0005-4AL |
| 4 | GDL-H0014-4AL | GDL-DUL0010-4CU | GDL-OSF0010-4AL |
| 5.5 | GDL-H0020-4AL | GDL-DUL0014-4CU | GDL-OSF0014-4AL |
| 7.5 | GDL-H0025-4AL | GDL-DUL0020-4CU | GDL-OSF0020-4AL |
| 11 | GDL-H0032-4AL | GDL-DUL0025-4CU | GDL-OSF0025-4AL |
| 15 | GDL-H0040-4AL | GDL-DUL0032-4CU | GDL-OSF0032-4AL |
| 18.5 | GDL-H0047-4AL | GDL-DUL0040-4AL | GDL-OSF0040-4AL |
| 22 | GDL-H0056-4AL | GDL-DUL0045-4AL | GDL-OSF0045-4AL |
| 30 | GDL-H0070-4AL | GDL-DUL0060-4AL | GDL-OSF0060-4AL |
| 37 | GDL-H0080-4AL | GDL-DUL0075-4AL | GDL-OSF0075-4AL |
| 45 | GDL-H0100-4AL | GDL-DUL0100-4AL | GDL-OSF0095-4AL |
| 55 | GDL-H0130-4AL | GDL-DUL0120-4AL | GDL-OSF0120-4AL |
| 75 | GDL-H0160-4AL | GDL-DUL0150-4AL | GDL-OSF0150-4AL |
| 90 | GDL-H0190-4AL | GDL-DUL0180-4AL | GDL-OSF0180-4AL |
| 110 | GDL-H0225-4AL | GDL-DUL0220-4AL | GDL-OSF0220-4AL |
| 132 | GDL-H0265-4AL | GDL-DUL0260-4AL | GDL-OSF0260-4AL |
| 160 | GDL-H0320-4AL | GDL-DUL0320-4AL | GDL-OSF0320-4AL |
| 185 | GDL-H0400-4AL | GDL-DUL0400-4AL | GDL-OSF0400-4AL |
| 200 | GDL-H0400-4AL | GDL-DUL0400-4AL | GDL-OSF0400-4AL |
| 220 | GDL-H0485-4AL | GDL-DUL0480-4AL | GDL-OSF0480-4AL |
| 250 | GDL-H0485-4AL | GDL-DUL0480-4AL | GDL-OSF0480-4AL |
| 280 | GDL-H0545-4AL | GDL-DUL0540-4AL | GDL-OSF0600-4AL |
| 315 | GDL-H0610-4AL | GDL-DUL0600-4AL | GDL-OSF0600-4AL |
| 355 | GDL-H0800-4AL | GDL-DUL0800-4AL | GDL-OSF0800-4AL |
| 400 | GDL-H0800-4AL | GDL-DUL0800-4AL | GDL-OSF0800-4AL |
| 450 | GDL-H1000-4AL | GDL-DUL1000-4AL | GDL-OSF1000-4AL |
| 500 | GDL-H1000-4AL | GDL-DUL1000-4AL | GDL-OSF1000-4AL |
| 560 | 2×GDL-H0545-4AL | 2×GDL-DUL0540-4AL | 2×GDL-OSF0600-4AL |
| 630 | 2×GDL-H0610-4AL | 2×GDL-DUL0600-4AL | 2×GDL-OSF0600-4AL |
| 710 | 2×GDL-H0800-4AL | 2×GDL-DUL0800-4AL | 2×GDL-OSF0800-4AL |
| 800 | 2×GDL-H0800-4AL | 2×GDL-DUL0800-4AL | 2×GDL-OSF0800-4AL |

**Note:**

✧ The preceding table lists only external accessories. You need to specify whether external or built-in accessories are needed in your purchase order.

✧ For the selection of accessories with different material requirements than those listed above, please refer to the low-voltage VFD GDL series filter option brochure.

## D.6 EMC filter

Table D-6 EMC filter model selection

| Rated power (kW) | Input filter | Output filter |
|---|---|---|
| 1.5 | FLT-P04006L-B | FLT-L04006L-B |
| 2.2 | FLT-P04006L-B | FLT-L04006L-B |
| 4 | FLT-P04016L-B | FLT-L04016L-B |
| 5.5 | FLT-P04032L-B | FLT-L04032L-B |
| 7.5 | FLT-P04032L-B | FLT-L04032L-B |
| 11 | FLT-P04045L-B | FLT-L04045L-B |
| 15 | FLT-P04045L-B | FLT-L04045L-B |
| 18.5 | FLT-P04065L-B | FLT-L04065L-B |
| 22 | FLT-P04065L-B | FLT-L04065L-B |
| 30 | FLT-P04100L-B | FLT-L04065L-B |
| 37 | FLT-P04100L-B | FLT-L04100L-B |
| 45 | FLT-P04100L-B | FLT-L04100L-B |
| 55 | FLT-P04150L-B | FLT-L04150L-B |
| 75 | FLT-P04240L-B | FLT-L04150L-B |
| 90 | FLT-P04240L-B | FLT-L04240L-B |
| 110 | FLT-P04240L-B | FLT-L04240L-B |
| 132 | FLT-P04400L-B | FLT-L04400L-B |
| 160 | FLT-P04400L-B | FLT-L04400L-B |
| 185 | FLT-P04400L-B | FLT-L04400L-B |
| 200 | FLT-P04400L-B | FLT-L04400L-B |
| 220 | FLT-P04600L-B | FLT-L04600L-B |
| 250 | FLT-P04600L-B | FLT-L04600L-B |
| 280 | FLT-P04600L-B | FLT-L04600L-B |
| 315 | FLT-P04800L-B | FLT-L04800L-B |
| 355 | FLT-P04800L-B | FLT-L04800L-B |
| 400 | FLT-P04800L-B | FLT-L04800L-B |
| 450 | FLT-P041000L-B | FLT-L041000L-B |
| 500 | FLT-P041000L-B | FLT-L041000L-B |
| 560 | 2*FLT-P04600L-B | 2*FLT-L04600L-B |
| 630 | 2*FLT-P04800L-B | 2*FLT-L04800L-B |
| 710 | 2×FLT-P04800L-B | 2×FLT-L04800L-B |
| 800 | 2×FLT-P04800L-B | 2×FLT-L04800L-B |

## D.7 List of other optional accessories

| Name | Specifications | Function | Remarks |
|---|---|---|---|
| External LED keypad | BOP-270 | Externally connected LED display and operation panel | Applicable to 1.5–22kW models |
| External LCD keypad | SOP-270 | Externally connected LCD display and operation panel | Applicable to all series<br>For details about how to operate the keypad, see chapter 5 in the operation manual for GD350 series high-performance multifunction VFD. |
| Keypad bracket | GD350-JPZJ | Used to fix the LED or LCD keypad for external connection to the electrical cabinet | Applicable to all series |
| Keypad protective cover | GD270-JPFH | When the local keypad is externally led, this protective cover prevents dust and foreign objects from entering through the keypad port. | Applicable to 30–630kW models |
| Rail assembly for cabinet mounting | GD270-DGZJ | Used to mount a VFD in a cabinet, improving mounting efficiency and safety | Applicable to 220–630kW models. For detailed instructions, see section 4.2.3 Cabinet design. |
| Flange mounting bracket | Consult the manufacturer. | Used to meet the flange mounting needs | Applicable to 1.5–200kW models |
| External braking unit busbar | - | Used to extend wiring connections when an external braking unit is required. | Applicable to 710–800 kW models. |

# Appendix E STO function (for -EU models only)

## E.1 Safety standards

The product has been integrated with the STO function and complies with the following safety standards.

| | |
|---|---|
| IEC 61000-6-7 | Electromagnetic compatibility (EMC)—Part 7: General standards—Immunity requirements for equipment used in industrial sites to perform safety related functions (functional safety) |
| IEC 61326-3-1 | EMC requirements for measurement, control, and laboratory electrical equipment—Part 31: Immunity requirements for safety related systems and equipment intended to perform safety related functions (functional safety)—General industrial applications |
| IEC 61508-1 | Functional safety of electrical/electronic/programmable electronic safety related systems—Part 1: General requirements |
| IEC 61508-2 | Functional safety of electrical/electronic/programmable electronic safety related systems—Part 2: Requirements for electrical/electronic/programmable electronic safety related systems |
| IEC/EN 61800-5-2 | Adjustable speed electrical power drive systems Part 5-2: Safety requirements—Function |
| IEC/EN 62061 | Safety of machinery—Safety-related functional safety of electrical, electronic, and programmable electronic control systems |
| EN/ISO 13849-1 | Safety of machinery—Safety related parts of control systems—Part 1: General principles for design |
| EN/ISO 13849-2 | Safety of machinery—Safety related parts of control systems—Part 2: Verification |

Safety standard related data is as follows.

| Code | Definition | Standard | Characteristics |
|---|---|---|---|
| SIL | Safety integrity level | IEC 61508<br>IEC 62061 | SIL3 |
| PFH | Probability of failure per hour | IEC 61508 | $2.87x10^{-10}$ |
| HFT | Hardware fault tolerance | IEC 61508 | 1 |
| SFF | Safe failure fraction | IEC 61508 | 97.59% |
| DC | Diagnosis coverage | ISO 13849-1 | Greater than 90% |
| Cat. | Category | ISO 13849-1 | 3 |

## E.2 Safety function description

### ■ STO function principle description

STO (Safe Torque Off) function turns off the drive output by shutting down the drive signal, cutting off the electrical power supply to the motor and thus stopping the outward torque output (see Figure E-3). When STO is activated, this function prevents the motor from accidentally starting if the motor is in static state. If the motor is rotating, it will continue to rotate by inertia until it comes to rest. If the motor has a brake, the brake closes immediately.

**Note:**

- In normal working mode, you are not recommended to use the STO function to stop the VFD running. The STO function cannot effectively prevent sabotage or misuse. If the STO function is used to stop a running VFD, the VFD will disconnect the power supply to the motor, and the motor will coast to stop. If the consequences caused by this action are unacceptable, related stop modes should be used to stop the VFD and mechanical equipment.
- When using a permanent magnet, reluctance, or nonsalient pole induction motor, even if the STO function is activated, there is still a possible failure mode (although the possibility is very low) that prevents the two power devices of the VFD from conducting. The drive system can output a uniform torque, which can rotate the permanent magnet motor shaft by a maximum electrical angle of 180°, or the nonsalient pole induction motor or reluctance motor shaft by an electrical angle of 90°. This possible failure mode must be allowed during the design of the machine system. Maximum motor shaft rotation angle = Electrical angle of 360°/Number of motor pole pairs.
- The STO function cannot replace the emergency stop function. When no other measures are taken, the power supply of the VFD cannot be cut off in an emergency.
- The STO function has priority over all other functions of the VFD.
- Although the STO function can reduce known hazardous conditions, it does not eliminate all potential hazards.
- Designing safety related systems requires professional safety knowledge. To ensure the safety of a complete control system, design the system according to the required safety principles. A single subsystem with the STO function, although intentionally designed for safety related applications, it cannot guarantee the safety of the entire system.

### ■ Emergency stop function description

When the emergency stop function is used in equipment, it mainly allows operators to take timely actions to prevent accidents in unexpected conditions. Its design may not necessarily be complex or intelligent, but it may use simple electromechanical devices to initiate a controlled rapid stop by cutting off the power supply or other means (such as dynamic or regenerative braking).

## E.3 Risk assessment

1. Before using the STO function, a risk assessment needs to be conducted on the drive system to ensure compliance with the required safety standards.
2. There may also be some other risks when the device is operating with safety functions. Therefore, safety must always be considered when conducting risk assessments.
3. If an external force (such as vertical axis gravity) is applied while the safety function is in operation, the motor will rotate. A separate mechanical brake must be provided to secure the motor.
4. If the drive fails, the motor can operate within the range of 180 degrees, ensuring safety even in dangerous situations.
5. The rotation number and moving distance of each type of motor are as follows:

- Rotating motor: can rotate up to 1/6 (of the motor shaft rotation angle).
- Drive motor: can rotate up to 1/20 (of the motor shaft rotation angle).
- Linear servo motor: can move up to 30mm.

## E.4 STO wiring

In the factory, the STO function terminals +24V, H1, and H2 have been shorted.

The wiring requirements are as follows:

1. When using the STO function of the VFD, remove the jumpers between +24V and H1 and between +24V and H2.
2. When the VFD is in normal operation, close K (the switches or relays).

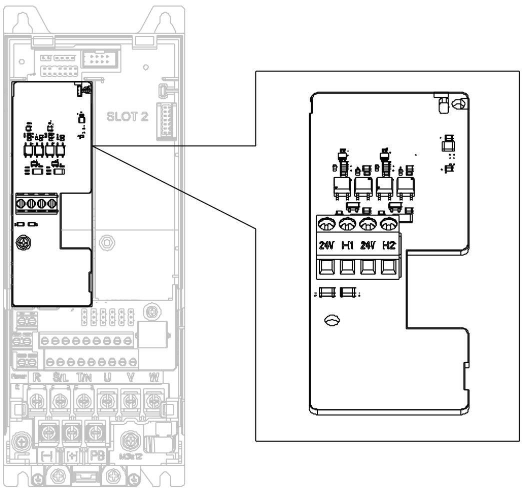



Figure E-1 STO function terminal diagram for 1.5–7.5kW models (SLOT1 position)

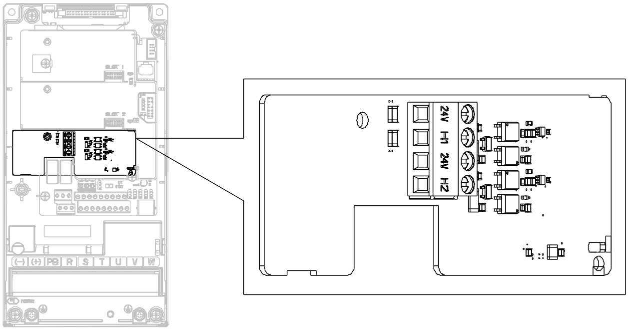



Figure E-2 STO function terminal diagram for 11–500kW models (SLOT3 position)

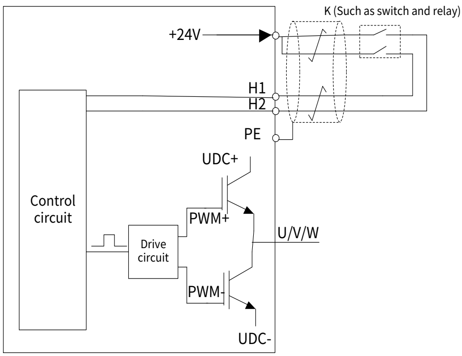



Figure E-3 STO function circuit wiring

**Note:**

- The symbol K in the preceding figure can represent components such as manual operation switch, emergency stop switch, safety relay, and safety PLC contact.
- The opening or closing of safety switch contact must be within 200.
- The maximum length of the double-shielded twisted pair cable between the VFD and safety switch is 25m.
- The cable shield layer should be connected to the PE terminal of the VFD.
- When the STO function is enabled, the switch or relay is opened. If the VFD stops output, the keypad displays "STO".

## E.5 STO function terminal description

STO function terminals are listed in the following table.

| Terminal symbol | Function description |
|---|---|
| +24V | Voltage range: 24V±15%<br>To disable the STO function, short +24V to H1 and to H2. |
| H1 | Voltage in STO action mode: 0V < H1 and H2 < 5V<br>Voltage in STO cut-off mode: 13V < H1 and H2 < 30V<br>Input current: 5mA<br>STO function channel signal input |
| H2 | |

**Note:** For the 1.5–7.5kW -EU models, the extended interface SLOT1 will be occupied due to the H1/H2 terminals, that is, 1.5–7.5kW -EU models only support extended interface SLOT2.

## E.6 STO function logic table

The function logics of H1 and H2 and keypad display are listed in the following table.

| H1 | H2 | VFD status | Keypad display | Fault description |
|---|---|---|---|---|
| H1 closed | H2 closed | Normal running | No exception displayed | - |
| H1 opened | H2 opened | Torque output off | STO | Safe torque off (STO) |
| H1 opened | H2 closed | Torque output off | STL1 | H1 is abnormal. |
| H1 closed | H2 opened | Torque output off | STL2 | H2 is abnormal. |

**Note:** STL3 indicates both H1 and H2 are abnormal.

## E.7 STO channel delay description

The following table describes the trigger and indication delay of the STO channels.

Table E-1 STO channel trigger and indication delay

| STO mode | STO trigger delay[1] and indication delay[2] |
|---|---|
| STO fault: STL1 | Trigger delay < 10ms<br>Indication delay < 280ms |
| STO fault: STL2 | Trigger delay < 10ms<br>Indication delay < 280ms |
| STO fault: STL3 | Trigger delay < 10ms<br>Indication delay < 280ms |
| STO fault: STO | Trigger delay < 10ms<br>Indication delay < 100ms |

[1]: STO trigger delay: time interval between trigger the STO function and switching off the drive output

[2]: STO instruction delay: Time interval between trigger the STO function and STO output state indication

## E.8 Acceptance test

| Alarm | |
|---|---|
| | • Technical personnel, operators, maintenance and repair personnel must receive relevant training to understand the requirements and principles of safety system design and debugging.<br>• Do not carry out maintenance on the VFD or motor before the power is cut off; otherwise, there may be a risk of electric shock or other electricity generated hazards.<br>• The safety function acceptance test must be carried out by personnel with professional safety function knowledge, and must be recorded and signed by test engineers. |

The acceptance test must be carried for the device in the following stages:

1. First starting of safety functions
2. After any safety function related change (including PCB, wiring, component, or setup)
3. After any safety function related maintenance work

The signed acceptance test report must be kept in machine logs. The report should include the documents of startup activities and test results, fault report references and fault solutions. Any new acceptance test conducted due to changes or maintenance should be recorded in the logs.

■ **Acceptance test checklist**

| Step | Test | Result |
|---|---|---|
| 1 | Ensure that the VFD can run or stop randomly during commissioning. | |
| 2 | Stop the VFD (if it is running), disconnect the input power supply, and isolate the drive from the power cable through the isolation switch. | |
| 3 | Check the STO function circuit connection according to the circuit diagram. | |
| 4 | Close the isolation switch to connect to the power. | |
| | Test the STO function as follows when the motor stops:<br>If the VFD is running, send a stop command to it and wait until the motor shaft stops rotating.<br>Disconnect the STO circuit. Then the VFD should enter the safe torque off mode and stop outputting voltage, and the keypad displays "STO".<br>Send a VFD startup command, but the motor does not start.<br>Close the STO circuit.<br>Remove the fault, start the VFD, and ensure that the motor can run properly. | |
| | Test the STO function as follows when the motor is running:<br>Start the VFD and ensure that the motor runs.<br>Disconnect the STO circuit. Then the VFD should enter the safe torque off mode and stop outputting voltage, and the keypad displays "STO". The motor | |

| Step | Test | Result |
|---|---|---|
| | should stop.<br>Remove the fault, start the VFD, and ensure that the motor keeps the static state.<br>Close the STO circuit.<br>Remove the fault, start the VFD, and ensure that the motor can run properly. | |
| 5 | Test and detect the VFD fault. At this time, the motor can be in running or stopped state.<br>Start the VFD and ensure that the motor runs properly.<br>Disconnect H1 and keep H2 closed. If the motor is running, it should coast to stop, and the keypad displays "STL1".<br>Send a VFD startup command, but the motor does not start.<br>Close the STO circuit.<br>At this time, the fault cannot be removed. Power off and restart the VFD, and ensure that the motor can run properly.<br>Disconnect H2 and keep H1 closed. If the motor is running, it should coast to stop, and the keypad displays "STL2".<br>Send a VFD startup command, but the motor does not start.<br>Close the STO circuit.<br>At this time, the fault cannot be removed. Power off and restart the VFD, and ensure that the motor can run properly. | |
| 6 | Record and sign the acceptance test report, which indicates the STO function is safe and can be put into service. | |

**Note:**

- If the steps in the acceptance test checklist can be carried out normally without other exceptions, it indicates that the STO functional circuit is normal. If the situations are different from the expected results of the preceding steps or if "E43" is displayed, it indicates that the STO function circuit is abnormal. For details about fault handling, see section 7.5.1 Faults and solutions.
- Fault "STO" can also be manually or automatically reset by setting P08.52.

| VFD fault | Fault code displayed | Response time | Reset method |
|---|---|---|---|
| Normal running | No exception displayed | - | - |
| Torque output off | STO | ≤20ms | Press STOP/RST. |
| Torque output off | STL1 | ≤20ms | Entire machine re-powered on |
| Torque output off | STL2 | ≤20ms | Entire machine re-powered on |

# Appendix F Effecicieny

Table F-1 Power loss and IE class

| Model | Relative loss (%) | | | | | | | | Standby | IE |
|---|---|---|---|---|---|---|---|---|---|---|
| | (0;25) | (0;50) | (0;100) | (50;25) | (50;50) | (50;100) | (90;50) | (90;100) | loss (W) | class |
| GD270-1R5-4(-C2)(-EU) | 0.78 | 0.95 | 1.03 | 0.86 | 1.17 | 1.23 | 1.35 | 2.02 | 13 | IE2 |
| GD270-2R2-4(-C2)(-EU) | 0.82 | 0.76 | 0.55 | 1.09 | 1.11 | 1.07 | 1.59 | 1.76 | 17 | IE2 |
| GD270-004-4(-C2)(-EU) | 0.74 | 1.20 | 1.55 | 1.15 | 1.28 | 1.89 | 1.45 | 2.29 | 16 | IE2 |
| GD270-5R5-4(-C2)(-EU) | 0.71 | 0.97 | 1.32 | 1.02 | 1.21 | 1.83 | 1.34 | 2.18 | 17 | IE2 |
| GD270-7R5-4(-C2)(-EU) | 0.68 | 0.78 | 1.75 | 0.76 | 1.03 | 1.79 | 1.22 | 2.06 | 20 | IE2 |
| GD270-011-4(-L1/-C2)(-EU) | 0.65 | 0.89 | 1.62 | 0.66 | 1.37 | 1.43 | 1.38 | 2.28 | 27 | IE2 |
| GD270-015-4(-L1/-C2)(-EU) | 0.96 | 1.30 | 2.26 | 0.74 | 0.90 | 1.43 | 0.87 | 1.49 | 27 | IE2 |
| GD270-018-4(-L1/-C2)(-EU) | 0.72 | 0.95 | 1.57 | 1.20 | 1.46 | 2.17 | 1.47 | 2.26 | 30 | IE2 |
| GD270-022-4(-L1/-C2)(-EU) | 0.67 | 0.87 | 1.44 | 1.07 | 1.29 | 1.92 | 1.27 | 2.04 | 30 | IE2 |
| GD270-030-4(-L1)(-C3)(-EU) | 0.71 | 0.98 | 1.76 | 1.22 | 1.89 | 2.42 | 2.17 | 2.83 | 30 | IE2 |
| GD270-037-4(-L1)(-C3)(-EU) | 0.67 | 0.85 | 1.60 | 1.09 | 1.75 | 2.37 | 1.91 | 2.73 | 30 | IE2 |
| GD270-045-4(-L1)(-C3)(-EU) | 0.47 | 0.62 | 1.14 | 1.09 | 1.27 | 1.90 | 1.52 | 2.02 | 30 | IE2 |
| GD270-055-4(-L1)(-C3)(-EU) | 0.42 | 0.69 | 1.04 | 0.98 | 1.19 | 1.72 | 1.45 | 1.88 | 31 | IE2 |
| GD270-075-4(-L1)(-C3)(-EU) | 0.52 | 0.80 | 1.35 | 1.06 | 1.42 | 2.10 | 1.67 | 2.23 | 32 | IE2 |
| GD270-090-4(-L1)(-C3)(-EU) | 0.40 | 0.72 | 1.29 | 0.93 | 1.31 | 1.98 | 1.58 | 2.11 | 31 | IE2 |
| GD270-110-4(-L1)(-C3)(-EU) | 0.42 | 0.69 | 1.20 | 0.84 | 0.98 | 1.67 | 1.27 | 1.72 | 33 | IE2 |
| GD270-132-4(-L1)(-C3)(-EU) | 0.50 | 0.65 | 1.28 | 0.97 | 1.12 | 1.74 | 1.22 | 1.85 | 35 | IE2 |
| GD270-160-4(-L1)(-EU) | 0.61 | 1.01 | 1.52 | 1.37 | 1.32 | 2.02 | 1.42 | 2.14 | 37 | IE2 |
| GD270-185-4(-L1)(-EU) | 0.56 | 0.95 | 1.45 | 1.13 | 1.19 | 1.88 | 1.37 | 2.07 | 37 | IE2 |
| GD270-200-4(-L1)(-EU) | 0.48 | 0.81 | 1.33 | 0.99 | 1.08 | 1.78 | 1.28 | 1.99 | 38 | IE2 |
| GD270-220-4(-L*n*)(-EU) | 0.59 | 0.85 | 1.76 | 1.24 | 1.58 | 2.61 | 1.68 | 2.65 | 40 | IE2 |
| GD270-250-4(-L*n*)(-EU) | 0.65 | 0.91 | 1.86 | 1.33 | 1.72 | 2.79 | 1.73 | 2.85 | 42 | IE2 |
| GD270-280-4(-L*n*)(-EU) | 0.68 | 0.98 | 1.92 | 1.27 | 1.61 | 2.54 | 1.62 | 2.69 | 48 | IE2 |
| GD270-315-4(-L*n*)(-EU) | 0.66 | 0.94 | 1.88 | 1.19 | 1.49 | 2.45 | 1.56 | 2.54 | 50 | IE2 |
| GD270-355-4(-L*n*)(-EU) | 0.72 | 1.01 | 1.87 | 1.11 | 1.37 | 2.30 | 1.47 | 2.47 | 52 | IE2 |
| GD270-400-4-L*n*(-EU) | 0.78 | 0.82 | 1.64 | 1.14 | 1.38 | 2.25 | 1.43 | 2.31 | 55 | IE2 |
| GD270-450-4-L*n*(-EU) | 0.75 | 0.89 | 1.52 | 1.08 | 1.27 | 2.16 | 1.37 | 2.23 | 58 | IE2 |
| GD270-500-4-L*n*(-EU) | 0.73 | 0.78 | 1.40 | 0.90 | 1.10 | 1.90 | 1.25 | 2.16 | 60 | IE2 |
| GD270-560-4-Ln(-EU) | 0.71 | 0.82 | 1.42 | 1.28 | 1.48 | 2.48 | 1.53 | 2.52 | 62 | IE2 |
| GD270-630-4-Ln(-EU) | 0.69 | 0.85 | 1.36 | 0.93 | 1.33 | 2.35 | 1.41 | 2.25 | 65 | IE2 |
| GD270-710-4-Ln(-EU) | 0.74 | 0.87 | 1.39 | 1.26 | 1.51 | 2.53 | 1.55 | 2.61 | 66 | IE2 |
| GD270-800-4-Ln(-EU) | 0.77 | 0.83 | 1.37 | 1.18 | 1.49 | 2.49 | 1.49 | 2.33 | 68 | IE2 |

**Note:** *n* = 1 or 3

Table F-2 Rated specifications

| Model | Apparent power (kVA) | Rated output power (kW) | Rated output current (A) | Max. working temperature (°C) | Rated power frequency (Hz) | Rated power voltage (V) |
|---|---|---|---|---|---|---|
| GD270-1R5-4(-C2)(-EU) | 2.44 | 1.5 | 3.7 | 50°C Derate by 1% for every increase of 1°C when the temperature exceeds 40°C. | 50/60Hz Allowed range: 47–63Hz | 3PH 380V |
| GD270-2R2-4(-C2)(-EU) | 3.98 | 2.2 | 5 | | | |
| GD270-004-4(-C2)(-EU) | 6.2 | 4 | 9.5 | | | |
| GD270-5R5-4(-C2)(-EU) | 8.6 | 5.5 | 13 | | | |
| GD270-7R5-4(-C2)(-EU) | 12.2 | 7.5 | 17 | | | |
| GD270-011-4(-L1/-C2)(-EU) | 16.5 | 11 | 25 | | | |
| GD270-015-4(-L1/-C2)(-EU) | 21 | 15 | 32 | | | |
| GD270-018-4(-L1/-C2)(-EU) | 24 | 18.5 | 38 | | | |
| GD270-022-4(-L1/-C2)(-EU) | 30 | 22 | 45 | | | |
| GD270-030-4(-L1)(-C3)(-EU) | 39.5 | 30 | 60 | | | |
| GD270-037-4(-L1)(-C3)(-EU) | 49 | 37 | 75 | | | |
| GD270-045-4(-L1)(-C3)(-EU) | 60 | 45 | 92 | | | |
| GD270-055-4(-L1)(-C3)(-EU) | 75.7 | 55 | 115 | | | |
| GD270-075-4(-L1)(-C3)(-EU) | 98.7 | 75 | 150 | | | |
| GD270-090-4(-L1)(-C3)(-EU) | 120 | 90 | 180 | | | |
| GD270-110-4(-L1)(-C3)(-EU) | 142 | 110 | 215 | | | |
| GD270-132-4(-L1)(-C3)(-EU) | 172 | 132 | 250 | | | |
| GD270-160-4(-L1)(-EU) | 200 | 160 | 305 | | | |
| GD270-185-4(-L1)(-EU) | 217 | 185 | 330 | | | |
| GD270-200-4(-L1)(-EU) | 250 | 200 | 380 | | | |
| GD270-220-4(-L*n*)(-EU) | 280 | 220 | 425 | | | |
| GD270-250-4(-L*n*)(-EU) | 316 | 250 | 460 | | | |
| GD270-280-4(-L*n*)(-EU) | 349 | 280 | 530 | | | |
| GD270-315-4(-L*n*)(-EU) | 395 | 315 | 600 | | | |
| GD270-355-4(-L*n*)(-EU) | 425 | 355 | 650 | | | |
| GD270-400-4-L*n*(-EU) | 474 | 400 | 720 | | | |
| GD270-450-4-L*n*(-EU) | 540 | 450 | 820 | | | |
| GD270-500-4-L*n*(-EU) | 566 | 500 | 860 | | | |
| GD270-560-4-Ln(-EU) | 671.32 | 560 | 1020 | | | |
| GD270-630-4-Ln(-EU) | 737.14 | 630 | 1120 | | | |
| GD270-710-4-Ln(-EU) | 829.28 | 710 | 1260 | | | |
| GD270-800-4-Ln(-EU) | 960.91 | 800 | 1460 | | | |

**Note:** *n* = 1 or 3

# Appendix G Further information

## G.1 Product and service queries

If you have any queries about the product, contact the local INVT office. Please provide the model and serial number of the product you query about. You can visit www.invt.com to find a list of INVT offices.

## G.2 Feedback on INVT VFD manuals

Your comments on our manuals are welcome. Visit www.invt.com, directly contact online service personnel or choose **Contact Us** to obtain contact information.

## G.3 Documents on the Internet

You can find manuals and other product documents in the PDF format on the Internet. Visit www.invt.com and choose **Support** > **Download**.

E-mail: overseas@invt.com.cn Website: www.invt.com

The products are owned by **Shenzhen INVT Electric Co.,Ltd.**
Two companies are commissioned to manufacture: (For product code, refer to the 2nd/3rd place of S/N on the name plate.)

**Shenzhen INVT Electric Co., Ltd.** (origin code: 01)
Address: INVT Guangming Technology Building, Songbai Road, Matian, Guangming District, Shenzhen, China

**INVT Power Electronics (Suzhou) Co., Ltd**. (origin code: 06)
Address: No.1 Kunlunshan Road, Science & Technology Town, Suzhou New District, Jiangsu, China

Industrial Automation: ■HMI ■PLC ■VFD ■Servo System
■Elevator Intelligent Control System ■Rail Transit Traction System

Energy & Power: ■UPS ■DCIM ■Solar Inverter ■SVG
■New Energy Vehicle Powertrain System ■New Energy Vehicle Charging System
■New Energy Vehicle Motor

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