



# INVERTER

Plug-in option

## FR-A8AL

# INSTRUCTION MANUAL

*Orientation control*

*Encoder feedback control*

*Vector control*

*Position control*

*Encoder pulse dividing output*

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Thank you for choosing this Mitsubishi inverter plug-in option.

This Instruction Manual provides handling information and precautions for use of this product. Incorrect handling might cause an unexpected fault. Before using this product, always read this Instruction Manual carefully to use this product correctly.

Please forward this Instruction Manual to the end user.

### Safety instructions

Do not attempt to install, operate, maintain or inspect the product until you have read through this Instruction Manual and appended documents carefully and can use the equipment correctly. Do not use this product until you have a full knowledge of the equipment, safety information and instructions. In this Instruction Manual, the safety instruction levels are classified into "Warning" and "Caution".



**Warning**

Incorrect handling may cause hazardous conditions, resulting in death or severe injury.



**Caution**

Incorrect handling may cause hazardous conditions, resulting in medium or slight injury, or may cause only material damage.



**Caution**

The **Caution** level may even lead to a serious consequence according to conditions. Both instruction levels must be followed because these are important to personal safety.

#### ◆ Electric Shock Prevention



**Warning**

- While the inverter power is ON, do not open the front cover or the wiring cover. Do not run the inverter with the front cover or the wiring cover removed. Otherwise you may access the exposed high voltage terminals or the charging part of the circuitry and get an electric shock.
- Do not remove the inverter front cover even if the power supply is disconnected. The only exception for this would be when performing wiring and periodic inspection. You may accidentally touch the charged inverter circuits and get an electric shock.
- Before wiring or inspection, LED indication of the inverter unit operation panel must be switched OFF. Any person who is involved in wiring or inspection shall wait for at least 10 minutes after the power supply has been switched OFF and check that there is no residual voltage using a tester or the like. For some time after the power-OFF, a high voltage remains in the smoothing capacitor, and it is dangerous.
- Any person who is involved in wiring or inspection of this equipment shall be fully competent to do the work.
- The plug-in option must be installed before wiring. Otherwise you may get an electric shock or be injured.
- Do not touch the plug-in option or handle the cables with wet hands. Otherwise you may get an electric shock.
- Do not subject the cables to scratches, excessive stress, heavy loads or pinching. Otherwise you may get an electric shock.

#### ◆ Injury Prevention



**Caution**

- The voltage applied to each terminal must be the ones specified in the Instruction Manual. Otherwise a burst, damage, etc. may occur.
- The cables must be connected to the correct terminals. Otherwise a burst, damage, etc. may occur.
- The polarity (+ and -) must be correct. Otherwise a burst or damage may occur.
- While power is ON or for some time after power OFF, do not touch the inverter as it will be extremely hot. Touching these devices may cause a burn.

#### ◆ Additional Instructions

The following instructions must be also followed. If the product is handled incorrectly, it may cause unexpected fault, an injury, or an electric shock.

### Caution

#### Transportation and mounting

- Do not install or operate the plug-in option if it is damaged or has parts missing.
- Do not stand or rest heavy objects on the product.
- The mounting orientation must be correct.
- Foreign conductive objects must be prevented from entering the inverter. That includes screws and metal fragments or other flammable substance such as oil.
- If halogen-based materials (fluorine, chlorine, bromine, iodine, etc.) infiltrate into a Mitsubishi product, the product will be damaged. Halogen-based materials are often included in fumigant, which is used to sterilize or disinfest wooden packages. When packaging, prevent residual fumigant components from being infiltrated into Mitsubishi products, or use an alternative sterilization or disinfection method (heat disinfection, etc.) for packaging. Sterilization or disinfection of wooden package should also be performed before packaging the product.

#### Trial run

- Before starting operation, each parameter must be confirmed and adjusted. A failure to do so may cause some machines to make unexpected motions.

### Warning

#### Usage

- Do not modify the equipment.
- Do not perform parts removal which is not instructed in this manual. Doing so may lead to fault or damage of the product.

### Caution

#### Usage

- When parameter clear or all parameter clear is performed, the required parameters must be set again before starting operations. Because all parameters return to their initial values.
- Static electricity in your body must be discharged before you touch the product.

#### Maintenance, inspection and parts replacement

- Do not carry out a megger (insulation resistance) test.

#### Disposal

- The product must be treated as industrial waste.

### General instruction

- Many of the diagrams and drawings in this Instruction Manual show the inverter without a cover or partially open for explanation. Never operate the inverter in this manner. The cover must be reinstalled and the instructions in the Instruction Manual must be followed when operating the inverter.

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# 1 PRE-OPERATION INSTRUCTIONS

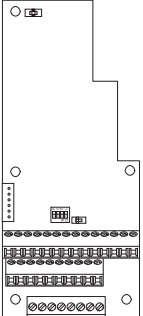
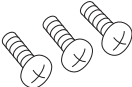
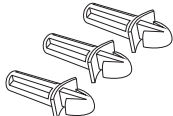
## 1.1 Unpacking and product confirmation

Take the plug-in option out of the package, check the product name, and confirm that the product is as you ordered and intact. This product is a plug-in option dedicated for the FR-A800 series.

### 1.1.1 Product confirmation

#### ◆ Product confirmation

Check the enclosed items.

Plug-in option.....1 	Mounting screw (M3 × 8 mm)....3 (Refer to <a href="#">page 10.</a> ) 	Spacer.....3 (Refer to <a href="#">page 10.</a> ) 
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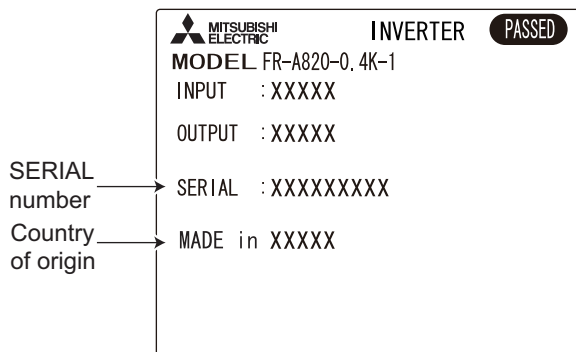
#### NOTE

- Connection diagrams in this Instruction Manual appear with the control logic of the input terminals as sink logic, unless otherwise specified. (For the control logic, refer to the Instruction Manual(Detailed) of the inverter.)

## 1.1.2 SERIAL number check

The FR-A8AL can be used for the inverter models listed below with the following SERIAL number or later. Check the SERIAL number indicated on the inverter rating plate or package. For the location of the rating plate, refer to the Instruction Manual (Detailed) of the inverter.

Rating plate example



□    ○    ○    ○ ○ ○ ○ ○  
Symbol    Year    Month    Control number  
**SERIAL**

The SERIAL consists of one symbol, two characters indicating the production year and month, and six characters indicating the control number.

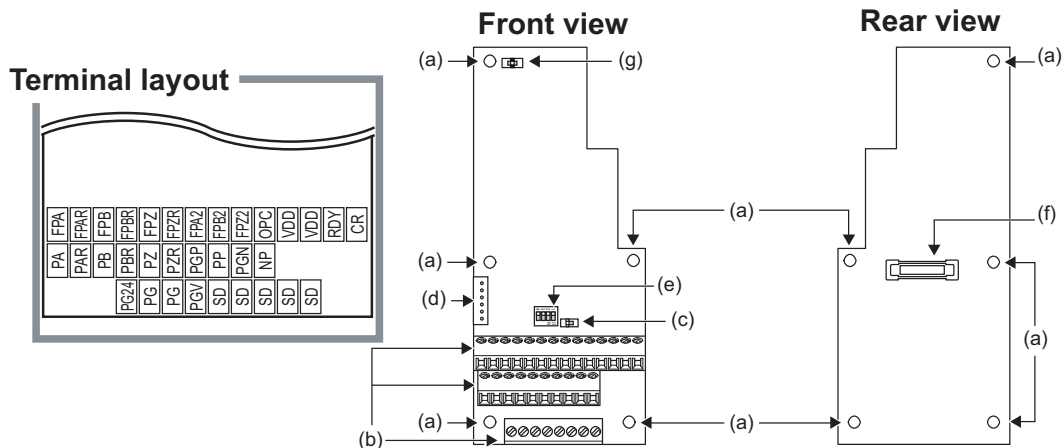
The last digit of the production year is indicated as the Year, and the Month is indicated by 1 to 9, X (October), Y (November), or Z (December).

- FR-A800 series

Model	Country of origin indication	SERIAL number
FR-A820-00046(0.4K) to 04750(90K) FR-A840-00023(0.4K) to 06830(280K) FR-A842-07700(315K) to 12120(500K) FR-A846-00023(0.4K) to 00470(18.5K)	MADE in Japan	□58○○○○○○ or later
	MADE in China	□59○○○○○○ or later



## 1.2 Component names



Symbol	Name	Description	Refer to page
a	Mounting hole	Fixes the option to the inverter with screws, or installs spacers.	10
b	Terminal block	Connects to the encoder.	15
c	Encoder type selection switch (SW3)	Switches the encoder type (differential line driver/ complementary).	13
d	CON2 connector	Connector for the FR-A8NS (SSCNET III) connection	—
e	Terminating resistor selection switches (SW2-1 to SW2-3)	Switches ON or OFF the internal terminating resistor.	13
	Encoder power supply selection switch (SW2-4)	Switches the voltage supplied to the encoder from terminal PGV.	
f	Connector	Connects to the option connector of the inverter.	10
g	Switch for manufacturer setting (SW1)	Do not change the initially-set status ( <input type="checkbox"/> ).	—

## **2** INSTALLATION

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### **2.1 Pre-installation instructions**

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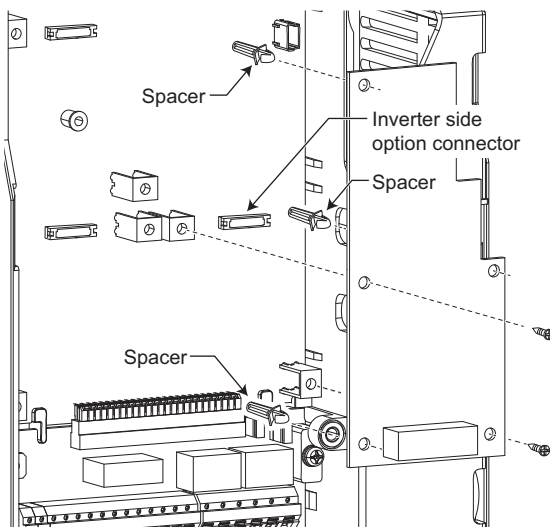
Check that the inverter's input power and the control circuit power are both OFF.

#### **Caution**

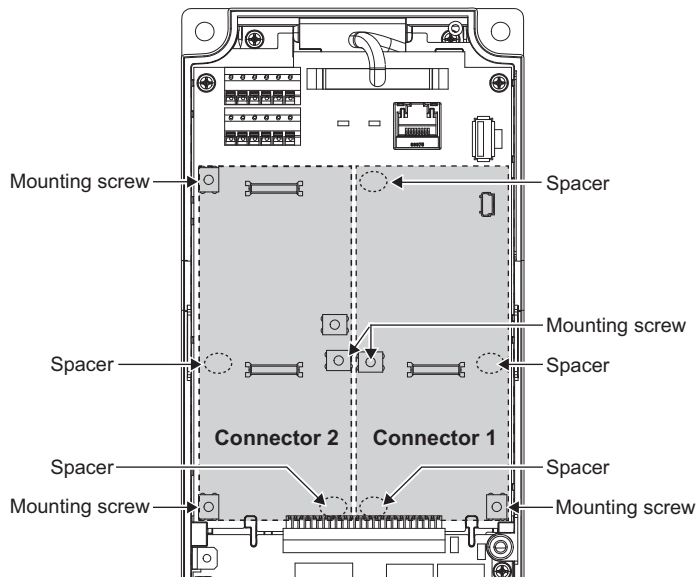
- With input power ON, do not install or remove the plug-in option. Otherwise, the inverter and plug-in option may be damaged.
- To avoid damage due to static electricity, static electricity in your body must be discharged before you touch the product.

## 2.2 Installation procedure

- (1) Remove the inverter front cover. (Refer to Chapter 2 of the Instruction Manual (Detailed) of the inverter for details on how to remove the front cover.)
- (2) As shown in the next page, when the plug-in option is installed to the connector 1, insert spacers in the three mounting holes that will not be tightened with mounting screws. (When the plug-in option is installed to the connector 2, insert spacers in the two mounting holes.)
- (3) Fit the connector of the plug-in option to the guide of the connector on the inverter unit side, and insert the plug-in option as far as it goes.
- (4) When the plug-in option is installed to the connector 1, fit the two locations, the left and right, of the product securely to the inverter unit by screwing in the supplied mounting screws. (When the plug-in option is installed to the connector 2, fit the three locations.) (tightening torque 0.33 N·m to 0.40 N·m) If the screw holes do not line up, the connector may not be inserted deep enough. Check the connector.



Example of installation to connector 1



**Insertion positions for screws and spacers**

 **NOTE**

- When mounting/removing the plug-in option, hold the sides of the option. Do not press on the parts on the option circuit board. Stress applied to the parts by pressing, etc. may cause a failure.
- Caution must be applied to mounting screws falling off when removing and mounting the plug-in option.
- If the FR-A8AL and the FR-A8AP (FR-A8APR) are installed together, the FR-A8AP (FR-A8APR) is disabled.
- Only one option can be used. When multiple options are mounted, priority is given to option connectors 1, 2 and 3 on the inverter in this order, and options having a lower priority do not function.
- When the inverter cannot recognize that the option unit is mounted due to improper installation, etc., the protective function (E.1 to E.3) is activated. A different indication will appear according to the mounted position (option connector 1 to 3).

Mounted position	Fault indication
Option connector 1	E. 1
Option connector 2	E. 2
Option connector 3	E. 3

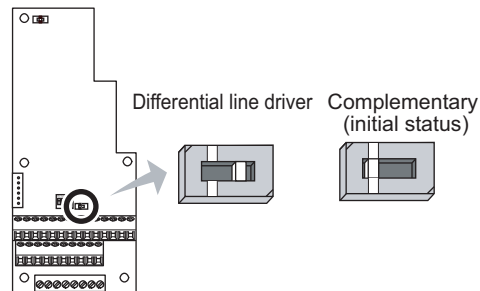
- When removing the plug-in option, remove the two screws on the left and right, then pull it straight out. Pressure applied to the connector and to the option board may break the option.

## 2.3 Encoder specification / terminating resistor switch setting

### ◆ Encoder specification selection switch (SW3)

Select either differential line driver or complementary.

It is initially set to the complementary. Switch its position according to output circuit.



### ◆ Terminating resistor selection switches (SW2-1 to SW2-3)

Select "ON"/"OFF" of the internal terminating resistor. Set the SW2-1 to SW2-3 switches to "ON" when an encoder output type is differential line driver and set to "OFF" when complementary (initial status).

ON : with internal terminating resistor

OFF : without internal terminating resistor (initial status)

### ◆ Encoder power supply selection switch (SW2-4)

Select 5 V or 12 V power to be supplied to the encoder from terminal PGV.

Set SW2-4 to the ON position for the 12 V power supply, or set SW2-4 to the OFF position (initial status) for the 5 V power supply.

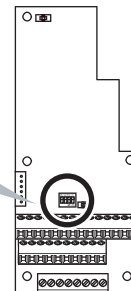
Internal terminating resistor-ON



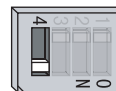
Internal terminating resistor-OFF (initial status)



5 V power supply for the encoder (initial status)



12 V power supply for the encoder



2

 **NOTE**

- If the encoder output type is differential line driver, set the terminating resistor switch to the "OFF" position when sharing the same encoder with other unit (CNC (computerized numerical controller), etc) or a terminating resistor is connected to other unit.
- Terminals PGV and PG24 cannot be used simultaneously.
- When using terminal PGV to supply power to the encoder, check that the voltage setting meets the encoder specification. Applying a voltage exceeding the encoder specification may damage the encoder.

◆ **Motor used and switch setting**

Motor		Encoder specification selection switch (SW3)	Terminating resistor selection switches (SW2 -1 to SW2-3)	Power specifications*2
Mitsubishi standard motor with encoder Mitsubishi high-efficiency motor with encoder	SF-JR	Differential	ON	5 V
	SF-HR	Differential	ON	5 V
	Others	*1	*1	*1*3
Mitsubishi constant-torque motor with encoder	SF-JRCA	Differential	ON	5 V
	SF-HRCA	Differential	ON	5 V
	Others	*1	*1	*1*3
Vector control dedicated motor	SF-V5RU	Complementary	OFF	12 V / 24 V
Other manufacturer's motor with encoder		*1	*1	*1*3

\*1 Set according to the motor encoder used.

\*2 Depending on the encoder to be used, prepare an external power supply (15 V) for the encoder. When the 24 V power supply of the FR-A8AL is used, the power is supplied to the encoder through terminal PG24. When the 5 V/12 V power supply of the FR-A8AL is used, the power is supplied to the encoder through terminal PGV.

\*3 When the encoder output is the differential line driver type, only 5 V can be input.

 **NOTE**

- Switch "SW1" is for manufacturer setting. Do not change the setting.

## 2.4 Wiring

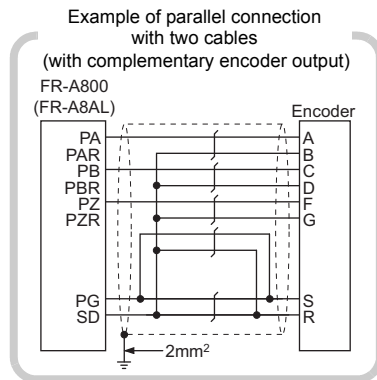
(1) Use twisted pair shield cables (0.2 mm<sup>2</sup> or larger) to connect the FR-A8AL and position detector.

For the wiring to the terminals PG and SD, use several cables in parallel or use a thick cable, according to the wiring length. To protect the cables from noise, run them away from any source of noise (e.g. the main circuit and power voltage).

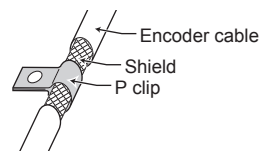
Wiring length	Parallel connection (Cable gauge 0.2 mm <sup>2</sup> )	Larger-size cable
Within 10 m	At least two cables in parallel	0.4 mm <sup>2</sup> or larger
Within 20 m	At least four cables in parallel	0.75 mm <sup>2</sup> or larger
Within 100 m *1	At least six cables in parallel	1.25 mm <sup>2</sup> or larger

\*1 When differential driver is set and a wiring length is 30 m or more  
The wiring length can be extended to 100 m by slightly increasing the 5 V power supply (approx. 5.5 V) and using six or more cables with gauge size of 0.2 mm<sup>2</sup> in parallel or a cable with gauge size of 1.25 mm<sup>2</sup> or more. Note that the voltage applied should be within power supply specifications of encoder.

To reduce noise of the encoder cable, earth (ground) the encoder shielded cable to the enclosure (as close as the inverter) with a P clip or U clip made of metal.



Earthing (grounding) example using a P clip



### NOTE

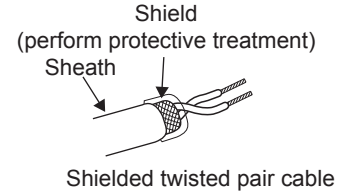
- For details of the optional encoder dedicated cable (FR-JCBL/FR-V7CBL), refer to [page 19](#).
- FR-V7CBL is provided with a P clip for earthing (grounding) shielded cable.



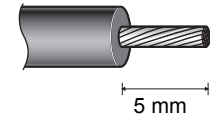
(2) Wire the shielded twisted pair cable after stripping its sheath to make its cables loose. Also, protect the shielded cable of the shielded twisted pair cable to ensure that it will not make contact with the conductive area.

Strip off the sheath for the below length. If the length of the sheath peeled is too long, a short circuit may occur with neighboring wires. If the length is too short, wires might come off.

Wire the stripped cable after twisting it to prevent it from becoming loose. In addition, do not solder it.

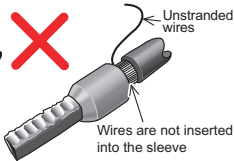
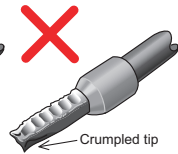
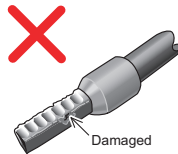
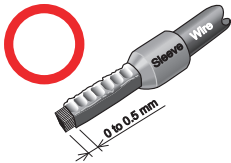


Cable stripping length



Use a ferrule terminal as necessary.

When using the ferrule terminal, use care so that the twisted wires do not come



**NOTE**

Blade terminals commercially available (as of February 2015. The product may be changed without notice.)

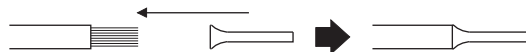
- Phoenix Contact Co., Ltd.

Terminal screw size	Cable gauge (mm <sup>2</sup> )	Ferrule terminal model		Crimping tool name
		With insulation sleeve	Without insulation sleeve	
M2	0.3, 0.5	AI 0,5-6WH	A 0,5-6	CRIMPFOX 6

- NICHIFU Co.,Ltd.

Terminal screw size	Cable gauge (mm <sup>2</sup> )	Blade terminal model	Insulation cap product number	Crimping tool product number
M2	0.3 to 0.75	BT 0.75-7	VC 0.75	NH 69

When using a blade terminal (without insulation sleeve), take caution that the twisted wires do not come out.

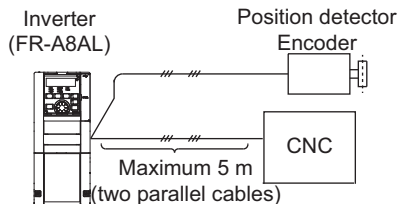


(3) Loosen the terminal screw and insert the cable into the terminal.

Screw size	Tightening torque	Cable size	Screwdriver
M2	0.22 N·m to 0.25 N·m	0.3 mm <sup>2</sup> to 0.75 mm <sup>2</sup>	Small ⊖ flat-blade screwdriver (Tip thickness: 0.4 mm/tip width: 2.5 mm)

### NOTE

- Undertightening can cause cable disconnection or malfunction. Overtightening can cause a short circuit or malfunction due to damage to the screw or unit.
- When wiring cables to the inverter's RS-485 terminals while a plug-in option is mounted, take caution not to let the cables touch the circuit board of the option or of the inverter. Otherwise, electromagnetic noises may cause malfunctions.
- When one position detector is shared between FR-A8AL and CNC (computerized numerical controller), its output signal should be connected as shown below. In this case, the wiring length between FR-A8AL and CNC should be as short as possible, within 5 m.

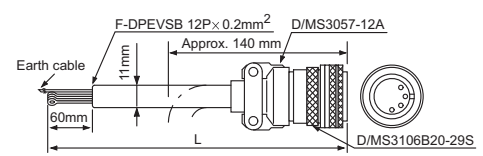
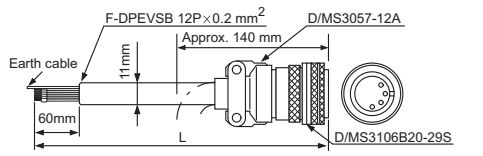
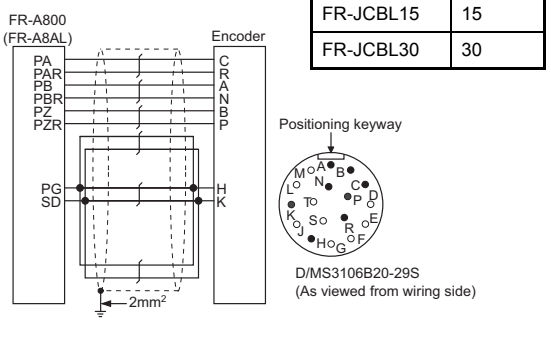
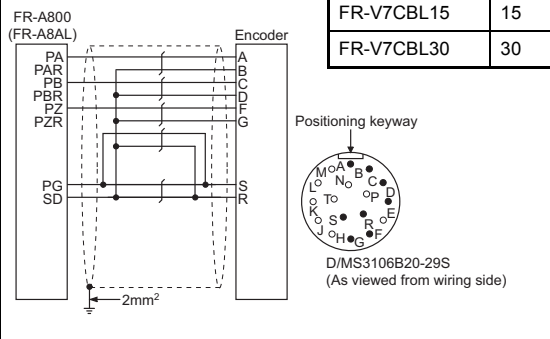


### CAUTION

- Do not use empty terminals as junction terminals because they are used in the option unit. If they are used as the junction terminals, the option unit may be damaged.
- After wiring, wire offcuts must not be left in the inverter. They may cause a fault, failure or malfunction.

## 2.5 Encoder cables dedicated to Mitsubishi motors

Use dedicated encoder cables to connect with Mitsubishi encoder-equipped motors.

FR-JCBL	FR-V7CBL																
<p>For SF-JR/HR/JRCA/HRCA (with encoder)</p> 	<p>For SF-V5RU and SF-THY</p> 																
<table border="1" style="margin-left: auto; margin-right: auto; border-collapse: collapse; text-align: center;"> <thead> <tr style="background-color: #00FFFF;"> <th>Type</th> <th>Length L (m)</th> </tr> </thead> <tbody> <tr> <td>FR-JCBL5</td> <td>5</td> </tr> <tr> <td>FR-JCBL15</td> <td>15</td> </tr> <tr> <td>FR-JCBL30</td> <td>30</td> </tr> </tbody> </table>	Type	Length L (m)	FR-JCBL5	5	FR-JCBL15	15	FR-JCBL30	30	<p>• A P clip for earthing (grounding) a shielded cable is provided.</p> <table border="1" style="margin-left: auto; margin-right: auto; border-collapse: collapse; text-align: center;"> <thead> <tr style="background-color: #00FFFF;"> <th>Type</th> <th>Length L (m)</th> </tr> </thead> <tbody> <tr> <td>FR-V7CBL5</td> <td>5</td> </tr> <tr> <td>FR-V7CBL15</td> <td>15</td> </tr> <tr> <td>FR-V7CBL30</td> <td>30</td> </tr> </tbody> </table>	Type	Length L (m)	FR-V7CBL5	5	FR-V7CBL15	15	FR-V7CBL30	30
Type	Length L (m)																
FR-JCBL5	5																
FR-JCBL15	15																
FR-JCBL30	30																
Type	Length L (m)																
FR-V7CBL5	5																
FR-V7CBL15	15																
FR-V7CBL30	30																
 <p style="text-align: center;">D/MS3106B20-29S (As viewed from wiring side)</p>	 <p style="text-align: center;">D/MS3106B20-29S (As viewed from wiring side)</p>																

\*1 As the terminal block of the FR-A8AL is an insertion type, earth (ground) cables need to be modified. (Refer to [page 16](#).)

◆ **Connection terminal compatibility table**

Motor		SF-JR/HR/JRCA/HRCA (with encoder)	SF-V5RU, SF-THY
Encoder cable		FR-JCBL	FR-V7CBL
FR-A8AL terminal	PA	PA	PA
	PAR	PAR	Keep this open.
	PB	PB	PB
	PBR	PBR	Keep this open.
	PZ	PZ	PZ
	PZR	PZR	Keep this open.
	PG	5E	PG
	SD	AG2	SD

## 2.6 Terminals

Function	Terminal symbol	Terminal (signal) name	Specification	Description	
Position control function	PGP PP	Forward rotation pulse train	Open collector/ differential line driver	Forward rotation pulse train input terminal. Input pulse train from the pulse generating unit.	For open collector, connect terminal VDD and OPC, then input pulses across terminal PP-SD and NP-SD. For differential line driver, open terminal OPC, then input pulse across terminal PP-PGP and NP-PGN.
	PGN NP	Reverse rotation pulse train		Reverse rotation pulse train input terminal. Input pulse train from the pulse generating unit.	
	CR	Clear	—	Shorting terminal CR-SD clears counter at the falling edge.	
	OPC	Open collector power input	24VDC	When inputting pulse by open collector method, connect this terminal to terminal VDD (24V power supply)	
	SD	Contact input common	—	Contact input common terminal. Do not earth (ground).	
	VDD	Driver power supply	24VDC	Driver power supply terminal for interface.	
	RDY	Preparation ready signal	—	When servo ON and ready to drive, the signal is output.	
	FPZ2	Encoder Z-phase output	Open collector output permissible load 24VDC, max. 50mA	Outputs one pulse per motor revolution.	

Function	Terminal symbol	Terminal (signal) name	Specification	Description	
Encoder pulse input	PA	Encoder A-phase signal input	Differential line driver/ complementary	A-, B- and Z-phase signals are input from the encoder.	
	PAR	Encoder A-phase inverse signal input			
	PB	Encoder B-phase signal input			
	PBR	Encoder B-phase inverse signal input			
	PZ	Encoder Z-phase signal input			
	PZR	Encoder Z-phase inverse signal input			
	PG	Power supply (positive side) input	—	Input power for the encoder power supply. Connect the external power supply (15 V) and the encoder power cable. When the encoder output is the differential line driver type, only 5 V can be input. Make sure the voltage of the external power supply the same as the encoder output voltage. (Check the encoder specification.) If using the 24 V power supply of the FR-A8AL, 24 V power can be supplied from terminal PG24.	
	SD	Encoder pulse dividing output common		—	Common terminal for the encoder pulse dividing output terminal.
		24 V encoder power supply common			Common terminal for the 24 V encoder power supply terminal (terminal PG24).
		12 V encoder power supply common			Common terminal for the 12 V encoder power supply terminal (terminal PGV).
5 V encoder power supply common		Common terminal for the 5 V encoder power supply terminal (terminal PGV).			


**NOTE**

- When the input power supply voltage to the encoder and its output voltage differ, the signal loss detection (E.ECT) may occur.

Function	Terminal symbol	Terminal (signal) name	Specification	Description	
Encoder pulse division output	Open collector	FPA2	Encoder A-phase signal output	Open collector output  Permissible load 24VDC max. 50mA	Outputs the A-phase, B-phase and Z-phase (origin and mark pulse) signals from the encoder. The A-phase and B-phase signals can be divided by the ratio (1/n) and output. n=1 to 32767 (integer). Set using <b>Pr.413 Encoder pulse division ratio</b> . Common terminal is terminal SD.
		FPB2	Encoder B-phase signal output		
		FPZ2	Encoder Z-phase signal output		
	Differential line driver	FPA	Encoder differential A-phase signal output	Differential line driver output  Permissible load 0.1A	Outputs the A-phase, B-phase and Z-phase (origin and mark pulse) signals from the encoder. The A-phase and B-phase signals can be divided by the ratio (1/n) and output. n=1 to 32767 (integer). Set using <b>Pr.413 Encoder pulse division ratio</b> .
		FPAR	Encoder differential A-phase inverse signal output		
		FPB	Encoder differential B-phase signal output		
		FPBR	Encoder differential B-phase inverse signal output		
		FPZ	Encoder differential Z-phase signal output		
		FPZR	Encoder differential Z-phase inverse signal output		



Function	Terminal symbol	Terminal (signal) name	Specification	Description
Power supply output for encoder	PG24	Encoder power supply terminal (positive side)	24 to 26.4 VDC 80 mA	Used for the 24 VDC power supply for an encoder. If used, connect this terminal to terminal PG, and this will supply power from the terminal PG to the encoder.
	PGV	Encoder power supply terminal (positive side)	10.8 to 13.2 VDC 120 mA	Used for the power supply for an encoder. When the encoder power supply selection switch (SW2-4) is set to the ON position, the terminal can be used as the 12 V power supply for the encoder. If used, connect this terminal to terminal PG, and this will supply power through terminal PG to the encoder.
			4.5 to 5.5 VDC 300 mA	Used for the power supply for an encoder. When the encoder power supply selection switch (SW2-4) is set to the OFF position (initial status), the terminal can be used as the 5 V power supply for the encoder. If used, connect this terminal to terminal PG, and this will supply power through terminal PG to the encoder.

### NOTE

- Do not use the encoder power supply output terminals (PG24 and PGV) except for supplying power to the encoder.
- The 5 V or 12 V output voltage can be selected by setting the encoder power supply selection switch (SW2-4). Always use the output voltage setting that meets the encoder voltage specifications. Applying an incorrect voltage may damage the encoder.

# 3 ENCODER SPECIFICATIONS AND PARAMETER SETTINGS

## 3.1 Encoder

### ◆ Position detection (pulse encoder)

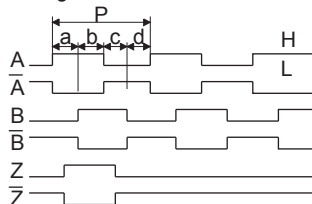
Output pulse specifications

Differential line driver

A/ $\bar{A}$  signal 1000 P/R to 4096 P/R

B/ $\bar{B}$  signal 1000 P/R to 4096 P/R

Z/ $\bar{Z}$  signal 1 P/R

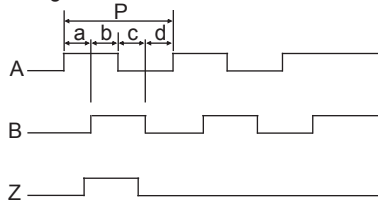


Complementary

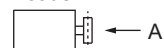
A signal 1000 P/R to 4096 P/R

B signal 1000 P/R to 4096 P/R

Z signal 1 P/R



Position detector  
Encoder



- When rotation is clockwise as viewed from the shaft end (A) of the encoder.
- a, b, c, d should be  $(1/4 \pm 1/8)P$

### NOTE

- When orientation control, encoder feedback control, vector control are used together, the encoder is shared between these controls.  
Use an encoder which has a pulse count of 1000 to 4096 ppr (pulse per revolution).
- The encoder should be coupled with the motor shaft or the spindle oriented with a speed ratio of 1 to 1 without any mechanical looseness.
- To ensure correct operation, the encoder must be set in the proper rotation direction and the A and B phases connected correctly.

## ◆ Power supply

Choose a power supply for encoder according to the encoder used (15 V etc.). When the encoder output is the differential line driver type, only 5 V can be input. Make sure the voltage of the external power supply the same as the encoder output voltage. (Check the encoder specification.) Use terminal PG24 for the 24 V encoder's power supply. Use terminal PGV for the 5 V/12 V encoder's power supply.

When an encoder is used under orientation control, encoder feedback control, and vector control, the power supply is shared between the inverter and encoder.

- Specifications of the encoders equipped in the motors with encoders and the vector-control dedicated motors

Item	Encoder for SF-JR/HR/JRCA/HRCA	Encoder for SF-V5RU, SF-THY
Resolution	1024 pulses/rev	2048 pulses/rev
Power supply voltage	5 VDC±10%	12 VDC±10%
Current consumption	150 mA	
Output signal form	A, B phases (90° phase shift) Z phase: 1 pulse/rev	
Output circuit	Differential line driver 74LS113 equivalent	Complementary
Output voltage	H level: 2.4 V or more L level: 0.5 V or less	H level: "Power supply for encoder-3 V" or more L level: 3 V or less





### NOTE

- When the input power supply voltage to the encoder and its output voltage differ, the protective function (E.ECT) may be activated.

## 3.2 Parameter setting

### 3.2.1 Parameter for encoder

Parameter Number	Pr. group	Name	Initial Value	Setting Range	Description	
359	C141	Encoder rotation direction	1	0	Set when using a motor for which forward rotation (encoder) is clockwise (CW) viewed from the shaft	Set for the operation at 120 Hz or less.
				100		Set for the operation at a frequency higher than 120 Hz.
				1	Set when using a motor for which forward rotation (encoder) is counterclockwise (CCW) viewed from the shaft	Set for the operation at 120 Hz or less.
				101		Set for the operation at a frequency higher than 120 Hz.
369	C140	Number of encoder pulses	1024	0 to 4096	Set the number of encoder pulses output. Set the number of pulses before it is multiplied by 4.	
862	C242	Encoder option selection	0	0	First motor: FR-A8AL, Second motor: FR-A8TP	
				1	First motor: FR-A8TP, Second motor: FR-A8AL	

#### NOTE

- If operating at a frequency higher than 120 Hz with **Pr.359** = "0 or 1", the motor rotation will be unstable.

- Using the FR-A8TP together with the plug-in option FR-A8AL enables vector control or machine end orientation control by switching between two encoder-equipped motors. Use **Pr.862** to set the combination of the motors (first/second) and the options (FR-A8TP/FR-A8AL).

Pr.862 Encoder option selection	Pr.393 Orientation selection	RT=OFF (First motor)	RT=ON (Second motor)*1	Machine end orientation control
0 (initial value)	0, 1, 2	FR-A8AL	FR-A8TP	Disabled
	10, 11, 12			
1	0, 1, 2	FR-A8TP	FR-A8AL	
	10, 11, 12	Motor end: FR-A8TP Machine end: FR-A8AL	—	

\*1 When **Pr.450 Second applied motor** = "9999", the first motor is selected even if the RT signal turns ON.

- Use the following parameters for the encoder input setting. The encoder input setting can be made regardless of the **Pr.862** setting and first/second motor setting.

Parameter name	Parameter for control terminal option (FR-A8TP)	Parameter for plug-in option (FR-A8AL)
Encoder rotation direction	852	359
Number of encoder pulses	851	369
Encoder signal loss detection enable/disable selection	855	376

- To input the RT signal, set "3" in any of **Pr.178 to Pr.182, Pr.185, or Pr.189 (input terminal function selection)** to assign the function to a terminal.

### 3.2.2 Parameter settings for the motor under vector control

Motor name		Pr.359 Encoder rotation direction	Pr.369 Number of encoder pulses
Mitsubishi standard motor	SF-JR	1 (Initial value)	1024 (Initial value)
	SF-JR 4P 1.5 kW or less	1 (Initial value)	1024 (Initial value)
	SF-HR	1 (Initial value)	1024 (Initial value)
	Others	*1	*1
Mitsubishi constant-torque motor	SF-JRCA 4P	1 (Initial value)	1024 (Initial value)
	SF-HRCA 4P	1 (Initial value)	1024 (Initial value)
	Others	*1	*1
Mitsubishi vector control dedicated motor	SF-V5RU	1 (Initial value)	2048
	SF-THY	1 (Initial value)	2048
Other manufacturer's standard motor	—	*1	*1
Other manufacturer's constant-torque motor	—	*1	*1

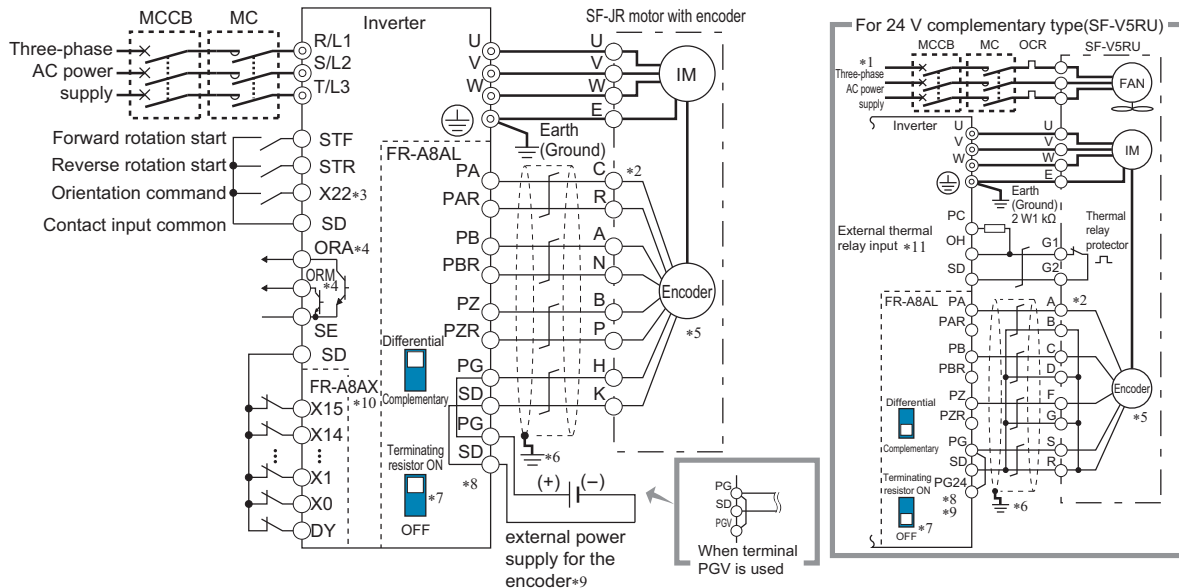
\*1 Set this parameter according to the motor (encoder) used.

# 4 ORIENTATION CONTROL

This function is used with a position detector (encoder) installed to the spindle of a machine tool, etc. to allow a rotary shaft to be stopped at the specified position (oriented).

For the details of the parameters used for orientation control, refer to the Instruction Manual (Detailed) of the inverter.

## 4.1 Wiring example



- \*1 For the fan of the 7.5 kW or less dedicated motor, the power supply is single phase (200 V/50 Hz, 200 to 230 V/ 60 Hz).
- \*2 The pin number differs according to the encoder used.
- \*3 Use **Pr. 178 to Pr. 189 (input terminal function selection)** to assign the function to any of terminal.  
Refer to the Instruction Manual (Detailed) for details of **Pr. 178 to Pr. 189 (input terminal function selection)**.
- \*4 Use **Pr. 190 to Pr. 196 (output terminal function selection)** to assign the function to any of terminal.  
Refer to the Instruction Manual (Detailed) for details of **Pr. 190 to Pr. 196 (output terminal function selection)**.
- \*5 Connect the encoder so that there is no looseness between the motor and motor shaft. Speed ratio should be 1:1.
- \*6 Earth (Ground) the shielded cable of the encoder cable to the enclosure with a P clip, etc. (Refer to [page 15](#).)
- \*7 For the differential line driver, set the terminating resistor selection switch to on position (initial status) to use. (Refer to [page 13](#).)  
Note that the terminating resistor switch should be set to off position when sharing the same encoder with other unit (CNC, etc.) and a terminating resistor is connected to other unit. For the complementary, set the switch to off position.
- \*8 For terminal compatibility of the FR-JCBL, FR-V7CBL and FR-A8AP, refer to [page 20](#).
- \*9 A separate external power supply of 15 V is necessary according to the encoder power specification. When the encoder output is the differential line driver type, only 5 V can be input. If using the 24 V power supply of the FR-A8AL, the power can be supplied from terminal PG24. If using the 5 V/12 V power supply of the FR-A8AL, the power can be supplied from terminal PGV. Do not use the external power supply simultaneously with the 5 V/12 V power supply or the 24 V power supply.  
Make the voltage of the external power supply the same as the encoder output voltage, and connect the external power supply between terminals PG and SD.  
When performing encoder feedback control and vector control together, an encoder and power can be shared.
- \*10 When a stop position command is input from outside, a plug-in option FR-A8AX is necessary. Refer to the Instruction Manual (Detailed) for details of external stop position command.
- \*11 To use a terminal as the terminal OH, assign the OH (external thermal O/L relay input) signal to an input terminal. (Set "7" in any of **Pr.178 to Pr.189**. For details, refer to the Instruction Manual (Detailed) of the inverter.)



## 4.2 Terminals

### ◆ Option FR-A8AX terminal

Terminal symbol	Terminal name	Description
X0 to X15	Digital signal input terminal	Input the digital signal at the relay contact or open collector terminal. Using <b>Pr. 360</b> , speed or position command is selected as the command signal entered.
DY	Data read timing input signal terminal	Used when a digital signal read timing signal is necessary. Data is read only during the DY signal is on. By switching the DY signal off, the X0 to X15 data before signal-off is retained.

### ◆ Inverter terminal

Terminal (signal)		Terminal (signal) name	Application explanation
Input	X22	Orientation command	Used to enter an orientation signal for orientation. For the terminal used for X22 signal input, set "22" in any of <b>Pr. 178 to Pr. 189</b> to assign the function. *1
Output	ORA	Orientation complete	Switched LOW if the orientation has stopped within the in-position zone while the start and X22 signals are input. For the terminal used for the ORA signal output, assign the function by setting "27 (positive logic) or 127 (negative logic)" in any of <b>Pr. 190 to Pr. 196</b> . *1
	ORM	Orientation fault	Switched LOW if the orientation has not completed within the in-position zone while the start and X22 signals are input. For the terminal used for the ORA signal output, assign the function by setting "28 (positive logic) or 128 (negative logic)" in any of <b>Pr. 190 to Pr. 196</b> . *1

\*1 Refer to the Instruction Manual (Detailed) for details of **Pr.178 to Pr.189 (input terminal function selection)** and **Pr.190 to Pr.196 (output terminal function selection)**.

## 4.3 Machine end simple orientation control

Pr.	Pr. group	Name	Initial value	Setting range	Description
369	C140	Number of encoder pulses	1024	0 to 4096	Set the number of motor end encoder pulses converted from the number of machine end encoder pulses.
829	A546	Number of machine end encoder pulses	9999	0 to 4096	Set the number of pulses of the encoder connected to the machine end. Set the number of pulses before multiplied by four.
				9999	Machine end orientation cannot be performed.

To enable encoder feedback control / vector control and the machine end orientation control at the same time using the machine end encoder, set the number of machine end encoder pulses in **Pr.829 Number of machine end encoder pulses**.

Pr.829 setting	Pr.862 setting	Description
9999	—	Machine end simple orientation control invalid
Other than 9999 (A number of machine end encoder pulses (before multiplied by four) is set.)	0	The machine end encoder enables encoder feedback control / vector control and the machine end orientation control at the same time.
	1	Machine end simple orientation control invalid

### • Setting example

When the number of machine end encoder pulses is 4000 pulses and the gear ratio of the motor end and the machine end is 4:1 (for every four revolutions of the motor, the machine makes one revolution)

$$\text{Number of encoder pulses equivalent to the number of motor end pulses} = 4000 \times 1/4 = 1000$$

Therefore, set **Pr.369** = "1000" and **Pr.829** = "4000" (number of machine end encoder pulses).



- Refer to the Instruction Manual of the Inverter for details on the encoder feedback control, vector control and orientation control.

## 4.4 Specifications

<b>Repeated positioning accuracy</b>	$\pm 1.5^\circ$ Depends on the load torque, moment of inertia of the load or orientation, creep speed, position loop switching position, etc.
<b>Permissible speed</b>	Encoder-mounted shaft speed (6000 r/min with 1024-pulse encoder). The drive shaft and encoder-mounted shaft must be coupled directly or via a belt without any slip. Gear changing shafts cannot be applied.
<b>Functions</b>	Orientation, creep speed setting, stop position command selection, DC injection brake start position setting, creep speed and position loop switch position setting, position shift, orientation in-position, position pulse monitor, etc.
<b>Holding force after positioning</b>	Under V/F control, Advanced magnetic flux vector control...without servo lock function Under vector control...with servo lock function
<b>Input signal (contact input)</b>	Orientation command, forward and reverse rotation commands, stop position command (open collector signal input (complementary) is enabled) Binary signal of maximum 16 bits (when used with the FR-A8AX)
<b>Output signal (open collector output)</b>	Orientation completion signal, orientation fault signal

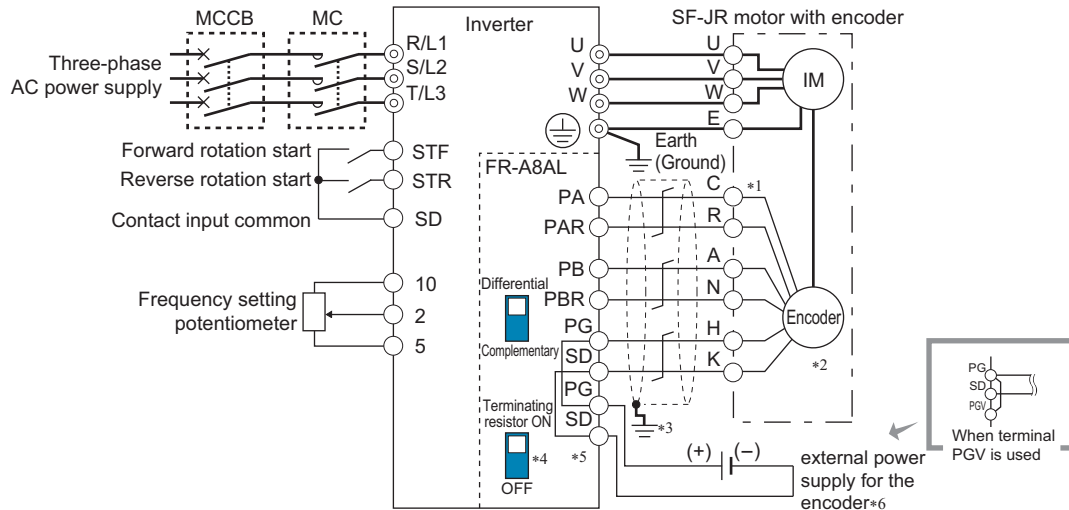
# 5 ENCODER FEEDBACK CONTROL

Mount FR-A8AL to an FR-A800 series inverter to perform encoder feedback control under V/F control or Advanced magnetic flux vector control.

This controls the inverter output frequency so that the motor speed is constant to the load variation by detecting the motor speed with the speed detector (encoder) to feed back to the inverter.

For the details of the parameters used for encoder feedback control, refer to the Instruction Manual (Detailed) of the inverter.

## 5.1 Wiring examples



- \*1 The pin number differs according to the encoder used.
- \*2 Connect the encoder so that there is no looseness between the motor and motor shaft. Speed ratio should be 1:1.
- \*3 Earth (Ground) the shielded cable of the encoder cable to the enclosure with a P clip, etc. (Refer to [page 15](#).)
- \*4 For the differential line driver, set the terminating resistor selection switch to on position (initial status) to use. (Refer to [page 13](#)) Note that the terminating resistor switch should be set to off position when sharing the same encoder with other unit (CNC, etc) and a terminating resistor is connected to other unit.  
For the complementary, set the switch to off position.
- \*5 For terminal compatibility of the FR-JCBL, FR-V7CBL and FR-A8AP, refer to [page 20](#).
- \*6 A separate external power supply of 15 V is necessary according to the encoder power specification. When the encoder output is the differential line driver type, only 5 V can be input. If using the 24 V power supply of the FR-A8AL, the power can be supplied from terminal PG24. If using the 5 V/12 V power supply of the FR-A8AL, the power can be supplied from terminal PGV. Do not use the external power supply simultaneously with the 5 V/12 V power supply or the 24 V power supply.  
Make the voltage of the external power supply the same as the encoder output voltage, and connect the external power supply between terminals PG and SD.  
To perform orientation control together, an encoder and power supply can be shared.

## 5.2 Specifications

<b>Speed variation ratio</b>	±0.1% (100% means 3600 r/min)
<b>Function</b>	<ul style="list-style-type: none"> <li>• Setting of speed feedback range</li> <li>• Setting of feedback gain</li> <li>• Setting of encoder rotation direction</li> </ul>
<b>Maximum speed</b>	V/F control: 590 Hz, Advanced magnetic flux vector control: 400 Hz (102400 pulse/s or less encoder pulses)

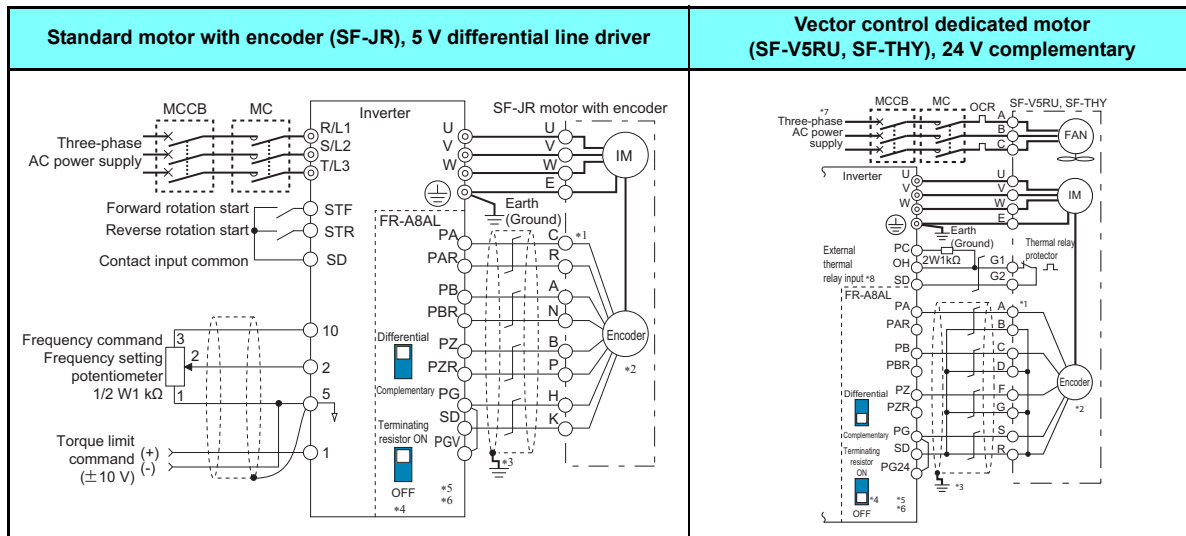
# 6 VECTOR CONTROL

When FR-A8AL is mounted on the FR-A800 series, full-scale vector control operation can be performed using a motor with encoder.

Speed control, torque control and position control by vector control can be performed. (Refer to the Instruction Manual (Detailed) for details.)

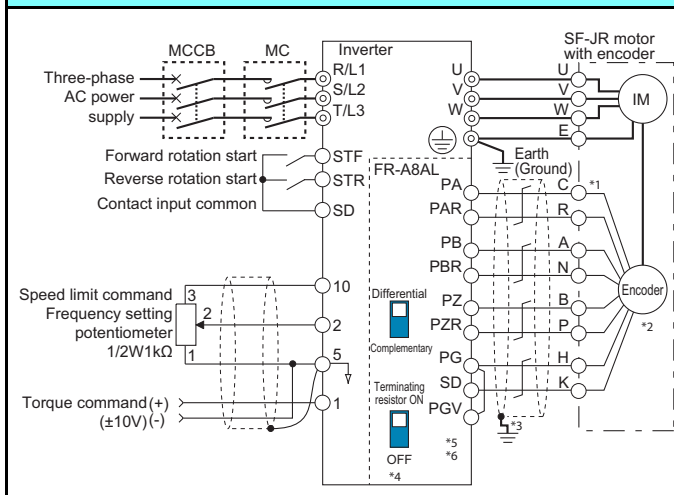
## 6.1 Wiring examples

### ◆ Speed control

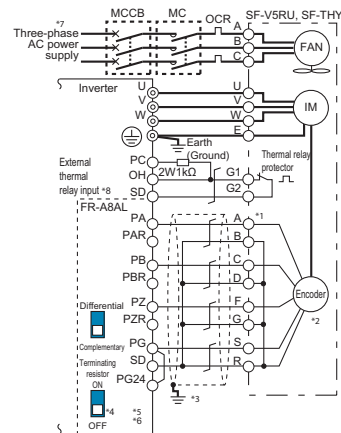


## ◆ Torque control

### Standard motor with encoder (SF-JR), 5 V differential line driver

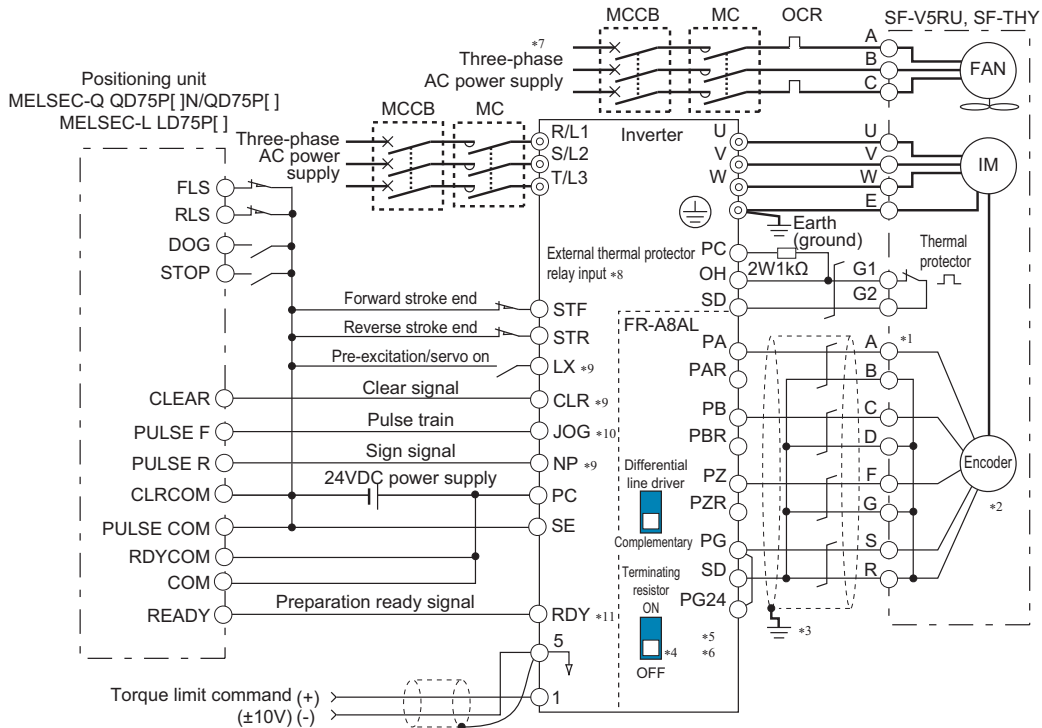


### Vector control dedicated motor (SF-V5RU, SF-THY), 24 V complementary



◆ **Position control**

**Vector control dedicated motor (SF-V5RU, SF-THY), 24 V complementary**





- \*1 The pin number differs according to the encoder used.  
Speed, control, torque control, and position control by pulse train input are available with or without the Z-phase being connected.
- \*2 Connect the encoder so that there is no looseness between the motor and motor shaft. Speed ratio must be 1:1.
- \*3 Earth (ground) the shield of the encoder cable to the enclosure using a tool such as a P-clip. (Refer to [page 15](#).)
- \*4 For the complementary, set the terminating resistor selection switch to OFF position. (Refer to [page 13](#).)
- \*5 A separate external power supply of 15 V is necessary according to the encoder power specification. When the encoder output is the differential line driver type, only 5 V can be input. If using the 24 V power supply of the FR-A8AL, the power can be supplied from terminal PG24. If using the 5 V/12 V power supply of the FR-A8AL, the power can be supplied from terminal PGV. Do not use the external power supply simultaneously with the 5 V/12 V power supply or the 24 V power supply.  
Make the voltage of the external power supply the same as the encoder output voltage, and connect the external power supply between terminals PG and SD.
- \*6 For terminal compatibility of the FR-JCBL, FR-V7CBL, and FR-A8AP, refer to [page 20](#).
- \*7 For the fan of the 7.5 kW or lower dedicated motor, the power supply is single phase. (200 V/50 Hz, 200 to 230 V/60 Hz)
- \*8 To use a terminal as the terminal OH, assign the OH (external thermal O/L relay input) signal to an input terminal. (Set "7" in any of **Pr.178 to Pr.189**. For details, refer to the Instruction Manual (Detailed) of the inverter.)
- \*9 Assign the function using **Pr.178 to Pr.184**, **Pr.187 to Pr.189** (input terminal function selection).
- \*10 When position control is selected, terminal JOG function is invalid and simple position pulse train input terminal becomes valid.
- \*11 Assign the function using **Pr.190 to Pr.194** (output terminal function selection).

## 6.2 Pulse train torque command

### 6.2.1 Parameter list

Pr.	Pr. group	Name	Setting range	Initial value
428	B009	Command pulse selection	0 to 5	0
432	D120	Pulse train torque command bias	0 to 400 %	0 %
433	D121	Pulse train torque command gain	0 to 400 %	150 %
800	G200	Control method selection	0 to 6, 9 to 14, 20, 100 to 106, 109 to 114	20
804	D400	Torque command source selection	0 to 6	0

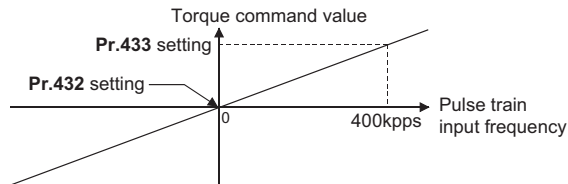
## 6.2.2 Pulse train torque command

### ◆ Pulse train torque command setting

When torque control is selected, setting "2" in **Pr. 804 Command pulse selection** enables torque command by pulse train input. Set the **Pr. 800** setting to "1, 2, or 5" to perform torque control. (When setting "2 or 5", torque control need to be selected by MC terminal switchover.) The inverter and torque command pulse train interface should be matched. (Refer to [page 37](#) for wiring.)

### ◆ Pulse train torque command calibration

Set bias (**Pr. 432**) and gain (**Pr. 433**) to the torque command. The relationship between input pulse and torque command value is shown on the right.



## 6.3 Specifications

Speed control	Speed control range	1:1500 (both driving/regeneration *1)
	Speed variation ratio	±0.01% (100% means 3000 r/min)
	Speed response	130 Hz
	Maximum speed	400 Hz (102400 pulse/s or less encoder pulses)
Torque control	Torque control range	1:50
	Absolute torque accuracy	±10% *2
	Repeated torque accuracy	±5% *2
Position control	Repeated positioning accuracy	±1.5° (at motor shaft end)
	Maximum input pulse frequency	100 kpps (Terminal JOG)
	Positioning feedback pulse	Number of encoder pulses per motor rotation ( <b>Pr.369</b> ) × 4
	Electronic gear setting	1/50 to 20
	In-position width	0 to 32767 pulses
	Error excess	0 to 400k pulses
Function	<ul style="list-style-type: none"> <li>• Setting of speed feedback range</li> <li>• Setting of feedback gain</li> <li>• Setting of encoder rotation direction</li> </ul>	

\*1 Regeneration unit (option) is necessary for regeneration

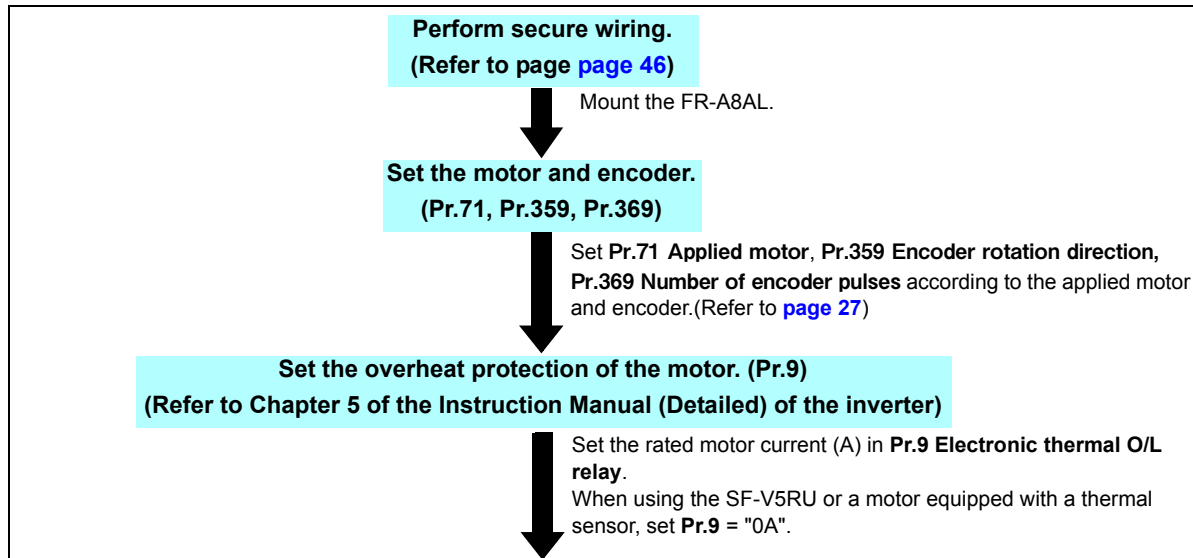
\*2 With online auto tuning (adaptive magnetic flux observer), dedicated motor, rated load

# 7 POSITION CONTROL FUNCTION

## 7.1 Position control

- In the position control, the speed command given to rotate the motor is calculated to eliminate the difference between command pulse (or parameter setting) and the number of feedback pulses from the encoder.
- This option enables position control by the programmable controller positioning module.

### ◆ Setting procedure



**Set the motor capacity and number of motor poles. (Pr.80, Pr.81)**  
**(Refer to Chapter 5 of the Instruction Manual (Detailed) of the inverter)**

Set the motor capacity (kW) in **Pr.80 Motor capacity**, and set the number of motor poles in **Pr.81 Number of motor poles**. (V/F control is performed when the setting is "9999" (initial value).)

**Set the motor capacity and number of motor poles. (Pr.83, Pr.84)**  
**(Refer to Chapter 5 of the Instruction Manual (Detailed) of the inverter)**

Set the rated motor voltage (V) in **Pr.83 Rated motor voltage**, and set the rated motor frequency (Hz) in **Pr.84 Rated motor frequency**.

**Select the control method. (Refer to page [page 51](#))**

Set **Pr.800** = "3" (position control), "4" (speed - position switching) or "5" (position - torque switching) to enable position control.

**Select the position command source. (Pr.419)**

Set **Pr.419**="1" that indicates the position command by the programmable controller positioning unit.

**Test run**

#### As required

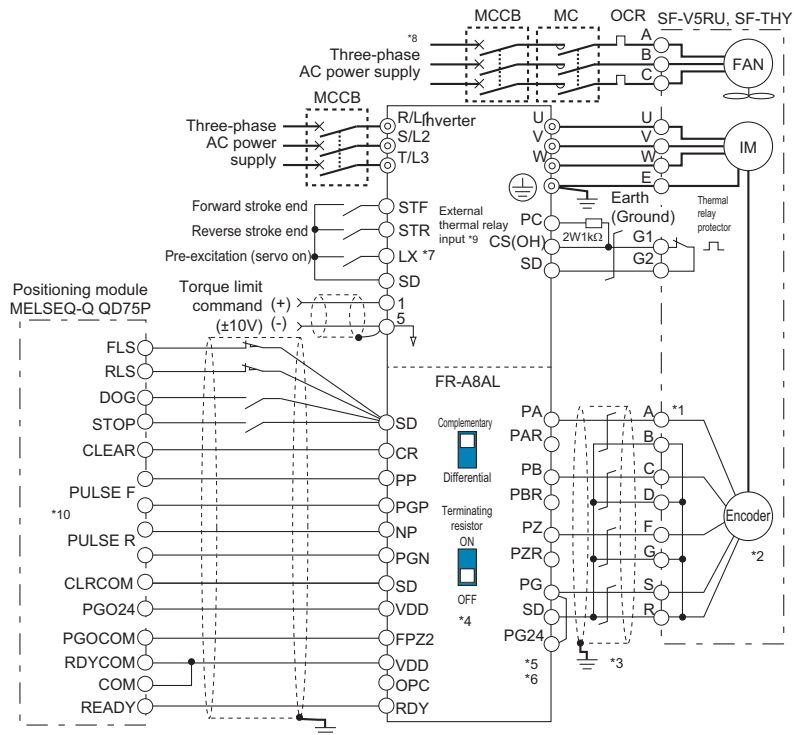
- Set the electronic gear. (Pr.420, Pr.421, Pr.424)
  - Set the position adjustment parameters. (Pr.426, Pr.427, Pr.1294 to Pr.1297)
  - Adjust the position control gain. (Pr.422, Pr.423, Pr.425, Pr.446, Pr.828, Pr.877, Pr.880)
- Refer to Chapter 5 of the Instruction Manual (Detailed) for details.)

#### NOTE

- The carrier frequency is limited during vector control. (Refer to Chapter 5 of the Instruction Manual (Detailed))

## 7.2 Wiring example

Connection with the MELSEC-Q series QD75P positioning module



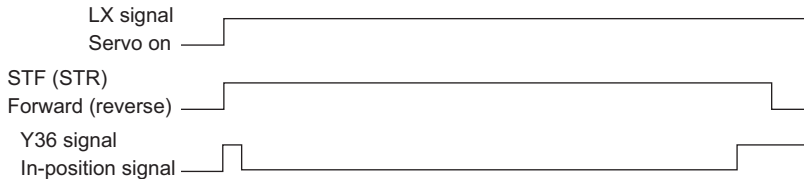
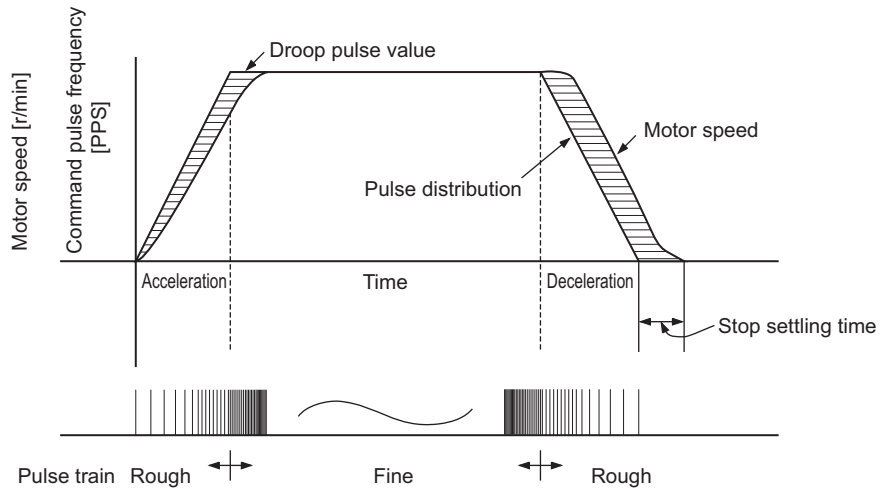
- \*1 The pin number differs according to the encoder used.  
Position control by pulse train input is properly performed even without connecting Z phase.
- \*2 The encoder should be coupled on the same axis with the motor shaft without any mechanical looseness.  
Speed ratio should be 1:1.
- \*3 Earth (Ground) the shielded cable of the encoder cable to the enclosure with a P clip, etc. (Refer to [page 15](#))
- \*4 For the complementary, set the terminating resistor selection switch to OFF position (initial status) to use. (Refer to [page 13](#))
- \*5 A separate external power supply of 15 V is necessary according to the encoder power specification. When the encoder output is the differential line driver type, only 5 V can be input. If using the 24 V power supply of the FR-A8AL, the power can be supplied from terminal PG24. If using the 5 V/12 V power supply of the FR-A8AL, the power can be supplied from terminal PGV. Do not use the external power supply simultaneously with the 5 V/12 V power supply or the 24 V power supply.  
Make the voltage of the external power supply the same as the encoder output voltage, and connect the external power supply between terminals PG and SD.
- \*6 Refer to [page 19](#) for terminal compatibility of the FR-JCBL, FR-V7CBL and FR-A8AL.
- \*7 Assign the function using **Pr.178 to Pr.184, Pr.187 to Pr.189 (input terminal function selection)**.
- \*8 For the fan of the 7.5kW or lower dedicated motor, the power supply is single phase (200V/50Hz, 200 to 230V/60Hz).
- \*9 To use a terminal as the terminal OH, assign the OH (external thermal O/L relay input) signal to an input terminal. (Set "7" in any of **Pr.178 to Pr.189**. For details, refer to the Instruction Manual (Detailed) of the inverter.)
- \*10 Pulse signal from the positioning unit can be output by either open collector or differential line driver. Note that connection is not the same. (The figure shows the connection in case of differential line driver. Refer to terminal description on [page 21](#) for connection.)

## 7.3 Operation

The speed command given to rotate the motor is calculated to eliminate the difference between the number of pulse train pulses and the number of pulses feed back from the motor end encoder.

- (1) When a pulse train (MELSEC-Q series positioning module QD75P, etc.) is input, pulses are accumulated in the deviation counter and these droop pulses act as position control pulses to give the speed command.
- (2) As soon as the motor starts running under the speed command of the inverter, the encoder generates feed back pulses and the droop of the deviation counter is counted down. The deviation counter maintains a given droop pulse value to keep the motor running.
- (3) When the command pulse input stops, the droop pulses of the deviation counter decreases, reducing the speed. The motor stops when there are no droop pulses.
- (4) When the number of droop pulses has fallen below the value set in **Pr. 426 In-position width**, it is regarded as completion of positioning and the in-position signal (Y36) turns on.





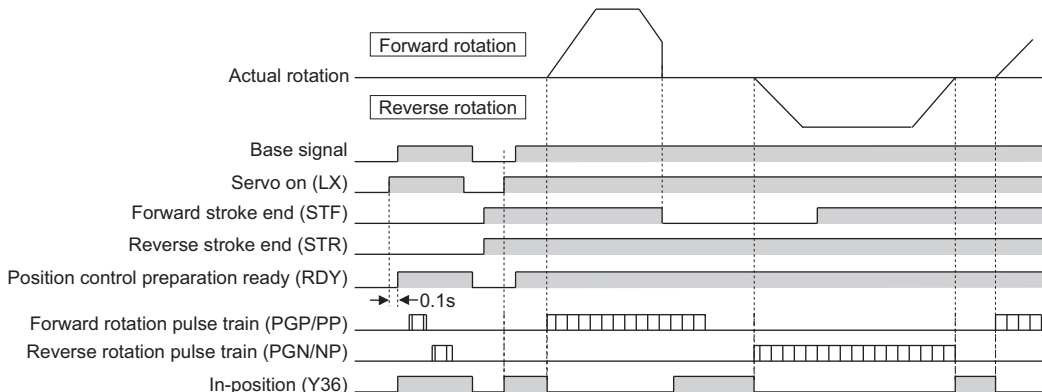
- The pulse train is rough during acceleration and fine at the maximum speed. During deceleration the pulse train is rough and at last there are no pulses. The motor stops shortly after the command pulses stop. This time lag is necessary for maintaining the stop accuracy and called stop settling time.

**NOTE**

- For the servo on signal (LX), set "23" in **Pr. 178 to Pr. 189 (input terminal function selection)** to assign the function.
- For the in-position signal (Y36), set "36" in **Pr. 190 to Pr. 196 (output terminal function selection)** to assign the function.

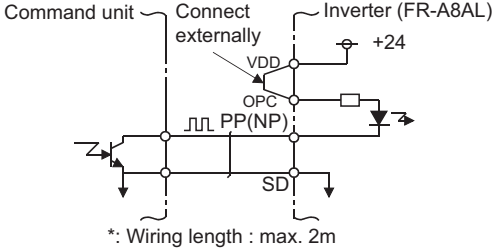
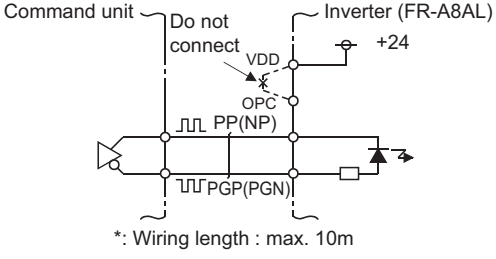
**◆ Operation by position command using pulse train**

Turning ON (short the terminal LX-SD) the servo on signal cancels the base circuit shut-off and operation ready signal is output after 0.1s has passed. (Assign the servo on (LX) signal using input function selection (**Pr. 178 to Pr. 189**.) When the terminal STF (forward stroke end signal) or terminal STR (reverse stroke end signal) and terminal SD are shorted, the motor runs in accordance with the command pulse. When the forward (reverse) stroke end signal opens, the motor does not run in that direction.



## 7.4 Interface of the positioning module and inverter

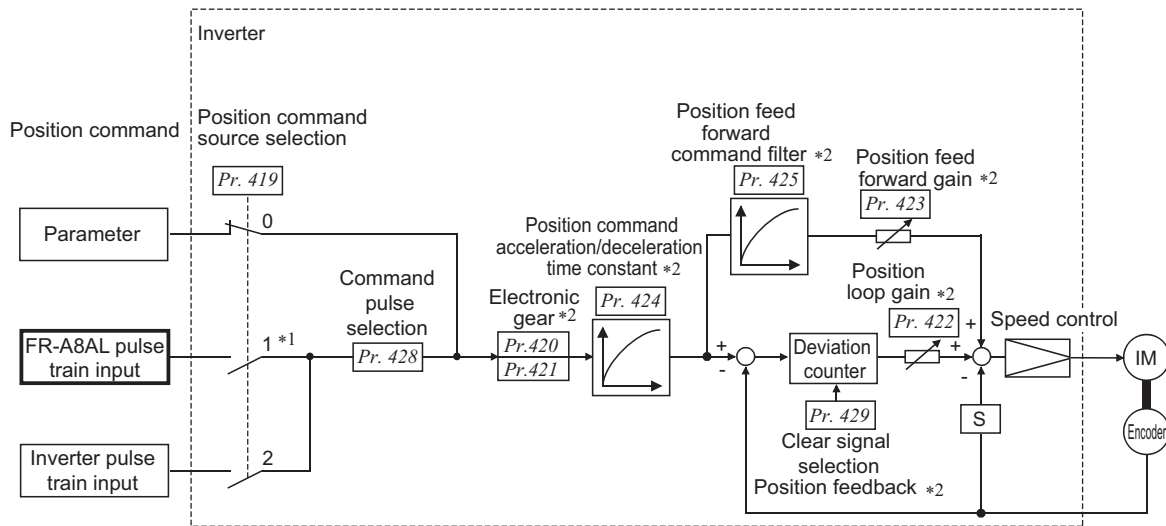
When running the inverter by each positioning module, interface of the positioning command pulse train need to be matched.

Output type	Hardware configuration	Input pulse frequency
Open collector	 <p>Command unit</p> <p>Connect externally</p> <p>Inverter (FR-A8AL)</p> <p>+24</p> <p>VDD</p> <p>OPC</p> <p>PP(NP)</p> <p>SD</p> <p>*: Wiring length : max. 2m</p>	Max. 200kpps
Differential line driver	 <p>Command unit</p> <p>Do not connect</p> <p>Inverter (FR-A8AL)</p> <p>+24</p> <p>VDD</p> <p>OPC</p> <p>PP(NP)</p> <p>PGP(PGN)</p> <p>*: Wiring length : max. 10m</p>	Max. 500kpps

## 7.5 Parameter setting and details

When performing position control with the FR-A8AL, set the following parameters.

### 7.5.1 Block diagram



\*1 When the FR-A8AL is not connected, "E.COP" is displayed.

\*2 For details, refer to the Instruction Manual (Detailed) of the inverter.)

### 7.5.2 Selection of control method (Pr. 800)

Set the **Pr. 800** setting to "3, 4, 5, 13, 14" to perform position control. Control circuit terminal function changes depending on parameter setting. (When the setting is "4, 5, or 14", select position control by switching MC signal.)

Terminal function changes by control mode switchover as below.

Classification	Terminal name	Description							
		Pr. 800 = "3"	Pr. 800 = "4"		Pr. 800 = "5"		Pr. 800 = "13"	Pr. 800 = "14"	
		Position control	Speed control MC signal: OFF	Position control MC signal: ON	Position control MC signal: OFF	Torque control MC signal: ON	Position control	Speed control MC signal: OFF	Position control MC signal: ON
Contact input signal	STF	Forward stroke end	Forward rotation command	Forward stroke end	Forward stroke end	Forward rotation command	Forward stroke end	Forward rotation command	Forward stroke end
	STR	Reverse stroke end	Reverse rotation command	Reverse stroke end	Reverse stroke end	Reverse rotation command	Reverse stroke end	Reverse rotation command	Reverse stroke end



#### NOTE

- Assign MC signal to **Pr. 180 to Pr. 188**. Set any of Pr. 180 to Pr. 188 to "26".
- For analog input terminal, function changes according to **Pr. 858 Terminal 4 function assignment, Pr. 868 Terminal 1 function assignment** setting. (Refer to the Instruction Manual(Detailed) of the Inverter for details.)

### 7.5.3 Position control

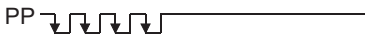
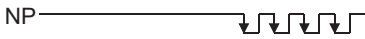
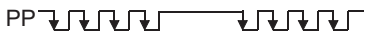
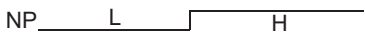
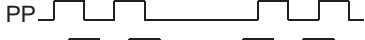
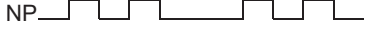
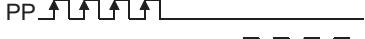
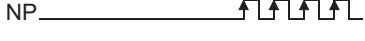
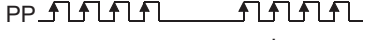



- Position command source selection (**Pr. 419**)

When using the FR-A8AL, set "1" in **Pr. 419**.

Pr. 419 setting	Description
0 (initial value)	Simple position control by point tables (position command by setting parameters).
1	Position command by pulse train input (when the FR-A8AL is mounted).
2	Conditional pulse train position command by inverter pulse train input.

- Pulse train form (Pr. 428)

Command pulse can be changed according to the positioning module as in the table below.

Command pulse train form		At forward rotation	At reverse rotation	Setting Pr. 428	Remarks
Negative logic	Forward rotation pulse train Reverse rotation pulse train	PP  NP 		0 (initial setting)	QD75D(CW/CWW mode) (Note) If (CW/CWW mode) and (PLS/SIGN mode) are misselected, the motor runs only in one direction.
	Pulse train + sign	PP  NP 		1	QD75D (PLS/SIGN mode)
	A phase pulse train B phase pulse train	PP  NP 		2	Counted after multiplying by four. Set the pulse train frequency multiplied by four to 500kpps or less with the differential driver type and to 200kpps or less with the open collector type.
Positive logic	Forward rotation pulse train Reverse rotation pulse train	PP  NP 		3	—
	Pulse train + sign	PP  NP 		4	—
	A phase pulse train B phase pulse train	PP  NP 		5	Counted after being multiplied by four. Set the pulse train frequency multiplied by four to 500kpps or less with the differential driver type and to 200kpps or less with the open collector type.

## 7.5.4 Troubleshooting

No.	Condition	Cause	Countermeasure
1	Motor does not rotate	The phase sequence of the motor or encoder wiring is wrong.	Check the wiring (Refer to <a href="#">page 46</a> )
		The control mode selection, <b>Pr.800</b> , setting is improper.	Check the Pr. 800 setting. (Refer to the Instruction Manual(Detailed) of the Inverter)
		The servo on signal or stroke end signal (STF, STR) is not input.	Check that the signals are input normally.
		Command pulse, position pulse sign (NP) are not correctly input.	<ul style="list-style-type: none"> <li>• Check that the command pulses are input normally. (Check the cumulative command pulse value in <b>Pr. 430</b>)</li> <li>• Check the command pulse form and command pulse selection, <b>Pr. 428</b>, setting.</li> </ul>
		The <b>Pr. 419 Position command source selection</b> , setting is not correct.	Check the position command source selection in <b>Pr. 419</b> .
2	Position shift occurs.	The command pulses are not input correctly.	<ul style="list-style-type: none"> <li>• Check the command pulse form and command pulse selection, <b>Pr. 428</b>, setting.</li> <li>• Check that the command pulses are input normally. (Check the cumulative command pulse value in <b>Pr. 430</b>)</li> </ul>
		The command is affected by noise. Or the encoder feedback signal is compounded with noise.	<ul style="list-style-type: none"> <li>• Decrease <b>Pr. 72 PWM frequency selection</b>.</li> <li>• Change the earthing (grounding) point of shielded wire. Or leave the cable suspended.</li> </ul>

No.	Condition	Cause	Countermeasure
3	Motor or machine hunts.	The position loop gain is high.	Decrease the <b>Pr. 422</b> value.
		The speed loop gain is high.	<ul style="list-style-type: none"> <li>• Perform easy gain tuning.</li> <li>• Decrease <b>Pr. 820</b> and increase Pr. 821.</li> </ul>
4	Machine operation is unstable	The acceleration/deceleration time setting has adverse effect.	Decrease <b>Pr. 7</b> and <b>Pr. 8</b> .

## 7.6 Specifications

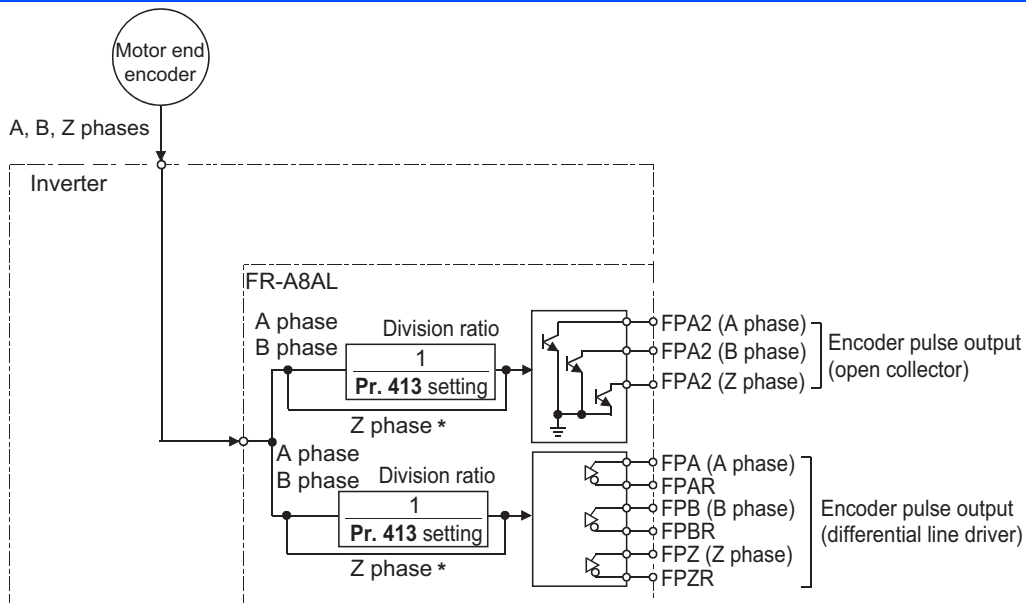
Repeated positioning accuracy	$\pm 1.5^\circ$ (motor shaft end) (changes according to load torque, moment of inertia J or backlash condition of the load)
Holding force after positioning	With servo lock
Power supply	24V power supply output for interface driver is provided
Maximum input pulse frequency	Differential line receiver: 500kpps, open collector: 200kpps
Positioning return pulse	Number of encoder pulses per motor rotation $\times$ 4 times
Electronic gear setting	1/50 to 20
In-position width setting	0 to 32767 pulses
Error excess	0 to 400K pulses



# 8 ENCODER PULSE DIVIDING OUTPUT

Pulse input of encoder connected to the inverter is divided and output from the FR-A8AL terminal.

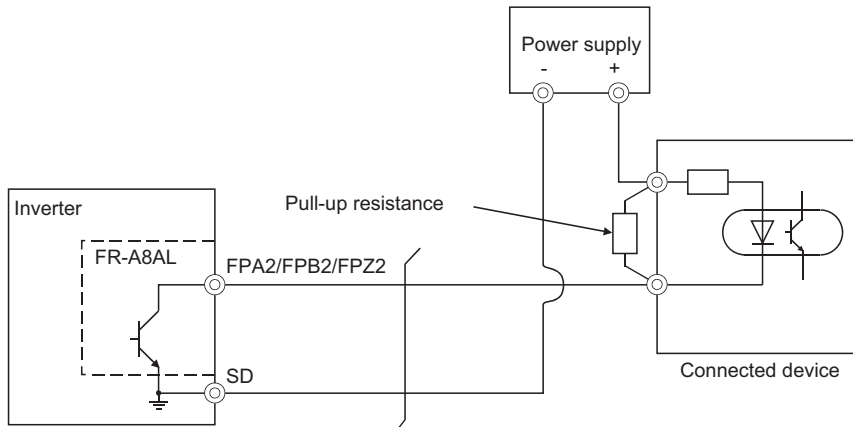
## 8.1 Wiring example



\* Z phase can not be divided.

**NOTE**

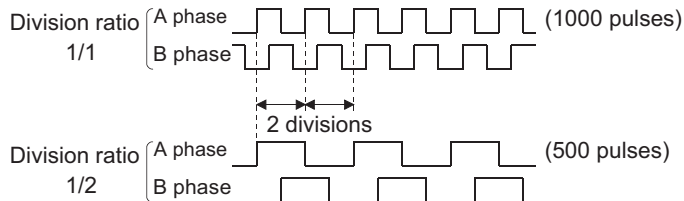
- For open collector output, the signal may become unstable if the input resistance of the connected device is large and the device may detect the signal incorrectly. In this case, adding a pull-up resistance as shown below will improve the phenomenon.
- Select a pull-up resistance in consideration of the input current of the connected device so that the open collector output current will not exceed the output permissible load current.



## 8.2 Parameter related to encoder pulse dividing output

Pr.	Pr. group	Name	Initial value	Setting range	Description
413	M601	Encoder pulse division ratio	1	1 to 32767	The encoder pulse signal at the motor end can be divided in division ratio set in <b>Pr. 413</b> and output. Use this parameter to make the response of the machine to be input slower, etc.

- Division waveform by division ratio  
Both ON-OFF width is division times. (50% duty)
  - Pulse waveform example at 1000 pulse input when **Pr. 413** = "2"



### NOTE

- Control of forward rotation/reverse rotation by phase difference between A phase and B phase.  
When A phase is 90° advanced as compared to B phase: forward rotation  
When A phase is 90° behind as compared to B phase: reverse rotation

# MEMO

## REVISIONS

\*The manual number is given on the bottom left of the back cover.

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