

SM-I/O PELV

Solutions Module

User Guide

Unidrive SP

Commander SK



Distributor for:

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Original Instructions

For the purposes of compliance with the EU Machinery Directive 2006/42/EC, the English version of this manual is the Original Instructions. Manuals in other languages are Translations of the Original Instructions.

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7 **Terminal specification41**

1 How to use this guide

1.1 Intended personnel

This guide is intended for personnel who have the necessary training and experience in system design, installation, commissioning and maintenance.

1.2 Information

This guide contains information covering the identification of the Solutions Module, terminal layout for installation, fitting of the Solutions Module to the drive, parameter details and diagnosis information. Additional to the aforementioned are the specifications of the Solutions Module.

2 Safety Information

2.1 Warnings, Cautions and Notes



A **Warning** contains information, which is essential for avoiding a safety hazard.



A **Caution** contains information, which is necessary for avoiding a risk of damage to the product or other equipment.



A **Note** contains information, which helps to ensure correct operation of the product.

2.2 Important safety information. Hazards. Competence of designers and installers

This guide applies to products which control electric motors either directly (drives) or indirectly (controllers, option modules and other auxiliary equipment and accessories). In all cases the hazards associated with powerful electrical drives are present, and all safety information relating to drives and associated equipment must be observed.

Specific warnings are given at the relevant places in this guide.

Drives and controllers are intended as components for professional incorporation into complete systems. If installed incorrectly they may present a safety hazard. The drive uses high voltages and currents, carries a high level of stored electrical energy, and is used to control equipment which can cause injury. Close attention is required to the electrical installation and the system design to avoid hazards either in normal operation or in the event of equipment malfunction. System design, installation, commissioning/start-up and maintenance must be carried out by personnel who have the necessary training and competence. They must read this safety information and this guide carefully.

2.3 Responsibility

It is the responsibility of the installer to ensure that the equipment is installed correctly with regard to all instructions given in this guide. They must give due consideration to the safety of the complete system, so as to avoid the risk of injury both in normal operation and in the event of a fault or of reasonably foreseeable misuse.

The manufacturer accepts no liability for any consequences resulting from inappropriate, negligent or incorrect installation of the equipment.

2.4 Compliance with regulations

The installer is responsible for complying with all relevant regulations, such as national wiring regulations, accident prevention regulations and electromagnetic compatibility (EMC) regulations. Particular attention must be given to the cross-sectional areas of conductors, the selection of fuses or other protection, and protective ground (earth) connections.

This guide contains instructions for achieving compliance with specific EMC standards.

All machinery to be supplied within the European Union in which this product is used must comply with the following directives:

2006/42/EC Safety of machinery.

2014/30/EU: Electromagnetic Compatibility.

2.5 Electrical hazards

The voltages used in the drive can cause severe electrical shock and/or burns, and could be lethal. Extreme care is necessary at all times when working with or adjacent to the drive. Hazardous voltage may be present in any of the following locations:

- AC and DC supply cables and connections
- Output cables and connections
- Many internal parts of the drive, and external option units

Unless otherwise indicated, control terminals are single insulated and must not be touched.

The supply must be disconnected by an approved electrical isolation device before gaining access to the electrical connections.

The STOP and Safe Torque Off functions of the drive do not isolate dangerous voltages from the output of the drive or from any external option unit.

The drive must be installed in accordance with the instructions given in this guide. Failure to observe the instructions could result in a fire hazard.

2.6 Stored electrical charge

The drive contains capacitors that remain charged to a potentially lethal voltage after the AC supply has been disconnected. If the drive has been energized, the AC supply must be isolated at least ten minutes before work may continue.

2.7 Mechanical hazards

Careful consideration must be given to the functions of the drive or controller which might result in a hazard, either through their intended behaviour or through incorrect operation due to a fault. In any application where a malfunction of the drive or its control system could lead to or allow damage, loss or injury, a risk analysis must be carried out, and where necessary, further measures taken to reduce the risk - for example, an over-speed protection device in case of failure of the speed control, or a fail-safe mechanical brake in case of loss of motor braking.

With the sole exception of the Safe Torque Off function, none of the drive functions must be used to ensure safety of personnel, i.e. they must not be used for safety-related functions.

The Safe Torque Off function may be used in a safety-related application. The system designer is responsible for ensuring that the complete system is safe and designed correctly according to the relevant safety standards.

The design of safety-related control systems must only be done by personnel with the required training and experience. The Safe Torque Off function will only ensure the safety of a machine if it is correctly incorporated into a complete safety system. The system must be subject to a risk assessment to confirm that the residual risk of an unsafe event is at an acceptable level for the application.

2.8 Access to equipment

Access must be restricted to authorized personnel only. Safety regulations which apply at the place of use must be complied with.

2.9 **Environmental limits**

Instructions in this guide regarding transport, storage, installation and use of the equipment must be complied with, including the specified environmental limits. This includes temperature, humidity, contamination, shock and vibration. Drives must not be subjected to excessive physical force.

2.10 **Hazardous environments**

The equipment must not be installed in a hazardous environment (i.e. a potentially explosive environment).

2.11 **Motor**

The safety of the motor under variable speed conditions must be ensured.

To avoid the risk of physical injury, do not exceed the maximum specified speed of the motor.

Low speeds may cause the motor to overheat because the cooling fan becomes less effective, causing a fire hazard. The motor should be installed with a protection thermistor. If necessary, an electric forced vent fan should be used.

The values of the motor parameters set in the drive affect the protection of the motor. The default values in the drive must not be relied upon. It is essential that the correct value is entered in the Motor Rated Current parameter.

2.12 **Mechanical brake control**

Any brake control functions are provided to allow well co-ordinated operation of an external brake with the drive. While both hardware and software are designed to high standards of quality and robustness, they are not intended for use as safety functions, i.e. where a fault or failure would result in a risk of injury. In any application where the incorrect operation of the brake release mechanism could result in injury, independent protection devices of proven integrity must also be incorporated.

2.13 **Adjusting parameters**

Some parameters have a profound effect on the operation of the drive. They must not be altered without careful consideration of the impact on the controlled system. Measures must be taken to prevent unwanted changes due to error or tampering.

2.14 **Electromagnetic compatibility (EMC)**

Installation instructions for a range of EMC environments are provided in the relevant Power Installation Guide. If the installation is poorly designed or other equipment does not comply with suitable standards for EMC, the product might cause or suffer from disturbance due to electromagnetic interaction with other equipment. It is the responsibility of the installer to ensure that the equipment or system into which the product is incorporated complies with the relevant EMC legislation in the place of use.

3 Introduction

3.1 Features

The SM-I/O PELV is designed to meet the I/O requirements of chemical and similar industries. The Solutions Module provides additional galvanic isolation to that within the drive itself. The requirements of PELV (Protective Extra Low Voltage) according to IEC 61800-5-1, and Namur NE37 are met.

All terminals on the SM-I/O PELV have the following provisions for electrical safety:

- Decisive voltage class A according to IEC 61800-5-1, i.e. less than 30Vac r.m.s., 42.4Vac peak, 60Vdc mean.
- Protective separation from live parts, comprising of supplementary insulation in conjunction with the basic insulation of the drive control circuits, suitable for all supply voltages and configurations for which the drive is intended.

The PELV circuit is permitted to be grounded. This connection must be made externally if required.

Note that PELV circuits do not require protection against contact, but this applies only when used within a zone of equipotential bonding. For further guidance on safety requirements and PELV consult the relevant electrical safety code for the region where the Solutions Module will be used.

The SM-I/O PELV can be used on the following products:

- Unidrive SP
- Commander SK

The SM-I/O PELV increases the I/O capability of the drive by adding the following to the existing I/O:

- 2 x Analogue current outputs
- 1 x Analogue input (current/voltage mode)
- 4 x Digital inputs/outputs*
- 1 x Digital input with optional freeze function**
- 2 x Relays (30Vdc contact rating)



The I/O connections direct to the drive itself have basic (single) insulation from live parts. They do not meet the requirements for PELV.

All connections from the Solutions Module to the drive are made via the drive connector.

Connections from external equipment to the 24V voltage input, relays, digital and analogue I/O are made via a 17-way pluggable screw connector.

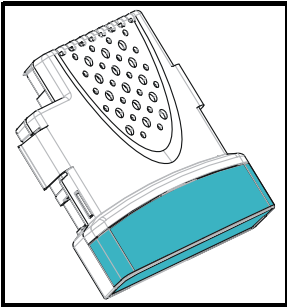
On the Unidrive SP a total of three SM-I/O PELV modules can be fitted at any one time. On the Commander SK only one can be fitted.

*Only three digital outputs are available with Commander SK.

**Freeze function is not available with Commander SK.

3.2 Solutions Module identification

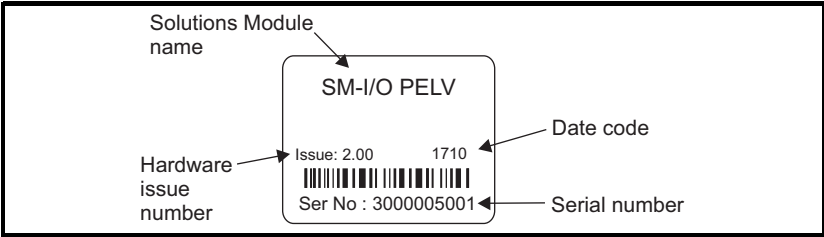
Figure 3-1 SM-I/O PELV



The SM-I/O PELV can be identified by:

1. The label located on the underside of the Solutions Module.
2. The colour coding across the front of the Solutions Module, with the SM-I/O PELV being turquoise blue.

Figure 3-2 SM-I/O PELV label



3.2.1 Date code format

The date code is four numbers. The first two numbers indicate the year and the remaining numbers indicate the week of the year in which the drive was built.

Example:

A date code of 1710 would correspond to week 10 of year 2017.

3.3 Drive software version

The SM-I/O PELV can only be used with the following drive software version:

Unidrive SP: ≥V01.07.00

Commander SK: ≥V01.06.00

- NOTE** When operating with Unidrive SP, the freeze function will be available for all drive software versions after V01.07.00. However, the freeze flag parameter will only be visible when the drive software version is V01.09.00 or later. Not available with Commander SK.
- NOTE** When operating with Unidrive SP, Pr **x.16** (Disable PELV user power supply trip) will only be available on drive software versions V01.10.00 and later.
- NOTE** When operating with Unidrive SP and drive software version V01.07.xx parameters Pr **x.06** (PELV user power supply state) and Pr **x.51** (Solutions Module Software sub-Version) will not be available.

3.4 Conventions used in this guide

The configuration of the host drive and Solutions Module is done using menus and parameters. A menu is a logical collection of parameters that have similar functionality. In the case of a Solutions Module, the parameters will appear in menu 15 for the Commander SK, and in menu 15, 16 or 17 for the Unidrive SP depending on the slot the module is fitted into. The menu is determined by the number before the decimal point.

The method used to determine the menu or parameter is as follows:

- Pr **xx.00** - signifies any menu and parameter number 00.
- Pr **x.XX** - where **x** signifies the menu allocated to the Solutions Module (this could be 15, 16 or 17 on the Unidrive SP but will always be 15 on the Commander SK) and **XX** signifies the parameter number.

3.5 Solutions Module I/O

NOTE Solution Module I/O only operates in positive logic mode.

NOTE All I/O and relays are user programmable for function and signal processing.

NOTE All new source and destination routing only changes to new set up locations when the drive is reset.

NOTE By default, the digital inputs/outputs on the Solutions Module are configured to operate as inputs, except Digital I/O 4 which is configured as an output (input only for Commander SK).

3.6 Digital I/O

All digital I/O complies with IEC 61131-2, clause 3.3.1 type 1, (i.e. >2mA @ +15Vdc). For type 2 input, the user will need to add extra load externally.

Function	Quantity
Digital inputs	1 (2 on Commander SK)

One terminal forms a dedicated digital input (2 on Commander SK); the functionality of this input is as follows:

- The logic state of the input is monitored by a RO parameter
- The logic state can be inverted
- The digital input can be programmed to any unprotected parameter. The destination parameter value will always be either 0 or 1 depending on the state of the input.
- The digital input may be programmed to provide a freeze signal to the drive*

*Freeze function is not available with Commander SK.

Function	Quantity
Programmable digital inputs / outputs	4**

Four terminals are programmable as either digital inputs or outputs, the functionality of these terminals is as follows:

Input

- The logic state of each input is monitored by a RO parameter
- The logic state can be inverted
- The digital input can be programmed to any unprotected parameter. The destination parameter value will always be either 0 or 1 depending on the state of the input

Output

- The logic state of each output is monitored by a RO parameter
- The logic state can be inverted
- The digital outputs can be sourced from any parameter.
In the case where an integer parameter is used as the source, the threshold of the output switching between low and high states is 50% of the parameter's maximum.

E.g. Source parameter = Pr **18.11** (maximum = 32767)

50% of 32767 = 16383 (due to integer truncation)

Therefore, if Pr **18.11** ≥ 16383 the output will be high

if Pr **18.11** < 16383 the output will be low

- The digital outputs can only source current
- The four digital outputs of a Solutions Module (three digital outputs with Commander SK) are able to source 40 mA to the total combination of output channels (e.g. 4 x 10mA or 1 x 40mA). When the current drawn exceeds safe limits, all the outputs will be disabled through hardware and trip the drive to alert the user to the fault condition.

**Only three digital outputs are available with Commander SK.

3.7 Analogue I/O

Function	Quantity
Unipolar current input/Bipolar voltage input	1

Two terminals form a combined voltage, or unipolar current, analogue input port. The function of this input is as follows:

- A scaling factor can be applied to the analogue input signal
- The analogue input signal can be inverted
- The analogue input can be programmed to any suitable unprotected destination parameter
- The input operates in one of the following modes as set in Pr **x.38**: 0-20, 20-0, 4-20.tr, 20-4.tr, 4-20 and 20-4, VOLT (Pr **x.38**: 0-20, 20-0, 4-20, 20-4, 4-20, 20-4, VolT on Commander SK).
- When the input current is <3.0mA in 4-20.tr or 20-4.tr mode (4-20 or 20-4 with Commander SK), the drive will initiate an SLX.Er / SL.Er trip. See Chapter 6 *Diagnostics* for details.

Function	Quantity
Unipolar current output	2

Two terminals have a dedicated analogue output with the following functions:

- The output can be used to convey the value of any valid source parameter to external equipment*.
- The output operates in one of the following modes as set in Pr **x.39**: 0-20, 20-0, 4-20 and 20-4.
- A scaling factor can be applied to the analogue output signal*

*Only available on analogue output 1 with Commander SK.

3.8 Relays

Function	Quantity
Number of relays	2

The relays can be used to convey the logic state of any suitable parameter to external equipment. The logic state is processed as follows:

- Any source parameter is assigned to each relay.
- The logic state can be inverted.
- The software state of the coil is monitored by a parameter.

3.9 PELV user power supply

A suitable supply of nominally 24V must be provided to drive the PELV circuits. The supply isolation must meet the PELV requirement.

The PELV user power supply must be a UL Class 2 power supply or a limited voltage, limited current power supply (LVLC).

4 Installing the Solutions Module



Before installing the Solutions Module, refer to Chapter 2 *Safety Information* on page 7.



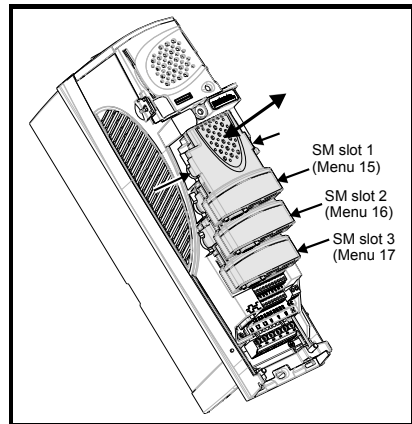
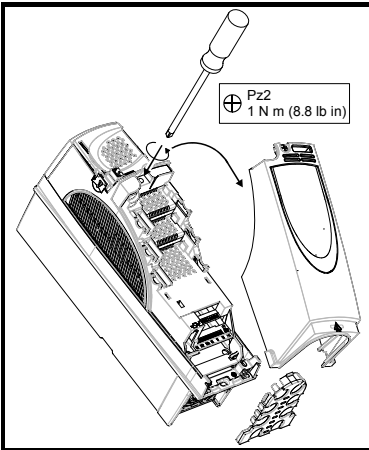
Do not remove the Solutions Module when the drive is powered-up. This could damage the drive and/or the Solutions Module.

4.1 Installation

4.1.1 Unidrive SP

Three Solutions Module slots are available on Unidrive SP. The Solutions Module can be plugged into any of these slots but it is recommended that slot 3 be used for the first Solutions Module, then slot 2 and then slot 1. This ensures the maximum mechanical support for the Solutions Module once fitted. See Figure 4-2.

Figure 4-1 Removing the Uni SP terminal cover **Figure 4-2 Fitting and removing a Solutions Module into the Unidrive SP**



1. Before installing a Solutions Module in any drive, ensure the AC supply has been disconnected for at least 10 minutes.
2. Ensure that any +24V and low voltage DC power supplies (if used) have been disconnected from the drive.
3. Check that the exterior of the Solutions Module is not damaged and the multiway connector on the underside of the module is free from dirt and debris.
4. Do not install a damaged or dirty Solutions Module in the drive.
5. Remove the terminal cover from the drive as shown in Figure 4-1.
6. Position the drive connector of the Solutions Module over the appropriate connector of the drive. Push the Solutions Module towards the rear of the drive until it locks into place. Make the +24V PELV user power supply connections to the Solutions Module and any other wiring connections as appropriate.



To maintain PELV isolation integrity it is important to ensure the correct 17 way connector is inserted into the Solutions Module.

SM-I/O PELV connections should be made using the high visibility yellow connector provided.

7. Re-fit the terminal cover to the drive by reversing the procedure shown in Figure 4-1.
8. Switch on the +24V PELV user power supply (refer to section 3.9 *PELV user power supply* on page 14)
9. Connect the AC supply or low voltage DC supply (if used) to the drive.
10. When a Solutions Module is fitted to a Unidrive SP for the first time, as the drive is powered-up, the drive will trip on SL1.dF or SL2.dF or SL3.dF depending on which slot the Solutions Module is fitted to. A parameter save must be performed.
Set Pr **xx.00** = 1000 (or 1001 in the case of solely using the 24V back-up power supply) and press the Stop/Reset button. If a parameter save is not performed, the drive will trip on the above trips the next time the drive is powered up.

NOTE When using the 24V back-up power supply only, the SLx.dF trip will not occur (as the drive is already displaying a UU trip).

NOTE When fitting two or more Solutions Modules simultaneously, the SLx.dF trip is only applicable to the module fitted in the lowest numerical slot.

NOTE If an SLx.dF trip is not seen after the first power-up, the Solutions Module is not fitted properly to the drive. Power down the drive, remove and re-fit the Solutions Module. Then power can be re-applied to the drive.

11. To access the advanced parameters refer to the *Unidrive SP User Guide*.
12. Check that Menu 15 (slot 1), 16 (slot 2), or 17 (slot 3) parameters are now available (depending on which slot is used).
13. Check that Pr **15.01**, Pr **16.01** or Pr **17.01** shows the correct code for the SM-I/O PELV: 204.
14. Power the drive down and back up. The Solutions Module is now ready for programming.

NOTE If the SM-I/O PELV is changed for another type of Solutions Module, the drive will trip as in step 10. Follow the above procedure.

15. If the checks in steps 12 and 13 fail, either the Solutions Module is not fully inserted, or it is faulty.
16. If a trip code is now present refer to *Chapter 6 Diagnostics* on page 37.

4.1.2 Commander SK

One Solutions Module slot is available on Commander SK. See Figure 4-4.



To allow a Solutions Module to be fitted to Commander SK, a protective cover must be removed to allow access to the PCB edge connector (see Figure 4-3). This protective cover provides protection from direct contact of the PCB edge connector by the user. When this cover is removed and Solutions Module fitted, the Solutions Module provides the protection from direct contact by the user. If the Solutions Module is then removed, this PCB edge connector becomes exposed. The user is required to provide protection in this case.

Figure 4-3 Removing the Commander SK terminal cover

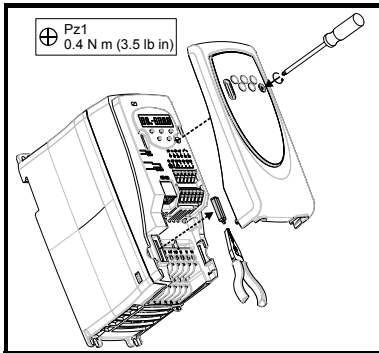
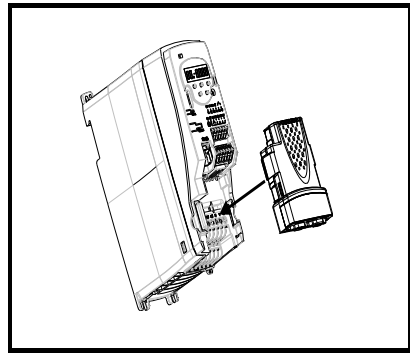


Figure 4-4 Fitting and removing a Solutions Module into the Commander SK



1. Before installing a Solutions Module in any drive, ensure the AC supply has been disconnected for at least 10 minutes.
2. Check that the exterior of the Solutions Module is not damaged and the multiway connector on the underside of the module is free from dirt and debris.
3. Do not install a damaged or dirty Solutions Module in the drive.
4. Remove the terminal cover from the drive as shown in Figure 4-3.
5. Ensure that the plastic tab which covers the drive's Solutions Module connector is removed before fitting any option. See Figure 4-4.

Position the drive connector of the Solutions Module over the appropriate connector of the drive. Push the Solutions Module towards the rear of the drive until it locks into place. Make the +24V PELV user power supply connections to the Solutions Module and any other wiring connections as appropriate.



To maintain PELV isolation integrity it is important to ensure the correct 17 way connector is inserted into the Solutions Module.

SM-I/O PELV connections should be made using the high visibility yellow connector provided.

6. Re-fit the terminal cover to the drive by reversing the procedure shown in Figure 4-3.
7. Switch on the +24V PELV user power supply (refer to section 3.9 *PELV user power supply* on page 14)
8. Connect the AC supply to the drive.
10. When a Solutions Module is fitted to a Commander SK for the first time, as the drive is powered-up, the drive will trip on SL.dF.
Press the STOP/RESET button to clear the trip
The Commander SK automatically saves the Solutions Module identity details to memory which will avoid any future SL.dF trips.

11. To access the advanced parameters refer to the *Commander SK Getting Started Guide*.

NOTE If an SL.dF trip is not seen after the first power-up, the Solutions Module is not fitted properly to the drive. Power down the drive, remove and re-fit the Solutions Module. Then power can be re-applied to the drive.

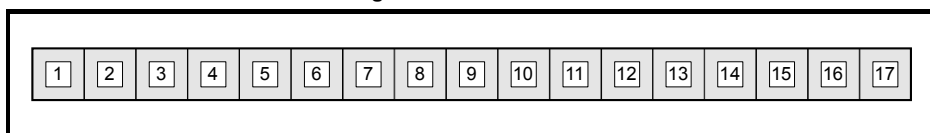
12. Check that Menu 15 parameters are now available.
13. Check that Pr **15.01** shows the correct code for the SM-I/O PELV: 204.
14. Power the drive down and back up. The Solutions Module is now ready for programming.

NOTE If the SM-I/O PELV is changed for another type of Solutions Module, the drive will trip as in step 10. Follow the above procedure.

15. If the checks in steps 12 and 13 fail, either the Solutions Module is not fully inserted, or it is faulty.
16. If a trip code is now present refer to *Chapter 6 Diagnostics* on page 37.

4.2 Terminal descriptions

Figure 4-5 SM-I/O PELV terminals



Provide fuse or other over-current protection in the relay circuit.

Table 4-1 Terminal descriptions

Term	Function
1	0V common
2	+24V input
3	Digital I/O 1
4	Digital I/O 2
5	Digital I/O 3
6	Digital I/O 4*
7	Digital input 5/Freeze input**
8	Analogue input 1 non-inverting input/V _{in}
9	Analogue input 1 inverting input (current mode only)
10	Analogue output 1
11	0V common
12	Analogue output 2
13	0V common
14	Relay 1 contact 1
15	Relay 1 contact 2
16	Relay 2 contact 1
17	Relay 2 contact 2

17-way 3.81mm pluggable screw connector.
*Digital input only with Commander SK
**Freeze input not available with Commander SK

4.3 Wiring, shield connections

The Solutions Module terminals are double insulated from live parts, therefore eliminating the need for additional protection from human contact. To maintain this level of safety, any external circuits connected to the SM-I/O PELV must also meet PELV requirements as highlighted in section 3.1 *Features* on page 10.

To highlight PELV wiring, connections to the SM-I/O PELV Solutions Module should be made using the high visibility yellow connector provided.

To prevent noise being induced onto any of the analogue inputs or outputs it is advisable to use a twisted pair cable shielded with overall shield.

If used, the shield connections should be terminated at one of the zero volts terminals on the Solutions Module and to the zero volts of the signal source if available. The termination of the shield should be kept as short as possible to prevent any noise being induced at this point.

Figure 4-6 Shield connections (current mode)

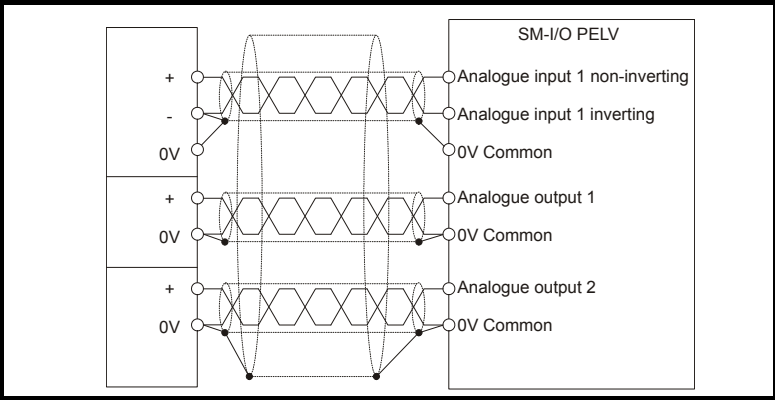
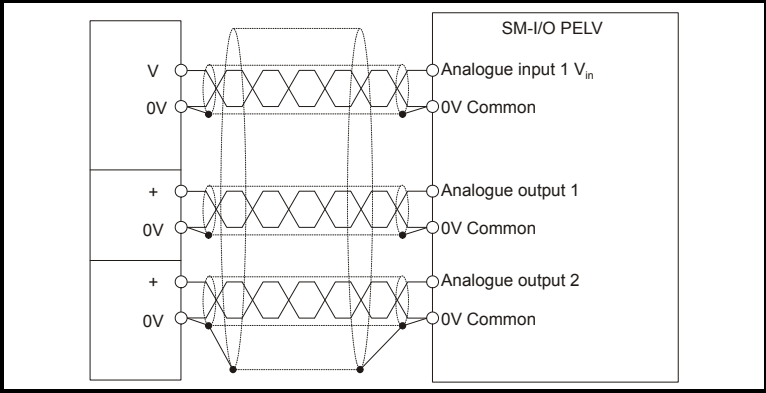


Figure 4-7 Shield connections (voltage mode)



5 Parameters

5.1 Introduction

The parameters listed in this chapter are used for programming and monitoring the SM-I/O PELV.

5.1.1 Parameter update times

The SM-I/O PELV is an intelligent Solutions Module. The update times for the parameters are defined by the drive type in use. The following apply only when the Solutions Module is used with a Unidrive SP:

Parameters shown as "Background" are updated at least once every 30ms.

When the digital inputs or the analogue input are the source for a parameter outside the Solutions Module menu, the data is written to the destination parameter every 4ms.

If the analogue input destination Pr **x.43** is set such that data is passed to preset speed 1 (Pr **1.21**), whilst preset speed 1 is selected as the speed reference, and if the drive is in closed-loop vector or servo mode, then the speed reference is updated every 500µs.

If the analogue input destination Pr **x.43** is set such that data is passed to the hard speed reference (Pr **3.22**), whilst the hard speed reference is selected, and if the drive is in closed-loop vector or servo mode, then the hard speed reference is updated every 500µs.

If the analogue input destination Pr **x.43** is set such that data is passed to the torque reference (Pr **4.08**), whilst the drive is in closed-loop vector or servo mode, then the torque reference is updated every 500µs.

If the destination parameter for any of the digital inputs on the module are set to Pr **x.42**, and the analogue input is being used to control a torque or speed reference as described above, the invert function operates within 500µs of any changes of the digital input state.

The following apply only when the Solutions Module is used with a Commander SK:

The module has two parameter update times; background and fast update. The actual update times for the two types of parameter are dependent upon the number of I/O used (i.e. that are mapped to a valid source or destination) on the module.

The update rate for fast update parameters can be calculated with the following expression:

$$t_{FU}(\text{ms}) = ((\text{Number of I/O used}) + 2) * 2\text{ms}$$

The update time for background level parameters can be calculated with the following expression:

$$t_{BU}(\text{ms}) = t_{FU} * 34$$

Only source and destination parameters that are routed to a valid parameter are updated at the fast rate.

Number of I/O source/ destinations active	Fast Update Time (ms)	Background Update Time (ms)
1	6	204
2	8	272
3	10	340
4	12	408
5	14	476
6	16	544
7	18	612
8	20	680
9	22	748
10	24	816

NOTE The analogue output 2 source is always active (set to Pr **4.02**), therefore the minimum fast update time with any other I/O active will be 8ms. The background update time will be a minimum of 272ms.

NOTE On the Unidrive SP, the “x” in the parameter number (e.g. Pr **x.01**), is either Menu 15 (slot 1), 16 (slot 2) or 17 (slot 3) depending on which slot is used. On Commander SK the “x” in the parameter number is Menu 15.



Before attempting to adjust any parameters, refer to Chapter 2 *Safety Information* on page 7.

Table 5-1 Key to parameter coding

Coding	Attribute
RW	Read/write: can be written by the user
RO	Read only: can only be read by the user
Bit	1 bit parameter
Bi	Bipolar parameter
Uni	Unipolar parameter
Txt	Text: the parameter uses text strings instead of numbers.
FI	Filtered: some parameters which can have rapidly changing values are filtered when displayed on the drive keypad for easy viewing.
DE	Destination: indicates that this parameter can be a destination parameter.
RA	Rating dependant: this parameter is likely to have different values and ranges with drives of different voltage and current ratings. These parameters are not transferred by SMARTCARDS / SmartSticks when the rating of the destination drive is different from the source drive.
NC	Not cloned: not transferred to or from SMARTCARDS / SmartSticks during cloning.
PT	Protected: cannot be used as a destination.
US	User save: saved in drive EEPROM when the user initiates a parameter save.
PS	Power-down save: automatically saved in drive EEPROM at power-down.

5.2 Single line descriptions

Parameter		Range(⇅)	Default(⇒)	Type					
x.01	Solutions Module ID	0 to 599	204	RO	Uni			PT	US
x.02	Solutions Module Main Software Version	0.00 to 99.99		RO	Uni		NC	PT	
x.03	T5 digital I/O 3 state	OFF (0) or On (1)		RO	Bit		NC	PT	
x.04	T6 digital I/O 4 state**	OFF (0) or On (1)		RO	Bit		NC	PT	
x.05	T7 digital input 5 state/freeze input****	OFF (0) or On (1)		RO	Bit		NC	PT	
x.06	PELV user power supply state	OFF (0) or On (1)		RO	Bit		NC	PT	
x.07	Relay 1 state	OFF (0) or On (1)		RO	Bit		NC	PT	
x.08	Relay 2 state	OFF (0) or On (1)		RO	Bit		NC	PT	
x.09	T3 digital I/O 1 state	OFF (0) or On (1)		RO	Bit		NC	PT	
x.10	T4 digital I/O 2 state	OFF (0) or On (1)		RO	Bit		NC	PT	
x.11	T3 digital I/O 1 invert	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.12	T4 digital I/O 2 invert	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.13	T5 digital I/O 3 invert	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.14	T6 digital I/O 4 invert**	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.15	T7 digital input 5 invert/ Freeze Input Edge Select****	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.16*	Disable PELV user power supply trip	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.17	Relay 1 invert	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.18	Relay 2 invert	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.19*	Freeze Flag	OFF (0) or On (1)		RW	Bit				
x.20	Digital I/O read word	0 to 255		RO	Uni		NC	PT	
x.21	T3 digital I/O 1 source/destination	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni	DE			US
x.22	T4 digital I/O 2 source/destination	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni	DE			US
x.23	T5 digital I/O 3 source/destination	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni	DE			US
x.24	T6 digital I/O 4 source/destination***	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni	DE			US
x.25	T7 digital input 5 destination	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni	DE			US
x.26	Not used								
x.27	Relay 1 source	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni				US
x.28	Relay 2 source	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni				US
x.29*	T6 digital I/O 4 output select	OFF (0) or On (1)	On (1)	RW	Bit				US
x.30	Not used								
x.31	T3 digital I/O 1 output select	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.32	T4 digital I/O 2 output select	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.33	T5 digital I/O 3 output select	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.34	Not used								
x.35	Not used								
x.36	Not used								
x.37	Not used								
x.38	Analogue input 1 mode	0-20, 20-0, 4-20.tr (4-20), 20-4.tr (20-4), 4-20 (4-.20), 20-4 (20-.4), VOLT (VOLT)	0-20	RW	Uni				US
x.39	Analogue output mode	0-20, 20-0, 4-20, 20-4	0-20	RW	Uni				US
x.40	Analogue input 1 level	0.0 to 100.0%		RO	Uni		NC	PT	
x.41	Analogue input 1 scaling	0.000 to 4.000	1.000	RW	Uni				US
x.42	Analogue input 1 invert	OFF (0) or On (1)	OFF (0)	RW	Bit				US
x.43	Analogue input 1 destination	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni	DE			US
x.44	Not used								
x.45*	Analogue output 2 scaling	0.000 to 4.000	1.000	RW	Uni				US
x.46	Not used								
x.47*	Analogue output 2 source	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni				US
x.48	Analogue output 1 source	Pr 0.00 to Pr 21.51	Pr 0.00	RW	Uni				US
x.49	Analogue output 1 scaling	0.000 to 4.000	1.000	RW	Uni				US
x.50	Solutions Module error status	0 to 255		RO	Uni		NC	PT	
x.51	Solutions Module software sub-version	0 to 99		RO	Uni		NC	PT	

* Parameter not available with Commander SK

** Digital input only with Commander SK

*** Destination only with Commander SK

**** Freeze input not available with Commander SK

5.3 Logic diagrams

Figure 5-1 Digital I/O logic diagram (Unidrive SP only)

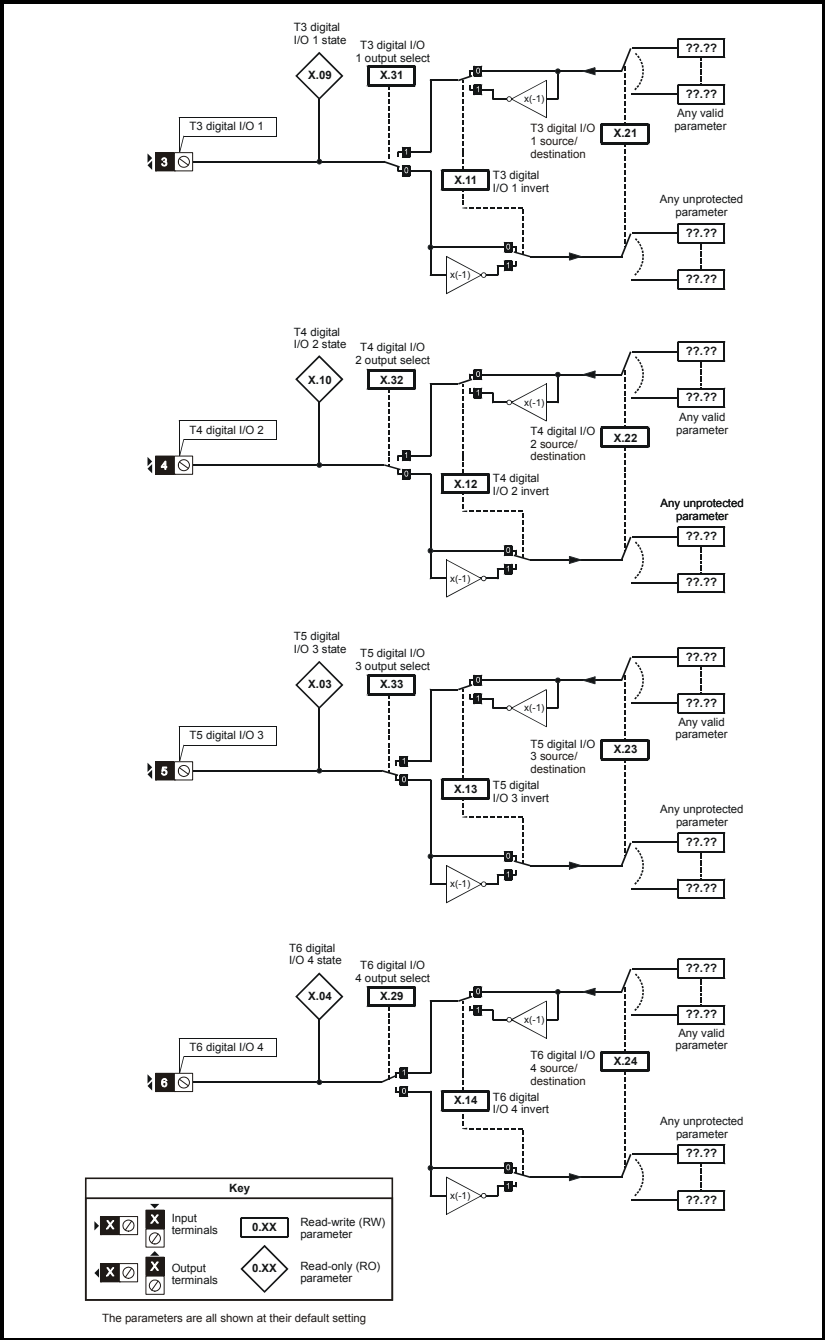


Figure 5-2 Digital I/O logic diagram (Commander SK only)

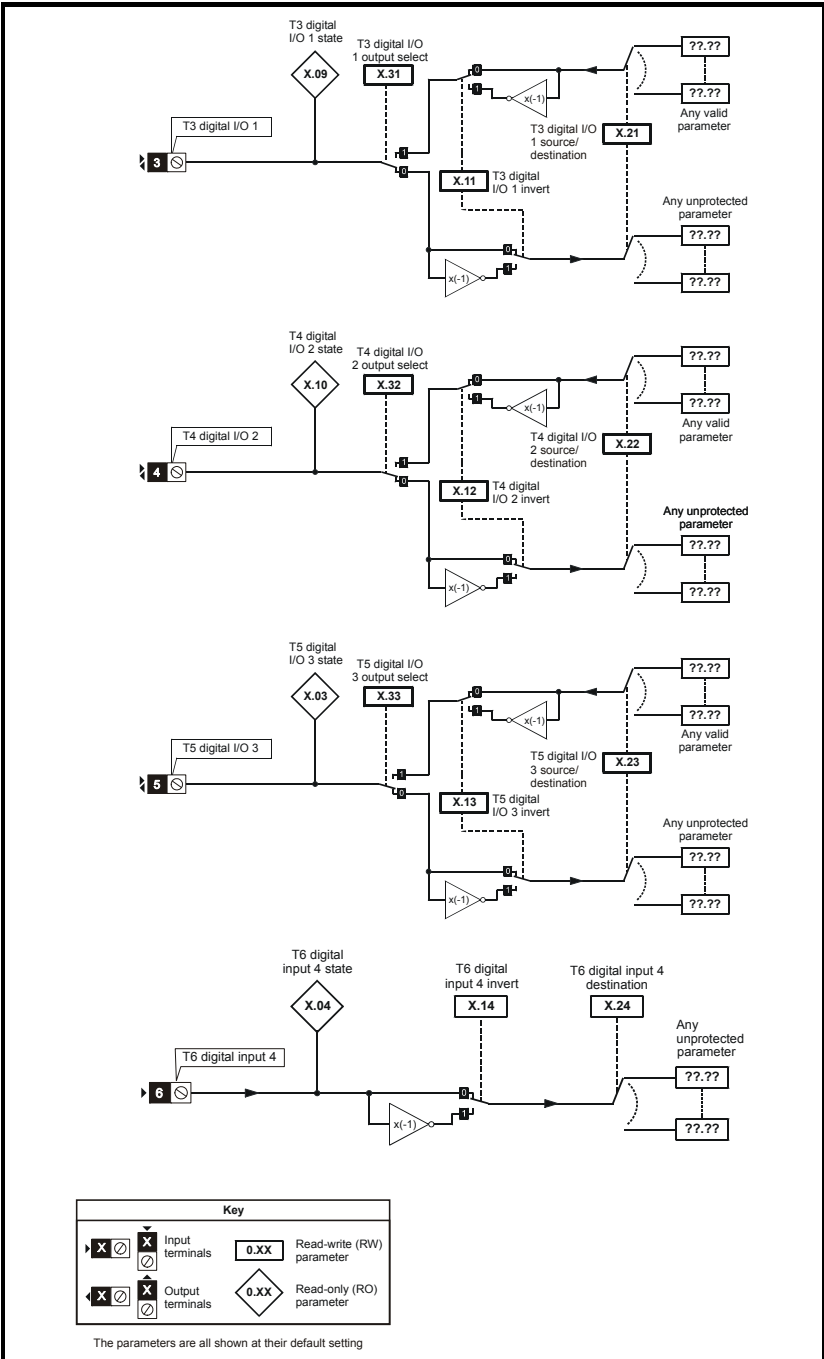
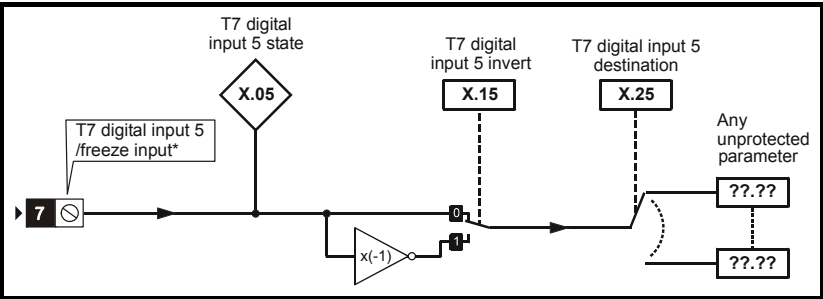


Figure 5-3 Digital input logic diagram



*Not available with Commander SK

NOTE

The performance of the freeze input is highly dependant upon the quality of the signal driving it. If negative edge triggering is used then care should be taken to ensure that the input is actively pulled low via low impedance. If positive edge triggering is used then care should be taken to ensure that the input is actively pulled high, or pulled high via a suitably low pull-up resistance.

Figure 5-4 Relay logic diagram

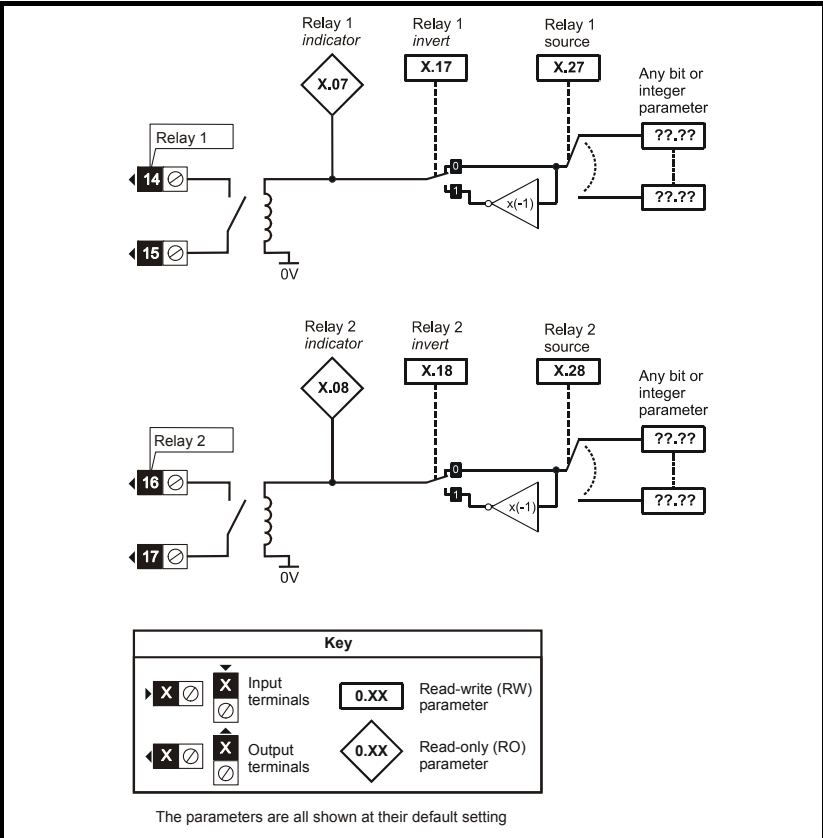


Figure 5-5 Analogue input logic diagram (current mode)

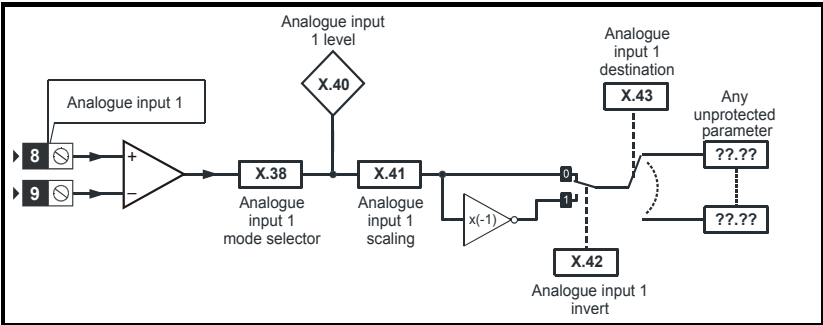


Figure 5-6 Analogue input logic diagram (voltage mode)

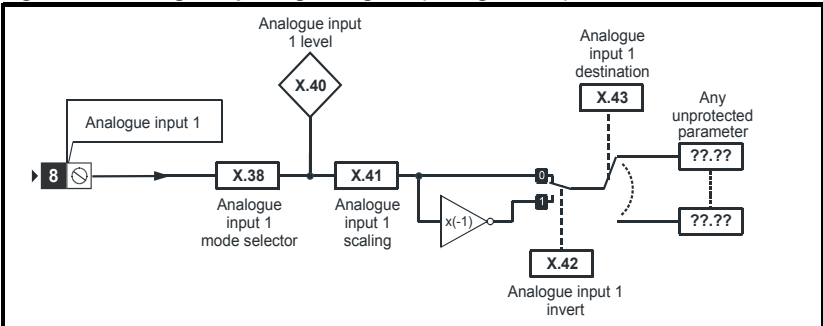


Figure 5-7 Analogue output logic diagram (Unidrive SP only)

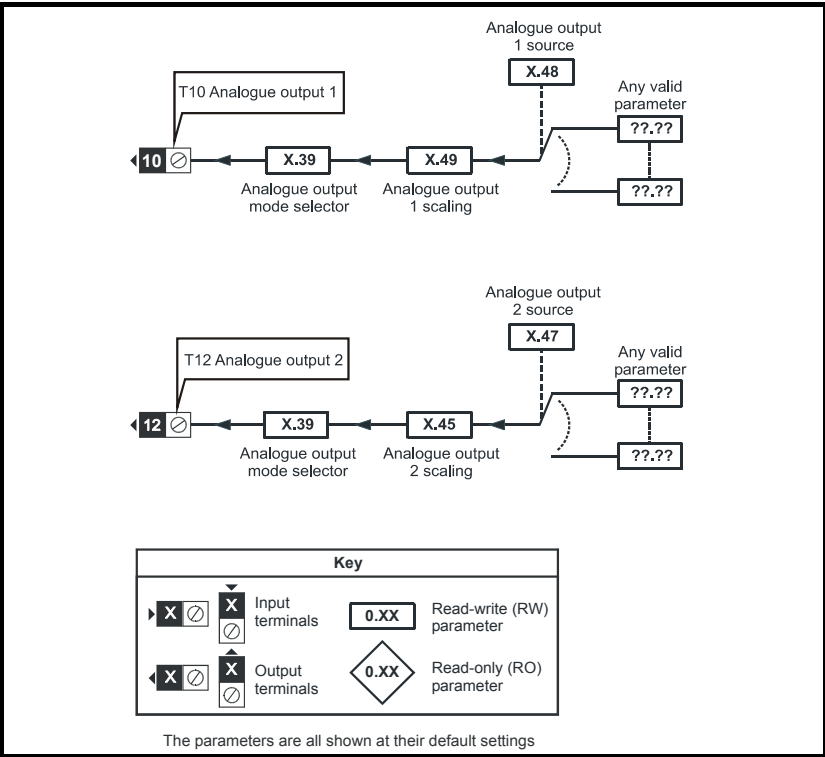
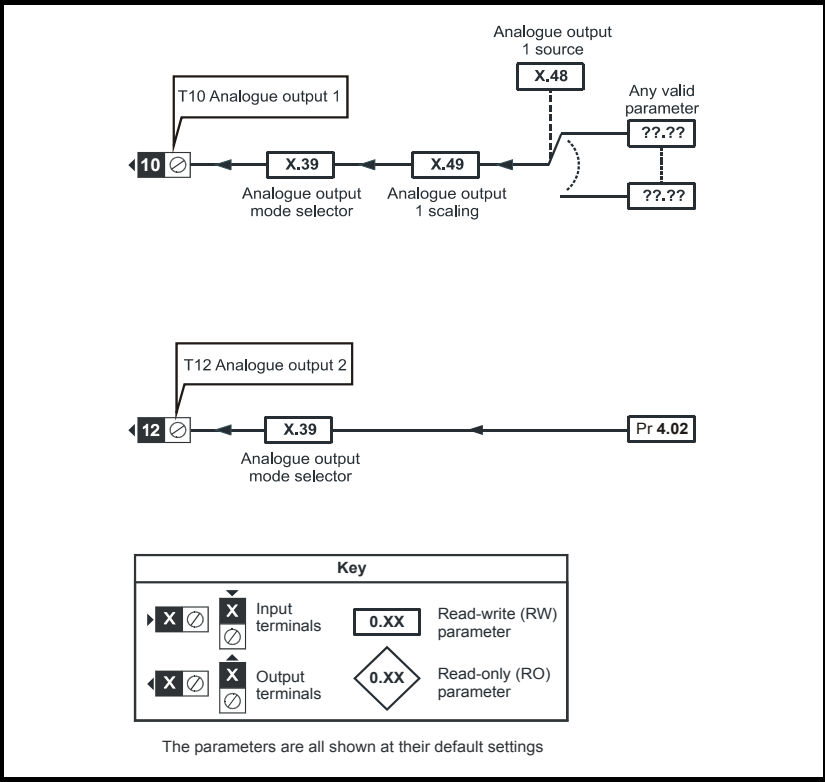


Figure 5-8 Analogue output logic diagram (Commander SK only)



5.4 Parameter descriptions

x.01		Option ID code							
RO	Uni						PT	US	
↕	0 to 599			⇒					
Update rate: Write on power-up									

On Unidrive SP the menu for the relevant slot appears for the new Solutions Module category with the default parameter values for the new category. For Commander SK it will always be menu 15.

When no Solutions Module is fitted in the relevant slot this parameter is zero. When a Solutions Module is fitted this parameter displays the identification code as shown below.

Code	Solutions Module	Category	Dumb module	Compatibility	
				Uni SP	Comm SK
0	No Solutions Module fitted				
101	SM-Resolver	Feedback	✓	✓	
102	SM-Universal Encoder Plus			✓	
104	SM-Encoder Plus		✓	✓	
201	SM-I/O Plus		✓	✓	
203	SM-I/O Timer	Automation		✓	✓
204	SM-I/O PELV			✓	✓
205	SM-I/O 24V Protected			✓	✓
206	SM-I/O 120V			✓	✓
207	SM-I/O Lite			✓	✓
301	SM-Applications			✓	
302	SM-Application Lite			✓	
303	SM-EZMotion			✓	
401	reserved			✓	
402	reserved			✓	
403	SM-Profibus DP	Fieldbus		✓	✓
404	SM-Interbus			✓	✓
405	reserved			✓	
406	SM-CAN			✓	
407	SM-DeviceNet			✓	✓
408	SM-CANopen			✓	✓
409	SM-SERCOS			✓	
410	SM-Ethernet			✓	✓
501	SM-SLM	Feedback		✓	

Unidrive SP

The new parameter values are not stored in the drive EEPROM until the user performs a parameter save by setting Pr **xx.00** to 1000 (or 1001 in the case of solely using the 24V back-up power supply) and pressing the stop/reset button. When parameters are saved by the user in the drive EEPROM, the option code of the currently fitted Solutions Module is saved in the drive EEPROM. If the drive is subsequently powered-up with a different Solutions Module fitted, or no Solutions Module is fitted when one was previously fitted, the drive will trip on SLx.dF or SLx.nF.

Commander SK

The new parameter values are stored automatically by the drive. If the drive is subsequently powered up with a different Solutions Module fitted, or no Solutions Module is fitted when one was previously fitted, the drive will trip on SL.dF or SL.nF.

x.02		Solutions Module main software version									
RO	Uni						NC	PT			
↕	00.00 to 99.99				⇒						
Update rate: Write on power-up											

This module contains two processors, and thus two software versions. Pr **x.02** shows the version number of the main module processor. Pr **x.51**, which is normally used to give a sub-version number, shows the software version in the slave processor, which operates on the PELV side of the isolation barrier.

x.03		T5 digital I/O 3 state									
x.04		T6 digital I/O 4 state*									
x.05		T7 digital input 5 state/freeze input**									
RO	Bit					NC	PT				
↕	OFF (0) or On (1)					⇒					
Update rate: 4ms write											

*Digital output 4 is not available with Commander SK.

**Freeze input is not available with Commander SK.

These parameters indicate the input and output states of the terminals.

NOTE The update rates stated are when used with Unidrive SP.

x.06		PELV user power supply state							
RO	Bit					NC	PT		
↕	OFF (0) or On (1)				⇒				
Update rate: 4ms write									

The status of the PELV user power supply is shown in this parameter.

x.07 x.08 x.09 x.10	Relay 1 state									
	Relay 2 state									
	T3 digital I/O 1 state									
	T4 digital I/O 2 state									
RO	Bit					NC	PT			
↕	OFF (0) or On (1)				⇒					
Update rate: 4ms write										

These parameters indicate the input and output states of the terminals.

x.11	T3 digital I/O 1 invert									
x.12	T4 digital I/O 2 invert									
x.13	T5 digital I/O 3 invert									
x.14	T6 digital I/O 4 invert*									
x.15	T7 digital input 5 invert									
RW	Bit							US		
⇕	OFF (0) or On (1)				⇒	OFF (0)				
Update rate: 4ms read										

*Digital output 4 is not available with Commander SK.

Setting these parameters to On(1) causes the input sense to the destination parameter to be inverted or the output sense from the source to be inverted.

NOTE

When digital input 5 is used to provide a freeze function, the invert Pr **x.15** will select whether the freeze is applied on the rising (Pr **x.15** = Off) or the falling edge (Pr **x.15** = On) of the input signal (not available on Commander SK).

x.16*		Disable PELV user power supply trip							
RW	Bit							US	
↕	OFF (0) or On (1)				⇒	OFF (0)			
Update rate: Background read									

***Parameter not available with Commander SK.**

On Unidrive SP this parameter is only available on drive software V01.10.00 and later.

With Pr **x.16** = OFF

The PELV user power supply absent trip is intended to detect when the PELV user supply connected to the module is below 19V. During power-up the PELV user supply may not be present until after the main drive supply. To avoid unwanted trips in this situation, the PELV user power supply present trip detection system is disabled until the supply has become active the first time. Therefore if the supply is applied and then removed a trip is initiated. The trip is also initiated at any time after drive power-up if the supply is not present and the drive becomes active (i.e. Pr **10.02** is one). This condition prevents the drive from operating if the PELV user supply is not present. The status of the PELV user supply can be monitored from parameter Pr **x.06** (Off (0) =inactive, On (1) =active).

With Pr **x.16** = On

The state of the PELV user power supply will never trip the drive. The drive can be enabled without the PELV user power supply present but all of the module IO will be inoperable. Digital and analogue inputs will read zero. Digital outputs will be in their inactive state and analogue outputs will be at 0mA.

x.17		Relay 1 invert									
x.18		Relay 2 invert									
RW	Bit									US	
⇕	OFF (0) or On (1)					⇒	OFF (0)				
Update rate: 4ms read											

Setting these parameters to On (1) causes the output sense from the source to be inverted.

x.19*		Freeze flag									
RW	Bit										
↕	OFF (0) or On (1)				⇒						
Update rate: See below											

***Parameter not available with Commander SK.**

The freeze input function is enabled for DI5 if the destination parameter for this input (Pr **x.25**) is set to Pr **x.19**. Each time the input becomes active (or inactive if the invert Pr **x.15** is on) the freeze flag (Pr **x.19**) is set, the freeze system in the drive is triggered and held active.

Pr **x.19** is updated within 500µs of the change on the freeze input, and the freeze event is registered with the drive after 500µs with a latency of 10µs. The freeze flag is not automatically cleared when DI5 reverts to its original state. Another freeze event cannot be registered by the drive until all freeze flags are cleared. If any other I/O destination is set to write to Pr **x.19**, the parameter value simply follows the data from the I/O and no freeze events are produced. If this parameter is set by the user, it will not cause a freeze event even if it is the destination for DI5.

A minimum of 500µs must pass between consecutive freeze inputs. If a freeze input should occur less than 500µs after the previous one, the second will be ignored and have no effect on the drive.

x.20		Digital I/O read word									
RO	Uni						NC	PT	US		
↕	0 to 255					⇒					
Update rate: 500μs write											

This word is used to determine the status of the digital I/O by reading one parameter. The bits in this word reflect the state of Pr **x.03** to Pr **x.10**.

Bit	Digital I/O	Parameter	Bit Update Rate Input/Output*
0	T3 (Digital I/O 1)	Pr x.09	500µs / 4ms
1	T4 (Digital I/O 2)	Pr x.10	500µs / 4ms
2	T5 (Digital I/O 3)	Pr x.03	500µs / 4ms
3	T6 (Digital I/O 4)**	Pr x.04	500µs / 4ms
4	T7 (Digital input 5)	Pr x.05	500µs / -
5	T2 (PELV user power supply state)	Pr x.06	500µs / -
6	T14 / T15 (Digital output 7 relay)	Pr x.07	- / 4ms
7	T16 / T17 (Digital output 8 relay)	Pr x.08	- / 4ms

*Update rates when used with Unidrive SP.

**Digital input 4 state only with Commander SK.

x.21	T3 digital I/O 1 source/destination									
x.22	T4 digital I/O 2 source/destination									
x.23	T5 digital I/O 3 source/destination									
x.24	T6 digital I/O 4 source/destination*									
x.25	T7 digital input 5 destination									
RW	Uni		DE					US		
⇕	Pr 0.00 to Pr 21.51				⇒	Pr 0.00				
Update rate: Read on drive reset										

*Digital input 4 destination only with Commander SK.

Source parameters define the parameter to be represented by the digital output terminal.

Destination parameters define the parameter each of the programmable inputs is to control.

x.27		Relay 1 source									
x.28		Relay 2 source									
RW	Uni								US		
⇕	Pr 0.00 to Pr 21.51				⇒	Pr 0.00					
Update rate: Read on drive reset											

Source parameters define the parameter to be represented by the digital output terminal.

x.29*		T6 digital I/O 4 output select							
RW	Bit							US	
↕	OFF (0) or On (1)				⇒	On (1)			
Update rate: Background read									

***Parameter not available with Commander SK (T6 is a digital input only).**

This parameter selects the function of terminal T6 as follows:

OFF (0) = digital input

On (1) = digital output

x.31	T3 digital I/O 1 output select										
	x.32	T4 digital I/O 2 output select									
		x.33	T5 digital I/O 3 output select								
RW	Bit								US		
↕	OFF (0) or On (1)					⇒	OFF (0)				
Update rate: Background read											

These parameters select the function of terminals T3 to T5 as follows:

OFF (0) = digital input

On (1) = digital output

x.38		Analogue input 1 mode									
RW	Uni								US		
↕	0-20, 20-0, 4-20.tr (4-20), 20-4.tr (20-4), 4-20 (4-.20), 20-4 (20-.4), VoLt (VoLt)				⇒	0-20					
Update rate: Background read											

Parameter value	Parameter string		Mode	Comments
	SP	SK		
0	0-20	0-20	0-20mA	
1	20-0	20-0	20-0mA	
2	4-20.tr	4-20	4-20mA with trip on loss	Trip 2 if I < 3.0mA
3	20-4.tr	20-4	20-4mA with trip on loss	Trip 2 if I < 3.0mA
4	4-20	4-.20	4-20mA with no trip on loss	
5	20-4	20-.4	20-4mA with no trip on loss	
6	VoLt	VoLt	±10V	

x.39		Analogue output mode									
RW	Uni								US		
↕	0-20, 20-0, 4-20, 20-4				⇒	0-20					
Update rate: Background read											

This parameter sets the output mode for terminals 10 and 12 as follows:

Parameter value	Parameter string	Mode
0	0-20	0-20mA
1	20-0	20-0mA
2	4-20	4-20mA
3	20-4	20-4mA
4*	VoLt	Not useable

*Only with Commander SK and not useable.

x.40		Analogue input 1 level									
RO	Bi						NC	PT			
↕	0.0 to 100.0%				⇒						
Update rate: 4ms write											

This parameter displays the level of the analogue signal present at analogue input 1.

x.41		Analogue input 1 scaling								
RW	Uni								US	
↕	0 to 4.000				⇒	1.000				
Update rate: Background read										

This parameter is used to scale the analogue input if so desired.

x.42		Analogue input 1 invert									
RW	Bit									US	
↕	OFF (0) or On (1)				⇒	OFF (0)					
Update rate: Background read											

This parameter can be used to invert the analogue input reference (i.e. multiply the input scaling result by -1).

x.43		Analogue input 1 destination									
RW	Uni		DE						US		
↕	Pr 0.00 to Pr 21.51				⇒	Pr 0.00					
Update rate: Read on reset											

Only unprotected parameters can be controlled by analogue inputs. If a non valid parameter is programmed to the destination, the input is not routed anywhere.

x.45*		Analogue output 2 scaling									
RW	Uni									US	
↕	0.000 to 4.000				⇒	1.000					
Update rate: Background read											

***Parameter not available with Commander SK.**

This parameter can be used to scale the analogue output if so desired.

x.47*		Analogue output 2 source									
RW	Uni									US	
↕	Pr 0.00 to Pr 21.51					⇒	Pr 0.00				
Update rate: Read on reset											

***Parameter not available with Commander SK (Analogue output 2 is a load output only [Pr 4.02]).**

The parameter required to be represented as an analogue signal by the analogue output on terminal 12, should be programmed into this parameter.

x.48		Analogue output 1 source									
RW	Uni									US	
↕	Pr 0.00 to Pr 21.51					⇒	Pr 0.00				
Update rate: Read on reset											

The parameter required to be represented as an analogue signal by the analogue output on terminal 10, should be programmed into this parameter.

x.49		Analogue output 1 scaling									
RW	Uni									US	
↕	0.000 to 4.000				⇒	1.000					
Update rate: Background read											

This parameter can be used to scale the analogue output if so desired.

x.50		Solutions Module error status							
RO	Uni					NC	PT		
↕	0 to 255				⇒				
Update rate: Background read									

The error status is provided so that only one option error trip is required for each Solutions Module slot. If an error occurs, the reason for the error is written to this parameter and the drive may produce a 'SLx.Er' trip, where x is the slot number (SL.Er on Commander SK). A value of zero indicates that the Solutions Module has not detected an error, a non-zero value indicates that an error has been detected. (See Chapter 6 *Diagnostics* for the meaning of the values in this parameter.) When the drive is reset, this parameter is cleared for the relevant Solutions Module.

This Solutions Module includes a temperature monitoring circuit. If the PCB temperature exceeds 90°C, the drive fan is forced to operate at full speed (for a minimum of 10s). If the temperature falls below 90°C, the fan can operate normally again. If the PCB temperature exceeds 100°C, the drive is tripped and the error status is set to 74.

NOTE

If the PCB temperature exceeds 90°C on the Commander SK, the fan will operate at full speed for a minimum of 20s.

x.51		Solutions Module software sub-version							
RO	Uni					NC	PT		
↕	0 to 99				⇒				
Update rate: Write on power-up									

This module contains two processors, and thus two software versions. Pr **x.02** shows the version number of the main module processor. Pr **x.51**, which is normally used to give a sub-version number, shows the software version in the slave processor, which operates on the PELV side of the isolation barrier.

6 Diagnostics

If the drive trips, the output is disabled so that the drive stops controlling the motor. The display indicates that a trip has occurred as shown in Figure 6-1 and Figure 6-3.

Trips are listed in section 6.2 *Unidrive SP trip descriptions* on page 39 and section 6.3 *Commander SK trip descriptions* on page 40 based on the trip indication shown on the drive display. Refer to Figure 6-1 for Unidrive SP and Figure 6-3 for Commander SK. If a display is not used on the Unidrive SP, the drive LED Status indicator will flash if the drive has tripped. Refer to Figure 6-2.

The trip indication can be read in Pr 10.20 providing a trip number.

6.1 Displaying the trip history

6.1.1 Unidrive SP

The drive retains a log of the last 10 trips that have occurred in Pr 10.20 to Pr 10.29 and the corresponding time for each trip in Pr 10.43 to Pr 10.51. The time of the trip is recorded from the powered-up clock (if Pr 6.28 = 0) or from the run time clock (if Pr 6.28 = 1).

Pr 10.20 is the most recent trip, or the current trip if the drive is in a trip condition (with the time of the trip stored in Pr 10.43). Pr 10.29 is the oldest trip (with the time of the trip stored in Pr 10.51). Each time a new trip occurs, all the parameters move down one, such that the current trip (and time) is stored in Pr 10.20 (and Pr 10.43) and the oldest trip (and time) is lost from the bottom of the log.

If any parameter between Pr 10.20 and Pr 10.29 inclusive is read by serial communications, then the trip number in section 6.2 *Unidrive SP trip descriptions* on page 39 is the value transmitted.

Figure 6-1 Unidrive SP keypad status modes

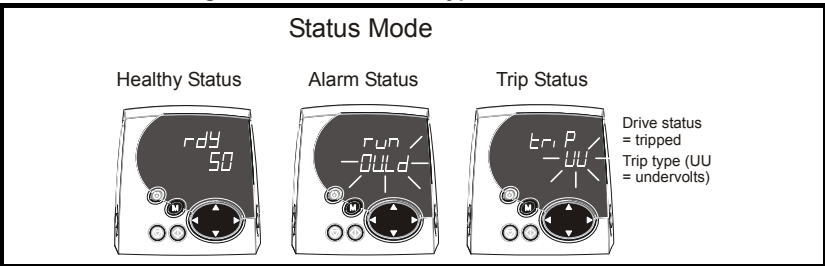
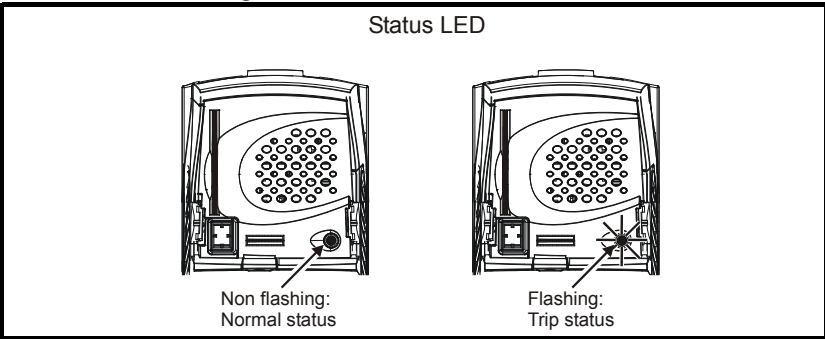


Figure 6-2 Location of the status LED



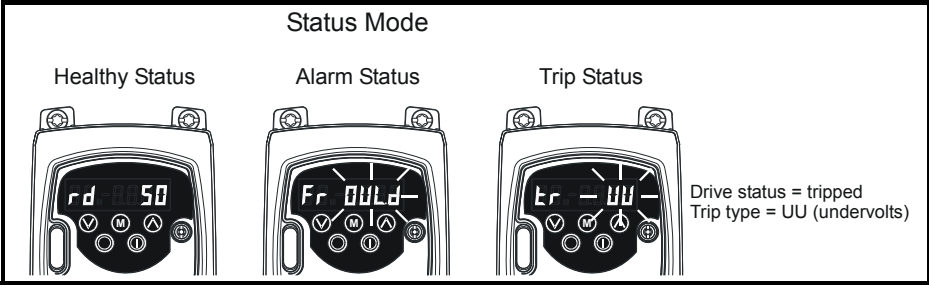
Any trip can be initiated by writing the relevant trip number to Pr **10.38**. If any trips shown as user trips are initiated the trip string is "txxx", where xxx is the trip number. Trips can be reset after 1.0s if the cause of the trip has been rectified. A full list of drive trips can be found in the *Unidrive SP User Guide*.

6.1.2 Commander SK

The drive retains a log of the last 10 trips that have occurred in Pr **10.20** to Pr **10.29**. Pr **10.20** is the most recent trip, or the current trip if the drive is in a trip condition, and Pr **10.29** is the oldest trip. Each time a new trip occurs, all the parameters move down one, such that the current trip (and time) is stored in Pr **10.20** and the oldest trip is lost from the bottom of the log.

If any parameter between Pr **10.20** and Pr **10.29** inclusive is read by serial communications, then the trip number in section 6.3 *Commander SK trip descriptions* on page 40 is the value transmitted.

Figure 6-3 Commander SK keypad status modes



Any trip can be initiated by writing the relevant trip number to Pr **10.38**. If any trips shown as user trips are initiated the trip string is "t0xx", where xx is the trip number. Trips can be reset after 1.0s if the cause of the trip has been rectified. A full list of drive trips can be found in the *Commander SK Advanced User Guide*.

6.2 Unidrive SP trip descriptions

Trip no.	String	Diagnosis														
200, 205, 210	SLX.HF	Solutions Module hardware fault Ensure Solutions Module is fitted correctly Return Soltutions Module to supplier														
201, 206, 211	SLX.tO	Solutions Module watchdog time-out Press reset If the trip persists, contact the supplier of the drive														
202, 207, 212	SLX.Er	Error detected with Solutions Module where X is the slot number <table><tr><th>Pr x.50</th><th>Fault description</th></tr><tr><td>0</td><td>No errors</td></tr><tr><td>1</td><td>Digital outputs overloaded</td></tr><tr><td>2</td><td>Digital inputs overloaded</td></tr><tr><td>3</td><td>Analogue input trip (4-20.tr/20-4.tr). (Occurs when input is <3.0mA.)</td></tr><tr><td>4</td><td>PELV user power supply absent</td></tr><tr><td>74</td><td>Solutions Module over temperature (>100°C)</td></tr></table>	Pr x.50	Fault description	0	No errors	1	Digital outputs overloaded	2	Digital inputs overloaded	3	Analogue input trip (4-20.tr/20-4.tr). (Occurs when input is <3.0mA.)	4	PELV user power supply absent	74	Solutions Module over temperature (>100°C)
Pr x.50	Fault description															
0	No errors															
1	Digital outputs overloaded															
2	Digital inputs overloaded															
3	Analogue input trip (4-20.tr/20-4.tr). (Occurs when input is <3.0mA.)															
4	PELV user power supply absent															
74	Solutions Module over temperature (>100°C)															
203, 208, 213	SLX.nF	Solutions Module has been removed Ensure Solutions Module is fitted correctly Save parameters and reset drive Replace Solutions Module														
204, 209, 214	SLX.dF	Solutions Module fitted in slot X has changed Save parameters and reset														
215	SL.rtd	Drive mode has changed and Solutions Module parameter routing is now incorrect Press reset If the trip persists, contact the supplier of the drive														

The 'PELV user power supply absent trip' will detect when the PELV user power supply connected to the module is below 19V. During power-up the PELV user power supply may not be present until after the main drive supply has been established. To avoid unwanted trips in this situation, the PELV user power supply trip detection system is disabled until after the supply has become active for the first time. Therefore, if the supply is applied and then removed again, a trip is initiated. The trip is also initiated at any time after drive power-up when the supply is not present and the drive becomes active (i.e. Pr **10.02** is one). This condition prevents the drive from operating whilst the PELV user power supply is not present. The status of the PELV user power supply can be monitored by using Pr **x.06** (0=inactive, 1=active).

6.3 Commander SK trip descriptions

Trip no.	String	Diagnosis														
200	SL.HF	Solutions Module hardware fault Ensure Solutions Module is fitted correctly Return Solutions Module to supplier														
201	SL.tO	Solutions Module watchdog time-out Press reset If the trip persists, contact the supplier of the drive														
202	SL.Er	Error detected with Solutions Module <table><tr><th>Pr x.50</th><th>Fault description</th></tr><tr><td>0</td><td>No errors</td></tr><tr><td>1</td><td>Digital outputs overloaded</td></tr><tr><td>2</td><td>Digital inputs overloaded</td></tr><tr><td>3</td><td>Analogue input trip (4-20/20-4). (Occurs when input is <3.0mA.)</td></tr><tr><td>4</td><td>PELV user power supply absent</td></tr><tr><td>74</td><td>Solutions Module over temperature (>100°C)</td></tr></table>	Pr x.50	Fault description	0	No errors	1	Digital outputs overloaded	2	Digital inputs overloaded	3	Analogue input trip (4-20/20-4). (Occurs when input is <3.0mA.)	4	PELV user power supply absent	74	Solutions Module over temperature (>100°C)
Pr x.50	Fault description															
0	No errors															
1	Digital outputs overloaded															
2	Digital inputs overloaded															
3	Analogue input trip (4-20/20-4). (Occurs when input is <3.0mA.)															
4	PELV user power supply absent															
74	Solutions Module over temperature (>100°C)															
203	SL.nF	Solutions Module has been removed Ensure Solutions Module is fitted correctly Replace Solutions Module														
204	SL.dF	Solutions Module fitted has changed Power down and back up														

For further information on the above trips, see Menu 10 in the *Commander SK Advanced User Guide*.

7 Terminal specification

NOTE Digital inputs are positive logic only.

1	0V
----------	-----------

2	+24V input
Nominal voltage	+24V
Minimum operating voltage	+19V
Maximum operating voltage	+30V
Current consumption with outputs loaded	150mA @ 30V

NOTE The SM-I/O PELV +24V input has an in-built fuse to provide protection in case of a serious internal failure.

3	Digital I/O 1
4	Digital I/O 2
5	Digital I/O 3
6	Digital I/O 4*
Type	Programmable positive logic digital input or output
Operating as an input	
Absolute maximum voltage range	±30V
Load	>2mA @ 15Vdc
Input switching threshold	10V ±0.8V
Operating as an output	
Maximum output current	40mA
Total of all 4 outputs	40mA
Output voltage when +24V input is 19V	16.5V
Output voltage when +24V input is 30V	27V
Typical input current @ 15V	2.8mA
Typical input current @ 5V	0.9mA

7	Digital input 5/freeze input**
Type	Positive logic digital input
Absolute maximum voltage range	±30V
Load	>2mA @ 15Vdc
Input switching threshold	10V to ±0.8V
Typical input current @ 15V	2.8mA
Typical input current @ 5V	0.9mA

*Digital input 4 only with Commander SK

**Freeze input not available with Commander SK.

8	Analogue input 1 non-inverting input	
9	Analogue input 1 inverting input	
Type of input	Bipolar Voltage Input / Unipolar Differential Current Input (for single ended use, connect terminal 9 to terminal 11)	
Parameter range	0-20, 20-0, 4-20.tr (4-20), 20-4.tr (20-4), 4-20 (4-20), 20-4 (20-4), VoLt (VoLt)	
Input impedance	100Ω @ 20mA (Current Mode) / 20kΩ (Voltage Mode)	
Resolution	10 bit	
Scale accuracy	5% of full scale (Current Mode) / 5% Typical Gain Accuracy (Voltage Mode)	
Maximum offset	±800μA / ±50mV typical	
Range	0 to 20mA (Current Mode) / ±10 (Voltage Mode)	
Absolute maximum current	±70mA	

10	Analogue output 1	
Type of output	Unipolar current source	
Current range	0-20, 20-0, 4-20, 20-4 (mA)	
Maximum offset (0Ω load)	±1mA typical	
Maximum output voltage for stated accuracy	12V	
Maximum load resistance	600Ω	
Resolution	12 bits	
Scale accuracy	5%	

11	0V
-----------	-----------

12	Analogue output 2	
Type of output	Unipolar current source	
Current range	0-20, 20-0, 4-20, 20-4 (mA)	
Maximum offset (0Ω load)	±1mA typical	
Maximum output voltage for stated accuracy	12V	
Maximum load resistance	600Ω	
Resolution	12 bits	
Scale accuracy	5%	

13	0V
-----------	-----------

14	Relay 1 contact 1	Normally open contacts
15	Relay 1 contact 2	
16	Relay 2 contact 1	
17	Relay 2 contact 2	
Contact maximum current rating		2A AC 50V rms 6A DC 30V resistive load (1.5A DC 60V for UL requirement) 0.3A DC 50V inductive load (L/R = 40ms)
Contact minimum recommended rating		12V 100mA



Provide fuse or other over-current protection in relay circuit.



The relay contacts give galvanic isolation from all other drive circuits and PELV isolation from the drive power circuits. They do not provide additional safety isolation from other PELV circuits on the Solutions Module.

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