

Function code	Function	Description(setting range)	Factory default																																																																								
P00.37	S1 type	<p>One place: 0: Positive logic 1: Reverse logic 2: Rising edge 3: Falling edge</p> <p>Tens place: 1: Rising edge toggle 2: Falling edge toggle</p> <p>Hundreds place: 1: The edge signal is not cleared by other edge signals</p> <p>Thousands place: 1: The edge signal is not cleared by the stop signal</p> <p>Function: select external terminal trigger type * Principle explanation: One place: 0: positive logic, High level is valid state, low level is invalid state; 1: Reverse logic, High level is invalid state, low level is valid state; 2: Rising edge, the rising edge is valid; 3: Falling edge, falling edge is valid.</p> <p>Tens place: 1: Rising edge ping-pong key; 2: Toggle on the falling edge.</p> <p>The tens position can control the edge signal and realize a reset button to control start and stop.</p> <p>Hundreds place: 1: The edge signal is not cleared by other edge signals; 2: The edge signal is not cleared by the stop signal.</p> <p>Thousands place: 1: The edge signal is not cleared by the stop signal.</p> <p>*two-line mode 1: the mode is most commonly used two-line mode, enable and direction combined, K1 and K2 control forward/reverse of motor</p> <table border="1"> <thead> <tr> <th>parameter no.</th> <th>setting value</th> <th>description</th> </tr> </thead> <tbody> <tr> <td>P00.30</td> <td>3</td> <td>start command source is S1</td> </tr> <tr> <td>P00.31</td> <td>4</td> <td>reverse start command source is S2</td> </tr> <tr> <td>P00.37</td> <td>0</td> <td>S1 type is positive logic</td> </tr> <tr> <td>P00.38</td> <td>0</td> <td>S2 type is negative logic</td> </tr> </tbody> </table> <p>*two-line mode 2: enable and direction separated, in this mode K1 is enable terminal, direction is controlled by K2.</p> <table border="1"> <thead> <tr> <th>parameter no.</th> <th>setting value</th> <th>description</th> </tr> </thead> <tbody> <tr> <td>P00.30</td> <td>3</td> <td>start command source is S1</td> </tr> <tr> <td>P00.32</td> <td>4</td> <td>reverse command source is S2</td> </tr> <tr> <td>P00.37</td> <td>0</td> <td>S1 type is positive logic</td> </tr> <tr> <td>P00.38</td> <td>0</td> <td>S2 type is positive logic</td> </tr> </tbody> </table> <p>*three line mode 1: this mode define SB2 as enable terminal, operation command is generated by SB1 or SB3, control operation direction at the same time. inverter is running and SB2 is in closed state, terminal SB1 or SB3 generates a rising edge signal to control inverter operation and direction; disconnection SB2 to stop inverter.</p> <table border="1"> <thead> <tr> <th>parameter no.</th> <th>setting value</th> <th>description</th> </tr> </thead> <tbody> <tr> <td>P00.30</td> <td>3</td> <td>start command source is S1</td> </tr> <tr> <td>P00.31</td> <td>5</td> <td>reverse start command source is S3</td> </tr> <tr> <td>P00.34</td> <td>4</td> <td>stop command source is S2</td> </tr> <tr> <td>P00.37</td> <td>2</td> <td>S1 type is rising edge</td> </tr> <tr> <td>P00.38</td> <td>1</td> <td>S2 type is negative logic</td> </tr> <tr> <td>P00.39</td> <td>2</td> <td>S3 type is rising edge</td> </tr> </tbody> </table> <p>*three line mode 2: this mode define SB2 as enable terminal, operation command is generated by SB1, direction command is controlled by K. inverter is running and SB2 is in closed state, terminal B1 generates a rising edge signal to control inverter operation, K control operation direction; disconnection SB2 to stop inverter.</p> <table border="1"> <thead> <tr> <th>parameter no.</th> <th>setting value</th> <th>description</th> </tr> </thead> <tbody> <tr> <td>P00.30</td> <td>3</td> <td>start command source is S1</td> </tr> <tr> <td>P00.32</td> <td>5</td> <td>reverse command source is S3</td> </tr> <tr> <td>P00.34</td> <td>4</td> <td>stop command source is S2</td> </tr> <tr> <td>P00.37</td> <td>2</td> <td>S1 terminal command type is rising edge</td> </tr> <tr> <td>P00.38</td> <td>1</td> <td>S2 terminal command type is negative logic</td> </tr> <tr> <td>P00.39</td> <td>0</td> <td>S3 terminal command type is positive logic</td> </tr> </tbody> </table>	parameter no.	setting value	description	P00.30	3	start command source is S1	P00.31	4	reverse start command source is S2	P00.37	0	S1 type is positive logic	P00.38	0	S2 type is negative logic	parameter no.	setting value	description	P00.30	3	start command source is S1	P00.32	4	reverse command source is S2	P00.37	0	S1 type is positive logic	P00.38	0	S2 type is positive logic	parameter no.	setting value	description	P00.30	3	start command source is S1	P00.31	5	reverse start command source is S3	P00.34	4	stop command source is S2	P00.37	2	S1 type is rising edge	P00.38	1	S2 type is negative logic	P00.39	2	S3 type is rising edge	parameter no.	setting value	description	P00.30	3	start command source is S1	P00.32	5	reverse command source is S3	P00.34	4	stop command source is S2	P00.37	2	S1 terminal command type is rising edge	P00.38	1	S2 terminal command type is negative logic	P00.39	0	S3 terminal command type is positive logic	0
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P00.41	AI1 low side voltage(current)	- 999999.000~999999.000 function: analog input AI1 setting *AI1 low side voltage(current): set the lowest voltage(current) of input signal. *AI1 high side voltage(current): set the highest voltage(current) of input signal.	0.000V(mA)
P00.42	AI1 high side voltage(current)	*AI1 low side setting: set corresponding value of low side voltage(current). *AI1 high side setting: set corresponding value of high side voltage(current).	10.000V(mA)
P00.43	AI1 low side setting	range setting AI1 high side setting AI1 terminal setting AI1 low side setting P00.43	0.000%
P00.44	AI1 high side setting	AI1 high side setting P00.44 AI1 terminal setting AI1 low side setting P00.43	100.000%
P00.45	AO1 signal source	0:always 0 1:always 10V/20mA 2:output frequency 3: motor current 4:output voltage 5: motor torque 6:output power 7:setting frequency 100~9999:high level parameter * principal interpretation: AO1 signal source function description as below:	2
P00.46	AO1 low side setting	- 999999.000~999999.000 * AO1 low side setting: set AO1 source minimum value. * AO1 high side setting: set AO1 source maximum value. * AO1 low side voltage(current): set the lowest voltage(current) of output signal. * AO1 high side voltage(current): set the highest voltage(current) of output signal.	0.000
P00.47	AO1 high side setting	range setting AO1 high side setting P00.47 AO1 terminal setting AO1 low side setting P00.46	50.000
P00.48	AO1 low side voltage(current)	AO1 high side voltage setting P00.48 AO1 terminal setting AO1 low side setting P00.46	0.000V(mA)
P00.49	AO1 high side voltage(current)	AO1 high side setting P00.47 AO1 terminal setting AO1 low side setting P00.46	10.000V(mA)
P00.50	PID proportional gain	0.000%~10.000% Determine the adjustment intensity of the whole PID regulator, bigger proportional gain is, bigger adjustment intensity is.	0.010%
P00.51	PID integral gain	0.001s~9999.000s Determine PID regulator to the integral speed adjustment of the division of PID feedback quantity and given quantity, smaller integral gain is, greater adjustment intensity is.	10.000s
P00.52	PID output upper limit	-1000.000%~1000.000% PID adjust the output maximum value, if higher than maximum value, then output PID output upper limit, relative to P0.11 maximum setting value percentage.	100.000%
P00.53	PID output lower limit	-1000.000%~1000.000% PID adjust the output minimum value, if lower than minimum value, then output PID output lower limit, relative to P0.11 maximum setting value percentage.	0.000%
P00.54	PID range	0.001%~9999.000% set according to actual feedback value, if lower than feedback value, then PID invalid.	100.000
P00.55	PID dormancy frequency	0.000%~500.000% set dormancy accurate frequency, relative to P0.11 maximum setting value percentage.	0.000%
P00.56	PID enter dormancy time	0.000s~3600.000s inverter reach enter dormancy time and meet to dormancy time, enter dormancy.	0.000s
P00.57	PID wakeup deviation	0.000%~100.000% percentage based on setting value.	0.000%
P00.58	PID enter wakeup time	0.000s~3600.000s inverter reach wakeup deviation and meet to wakeup time, operation again.	0.000s
P00.59	PID dormancy action	0: no dormancy; 1: PID stop; 2: decelerate to stop; 3: free stop; 4: pause; 5: operate in lowest frequency; PID enter dormancy according to setting dormancy action.	0
P00.60	startup function	0: start frequency operation 1: speed start 2: DC injection * principle interpretation: 0: no frequency output startup mode, meet to P00.61 startup time setting, P00.62 start frequency start to startup operation. 1: speed start, search rotating motor speed, smooth start without impact from search speed. 2: DC injection, inverter startup by "DC injection before startup" mode.	0
P00.61	startup time	0.000s~60000.000s principle interpretation: when system startup, setting start function work within setting start time.	0.000s
P00.62	start frequency	0.000Hz~100.000Hz principle interpretation: start function finish, if setting frequency bigger than start frequency, system start from start frequency; if setting frequency smaller than start frequency, system start from starting frequency.	0.000Hz
P00.63	DC injection current	0.000%~200.000% function: set magnitude of DC injection current. (set P00.60*2 as DC injection) * principle interpretation: start mode is DC injection, need to set magnitude of DC braking current, 100% corresponding to inverter rated current.	100.000%
P00.64	stop function	units: 0: free stop; 1: DC braking; tens: 1: accurate stop * principle interpretation: during stop process, stop function starts work when output frequency smaller than stop frequency. accurate stop: stop at any speed motor rotation turns are same, realize consistent repeatability of stop position. To get the best efficiency, deceleration time not to trigger over pressure and over loss rate prevention function as long as possible.	0
P00.65	stop frequency	0.000Hz~1000.000Hz interpretation refer to 0.64	0.000Hz
P00.66	DC braking current	0.000%~300.000% set DC braking current.	100.000%
P00.67	DC braking time	0.000s~1000.000s set DC braking time.	0.000s
P00.68	braking resistor mode	0: invalid 1: valid function: braking resistor braking mode parameter set	1
P00.70	control mode	0: V/F 1: vector control 1 function: select motor control algorithm	1
P00.71	carrier frequency	2kHz~16kHz function: set carrier frequency	*kHz
P00.72	motor power	0.000kW~100000.000kW function: set motor parameters	*kW
P00.73	motor voltage	0V~1000V function: set motor parameters	*V
P00.74	motor frequency	1Hz~3000Hz function: set motor parameters	*Hz
P00.75	motor current	0.00A~1000.00A function: set motor parameters	*A
P00.76	motor speed	10rpm~65535rpm function: set motor parameters	*rpm
P00.78	VF curve-F1	0.0Hz~3000.0Hz	50.0Hz
P00.79	VF curve-F2	* principle interpretation: set V/F curve under V/F control mode. When vector control 1 is adopted, set the corresponding frequency points of V/F curve to adjust control characteristics of the corresponding control points.	50.0Hz
P00.80	VF curve-F3	50.0Hz	50.0Hz
P00.81	VF curve-F4	50.0Hz	50.0Hz
P00.82	VF curve-V0	0V~1000V	0V
P00.83	VF curve-V1	* principle interpretation: set V/F curve under V/F control mode. When vector control 1 is adopted, set the corresponding voltage points of V/F curve to adjust control characteristics of the corresponding control points.	*V
P00.84	VF curve-V2	*V	*V
P00.85	VF curve-V3	*V	*V
P00.86	VF curve-V4	*V	*V
P01.41	local address	0~247 function: set inverter local address	1
P01.42	baud rate	0: 2400bps 1: 4800bps 2: 9600bps 3: 19200bps 4: 38400bps 5~10: reserved function: Communication port configuration	3

Function code	Function	Description(setting range)	Factory default
P01.43	odd-even check	0: no check 1: even check 2: odd check function: Communication port configuration	0
P01.44	data bits	7~8 function: Communication port configuration	8bits
P01.45	stop bits	0.0~2.0 function: Communication port configuration	1.0bit
P01.47	parameter decimal place mode	0~123 units: 0: remain decimal place, 1: decimal place change to 2 places, 2: decimal place change to 1 place, 3: no decimal place tens: 0: remain decimal place, 1: decimal place change to 1 place, 2: no decimal place; hundreds' digit: 0: remain decimal place, 1: no decimal place; * principle interpretation: parameter decimal place mode only work to communication, which change parameter value during communication transmission. * P01.47 units aim at parameters with 3 decimal places: 0: remain decimal place, 1: decimal place change to 2 places, 2: decimal place change to 1, 3: no decimal place. * P01.47 tens aim to parameters with 2 decimal places: 0: remain decimal place, 1: decimal place change to 1 place, 2: no decimal place. * P01.47 hundreds' digit aim to parameters with 1 place: 0: remain decimal place, 1: no decimal place.	0
P01.63	keyboard setting source	0: keyboard digital setting; 1: keyboard potentiometer setting; * principle interpretation: select keyboard setting value source, digit setting (P02.92) or keyboard potentiometer.	1
P02.03	(UP) command source	units: keyboard; tens: communication; hundreds' digit: S1; thousands' digit: S2; ...	0
P02.04	(DOWN) command source	units: keyboard; tens: communication; hundreds' digit: S1; thousands' digit: S2; ...	0
P10.61	history fault no. 1	-	0
P10.62	history fault no. 2	-	0
P10.63	history fault no. 3	-	0
P11.10	output frequency upon current fault	-	0.0Hz
P11.11	output current upon current fault	-	0.00A
P11.12	bus voltage upon current fault	-	0.0V
P11.13	inverter temperature upon current fault	-	0°C
P11.14	S terminal status upon current fault	-	0
P11.15	Y terminal status upon current fault	-	0
P11.16	cumulative running time upon current fault	-	0h

NO.6 Fault code

Fault Code	Protection function	Description
E0001	protection function	inverter components fault or software fault
E0004	ground fault	Abnormal resistance to ground, cause electric leakage
E0005	short circuit to ground	short circuit to ground
E0006	output short circuit	inverter cut off output when inverter output current is 250% larger than inverter rated current.
E0007	output over current	inverter cut off output when inverter output current is 200% larger than inverter rated current.
E0008	DC bus over voltage	inverter cut off output if main circuit DC voltage is higher than 400V(220V motor type) or 800V(380V motor type) when motor decelerates.
E0009	DC bus low voltage	input voltage decrease, inverter cut off output if main circuit DC voltage too low.
E0010	inverter over heat	inverter cut off output if cooling fin is over heat.
E0011	self-learning failure	self-learning parameter wrong or motor abnormal.
E0013	rectifier over heat	rectifier module over heat.
E0014	U phase loss	output U phase loss.
E0015	V phase loss	output V phase loss.
E0016	W phase loss	output W phase loss.
E0019	no motor connect	motor lost connection during operation.
E0020	input phase loss	power input phase loss.
E0021	inverter over load	inverter cut off output when inverter output current exceed inverter rated level (150% 60S).
E0022	over torque	motor over torque
E0024	motor over heat	motor temperature is over heat.
E0025	motor over load	inverter cut off output when inverter output current exceed motor rated level (150% 60S).
E0026	current limit	output current exceed setting limit threshold.
E0027	Input power down	The input voltage is lower than the power down standard value (P05.86)
E0033	ST0	Safe torque output stop function operation
E0034	ST1	Alarm of ST1 internal circuit diagnosis
E0035	ST2	Alarm of ST2 internal circuit diagnosis
E0036	ST3	Alarm of internal circuit diagnosis
E0063	user fault	user defined fault(P03.08)

Note: The alarm code is compared to the above table, for example: the keyboard displays "A0025" which means the motor overload alarm.