



SV660P Series Servo Drive Troubleshooting Guide



Industrial
Automation



Intelligent
Elevator



New Energy
Vehicle



Industrial
Robot



Rail
Transit



Data code 19011907B00

Preface

Introduction

Thank you for purchasing the SV660P series servo drive developed by Inovance.

The SV660P series high-performance AC servo drive covers a power range from 50 W to 7.5 kW. The servo drive, which covers a power range from 0.05 kW to 7.5 kW, supports Modbus, CANopen and CANlink communication protocols and carries necessary communication interfaces to operate with the host controller for a networked operation of multiple servo drives.

The drive supports adaptive stiffness level setting, inertia auto-tuning, and vibration suppression for easy use. Used with a small- or medium-inertia MS1 series high response servo motor (23-bit absolute single- or multi-turn encoder), it can offer quieter operation and more precise positioning control.

The drive serves to achieve quick and accurate position control, speed control, and torque control in automation equipment such as electronic manufacturing devices, manipulators, packing devices, and machine tools.

This guide Introduces faults and fault levels, the troubleshooting process, warning codes and fault codes.

More Data

Data name	Data Code	Description
SV660P series servo drive selection guide	19011390	Provides instructions on product selection, including the list of supporting components, technical data on the drive and motor, and the selection guide of cables.
SV660P series servo drive hardware guide	19011391	Presents electrical design guidance of the equipment, description of terminals, required certificates and standards and solutions to common EMC problems.
SV660P Series Servo Drive Commissioning Guide	19011392	Presents servo commissioning, parameter descriptions, troubleshooting, including the operating panel, commissioning software, commissioning procedure and a parameter list.
SV660P Series Servo Drive Function Guide	19011393	Presents functions and parameters, including function overview, basic servo functions, adjustment and parameter list.

Data name	Data Code	Description
SV660P Series Servo Drive Communication Guide	19012201	Presents functions and parameters of the servo drive, including Modbus communication configuration, parameter descriptions, and communication application cases.
SV660P Series Servo Drive Troubleshooting Guide	19011907	Introduces faults and fault levels, the troubleshooting process, warning codes and fault codes.
SV660P Series Servo Drive Safety Guide	19011884	Presents the safety function and related certifications and standards, wiring, commissioning process, troubleshooting, and functions.
SV660P Series Servo Drive Manual Package	PS00005513	Provides information on selection, installation, commissioning, function, troubleshooting and parameters of the equipment.

Revision History

Date	Version	Description
2023-03	B00	Updated information on faults according to the latest fault list.
2023-01	A01	<ul style="list-style-type: none"> ● Added warranty information in the preface. ● Updated information on faults. ● Modified the description of fault logging.
2022-08	A00	First release

Document acquisition

This guide is not delivered along with the product. You can download the PDF version in the following means:

- <http://www.inovance.com>.
- Scan the QR code on the equipment to acquire more.

Warranty agreement

Inovance provides warranty services within the warranty period (as specified in your order) for any fault or damage that is not caused by improper operation. You will be charged for any repair work after the warranty period expires.

The warranty does not cover any damage caused by:

- your failure to operate the product in accordance with the user guide
- events beyond our reasonable control, such as fire, flood and abnormal voltage
- function misuse
- out-of-range application

- other events of force majeure, including but not limited to lightning, earthquake and other extreme weather events

The maintenance fee is charged according to the latest Maintenance Price List of Inovance. If otherwise agreed upon, the agreed terms and conditions shall prevail.

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General Safety Instructions

Safety Precautions

- This section explains the safety precautions that need to be observed to use this product correctly. Before using this product, please read the instruction manual and correctly understand the relevant information of safety precautions. Failure to comply with the safety precautions may result in death, serious injury, or equipment damage.
- "CAUTION", "WARNING", and "DANGER" items in the guide only indicate some of the precautions that need to be followed; they just supplement the safety precautions.
- Use this equipment according to the designated environment requirements. Damage caused by improper use is not covered by warranty.
- Inovance shall take no responsibility for any personal injuries or property damage caused by improper use.

Safety Levels and Definitions



Indicates that failure to comply with the notice will result in death or severe personal injuries.



Indicates that failure to comply with the notice may result in death or severe personal injuries.



Indicates that failure to comply with the notice may result in minor or moderate personal injuries or equipment damage.

General Safety Instructions

- Drawings in the selection guide are sometimes shown without covers or protective guards. Remember to install the covers or protective guards as specified first, and then perform operations in accordance with the instructions. Install the covers or protective guards as specified, and use the equipment in accordance with the instructions described in the user guide.
- The drawings in the guide are shown for illustration only and may be different from the product you purchased.

Unpacking

 WARNING

- Do not install the equipment if you find damage, rust, or signs of use on the equipment or accessories upon unpacking.
- Do not install the equipment if you find water seepage or missing or damaged components upon unpacking.
- Do not install the equipment if you find the packing list does not conform to the equipment you received.

 CAUTION

- Check whether the packing is intact and whether there is damage, water seepage, dampness, and deformation before unpacking.
- Unpack the package by following the unpacking sequence. Do not strike the package violently.
- Check whether there is damage, rust, or injuries on the surface of the equipment and equipment accessories before unpacking.
- Check whether the package contents are consistent with the packing list before unpacking.

Storage and Transportation

 WARNING

- Large-scale or heavy equipment must be transported by qualified professionals using specialized hoisting equipment. Failure to comply may result in personal injuries or equipment damage.
- Before hoisting the equipment, ensure the equipment components such as the front cover and terminal blocks are secured firmly with screws. Loosely-connected components may fall off and result in personal injuries or equipment damage.
- Never stand or stay below the equipment when the equipment is being hoisted by the hoisting equipment.
- When hoisting the equipment with a steel rope, ensure the equipment is hoisted at a constant speed without suffering from vibration or shock. Do not turn the equipment over or let the equipment stay hanging in the air. Failure to comply may result in personal injuries or equipment damage.

 CAUTION

- Handle the equipment with care during transportation and mind your steps to prevent personal injuries or equipment damage.
- When carrying the equipment with bare hands, hold the equipment casing firmly with care to prevent parts from falling. Failure to comply may result in personal injuries.
- Store and transport the equipment based on the storage and transportation requirements. Failure to comply will result in equipment damage.
- Avoid storing or transporting the equipment in environments with water splash, rain, direct sunlight, strong electric field, strong magnetic field, and strong vibration.
- Avoid storing the equipment for more than three months. Long-term storage requires stricter protection and necessary inspections.
- Pack the equipment strictly before transportation. Use a sealed box for long-distance transportation.
- Never transport the equipment with other equipment or materials that may harm or have negative impacts on this equipment.

Installation DANGER

- The equipment can be operated by well-trained and qualified professionals only. Non-professionals are not allowed.

 WARNING

- Read through the guide and safety instructions before installation.
- Do not install this equipment in places with strong electric or magnetic fields.
- Before installation, check that the mechanical strength of the installation site can bear the weight of the equipment. Failure to comply will result in mechanical hazards.
- Do not wear loose clothes or accessories during installation. Failure to comply may result in an electric shock.
- When installing the equipment in a closed environment (such as a cabinet or casing), use a cooling device (such as a fan or air conditioner) to cool the environment down to the required temperature. Failure to comply may result in equipment over-temperature or a fire.
- Do not retrofit the equipment.
- Do not fiddle with the bolts used to fix equipment components or the bolts marked in red.
- When the equipment is installed in a cabinet or final assembly, a fireproof enclosure providing both electrical and mechanical protections must be provided. The IP rating must meet IEC standards and local laws and regulations.
- Before installing devices with strong electromagnetic interference, such as a transformer, install a shielding device for the equipment to prevent malfunction.
- Install the equipment onto an incombustible object such as a metal. Keep the equipment away from combustible objects. Failure to comply will result in a fire.

 CAUTION

- Cover the top of the equipment with a piece of cloth or paper during installation. This is to prevent unwanted objects such as metal chippings, oil, and water from falling into the equipment and causing faults. After installation, remove the cloth or paper on the top of the equipment to prevent over-temperature caused by poor ventilation due to blocked ventilation holes.
- Resonance may occur when the equipment operating at a constant speed executes variable speed operations. In this case, install the vibration-proof rubber under the motor frame or use the vibration suppression function to reduce resonance.

Wiring

 DANGER

- Equipment installation, wiring, maintenance, inspection, or parts replacement must be performed only by professionals.
- Before wiring, cut off power connections with all equipment. Residual voltage exists after power cut-off. Therefore, wait at least the time designated on the equipment warning label before further operations. Measure the DC voltage of the main circuit and make sure it is below the safe voltage, otherwise there will be the danger of electric shock.
- Do not perform wiring, remove the equipment cover, or touch the circuit board with power ON. Failure to comply will result in an electric shock.
- Check that the equipment is grounded properly. Failure to comply will result in an electric shock.

 WARNING

- Do not connect the input power supply to the output end of the equipment. Failure to comply will result in equipment damage or even a fire.
- When connecting a drive to the motor, check that the phase sequences of the drive and motor terminals are consistent to prevent reverse motor rotation.
- Cables used for wiring must meet cross sectional area and shielding requirements. The shield of the cable must be reliably grounded at one end.
- Fix the terminal screws with the tightening torque specified in the user guide. Improper tightening torque may overheat or damage the connecting part, resulting in a fire.
- After wiring is done, check that all cables are connected properly and no screws, washers or exposed cables are left inside the equipment. Failure to comply may result in an electric shock or equipment damage.

 CAUTION

- During wiring, follow the proper electrostatic discharge (ESD) procedure, and wear an antistatic wrist strap. Failure to comply will damage the equipment or the internal circuits of the equipment.
- Use shielded twisted pairs for the control circuit. Connect the shield to the grounding terminal of the equipment for grounding purpose. Failure to comply will result in equipment malfunction.

Power-on



- Before power-on, check that the equipment is installed properly with reliable wiring and the motor can be restarted.
- Check that the power supply meets equipment requirements before power-on to prevent equipment damage or a fire.
- After power-on, do not open the cabinet door or protective cover of the equipment, touch any terminal, or disassemble any unit or component of the equipment. Failure to comply will result in an electric shock.



- Perform a trial run after wiring and parameter setting to ensure the equipment operates safely. Failure to comply may result in personal injuries or equipment damage.
- Before power-on, make sure that the rated voltage of the equipment is consistent with that of the power supply. Failure to comply may result in a fire.
- Before power-on, check that no one is near the equipment, motor, or machine. Failure to comply may result in death or personal injuries.

Operation



- The equipment must be operated only by professionals. Failure to comply will result in death or personal injuries.
- Do not touch any connecting terminals or disassemble any unit or component of the equipment during operation. Failure to comply will result in an electric shock.







- Do not touch the equipment casing, fan, or resistor with bare hands to feel the temperature. Failure to comply may result in personal injuries.
- Prevent metal or other objects from falling into the equipment during operation. Failure to comply may result in a fire or equipment damage.

Maintenance



- Equipment installation, wiring, maintenance, inspection, or parts replacement must be performed only by professionals.
- Do not maintain the equipment with power ON. Failure to comply will result in an electric shock.
- Before maintenance, cut off all the power supplies of the equipment and wait for at least the time designated on the equipment warning label.
- In case of a permanent magnet motor, do not touch the motor terminals immediately after power-off because the motor terminals will generate induced voltage during rotation even after the equipment power supply is off. Failure to comply will result in an electric shock.

 WARNING
<ul style="list-style-type: none">• Perform routine and periodic inspection and maintenance on the equipment according to maintenance requirements and keep a maintenance record.
Repair
 DANGER
<ul style="list-style-type: none">• Equipment installation, wiring, maintenance, inspection, or parts replacement must be performed only by professionals.• Do not repair the equipment with power ON. Failure to comply will result in an electric shock.• Before inspection and repair, cut off all the power supplies of the equipment and wait for at least the time designated on the equipment warning label.
 WARNING
<ul style="list-style-type: none">• Submit the repair request according to the warranty agreement.• When the fuse is blown or the circuit breaker or earth leakage current breaker (ELCB) trips, wait for at least the time designated on the equipment warning label before power-on or further operations. Failure to comply may result in death, personal injuries or equipment damage.• When the equipment is faulty or damaged, the troubleshooting and repair work must be performed by professionals that follow the repair instructions, with repair records kept properly.• Replace quick-wear parts of the equipment according to the replacement instructions.• Do not use damaged equipment. Failure to comply may result in death, personal injuries, or severe equipment damage.• After the equipment is replaced, check the wiring and set parameters again.
Disposal
 WARNING
<ul style="list-style-type: none">• Dispose of retired equipment in accordance with local regulations and standards. Failure to comply may result in property damage, personal injuries, or even death.• Recycle retired equipment by observing industry waste disposal standards to avoid environmental pollution.

Additional Precautions


Cautions for the dynamic brake

- Dynamic braking can only be used for emergency stop in case of failure and sudden power failure. Do not trigger failure or power failure frequently.
- Ensure that the dynamic braking function has an operation interval of more than 5 minutes at high speed, otherwise the internal dynamic braking circuit may be damaged.

- Dynamic braking is common in rotating mechanical structures. For example, when a motor has stopped running, it keeps rotating due to the inertia of its load. In this case, this motor is in the regenerative state and short-circuit current passes through the dynamic brake. If this situation continues, the drive, and even the motor, may be burned.

Safety Label

For safe equipment operation and maintenance, comply with the safety labels on the equipment. Do not damage or remove the safety labels. See the following table for descriptions of the safety labels.

Safety Label	Description
 <p>危険 DANGER</p> <p>高压注意 Hazardous Voltage</p> <p>高温注意 High Temperature</p>	<ul style="list-style-type: none"> • Never fail to connect the protective earth (PE) terminal. Read through the guide and follow the safety instructions before use. • Never fail to connect Protective Earth (PE) terminal. Read the manual and follow the safety instructions before use. • Do not touch terminals within 15 minutes after disconnecting the power supply to prevent the risk of electric shock. • Do not touch terminals with 15 minutes after Disconnect the power. Risk of electrical shock. • Do not touch the heatsink with power ON to prevent the risk of burn. • Do not touch heatsink when power is ON. Risk of burn.

1 Fault Level and Display

Faults and warnings of the servo drive are divided into three levels based on severity: No. 1 > No. 2 > No. 3, as shown below.

- No. 1 non-resettable fault
- No. 1 resettable fault
- No. 2 resettable fault
- No. 3 resettable warning

Note

"Resettable" means the keypad stops displaying the fault/warning once a "Reset signal" is input.

Fault and warning log

The servo drive can record the latest 20^[1] faults and warnings and values of status parameters upon fault/warning. If a repeated fault or warning is present in the latest 5 records, the repeated fault can be logged more than once after being cleared.

A fault/warning will still be saved in the fault log after reset. To remove the fault/warning from the fault log, set H02.31 to 1. The following figure shows the details.



Read the value of H0b.34 to get the fault/warning code. See examples in the following table.

H0b.34 (hexadecimal)	Description of H0b.34 (hexadecimal)
0101	0: Fault subcode 101: Fault Code

Note

[1]: To show 20 fault records: The MCU software version is required to be 6.3 and above, and the commissioning software must be the latest.

2 Troubleshooting During Startup

Position control mode

- Fault diagnosis

Start process	Symptom	Cause	Confirming Method
Turn on the control power L1C, L2C Main power supply (L1, L2) (L1, L2, L3) (R, S, T)	The LED neither lights up nor displays "rdy".	1.Control power voltage fault	The fault persists though CN1, CN2, CN3, and CN4 are disconnected. Measure the AC voltage between L1C and L2C.
		2.Mains voltage fault	<ul style="list-style-type: none"> ● For single-phase 220 V models, measure the AC voltage between L1 and L2. When the DC bus voltage amplitude (voltage between P⊕ and N⊖) is lower than 235 V, the keypad displays "nrd". ● For three-phase 220 V/380 V models, measure the AC voltage among L1, L2, L3/R, S, T. When the DC bus voltage amplitude (voltage between P⊕ and N⊖) is lower than 451 V, the keypad displays "nrd".
		3.Programming terminal is shorted	Check whether the programming terminal is shorted.
		4.The servo drive is faulty.	-
	The keypad displays "Exxx.x".	Rectify the fault causes according to "5.1 Solutions to Faults" on page 41 and "Solutions to Warnings" on page 24 .	
The keypad displays "rdy" after preceding faults are cleared.			
Switching on the S-ON signal (S-ON signal switched on)	The keypad displays "Exxx.x".	Rectify the fault causes according to "5.1 Solutions to Faults" on page 41 and "Solutions to Warnings" on page 24 .	
	The servo motor shaft is in the free running state.	1.The S-ON signal is inactive.	Switch the keypad display to the servo status interface and view whether the keypad displays "rdy" instead of "run". <ul style="list-style-type: none"> ● Check parameters in groups H03 or H17 to see whether FunIN.1 (S-ON) is assigned to a DI. If FunIN.1 is assigned, check whether the corresponding DI logic is active. If FunIN.1 is not assigned, assign FunIN.1 to a DI and activate the logic of this DI. See parameter settings for Groups H03 and H17 in the SV660P Series Servo Drive Function Guide. ● If the keypad keeps displaying "rdy" even though the S-ON signal has been assigned to a DI through parameters in group H03 or H17 and the corresponding DI logic is active, check whether the DI is connected correctly according to Chapter "Wiring" in SV660P Series Servo Drive Hardware Guide.
		2.Wrong control mode	Check whether H02.00 (Control mode selection) is set to 1 (Position control mode). If it is set to 2 (Torque control mode), the motor shaft will be in the free running state because the default torque reference is 0.
The keypad displays "run" after preceding faults are cleared.			

Start process	Symptom	Cause	Confirming Method
Inputting position references	The servo motor does not rotate.	The value of the input position reference counter (H0b.13) is 0.	<ul style="list-style-type: none"> ● The high/low-speed pulse input terminal is wired incorrectly. When H05.00 (Position reference source) is set to 0, check whether the high/low-speed pulse input terminal is connected correctly according to section "Description of Terminals" . Additionally, check whether the setting of H05.01 (Pulse reference input terminal selection) is matched. ● No position reference is inputted. ● Check whether FunIN.13 (Inhibit, position reference inhibited) or FunIN.37 (PulseInhibit, pulse reference inhibited) is used. ● When H05.00 (Position reference source) is set to 0 (Pulse input) but no pulse is received from the host controller or other pulse output device, check whether there are pulses input to the high/low-speed pulse input terminal with an oscilloscope. See section Description of Terminals for details. ● When H05.00 (Position reference source) is set to 1 (Step reference), check whether H05.05 (Step reference) is 0. If not, check whether FunIN.20 (PosStep, step reference enabled) is assigned to a DI and whether the logic of this DI is active. ● When H05.00 (Position reference source) is set to 2 (Multi-position reference), check whether parameters in group H11 are set correctly. If yes, check whether FunIN.28 (PosInSen, internal multi-position enable) is assigned to a DI, and whether the logic of this DI is active. ● If interrupt positioning is used, check whether H05.29 (Interrupt positioning cancellation) is set to 1 (Enabled). If yes, check whether FunIN.29 (XintFree, interrupt positioning cancellation) is used.
Inputting position references	The servo motor rotates in the reverse direction.	The value of the input position reference counter (H0b.13) is a negative number.	<ul style="list-style-type: none"> ● When H05.00 (Position reference source) is set to 0 (Pulse reference), check whether the setting of H05.15 (Pulse reference form) is consistent with the actual input pulses. If not, H05.15 is set improperly or terminals are wired incorrectly. ● When H05.00 (Position reference source) is set to 1 (Step reference), check whether the value of H05.05 (Step reference) is positive or negative. ● When H05.00 (Position reference source) is set to 2 (Multi-position reference), check the sign (+/-) of each displacement reference value in parameter group H11. ● Check whether FunIN.27 (PosDirSel, position reference direction selection) is assigned to a DI and whether the logic of this DI is active. ● Check whether H02.02 (Direction of rotation) is set properly.
The servo motor can rotate after preceding faults are cleared.			

Start process	Symptom	Cause	Confirming Method
Rotating unstably at low speed	The motor speed is unstable during low-speed operation.	Gains are set improperly.	See section Adjustments for automatic gain adjustment.
	The motor shaft vibrates leftward and rightward.	The load moment of inertia ratio (H08.15) is excessively high.	If the motor can operate safely , perform inertia auto-tuning and gain auto-tuning according to section "Adjustment".
	The servo motor can rotate properly after preceding fault are cleared.		
Running normally	The positioning is inaccurate.	The position deviation is beyond the permissible range.	Check the position reference counter (H0b.13), feedback pulse counter (H0b.17), and the mechanical stop position according to the following procedure.

● **Procedure for checking the causes of inaccurate positioning**

●

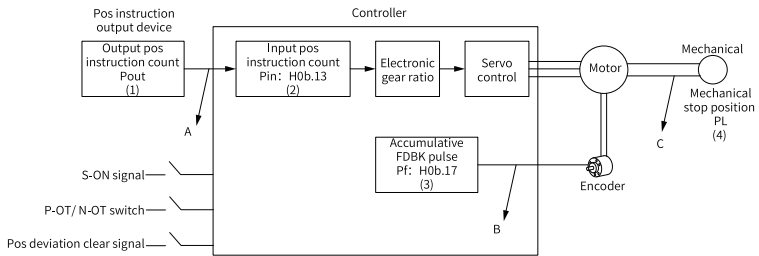


Figure 2-1 Schematic diagram for positioning control

- When inaccurate positioning occurs, check the following four signals in the preceding figure.
 - Output position reference count value (Pout) in the position reference output device (host controller or internal parameters of the servo drive)
 - Input position reference count value (Pin) received by the servo drive, corresponding to H0b.13 (Position reference counter)
 - Accumulative pulse feedback value (Pf) returned by the encoder, corresponding to H0b.17 (Feedback pulse counter)
 - Mechanical stop position (PL)
- The A, B, C shown in the preceding figure represent the three causes that lead to inaccurate positioning.
 - A: A position reference count error occurs due to the noise in the wiring of the host controller and the servo drive.
 - B: Input position reference is interrupted during motor running.
Cause: Servo ON signal (S-ON) is set to OFF, the positive/negative limit switch signal (P-OT or N-OT) is ON and the position deviation clearing signal (ClrPosErr) is ON.

- C: Mechanical position slides between machine and servo motor.
- In an ideal scenario where the position deviation is 0, the following relations exist:
 - $P_{out} = P_{in}$: Output position reference count value = Input position reference count value
 - $P_{in} \times \text{Electronic gear ratio} = P_f$: Input position reference count value \times Electronic gear ratio = Accumulative pulse feedback
 - $P_f \times \Delta L = PL$: Accumulative pulse feedback \times Load displacement per position reference = Mechanical stop position
- When inaccurate positioning occurs, check the causes based on the following steps:

- $P_{out} \neq P_{in}$
Cause: A

To rectify cause A, do as follows:

1. Check if twisted pair shielded cables are connected to pulse input terminals (For low or high speed pulse input terminals, see section "Description of Terminals").
2. If the open-collector input mode for low-speed pulse input terminals is used, change to the differential input mode.
3. Route pulse input terminals and the main circuit terminals (L1, L2/R, S, T/ U, V, W) through different routes.
4. If low-speed pulse input terminals are used, increase the filter time constant of low-speed pulse input pins (H0A.24). If high-speed pulse input terminals are used, increase the filter time constant of the high-speed pulse input pins (H0A.30).

- $P_{in} \times \text{Electronic gear ratio} \neq P_f$:
Cause: B

To rectify cause A, do as follows:

1. Check whether a fault occurs during operation, causing the servo drive to stop before executing all the commands.
2. If the fault is caused by an active position deviation clear signal (ClrPosErr), check whether the position deviation clear mode (H05.16) is proper.

- $P_f \times \Delta L \neq PL$:
Cause: C

To rectify cause A, do as follows: Check mechanical connections and find the position where the relative slip occurs.

Speed Control Mode

Start process	Symptom	Cause	Confirming Method
Turn on the control power L1C, L2C Main power supply (L1, L2) (L1, L2, L3) (R, S, T)	The LED neither lights up nor displays "rdy".	1.Control power voltage fault	The fault persists though CN1, CN2, CN3, and CN4 are disconnected. Measure the AC voltage between L1C and L2C.
		2.Input voltage error	<ul style="list-style-type: none"> For single-phase 220 V models, measure the AC voltage between L1 and L2. When the DC bus voltage amplitude (voltage between P⊕ and N⊖) is lower than 235 V, the keypad displays "nrd". For three-phase 220 V/380 V models, measure the AC voltage among L1, L2, L3/R, S, T. When the DC bus voltage amplitude (voltage between P⊕ and N⊖) is lower than 451 V, the keypad displays "nrd".
		3.Programming terminal is shorted	Check whether the programming terminal is shorted.
		4.The servo drive is faulty.	-
	The keypad displays "Exxx.x".	Rectify the fault causes according to "5.1 Solutions to Faults" on page 41 and "Solutions to Warnings" on page 24 .	
The keypad displays "rdy" after preceding faults are cleared.			
Switching on the S-ON signal (S-ON signal switched on)	The keypad displays "Exxx.x".	Rectify the fault causes according to "5.1 Solutions to Faults" on page 41 and "Solutions to Warnings" on page 24 .	
	The servo motor shaft is in the free running state.	1.The S-ON signal is inactive.	Switch the keypad display to the servo status interface and view whether the keypad displays "rdy" instead of "run". <ul style="list-style-type: none"> Check parameters in groups H03 or H17 to see whether FunIN.1 (S-ON) is assigned to a DI. If FunIN.1 is assigned, check whether the corresponding DI logic is active. If FunIN.1 is not assigned, assign FunIN.1 to a DI and activate the logic of this DI. See parameter settings for Groups H03 and H17 in the SV660P Series Servo Drive Function Guide. If the keypad keeps displaying "rdy" even though the S-ON signal has been assigned to a DI through parameters in group H03 or H17 and the corresponding DI logic is active, check whether the DI is connected correctly according to section "Description of Terminals" .
		2.Wrong control mode	Check whether H02.00 (Control mode selection) is set to 0 (Position control mode). If it is set to 2 (Torque control mode), the motor shaft will be in the free running status because the default torque reference is 0.
The keypad displays "run" after preceding faults are cleared.			

Start process	Symptom	Cause	Confirming Method
Inputting speed references	The servo motor does not rotate or the motor speed is incorrect.	The speed reference (H0b.01) is 0.	<ul style="list-style-type: none"> • The speed reference selected is wrong. Check whether H06.02 (Speed reference selection) is set correctly. • No speed reference is inputted or the speed reference is abnormal. • When the speed reference is set through the keypad, check whether H06.03 (Speed reference set through keypad) is set correctly. • When the speed reference is set through multi-speed references, check whether parameters in group H12 are set correctly. • When the speed reference is set through communication, check whether H31.09 (Speed reference set through communication) is set correctly. • When the speed reference is set through jog speed references, check whether H06.04 (Jog speed) is set correctly and whether FunIN.18 (JOGCMD+, forward jog) and FunIN.19 (JOGCMD, reverse jog) are assigned to DIs and whether the DI logics are active. • Check whether H06.05 (Acceleration time constant of speed reference) and H06.06 (Deceleration time constant of speed reference) are set correctly. • Check whether the FunIN.12 (ZCLAMP, zero clamp) is misassigned and whether the active logic of the corresponding DI is correct.
Inputting speed references	The servo motor rotates in the reverse direction.	The value of the speed reference (H0b.01) is a negative number.	<ul style="list-style-type: none"> • When the speed reference is set through the keypad, check whether the value of H06.03 (Speed reference set through keypad) is lower than 0. • When the speed reference is set through multi-speed references, check the sign (+/-) of each speed reference value in group H12. • When the speed reference is set through communication, check whether the value of H31.09 (Speed reference set through communication) is lower than 0. • When the speed reference is set through jog speed references, check whether the value of H06.04 (Jog speed) and the active logics of FunIN.18 (JOGCMD+, forward jog) and FunIN.19 (JOGCMD-, reverse jog) match the desired direction of rotation. • Check whether FunIN.26 (SpdDirSel, speed reference direction selection) is assigned to a DI and whether the logic of the DI is active. • Check whether H02.02 (Direction of rotation) is set properly.
The servo motor can rotate after preceding faults are cleared.			
Rotating unstably at low speed	The motor speed is unstable during low-speed operation.	Gains are set improperly.	See section Adjustments for automatic gain adjustment.
	The motor shaft vibrates leftward and rightward.	The load moment of inertia ratio (H08-15) is excessively high.	If the motor can operate safely, perform inertia auto-tuning according to section Adjustment. See section Adjustments for automatic gain adjustment.

Torque control mode

Start process	Symptom	Cause	Confirming Method
Switch on the control power supply (L1C, L2C) Main power supply (L1, L2) (L1, L2, L3) (R, S, T)	The LED neither lights up nor displays "rdy".	1.Control power voltage fault	The fault persists though CN1, CN2, CN3, and CN4 are disconnected. Measure the AC voltage between L1C and L2C.
		2.Mains voltage fault	<ul style="list-style-type: none"> For single-phase 220 V models, measure the AC voltage between L1 and L2. When the DC bus voltage amplitude (voltage between P⊕ and N⊖) is lower than 235 V, the keypad displays "nrd". For three-phase 220 V/380 V models, measure the AC voltage among L1, L2, L3/R, S, T. When the DC bus voltage amplitude (voltage between P⊕ and N⊖) is lower than 451 V, the keypad displays "nrd".
		3.Programming terminal is shorted	Check whether the programming terminal is shorted.
		4.The servo drive is faulty.	-
	The keypad displays "Exxx.x".	Rectify the fault causes according to "5.1 Solutions to Faults" on page 41 and " Solutions to Warnings" on page 24 .	
The keypad displays "rdy" after preceding faults are cleared.			
Switching on the S-ON signal (S-ON signal switched on)	The keypad displays "Exxx.x".	Rectify the fault causes according to "5.1 Solutions to Faults" on page 41 and " Solutions to Warnings" on page 24 .	
	The servo motor shaft is in the free running state.	The S-ON signal is inactive.	<ul style="list-style-type: none"> Switch the keypad display to the servo status interface and view whether the keypad displays "rdy" instead of "run". Check parameters in groups H03 or H17 to see whether FunIN.1 (S-ON) is assigned to a DI. If FunIN.1 is assigned, check whether the corresponding DI logic is active. If FunIN.1 is not assigned, assign FunIN.1 to a DI and activate the logic of this DI. See parameter settings for Groups H03 and H17 in the SV660P Series Servo Drive Function Guide. If the keypad keeps displaying "rdy" even though the S-ON signal has been assigned to a DI through parameters in group H03 or H17 and the corresponding DI logic is active, check whether the DI is connected correctly according to section Description of Terminals.
	The keypad displays "run" after preceding faults are cleared.		

Start process	Symptom	Cause	Confirming Method
Inputting torque references	The servo motor does not rotate.	The internal torque reference (H0b.02) is 0.	<p>The torque reference selected is wrong. Check whether H07.02 (Torque reference source) is set correctly. No torque reference is inputted.</p> <ul style="list-style-type: none"> When the torque reference is set through the keypad, check whether H07.03 (Torque reference set through keypad) is set to 0. When the torque reference is set through communication, check whether H31.11 (Torque reference set through communication) is set to 0.
	The servo motor rotates in the reverse direction.	The value of the internal torque reference (H0b.02) is a negative number.	<ul style="list-style-type: none"> When the torque reference is set through keypad, check whether the value of H07.03 (Torque reference set through keypad) is lower than 0. When the torque reference is set through communication, check whether the value of H31.11 (Torque reference set through communication) is lower than 0. Check whether FunIN.25 (ToqDirSel, speed reference direction selection) is assigned and whether the corresponding DI logic is active. Check whether H02.02 (Direction of rotation) is set properly.
	The servo motor can rotate after preceding faults are cleared.		
Rotating unstably at low speed	The motor speed is unstable during low-speed operation.	Gains are set improperly.	Perform gain auto-tuning.
	The motor shaft vibrates leftward and rightward.	The load moment of inertia ratio (H08.15) is excessively high.	<p>If the servo motor can operate safely, perform inertia auto-tuning again.</p> <p>Perform gain auto-tuning.</p>

3 Fault Reset

Faults and warnings of the servo drive are divided into three levels based on severity: No. 1 > No. 2 > No. 3, as shown below.

- No. 1 non-resettable fault
 - No. 1 resettable fault
 - No. 2 resettable fault
 - No. 3 resettable warning
-

Note

"Resettable" means the keypad stops displaying the fault/warning once a "Reset signal" is input.

Operating procedure:

- To stop the keypad from displaying the fault/warning, set H0d.01 (Fault reset) to 1 or activate the DI terminal assigned with DI function 2 (FunIN.2: ALM- RST, fault and warning reset).
 - To reset No. 1 and No. 2 faults, switch off the S-ON signal, and then set H0d.01 to 1 or activate the DI terminal allocated with DI function 2.
 - To reset No. 3 warnings, set H0d.01 to 1 or activate the DI terminal allocated with DI function 2.
-

Note

- Some faults and warnings can be reset only after the fault causes are rectified by modifying the settings. However, a reset operation does not necessarily activate the modifications to settings.
 - For modifications activated at next power-on (R, S, T/L1C, L2C powered on again), perform a power cycle.
 - For modifications activated after stop, switch off the S-ON signal. The servo drive can operate normally only after modifications are activated.
-

☆Related function No.

Start Process	Fault Symptom	Cause	Check method
FunIN.2	ALM-RST	Fault/Warning reset signal	<p>The servo drive may, depending on the warning types, continue running after warning reset. When FunIN.2 is assigned to a low-speed DI, the effective level change of this DI must be kept for more than 3 ms. Otherwise, fault reset will be inactive. Do not assign FunIN.2 to a high-speed DI. Otherwise, fault/warning reset will be inactive.</p> <ul style="list-style-type: none">• Inactive: Not resetting the fault/warning• Active: Resetting the fault/warning

4 Description of Warning Codes

- E108.0: Parameter write error

Description:

Parameter values cannot be written to EEPROM.

Possible Causes	Confirming Method	Solution
An error occurs during parameter-writing.	Modify a certain parameter, power off and on the servo drive again and check whether the modification is saved.	If the modification is not saved and the fault persists after the servo drive is powered off and on repeatedly, replace the servo drive.

- E108.1: Parameter read error

Description:

Parameter values cannot be read in EEPROM.

Possible Causes	Confirming Method	Solution
The parameter-read operation is abnormal, and the system indicates an EEPROM read failure.	Modify a certain parameter, power off and on the servo drive again and check whether the modification is saved.	If the modification is not saved and the fault persists after the servo drive is powered off and on repeatedly, replace the servo drive.

- E108.2: Invalid check on data written in EEPROM

Description:

The check on the data written in EEPROM fails.

Possible Causes	Confirming Method	Solution
An error occurs during parameter-writing.	Modify a certain parameter, power off and on the servo drive again and check whether the modification is saved.	If the modification is not saved and the fault persists after the servo drive is powered off and on repeatedly, replace the servo drive.

- E108.3: Invalid check on data read in EEPROM

Description:

The check on the data read in EEPROM fails.

Possible Causes	Confirming Method	Solution
An error occurs during parameter-reading.	Modify a certain parameter, power off and on the servo drive again and check whether the modification is saved.	If the modification is not saved and the fault persists after the servo drive is powered off and on repeatedly, replace the servo drive.

- E108.4: Single data is stored too many times

Description:

Single data is stored too frequently.

Possible Causes	Confirming Method	Solution
That may damage EEPROM over time.	<ol style="list-style-type: none"> 1. Check H0b.90 and H0b.91. H0b.90 shows the parameter in question or object dictionaries (in hexadecimal). If H0b.91=15, H0b.90 shows internal variables of software. 2. Check "Func Test 1" through the oscilloscope channel. Be sure to display it in hexadecimal. This channel displays the address that EEPROM is storing. 3. Check the storage count through the oscilloscope channel "Func Test 2". 	<ol style="list-style-type: none"> 1. If the alarm is caused by manually modifying a certain parameter or object dictionary, there will be no frequent storage of a certain data during operation, and you can reset the fault. 2. Check the parameter in question through H0b.90 or oscilloscope channel to locate the cause. For example: The host controller program frequently writes parameters through SDO, which problem can be solved by modifying the host controller program.

- E110.0: Frequency-division pulse output setting error

Description:

The number of frequency divisions (quadrupled) exceeds the motor revolutions

Possible Causes	Confirming Method	Solution
The number of frequency divisions (quadrupled) exceeds the motor revolutions	Check the setpoint of H05.17.	Adjust the value of H05.17 on the basis of the motor revolutions.

- E121.0: Invalid S-ON command

Description:

A redundant S-ON signal is sent when some auxiliary functions are used.

Possible Causes	Confirming Method	Solution
The Communication S-ON signal is active when servo drive is enabled internally.	Check whether auxiliary functions (H0D.02, H0D.03, and H0D.12) are used and DI function 1 (FunIN.1: S-ON signal) is active.	Deactivate the DI assigned with FunIN.1 (both hardware DI and virtual DI).

- E122.0: Multi-turn absolute encoder setting error

Description:

The motor does not match the absolute position mode or the motor code is set improperly.

Possible Causes	Confirming Method	Solution
The motor does not match the absolute position mode or the motor code is set incorrectly.	<ol style="list-style-type: none"> 1. Check the motor nameplate to see whether the motor is configured with a multi-turn absolute encoder. 2. Check whether H00.00 (motor code) is set properly. 	Reset H00.00 (motor code) according to the motor nameplate or use a suitable motor.

- E510.0: Frequency division pulse output overspeed

Description:

The single-channel output pulse frequency exceeds the frequency upper limit allowed by the hardware (4 MHz) when pulse output is used (H05.38 = 0/1/2).

Possible Causes	Confirming Method	Solution
The MCU detects excessive pulse increment fed back by FPGA.	When H05.38 is set to 0 (Encoder frequency-division output), check whether the output pulse frequency corresponding to the motor speed upon fault exceeds the limit. Output pulse frequency (Hz) = Motor speed (rpm)/60 x H05.17	Decrease the value of H05.17 (encoder frequency-division pulses) to allow the output pulse frequency, within the speed range required by the machine, to drop below the frequency upper limit allowed by the hardware.
	The input pulse frequency exceeds 2 MHz or interference exists in the pulse input pins when H05.38 is set to 1 (Reference pulse synchronous output). <ul style="list-style-type: none"> Low-speed pulse input pins: Open collector input terminals: PULLHI, PULSE+, PULSE-, SIGN+, SIGN-; maximum single-channel pulse frequency: 200 kpps. High-speed pulse input pins: Differential input terminals: HPULSE+, HPULSE-, HSIGN+, HSIGN-, maximum single-channel pulse frequency: 4 Mpps 	Decrease the input pulse frequency to a value within the frequency upper limit allowed by hardware. Note: In this case, if you do not modify the electronic gear ratio, the motor speed will be reduced. If the input pulse frequency is high but is still within the frequency upper limit allowed by the hardware, take anti-interference measures (use STP cable for pulse input and set pin filter parameter H0A.24 or H0A.30). This is to prevent false warnings caused by interference pulses superimposed to actual pulse references.

- E600.0: Inertia auto-tuning failure

Description:

Vibration cannot be suppressed. You can set notch parameters (H09.12...H09.23) manually to suppress vibration.

The auto-tuned values fluctuate dramatically. Increase the maximum operating speed, reduce the acceleration/deceleration time, and shorten the stroke of the lead screw during ETune operation.

Mechanical couplings of the load are loose or eccentric. Rectify the mechanical faults.

A warning occurs during auto-tuning and causes interruption. Rectify the fault causes and perform inertia auto-tuning again.

The vibration cannot be suppressed if the load carries a large inertia. In this case, increase the acceleration/deceleration time first to ensure the motor current is unsaturated.

Possible Causes	Confirming Method	Solution
<ol style="list-style-type: none"> 1. Continuous vibration occurs during auto-tuning. 2. The auto-tuned values fluctuate dramatically. 3. Mechanical couplings of the load are loose or eccentric. 4. A warning occurs during auto-tuning and causes interruption. 5. The vibration cannot be suppressed if the load carries a large inertia. In this case, increase the acceleration/deceleration time first to ensure the motor current is unsaturated. 	<ul style="list-style-type: none"> • Perform internal inspection to check whether the torque jitters upon stop (not FFT). • Check whether Three times more than the last auto-tuned value for variation less than 5 times; 0.5 times more than last auto-tuned value for variation above 5 times 	<ol style="list-style-type: none"> 1. Rectify the fault and perform inertia auto-tuning again. 2. For vibration that cannot be suppressed, enable vibration suppression. 3. Ensure mechanical couplings are connected securely. 4. Increase the maximum operating speed, reduce the acceleration/ deceleration time, and shorten the stroke of the lead screw during ETune operation.

- E601.0: Homing warning

Description:

The homing time exceeds the time set by H05.35.

Possible Causes	Confirming Method	Solution
1.The home switch fails.	There is only high-speed searching but no low-speed searching during homing. After high-speed searching, low-speed searching in the reverse direction applies.	If a hardware DI is used, check whether the corresponding DI function is assigned to a certain DI in group H03 and check the wiring of this DI. Change the DI logic manually and observe the value of H0b.03 to monitor whether the servo drive receives corresponding DI level changes. If the home signal is Z signal and the home signal cannot be found, check the condition of the Z signal.
2.The time limit for homing is too short.	Check whether the value of H05.35 (Time limit for homing) is too small.	Increase the value of H05.35.
3.The speed in high-speed searching for the home switch signal is too low.	Check the distance between the start position of homing and the home switch. Then check whether the setpoint of 6099-01h is too low, resulting in a long homing process.	Increase the value of 6099-01h.

- E601.1: Homing switch error

Description:

The homing switch is set improperly.

Possible Causes	Confirming Method	Solution
The homing switch is set improperly.	Check whether the limit signals at both sides are activated. Check whether the limit signal and the deceleration point signal/home signal are both activated. Check whether the positive and negative position limits are activated successively.	Set the position of the physical switch properly.

- E601.2: Homing mode setting error

Description:

The homing method value is too large.

Possible Causes	Confirming Method	Solution
The homing method value is too large.	Check if the homing method value exceeds the existent homing mode (technology segment homing, H22.70).	Adjust the value of H22.70.

- E730.0: Encoder battery warning

Description:

The battery voltage of the absolute encoder is lower than 3.0 V.

Possible Causes	Confirming Method	Solution
The battery voltage of the absolute encoder is lower than 3.0 V.	Measure the battery voltage.	Use a new battery with the matching voltage.

Note

E731.0 and E733.0 can trigger E730.0. See E731.0 and E733.0 for other solutions.

- E731.0: Encoder battery failure

Description:

The voltage of the absolute encoder battery is lower than 2.9 V.

Possible Causes	Confirming Method	Solution
1.The battery is not connected during power-off.	Check whether the battery is connected during power-off.	Set H0d.20 to 1 to clear the fault.
2.The encoder battery voltage is too low.	Measure the battery voltage.	Use a new battery with the matching voltage.

Note

1. Use H05.31 to first select the homing method, and then perform homing. The warning is automatically cleared after homing is completed.
 2. Set H05.30 = 6 to use the current position as the home, and the warning will be cleared immediately.
 3. Use DI to configure function 41 (with the current position as the home), and then trigger DI to be active, and the warning is cleared immediately.
-

- E831.1: AI1 zero offset too large

Description:

AI1 zero offset too large

Possible Causes	Confirming Method	Solution
1.The wiring is incorrect or interference exists.	Check the wiring according to the correct wiring diagram.	Use shielded twisted pairs and shorten the circuit length. Increase AI1 input filter time.
2.The servo drive is faulty.	Disconnect AI1 and measure whether the actual terminal voltage exceeds 0.5 V.	If not, replace the drive.

- E834.1: AI1 overvoltage

Description:

AI1 overvoltage

Possible Causes	Confirming Method	Solution
1.The wiring is incorrect or interference exists.	Check the wiring according to the correct wiring diagram	Use shielded twisted pairs and shorten the circuit length. Increase AI1 input filter time.
2.The input voltage is too high.	Measure whether the actual terminal voltage exceeds 11.5 V.	Adjust the input voltage to a value lower than 11.5 V.

- E900.0: Emergency braking

Description:

The logic of the DI terminal (including the hardware DI and virtual DI) allocated with DI function 34 (FunIN.34) is effective.

Possible Causes	Confirming Method	Solution
DI function 34: EmergencyStop is triggered.	Check DI function 34: Check whether the logic of the DI assigned with EmergencyStop is active.	Check the operation mode and clear the active DI braking signal without affecting the safety performance.

- E902.0: DI setting invalid

Description:

DI function parameters are set to invalid values.

Possible Causes	Confirming Method	Solution
DI1–DI8 function selections are invalid.	H0b.45=0x 0902, Check whether H03.02, H03.04, H03.06, H03.08, H03.10, H03.12, H03.14, and H03.16 are set to invalid values.	Set DI function parameters to valid values.

- E902.1: DO setting invalid

Description:

DO function parameters are set to invalid values.

Possible Causes	Confirming Method	Solution
DO1–DO5 function selections are invalid.	H0b.45= 0x 1902. Check whether H04.00, H04.02, H04.04, H04.06 and H04.08 are set to invalid values.	Set DO function parameters to valid values.

- E902.2: Torque reach setting invalid

Description:

The DO parameter set for torque reach in the torque control mode is invalid.

Possible Causes	Confirming Method	Solution
The DO parameter set for torque reach in the torque control mode is invalid.	Check whether the value of H07.22 is lower than or equal to the value of H07.23 (unit: 0.1%).	Set H07.22 to a value higher than that of H07.23.

- E908.0: Model identification failure

Description:

The model parameter identification check code failed.

Possible Causes	Confirming Method	Solution
1.The model identification check word saved in EEPROM is incorrect.	Check whether the warning persists after restart.	Set H01-72 to 1 to disable model identification temporarily.
2.The model parameters are not written in the drive before delivery.	Check whether parameters can be saved to EEPROM.	

- E909.0: Motor overload

Description:

Motor accumulated heat exceeds overload protection warning value.

Possible Causes	Confirming Method	Solution
1.The motor and encoder cables are connected improperly or in poor contact.	Check the wiring among the servo drive, servo motor and the encoder according to the correct wiring diagram.	Connect cables according to the correct wiring diagram. It is recommended to use the cables provided by Inovance. When customized cables are used, prepare and connect the customized cables according to the wiring instructions.
2.The load is so heavy that the effective torque outputted by the motor keeps exceeding the rated torque.	Confirm the overload characteristics of the servo drive or motor. Check whether the average load rate (H0b.12) keeps exceeding 100.0%.	Use a servo drive of higher capacity and a matching servo motor. Reduce the load and increase the acceleration/ deceleration time.
3.Acceleration/Deceleration is too frequent or the load inertia is too large.	Check the mechanical inertia ratio or perform inertia auto-tuning. View the value of H08.15 (load moment of inertia ratio). Confirm the individual operation cycle when the servo motor operates cyclically.	Increase the acceleration/ deceleration time.
4.Gains are improper or the stiffness level is too high.	Check whether the motor vibrates and generates unusual noise during operation.	Adjust the gains again.
5.The model of the servo drive or motor is set improperly.	View the model of the motor equipped with a serial-type encoder in H00.05 and the servo drive model in H01.10.	Read the servo drive nameplate and set the Servo servo drive model (H01.10) and motor model properly according to section "Servo Drive Model and Nameplate" in the Selection Guide.

Possible Causes	Confirming Method	Solution
6.The motor is stalled due to mechanical factors, resulting in overload during operation.	<p>Check the reference and the motor speed (H0b.00) through the software tool or the keypad.</p> <ul style="list-style-type: none"> References in the position control mode: H0b.13 (Position reference counter) References in the speed control mode: H0b.01 (Speed reference) References in the torque control mode: H0b.02 (Internal torque reference) <p>Check whether the reference value is not 0 or is very large but the motor speed is 0 RPM in the corresponding mode.</p>	Eliminate the mechanical factors.
7.The servo drive is faulty.	Power off and on the servo drive again.	Replace the servo drive if the fault persists after the servo drive is powered off and on again.

- E910.0: Control circuit overvoltage

Description:

Overvoltage occurred on the control circuit of the drive.

Possible Causes	Confirming Method	Solution
Overvoltage occurred on the control circuit of the drive.	<ol style="list-style-type: none"> 1. Measure whether the input voltage in the control circuit cable is within the following range: 220 V servo drive: Value range: 220 V to 240 V Allowable deviation: -10% to +10% (198 V to 264 V) 380 V servo drive: Value range: 380 V to 440 V Allowable deviation: -10% to +10% (342 V to 484 V) 2. Check whether control circuit cables are connected properly and whether the voltage of control circuit cables (L1C, L2C) is within the specified range. 	Re-connect or replace the cables.

- E920.0: The regenerative resistor is overloaded.
Description:

The accumulative heat of the regenerative resistor exceeds the set value.

Possible Causes	Confirming Method	Solution
1.The cable connected to the external regenerative resistor is in poor contact, disconnected or broken.	Remove the external regenerative resistor and measure whether its resistance is " ∞ " (infinite). Measure whether the resistance between terminals P \oplus and C is " ∞ " (infinite).	Replace the external brake resistor. Measure the resistance of the new resistor and ensure it is the same as the nominal value. Connect it between P \oplus and C.
		Use a suitable cable to connect both ends of the resistor to P \oplus and C.
2.When you use an internal regenerative resistor, the cable between the power terminal \oplus and D is broken or disconnected	Measure whether the resistance between terminals P \oplus and D is " ∞ " (infinite).	Ensure terminals P \oplus and D are jumpered.

Possible Causes	Confirming Method	Solution
3. H02.25 (Regenerative resistor type) is set improperly when an external regenerative resistor is used.	<ul style="list-style-type: none"> ● Check the setpoint of H02.25. ● Measure the resistance of the used resistor between P⊕ and C. Compare the result with the value of H02.25; ● Check whether H02.27 is greater than the resistance of the used resistor between P⊕ and C. 	Set H02.25 according to section Wiring and Setting of Regenerative Resistor in the Hardware Guide. H02.25 = 1 (external, naturally ventilated) H02.25 = 2 (external, forced-air cooling)
4. The resistance of the external regenerative resistor used is too large.		Select a proper regenerative resistor according to section "Specifications of the Regenerative Resistor" in the Commissioning Guide.
5. The setpoint of H02.27 (Resistance of external regenerative resistor) is higher than the resistance of the external regenerative resistor used.		Set H02.27 according to the resistance of the external regenerative resistor used.
6. The input voltage of the main circuit is beyond the specified range.	<p>Check whether the input voltage of the main circuit cable on the drive side is within the following range:</p> <ul style="list-style-type: none"> ● 220 V servo drive: Value range: 220 V to 240 V Allowable deviation: -10% to +10% (198 V to 264 V) ● 380 V servo drive: Value range: 380 V to 440 V Allowable deviation: -10% to +10% (342 V to 484 V) 	Replace or adjust the power supply according to the specified range.

Possible Causes	Confirming Method	Solution
7.The load moment of inertia is too large.	Perform moment of inertia auto-tuning according to section "Inertia auto-tuning" in the Function Guide or calculate the total mechanical inertia based on mechanical parameters. Check whether the actual load inertia ratio exceeds 30.	<ul style="list-style-type: none"> • Select an external regenerative resistor with large capacity and set H02.26 to a value consistent with the actual power. • Select a servo drive with large capacity. • Reduce the load if allowed. • Increase the acceleration/ deceleration time if allowed. • Increase the motor operation cycle if allowed.
8.The motor speed is excessively high and deceleration is not done within the set time. The motor is in the continuous deceleration status during cyclic operation.	View the motor speed curve during cyclic operation and check whether the motor is in the deceleration status continuously.	
9.The capacity of the servo drive or the regenerative resistor is insufficient.	View the motor speed curve in an individual cycle and calculate whether the maximum braking energy can be absorbed completely.	
10. The servo drive is faulty.	-	Replace with a new servo drive.

- E922.0: Resistance of the external regenerative resistor too small

Description:

The value of H02.27 (resistance of external regenerative resistor) is lower than the value of H02.21 (permissible min. resistance of external regenerative resistor).

Possible Causes	Confirming Method	Solution
When an external regenerative resistor is used (H02.25 = 1 or 2), the resistance of this resistor is lower than the minimum resistance allowed by the servo drive.	Measure whether the resistance of the external regenerative resistor between terminals P⊕ and C is lower than the value of H02.21 (Permissible minimum resistance of regenerative resistor).	<ul style="list-style-type: none"> • If yes, replace with an external regenerative resistor that matches the servo drive, then set H02.27 according to the resistance of the resistor used. Finally, connect the new resistor between P⊕ and C. • If not, set H02.27 to a value consistent with the resistance of the external regenerative resistor used.

- E924.0: Regenerative transistor over-temperature

Description:

The estimated temperature of the regenerative transistor is higher than H0A.18 (IGBT overtemperature threshold).

Possible Causes	Confirming Method	Solution
1.The junction temperature of the braking is too high. 2.The regenerative transistor will be turned off automatically after overload occurs.	The regenerative transistor temperature exceeds the threshold defined by H0A.49.	Control the working conditions and usage of the regenerative transistor.

- E941.0: Modified parameters activated at next power-on

Description:

The parameters modified are those whose "Effective time" is "Next power-on".

Possible Causes	Confirming Method	Solution
The parameters modified are those whose "Effective time" is "Next power-on".	Check whether parameters you modified are those whose "Effective Time" is "Next power-on".	Power off and on again.

- E942.0: Parameters saved frequently

Description:

The number of parameters modified at a time exceeds 200.

Possible Causes	Confirming Method	Solution
Too many parameters are modified and saved to EEPROM (H0C.13 = 1) at a brief interval.	Check whether parameters are modified through the host controller at a brief interval.	Check the operation mode. For parameters that need not be saved to EEPROM, set H0C.13 to 0.

- E950.0: Forward overtravel warning

Description:

The logic of the DI allocated with function 14 (FunIN.14, P-OT, positive overtravel switch) is valid.

Possible Causes	Confirming Method	Solution
1. DI function 14: P-OT (Positive limit switch) is valid.	<ul style="list-style-type: none"> • Check whether a certain DI in group H03 is assigned with FunIN.14. • Check whether the logic of DI corresponding to the bit of H0b.03 (Monitored DI status) is effective. 	Check the operation mode and on the prerequisite of ensuring safety, send a reverse run command or rotate the motor to deactivate the logic of the DI assigned with FunIN.14.
2.The servo position feedback reaches the positive software position limit.	Check whether the position feedback (H0b.17) is close to the value of H0A.41. Check whether the software position limit is set in H0A.40.	Check if the motor stroke needs to exceed the forward soft limit. If so, adjust the forward soft limit value; If not, adjust the motor stroke.

- E952.0: Reverse overtravel warning

Description:

The logic of the DI allocated with function 15 (FunIN.15, N-OT, negative overtravel switch) is valid.

Possible Causes	Confirming Method	Solution
1. DI function 15: Negative limit switch is valid.	<ul style="list-style-type: none"> • Check whether a certain DI in group H03 is assigned with FunIN.15. • Check whether the logic of DI corresponding to the bit of H0b.03 (Monitored DI status) is effective. 	Check the operation mode. On the prerequisite of ensuring safety, send a forward run command or rotate the motor to deactivate the logic of DI assigned with FunIN.15.
2.The servo position feedback reaches the negative software position limit.	Check whether the position feedback (H0b.17) is close to the value of H0A.43. Check whether the software position limit is set in H0A.40.	Check if the motor stroke needs to exceed the reverse soft limit. If so, adjust the reverse soft limit value; If not, adjust the motor stroke.

- E980.0: Encoder algorithm error

Description:

An encoder algorithm error occurs

Possible Causes	Confirming Method	Solution
An encoder algorithm error occurs	<ol style="list-style-type: none"> 1. Check the wiring. 2. If the servo drive is powered off and on several times but the warning is still reported, it indicates that the encoder is faulty. 	Replace the servo motor.

- E990.1: Pulse input overspeed warning

Description:

Pulse input overspeed warning.

Possible Causes	Confirming Method	Solution
Pulse input overspeed warning	Check the input pulse frequency.	Reduce input pulse frequency to within 4M.

- EA41.0: Torque fluctuation compensation failure

Description:

The torque compensation fails.

Possible Causes	Confirming Method	Solution
Auto-tuning torque fluctuation compensation failure	-	Turn off the torque fluctuation compensation function.

5 Fault Codes

5.1 Solutions to Faults

- E101.0: Abnormal parameters in groups H02 and above

Cause:

The total number of parameters changes, which generally occurs after software update.

Values of parameters in groups H02 and above exceed the limit, which generally occurs after software update.

Possible Causes	Confirming Method	Solutions
1.The voltage of the power supply used for the control circuit drops instantaneously.	1.Check whether the control circuit (L1C, L2C) is in the process of power-off or instantaneous power failure occurs.	Restore system parameters to default settings (H02.31 = 1) and write parameters again.
	2.Measure whether the input voltage of the control circuit cable on the non-drive side is within the following range: 220 V servo drive: Value range: 220 V to 240 V Allowable deviation: -10% to +10% (198 V to 264 V) 380 V servo drive: Value range: 380 V to 440 V Allowable deviation: -10% to +10% (342 V to 484 V)	Increase the power supply capacity or replace with a power supply of higher capacity. Restore system parameters to default settings (H02.31 = 1), and write parameters again.
2.Instantaneous power failure occurs during saving parameters.	Check whether instantaneous power failure occurs when saving parameters.	Power on the system again, restore system parameters to default settings (H02.31 = 1), and write parameters again.
3.The number of write operations within a certain period of time exceeds the limit.	1. Check whether instantaneous power failure occurs when saving parameters. 2. Check whether parameters are updated frequently through the host controller.	1. Power on the system, restore default settings (H02-31 = 1) and write parameters again. 2. Change the write mode and write parameters again. If the servo drive is faulty, replace it.

Possible Causes	Confirming Method	Solutions
4.The software is updated.	Check whether parameter values in group H02 and above exceed the upper/lower limit due to software update.	Reset the servo drive model and servo motor model, and restore system parameters to default settings (H02.31 = 1).
5.The servo drive is faulty.	If the fault persists though parameters are restored to default settings and the servo drive is powered off and on repeatedly, the servo drive is faulty.	Replace the servo drive.

- E101.1: Parameter error in group H00/H01

Cause:

The total number of parameters changes, which generally occurs after software update.

Values of parameters in groups H00 or H01 exceed the limit, which generally occurs after software update.

Possible Causes	Confirming Method	Solutions
The servo drive detects whether parameter values in groups H00 and H01 exceed the upper/lower limit during initialization upon power-on.	Check groups H00 and H01 to find the parameter whose value exceeds the limit. Confirm whether this parameter range is abnormal.	Set the servo drive model (H01.10) to a wrong value first and perform a power cycle, and then set the servo drive model to the correct value and perform a power cycle.

- E101.2: Address error in read/write operation after the number of parameters changes

Cause:

Address error in read/write operation after the number of parameters changes

Possible Causes	Confirming Method	Solutions
Address error in read/write operation after the number of parameters changes.	Read H0b.90 and H0b.91 and obtain the abnormal parameter group number.	Rectify the wrong values value or restore the factory settings.

- E101.9: Parameter attribute initialization check error.

Cause:

Parameter attribute initialization check error.

Possible Causes	Confirming Method	Solution
Parameter attribute initialization check error.	Check that H0A.99 = AA5C.	If the fault persists after repeated restart, replace the drive.

- E102.0: FPGA communication establishment error

Cause:

The communication between MCU and FPGA cannot be established.

Possible Causes	Confirming Method	Solutions
The communication between MCU and FPGA cannot be established.	The fault persists after repeated restart.	Replace the servo drive.

- E102.1: FPGA initialization start error

Cause:

FPGA failed.

Possible Causes	Confirming Method	Solution
FPGA cannot start.	The fault persists after repeated restart.	Replace the servo drive.

- E102.8: FPGA and MCU version mismatch

Cause:

The software versions of MCU and FPGA do not match.

Possible Causes	Confirming Method	Solutions
FPGA and MCU version mismatch	<ul style="list-style-type: none"> ● Check whether the MCU version number of H01.00 is: 9xx.x (the 4th digit on the panel screen is 9); ● Check whether the FPGA version number of H01.01 is: 9xx.x (the 4th digit on the panel screen is 9). 	Contact Inovance for technical support. Update the FPGA or MCU software.

- E104.1: MCU running timeout (MCU break down)

Cause:

MCU Access timeout (MCU break down).

Possible Causes	Confirming Method	Solutions
1. The MCU failed.	The fault persists after repeated restart.	Replace the servo drive.
2. Real-time communication error between MCU and FPGA.		

- E104.2: FPGA running timeout (FPGA break down).

Cause:

FPGA running timeout (FPGA break down).

Possible Causes	Confirming Method	Solutions
1.FPGA failure	The fault persists after repeated restart.	Replace the servo drive.
2. The communication handshake between the FPGA and the MCU is abnormal.		

- E104.4: MCU command update timeout

Cause:

Take the moment when interrupt starts as the starting time, if the time when commands are written to MCU is larger than the time when position and speed regulators are started by FPGA, a warning will be reported.

Possible Causes	Confirming Method	Solutions
The system reports that the encoder communication time is set improperly or the command calculation time is too long.	The fault persists after repeated restart.	1. Hide unnecessary functions. 2. Replace the servo drive.

- E120.0: Unknown encoder model

Cause:

The servo drive detects the encoder model during initialization upon power-on. If the encoder model does not comply with the requirement, E120.0 occurs.

Possible Causes	Confirming Method	Solutions
1.The product (motor or servo drive) code does not exist.	Read the nameplates of the servo drive and motor to check whether a SV660P drive and motor with a 23-bit encoder are used. Meanwhile, check whether H00.00 (Motor code) is set to 14101.	If the motor code is unknown, set H00.00 to 14101 when SV660P series servo drive and the motor equipped with a 23-bit encoder are used.
	Check the servo drive code (H01.02) to see whether this servo drive code exists.	If the drive code is absent, set the servo drive model correctly according to the nameplate.
2.The power rating of the motor does not match that of the servo drive.	Check whether the servo drive code (H01.02) matches the serial-type motor code (H00.05).	Replace the unmatched products.
The encoder type does not match the servo drive.	Check whether the encoder model is correct.	Set the motor code properly.

- E120.1: Unknown motor model

Cause:

The servo drive detects the motor model defined by H00.00 during initialization upon power-on. If the motor model does not exist, E120.1 occurs.

Possible Causes	Confirming Method	Solutions
The motor model (H00.00) is set improperly.	Check whether the value of H00.00 matches the used motor.	Rectify the value of H00.00.

- E120.2: Unknown drive model

Cause:

The servo drive detects the servo drive model defined by H01.10 during initialization upon power-on. If the servo drive model does not exist, E120.2 occurs.

Possible Causes	Confirming Method	Solutions
The servo drive model (H01.10) is set improperly.	Check the value of H01.10.	Disable servo drive model auto detection and set H01.10 to a proper value manually..

- E120.5: Motor and drive current mismatch

Cause:

The rated output of the servo drive is far higher than the rated current of the motor. You must use a servo drive of lower rated output or a motor with higher rated current.

Possible Causes	Confirming Method	Solutions
The internal scale value is abnormal.	Check whether the servo drive model is correct. If the set current sampling coefficient is too large, calculation overflow will occur.	Replace the servo drive.

- E120.6: FPGA and motor model mismatch

Cause:

- The motor model is set improperly, causing mismatch and malfunction of the servo drive.
- The motor model is set properly, but the motor encoder is not supported by the servo drive.

Possible Causes	Confirming Method	Solutions
FPGA software version and H00.00 mismatch	Check whether the FPGA software version (H01.01) supports the motor model set by H00.00.	Update the FPGA software to support the motor model defined by H00.00.

- E120.7: Model check error

Cause:

The servo drive model parameter cannot be identified.

Possible Causes	Confirming Method	Solutions
Model parameter CRC check failed	Check whether the model parameter is not programmed or is lost.	Program the model parameter again.

- E120.8: Junction temperature parameter check error
Cause:

The junction temperature parameter is identified incorrectly.

Possible Causes	Confirming Method	Solutions
Junction temperature parameter CRC check failed	Check that the junction temperature parameter is present	Program the junction temperature parameter again.

- E122.1: Different DIs assigned with the same function
Cause:

The same function is assigned to different DIs.

The DI function No. exceeds the maximum number allowed for DI functions.

Possible Causes	Confirming Method	Solutions
1. Multiple DIs are assigned with the same function.	Check whether DI function numbers set in group H03 are repetitive.	Change any repetitive number.
2. The DI function No. exceeds the maximum number allowed for DI functions	Check whether the MCU program is updated.	Restore system parameters to default values (H02.31 = 1) and restart the servo drive.

- E122.2: Different DOs assigned with the same function
Cause:

The DO function No. exceeds the maximum number allowed for DO functions

Possible Causes	Confirming Method	Solutions
The DO function No. exceeds the maximum number allowed for DO functions	Check the DO function numbers defined by H04.00, H04.02 and H04.04.	Set the correct DO function No.

- E122.3: Upper limit in the rotation mode too high
Cause:

The upper limit (reference range) of the mechanical single-turn position exceeds 2³¹ in the absolute position rotation mode.

Possible Causes	Confirming Method	Solutions
The upper limit of the mechanical single-turn position exceeds 231.	Check the setting of the mechanical gear ratio, the upper limit of mechanical single-turn position and the electronic gear ratio when the servo drive runs in the absolute rotation mode (H02.01 = 2).	Reset the mechanical gear ratio, the upper limit of mechanical single-turn position, and the electronic gear ratio to ensure the upper limit of the mechanical single-turn position (reference range) does not exceed 2 ³¹ .

- E122.4: Different VDIs assigned with the same function

Cause:

The same VDI function is reassigned. The VDI function number exceeds the number of VDI functions.

Possible Causes	Confirming Method	Solutions
1 Two or more VDIs are assigned with the same function No.	Check whether the same DI function No. is set in group H17 repetitively.	Ensure each VDI is assigned with a unique function No..
2. The VDI function No. exceeds the maximum number allowed for VDI functions	Check whether the MCU program is updated.	Restore system parameters to default values (H02.31 = 1) and restart the servo drive.

- E122.5: DI and VDI assigned with the same function

Cause:

The same VDI function is reassigned. The VDI function number exceeds the number of VDI functions.

Possible Causes	Confirming Method	Solutions
1 Two or more DIs and VDIs are assigned with the same function No.	Check whether the same DI function No. is set in groups H03 and H17.	Assign different DI function numbers to these parameters, and then re-energize the control circuit to activate the assignment, or switch off the S-ON signal and send a "RESET" signal to activate the assignment.

- E136.0: Encoder ROM motor parameter check error

Cause:

When reading parameters in the encoder ROM, the servo drive detects that no parameters are saved there or parameter values are inconsistent with the setpoints.

Possible Causes	Confirming Method	Solutions
1.The servo drive model does not match the motor model.	Check if devices used are the SV660P series servo drive and a compatible motor.	Replace the servo drive and motor.
2.A parameter check error occurs or no parameter is saved in the ROM of the serial incremental encoder.	<ol style="list-style-type: none"> 1. Check whether the encoder cable provided by Inovance is used. For cable specifications, see "Matching Cables". The cable must be connected securely without scratching, breaking or poor contact. 2. Measure the following signals at both ends of the encoder cable: PS+, PS-, +5V and GND. Observe whether signals at both ends are consistent. For signal assignment, see Chapter "Wiring" in the user guide. 	<ol style="list-style-type: none"> 1. Use the encoder cable provided by Inovance. Ensure motor terminals are connected securely and servo drive screws are tightened properly. Use a new encoder cable if necessary. 2. Route encoder cables and power cables (R/S/T, U/V/W) through different routes.
3.The servo drive is faulty.	The fault persists after the servo drive is restarted.	Replace the servo drive.

- E136.1: Encoder ROM motor parameter read error
Cause:

- The encoder cable is disconnected.
- A communication error occurs on the encoder due to interference.

Possible Causes	Confirming Method	Solutions
1The encoder cable is connected improperly.	Check the encoder cable connection. Check whether ambient vibration is too large, which loosens the encoder cable and even damages the encoder.	Connect the cables again according to the correct wiring diagram. Connect the cables again and ensure encoder terminals are connected securely.
2.The servo drive is faulty.	The fault persists after the servo drive is restarted.	Replace the servo drive.

- E150.0: STO safety state applied
Cause:

The STO input protection applies (safety state).

Possible Causes	Confirming Method	Solutions
Two 24 V inputs are disconnected simultaneously, triggering the STO function.	1. Check whether the STO function is activated.	There is no need to take any corrective actions. After the STO terminal is back to normal, clear the fault using the fault reset function.
	2. Check whether the STO power supply is normal.	Check whether the 24 V power supply for the STO is stable. Tighten the cables that are loose or disconnected.
	3. The fault persists after preceding causes are rectified.	Replace the servo drive.

- E150.1: STO input state abnormal

Cause:

The single-channel input of STO is ineffective.

Possible Causes	Confirming Method	Solutions
1. The STO power supply is abnormal.	Check whether the STO power supply is normal.	Check whether the 24 V power supply for the STO is stable. Tighten the cables that are loose or disconnected.
2. The input resistor is abnormal.	After STO is triggered, only one STO signal is sent to MCU after the 24 V power supply is cut off due to input resistor drift.	Replace the servo drive.
3. STO is ineffective	The fault persists after preceding causes are rectified.	Replace the servo drive.

- E150.2: Abnormal measured buffer 5 V voltage

Cause:

The MCU monitors the 5 V power supply of the PWM Buffer to detect whether overvoltage or undervoltage occurs. If the voltage is abnormal, E150.2 occurs.

Possible Causes	Confirming Method	Solutions
The 5 V voltage supplied to the STO Buffer is abnormal due to undervoltage or overvoltage.	Check whether the fault can be removed by a restart. If not, the 5 V voltage supplied to the Buffer is abnormal.	Replace the servo drive.

- E150.3: STO input circuit hardware diagnosis failure

Cause:

Short circuit occurs on the optocoupler of the upstream hardware circuit of STO.

Possible Causes	Confirming Method	Solutions
The upstream optocoupler of STO1 or STO2 failed.	The fault persists when the 24 V power supply is powered off and on again. The drive displays E150.3.	Replace the servo drive.

- E150.4: PWM buffer hardware diagnosis failure

Cause:

An error occurs on the PWM buffer integrated circuit during initialization detection upon power-on (the PWM signal cannot be blocked).

Possible Causes	Confirming Method	Solutions
STO Buffer power-on test error	The fault persists and the servo drive displays E150.4 when the 24 V power supply is powered off and on again.	Replace the servo drive.

- E201.0: Phase-P overcurrent

Cause:

An excessively high current flows through the positive pole of the DC-AC circuit.

Possible Causes	Confirming Method	Solutions
1.The gain is set improperly and the motor oscillates.	Check whether vibration or sharp noise occurs during start and operation of the motor, or view "Current feedback" in the software tool.	<ol style="list-style-type: none"> 1. Motor parameters are set improperly, modify motor parameter values. 2. Current loop parameters are set improperly, modify current loop parameter values. 3. Speed loop parameters are set improperly, leading to motor oscillation. 4. Servo drive operates improperly. Replace it.
2.The encoder cable is aged, corroded, or connected incorrectly or loosely.	<ol style="list-style-type: none"> 1. Check whether the encoder cable provided by Inovance is used and whether the cable is aging, corroded, or connected loosely. 2. Switch off the S-ON signal and rotate the motor shaft manually. Check whether the value of H0b.17 (Electrical angle) changes as motor shaft rotates. 	Re-solder, tighten or replace the encoder cable.
3.Regenerative resistor overcurrent	Check whether resistance of the external regenerative resistor is too small or the regenerative resistor is short-circuited (between terminals P, C).	Use a regenerative resistor of matching resistance. Perform wiring again.
4.The servo drive is faulty.	Disconnect the motor cable but the fault persists after the servo drive is powered off and on again.	Replace the servo drive.

- E201.1: Phase-U overcurrent
Cause:

A current higher than threshold is collected in the phase-U current.

Possible Causes	Confirming Method	Solutions
1.Motor cables are in poor contact.	Check whether the servo drive power cables and motor cables on the U, V, and W sides of the servo drive are loose.	Tighten the cables that are loose or disconnected.
2.Motor cables are grounded.	After ensuring that the drive power cable and motor cable are tightly connected, measure whether the insulation resistance between the drive U/V/W side and the PE cable is at MΩ level.	Replace the motor in case of poor insulation.
3.U/V/W cables of the motor are short-circuited.	Disconnect the motor cables and check whether short circuit occurs among U, V, and W phases and whether burrs exist in the wiring.	Connect the motor cables correctly.
4.The motor is damaged due to overheat.	<ol style="list-style-type: none"> 1. Disconnect motor cables and check whether short circuit occurs among motor U/V/W cables and whether burrs exist in the wiring. 2. Disconnect the motor cables and measure whether the resistance among UVW phases of motor cables is balanced. 	<ol style="list-style-type: none"> 1. Connect the motor cables correctly. 2. Replace the motor if the resistance is unbalanced.

- E201.2: Phase-V overcurrent

Cause:

A current higher than the threshold is collected in the phase-V current.

Possible Causes	Confirming Method	Solutions
1.Motor cables are in poor contact.	Check whether the servo drive power cables and motor cables on the U, V, and W sides of the servo drive are loose.	Tighten the cables that are loose or disconnected.
2.Motor cables are grounded.	After ensuring that the drive power cable and motor cable are tightly connected, measure whether the insulation resistance between the drive U/V/W side and the PE cable is at MΩ level.	Replace the motor in case of poor insulation.
3.U/V/W cables of the motor are short-circuited.	Disconnect the motor cables and check whether short circuit occurs among U, V, and W phases and whether burrs exist in the wiring.	Connect the motor cables correctly.
4.The motor is damaged due to overheat.	<ol style="list-style-type: none"> 1. Disconnect motor cables and check whether short circuit occurs among motor U/V/W cables and whether burrs exist in the wiring. 2. Disconnect the motor cables and measure whether the resistance among UVW phases of motor cables is balanced. 	<ol style="list-style-type: none"> 1. Connect the motor cables correctly. 2. Replace the motor if the resistance is unbalanced.

- E201.4: Phase-N overcurrent

Cause:

An excessively high current flows through the negative pole of the DC-AC circuit.

Possible Causes	Confirming Method	Solutions
1.The gain is set improperly and the motor oscillates.	Check whether vibration or sharp noise occurs during start and operation of the motor, or view "Current feedback" in the software tool.	Adjust the gains.
2.The encoder cable is aged, corroded, or connected incorrectly or loosely.	Check whether the encoder cable provided by Inovance is used and whether the cable is aging, corroded, or connected loosely.	Re-solder, tighten or replace the encoder cable.
3.Regenerative resistor overcurrent	Check whether resistance of the external regenerative resistor is too small or the regenerative resistor is short-circuited (between terminals P⊕ and C).	Replace with a regenerative resistor of matching resistance. Perform wiring again.
4.Overcurrent is caused by the superposition of the braking current and phase current.	Check if the drive accelerates abruptly during braking. Check if the voltage feedback exceeds the release threshold through the Inovance drive commissioning platform, and if the torque command increases abruptly.	Increase the acceleration/ deceleration time.
5.The servo drive is faulty.	Switch off the S-ON signal and rotate the motor shaft manually. Check whether the value of H0b.17 (Electrical angle) changes as motor shaft rotates. Disconnect the motor cable but the fault persists after the servo drive is powered off and on again.	Replace the servo drive.

- E208.2: Encoder communication timeout

Cause:

The servo drive fails to receive the data fed back by the encoder in three consecutive cycles.

Possible Causes	Confirming Method	Solutions
The servo drive fails to receive the data fed back by the encoder in three consecutive cycles.	<ol style="list-style-type: none"> 1. Check bit12 of H0b.30. 2. The encoder cable is connected improperly. 3. The encoder cable is connected loosely. 4. The encoder cable is too long. 5. The encoder communication is being disturbed. 6. The encoder is faulty. 	<ol style="list-style-type: none"> 1. Check whether the motor model is correct. 2. Check whether the encoder cable is proper. 3. Check whether the encoder version (H00.04) is set properly. 4. The servo drive operates improperly. Replace it.

- E208.4: FPGA current loop operation timeout

Cause:

The operating time of the current loop exceeds the interval threshold.

Possible Causes	Confirming Method	Solutions
FPGA operation timeout	Internal fault code H0b.45 = 4208: Current loop operation timed out.	Disable some unnecessary functions to reduce the operating load of the current loop.

- E210.0: Output short circuited to ground

Cause:

An abnormal motor phase current or bus voltage is detected during power-on self-testing.

- The DC bus voltage exceeds the braking threshold.
- The U-phase current of SIZE C/D/E is greater than the setpoint.
- Overcurrent occurs on phase-P and phase-N of servo drives in SIZE A and B.

Possible Causes	Confirming Method	Solutions
1The servo drive power cables (U/V/W) are short-circuited to ground.	Disconnect the motor cables and measure whether the servo drive power cables (U/V/W) are short-circuited to ground (PE).	Connect the cables again or replace the servo drive power cables.
2.The motor is short-circuited to the ground	After confirming the servo drive power cables and motor cables are connected properly, measure whether the insulation resistance between the servo drive U/V/W side and the PE cable is at MΩ level.	Replace the motor.

Possible Causes	Confirming Method	Solutions
3.The servo drive is faulty.	Disconnect the power cables from the servo drive, but the fault persists after the servo drive is powered off and on repeatedly.	Replace the servo drive.
4.The motor speed is too high during phase-to-ground detection.	Check whether the motor is in the generating status during power-on.	Reduce the motor speed.

- E234.0: Runaway
Cause:

The torque reference direction is opposite to the speed feedback direction in the torque control mode.

The speed feedback direction is opposite to the speed reference direction in the position or speed control mode.

Possible Causes	Confirming Method	Solutions
1. The U/V/W cables are connected in the wrong phase sequence.	Check whether the servo drive power cables are connected in the correct sequence at both ends.	Connect the U/V/W cables in the correct phase sequence.
2.An error occurs on the initial phase detection of the motor rotor due to disturbing signals upon power-on.	The UVW phase sequence is correct. But Er.234 occurs when the servo drive is enabled.	Power off and on again.
3.The encoder model is wrong or the encoder is wired improperly.	View the nameplates of the servo drive and motor to check whether SV660P series servo drive and the motor equipped with a 23-bit encoder are used.	Replace with a mutually-matching servo drive and motor. For use of SV660P series servo drive and the motor equipped with a 23-bit encoder, set H00.00 to 14101. Check the motor model, encoder type, and encoder cable connection again.

Possible Causes	Confirming Method	Solutions
4.The encoder cable is aged, corroded, or connected incorrectly or loosely.	<ol style="list-style-type: none"> 1. Check whether the encoder cable provided by Inovance is used and whether the cable is aging, corroded, or connected loosely. 2. Switch off the S-ON signal and rotate the motor shaft manually. Check whether the value of H0b.10 (Electrical angle) changes as motor shaft rotates. 	Re-solder, tighten or replace the encoder cable.
5.Improper parameter settings lead to excessive vibration.	The stiffness level is set to an excessively high value, leading to excessive vibration.	Set a proper stiffness level to avoid excessive vibration.
6.The gravity load is too heavy in vertical axis applications.	Check whether the load of the vertical shaft is too large. Adjust brake parameters H02.09...H02.12 and check whether the fault is cleared.	Reduce the load of the vertical axis, increase the stiffness level, or hide this fault without affecting the safety performance and normal use.

- E320.0: The regenerative resistor is overloaded.

Cause:

The regenerative resistor is overloaded.

Possible Causes	Confirming Method	Solutions
The accumulative heat of the regenerative resistor exceeds the maximum thermal capacity of the regenerative resistor.	Check whether the value of H0b.67 exceeds 100%.	<ol style="list-style-type: none"> 1. Check if large regenerative current is present due to high bus voltage. 2. Ensure that the motor cannot be driven reversely. 3. Replace the servo drive.



In applications where the motor drives a vertical axis or is driven by the load, set H0A.12 to 0 to hide the runaway fault.

- E400.0: Main circuit overvoltage

Cause:

The DC bus voltage between P \oplus and N \ominus exceeds the overvoltage threshold.

220 V servo drive: normal value: 310 V, undervoltage level: 420 V

380 V servo drive: normal value: 540 V, undervoltage level: 760 V

Possible Causes	Confirming Method	Solutions
1.The voltage input to the main circuit is too high.	Check the power input specifications of the servo drive and measure whether the voltage input to main circuit cables (R/S/T) on the drive side is within the following range: 220 V servo drive: Value range: 220 V to 240 V Allowable deviation: -10% to +10% (198 V to 264 V) 380 V servo drive: Value range: 380 V to 440 V Allowable deviation: -10% to +10% (342 V to 484 V)	Replace or adjust the power supply according to the specified range.
2.The power supply is unstable or affected by lightning.	Check whether the power supply is unstable, affected by lightning, or complies with the preceding range.	Connect a surge protection device and then switch on the main circuit and control circuit power supplies again. If the fault persists, replace the servo drive.

Possible Causes	Confirming Method	Solutions
<p>3.The regenerative resistor fails.</p>	<p>If the built-in regenerative resistor is used (H02.25 = 0), check whether terminals P ⊕ and D are jumpered. If yes, measure the resistance between terminals C and D. If an external regenerative resistor is used (H02.25 = 1 or 2), measure the resistance of the external regenerative resistor connected between terminals P ⊕ and C. For details, See table "Specifications of the regenerative resistor" in the Commissioning Guide.</p>	<ol style="list-style-type: none"> 1. If the resistance is "∞" (infinite), the regenerative resistor is disconnected internally. 2. If a built-in regenerative resistor is used, change to use an external regenerative resistor (H02.25 = 1 or 2) and remove the jumper between terminals P ⊕ and D. Select an external regenerative resistor of the same resistance and equal or higher power than the built-in one. 3. If an external regenerative resistor is used, replace with a new one and connect it between terminals P ⊕ and C. 4. Set H02.26 (Power of external regenerative resistor) and H02.27 (Resistance of external regenerative resistor) to values consistent with the specifications of the external regenerative resistor used.

Possible Causes	Confirming Method	Solutions
4.The resistance of the external regenerative resistor is too large, resulting in insufficient energy absorption during braking.	Measure the resistance of the external regenerative resistor connected between terminals P⊕ and C, and compare the measured value with the recommended value.	<ol style="list-style-type: none"> 1. Replace with an external regenerative resistor of recommended resistance, and connect it between terminals P⊕ and C. 2. Set H02.26 (Power of external regenerative resistor) and H02.27 (Resistance of external regenerative resistor) to values consistent with the specifications of the external regenerative resistor used.
5.The motor is in abrupt acceleration/deceleration status and the maximum braking energy exceeds the energy absorption value.	Confirm the acceleration/ deceleration time during operation and measure whether the DC bus voltage between terminals P⊕ and N⊖ exceeds the overvoltage threshold during deceleration.	After confirming the input voltage of the main circuit is within the specified range, increase the acceleration/ deceleration time if the operating conditions allow.
6.The bus voltage sampling value deviates greatly from the measured value.	Check whether H0b.26 (Bus voltage) is within the following range: 220 V servo drive: H0b.26 > 420 V 380 V servo drive: H0b.26 > 760 V Measure if the DC bus voltage between P ⊕ and N ⊖ is normal and less than the value of H0b.26.	Contact Inovance for technical support.
7.The servo drive is faulty.	The fault persists after the main circuit is powered off and on repeatedly.	Replace the servo drive.

- E410.0: Main circuit undervoltage

Cause:

The DC bus voltage between terminals P⊕ and N⊖ is lower than the undervoltage threshold.

220 V servo drive: normal value: 310 V, fault value: 200 V (S5R5 model is 180 V).

380 V servo drive: normal value: 540 V, undervoltage level: 380 V

Possible Causes	Confirming Method	Solutions
1.The power supply of the main circuit is unstable or power failure occurs.	Check the power input specifications of the servo drive and measure whether the input voltage at the power supply side of the main circuit cables and R/S/T on the drive side is within the following range: 220 V servo drive: Value range: 220 V to 240 V Allowable deviation: -10% to +10% (198 V to 264 V) Measure the voltages of all the three phases.	Increase the capacity of the power supply.
2.Instantaneous power-off occurs.		
3.Check whether the power voltage drops during running.		
4.A three-phase servo drive is connected to a single-phase power supply, leading to phase loss.	Check whether the main circuit is wired correctly and whether phase loss detection (H0A.00) is hidden.	Replace the cables and connect the main circuit cables correctly. Three phases: R, S, T.
5.The servo drive is faulty.	Check whether H0b.26 (Bus voltage) is within the following range: 220 V servo drive: H0b.26 < 200 V 380 V servo drive: H0b.26 < 380 V The fault persists after the main circuit is powered off and on repeatedly.	Replace the servo drive.

- E410.1: Main circuit de-energized

Cause:

Phase loss occurs on the three-phase servo drive.

Possible Causes	Confirming Method	Solutions
The power supply is disconnected during operation..	Check the power input specifications of the servo drive and measure whether the input voltage at the power supply side of the main circuit cables and R/S/T on the drive side is within the following range: 220 V servo drive: Value range: 220 V to 240 V Allowable deviation: -10% to +10% (198 V to 264 V) Measure the voltages of all the three phases.	Increase the capacity of the power supply.
	Monitor the power supply voltage and check whether the main circuit power supply is applied to other devices, resulting in insufficient power capacity and voltage drop.	
	Check whether the main circuit is wired correctly and whether phase loss detection (H0A.00) is hidden.	Replace the cables and connect the main circuit cables correctly. Three phases: R, S, T.
	Check whether H0b.26 (Bus voltage) is within the following range: 220 V servo drive: H0b.26 < 200 V 380 V servo drive: H0b.26 < 380 V The fault persists after the main circuit is powered off and on repeatedly.	Replace the servo drive.

- E420.0: Main circuit phase loss
Cause:
Main circuit PL signal detection error

Possible Causes	Confirming Method	Solutions
1.The three-phase input cables are connected improperly.	Check whether the cables between the power supply side and R/S/T terminals of the servo drive are connected properly.	Replace the cables and connect the main circuit cables correctly.
2.A single-phase power supply is used for a three-phase servo drive.	Check the specifications of the power supply and measure whether the voltage input to the main circuit is within the following range: 220 V servo drive: Value range: 220 V to 240 V Allowable deviation: -10% to +10% (198 V to 264 V) 380 V servo drive: Value range: 380 V to 440 V Allowable deviation: -10% to +10% (342 V to 484 V) Measure the voltages of all the three phases.	Servo drives of 0.75 kW (H01.02 = 5) can be supplied by single-phase power supplies. If the input voltage is within the specified range, set H0A.00 to 2 (Inhibit power input phase loss fault and warning). If it exceeds the specified range, replace or adjust the power supply according to the specified range.
3.The three-phase power supply is unbalanced or the voltages of the three phases are too low.		
4.The servo drive is faulty.	The fault persists after the main circuit (R/S/T) is powered off and on repeatedly.	Replace the servo drive.

- E500.0: Motor overspeed

Cause:

The actual speed of the motor exceeds the overspeed threshold.

Possible Causes	Confirming Method	Solutions
1.The phase sequence of motor cables is wrong.	Check whether the servo drive power cables are connected in the correct sequence at both ends.	Connect the U/V/W cables in the correct phase sequence.
2. H0A.08 is set improperly.	Check whether the overspeed threshold is lower than the maximum speed needed: Overspeed threshold = $1.2 \times$ Maximum motor speed (H0A.08 = 0). Overspeed threshold = H0A.08 (H0A.08 \neq 0 and H0A.08 < 1.2 times the maximum motor speed).	Reset the overspeed threshold according to the mechanical requirements.

Possible Causes	Confirming Method	Solutions
3.The input reference exceeds the overspeed threshold.	<p>Check whether the motor speed corresponding to the input reference exceeds the overspeed threshold.</p> <ul style="list-style-type: none"> Position control mode: In CSP mode, check the gear ratio 6091.01h/6091.02h to determine the position reference increment for an individual synchronization period and convert it to the speed information. In PP mode, check the gear ratio 6091.01h/6091.02h and determine the 6081h (Profile velocity). In HM mode, check the gear ratio 6091.01h/6091.02h, and determine 6099.01h and 6099.02h. Speed control mode: Check the gear ratio (6091h), target velocity (60FFh), speed limits (H06.06 to H06.09), and the maximum profile velocity (607Fh). Torque control mode: Check the speed limit defined by H07.17 in the torque control mode and check the corresponding speed limit. 	<ul style="list-style-type: none"> Position control mode: CSP: Decrease the position reference increment per synchronization cycle. The host controller should cover the position ramp when generating references. PP: Decrease the value of 6081h or increase the acceleration/deceleration ramp (6083h, 6084h). HM: Decrease the values of 6099.01h and 6099.02h or increase the acceleration/deceleration ramp (609Ah). Decrease the gear ratio according to actual conditions. Speed control mode: Decrease the target velocity, speed limit, and gear ratio. In PV mode, increase the speed ramp (6083h and 6084h). In CSV mode, the host controller should cover the speed ramp. Torque control mode: Set the speed limit to a value lower than the overspeed threshold.
4.The motor speed overshoots.	Check in the software tool whether the speed feedback exceeds the overspeed threshold.	Adjust the gains or mechanical operating conditions.
5.The servo drive is faulty.	The fault persists after the servo drive is powered off and on again.	Replace the servo drive.

- E500.1: Speed feedback overflow
Cause:

The FPGA speed measurement overflows.

Possible Causes	Confirming Method	Solutions
1. FPGA internal speed overflows.	Check whether the servo drive power cables are connected in the correct sequence at both ends.	Connect the U/V/W cables in the correct phase sequence.
2.The motor speed overshoots.	Check in the software tool whether the speed feedback exceeds the overspeed threshold.	Adjust the gains or mechanical operating conditions.
3. FPGA speed measurement is abnormal.	Check whether bit9 of H0b.30 is 1.	<ol style="list-style-type: none"> 1. The speed feedback is abnormal, check whether the encoder version (H00.04) is set properly. 2. The encoder cable is abnormal, replace the encoder cable. 3. The encoder cable is being disturbed. Re-connect the grounding cable and the shielded cable or install a magnetic ring.

- E500.2: FPGA position feedback pulse overspeed

Cause:

FPGA feedback speed overflow.

Possible Causes	Confirming Method	Solutions
Communication error occurred between boards of the drive.	The alarm persists in spite of repeated power off and on.	Replace the drive.

- E602.2: U/V/W phase sequence reversed

Cause:

A wrong U/V/W phase sequence is detected during angle auto-tuning.

Possible Causes	Confirming Method	Solutions
Incorrect UVW is detected during angle auto-tuning.	Check whether U/V/W phases are wired correctly.	Exchange cables of any two phases among U/V/W and perform auto-tuning again.

- E605.0: Speed too fast upon S-ON

Cause:

The motor speed exceeds the rated speed when the servo drive in size A/B is switched on.

Possible Causes	Confirming Method	Solutions
The motor speed exceeds the motor rated speed when the servo drive is switched on.	Check if the drive is enabled when the motor has been driven.	Enable the drive when the motor is at standstill.

- E620.0: Motor overload

Cause:

The accumulative heat of the motor reaches the fault threshold.

Possible Causes	Confirming Method	Solutions
1.The motor and encoder cables are connected improperly or in poor contact.	Check the wiring between the servo drive, servo motor and the encoder according to the correct "wiring diagram".	Connect cables according to the correct wiring diagram. It is recommended to use the cables provided by Inovance. When customized cables are used, prepare and connect the customized cables according to the wiring instructions.
2.The load is so heavy that the effective torque outputted by the motor keeps exceeding the rated torque.	Confirm the overload characteristics of the servo drive or motor. Check whether the average load rate (H0b.12) keeps exceeding 100.0%.	Use a servo drive of higher capacity and a matching servo motor, or reduce the load and increase the acceleration/deceleration time.
3.Acceleration/deceleration is too frequent or the load inertia is too large.	Calculate the mechanical inertia ratio or perform inertia auto-tuning. Check the value of H08.00 (Load inertia ratio). Confirm the individual operation cycle when the servo motor operates cyclically.	Increase the acceleration/deceleration time in an individual operation cycle.
4.The gains are improper or the stiffness level is too high.	Check whether the motor vibrates and generates unusual noise during operation.	Adjust the gains again.
5.The model of the servo drive or motor is set improperly.	View the motor model (H00.05) saved in the serial-type encoder and the servo drive model (H01.10).	Check the servo drive nameplate and the section "Servo Drive Model and Nameplate" in the Hardware Guide to set the servo drive model (H01.10) and motor model properly.

Possible Causes	Confirming Method	Solutions
6.The motor is stalled due to mechanical factors, resulting in overload during operation.	Check the reference and motor speed (H0b.00) through the software tool or keypad. <ul style="list-style-type: none"> References in the position control mode: H0b.13 (Position reference counter) References in the speed control mode: H0b.01 (Speed reference) References in the torque control mode: H0b.02 (Internal torque reference) Check whether the reference value is not 0 but the motor speed is 0 rpm in the corresponding mode.	Eliminate the mechanical factors.
7.The servo drive is faulty.	The fault persists after the servo drive is powered off and on again.	Replace the servo drive.

Note

When E620.0 occurs, stop the servo drive for at least 30s before further operations.

- E625.0: Brake abnormality enabled

Cause:

The brake fails when it is released.

Possible Causes	Confirming Method	Solutions
The brake fails when it is released.	Check if the motor shaft end is held by the brake when the brake release signal is active.	1. Check the brake wiring. 2. Replace the Brake motor.

- E626.0: Brake abnormality enabled

Cause:

The brake fails when it is released.

Possible Causes	Confirming Method	Solutions
The brake fails when it closes.	Check if the motor shaft end is not held tightly by the brake when the braking signal is active.	1. Check the brake wiring. 2. Replace the Brake motor.

- E630.0: Motor stall overtemperature protection

Cause:

The actual motor speed is lower than 10rpm but the torque reference reaches the limit, and such status lasts for the time defined by H0A.32.

Possible Causes	Confirming Method	Solutions
1.U/V/W output phase loss, wire breakage or incorrect phase sequence occurs on the servo drive.	Perform motor trial run without load and check cable connections and the phase sequence.	Connect cables again according to the correct wiring diagram or replace the cables.
2.Incorrect motor parameters: Incorrect motor parameters (especially the number of pole pairs), angle auto-tuning is not performed	View parameters in group H00 to check whether the number of pole pairs are set properly. Perform angle auto-tuning on the motor several times and check whether the value of H00.28 is consistent during angle auto-tuning.	Modify the motor parameter values.
3.Interference with communication instructions	Check whether jitter occurs on the commands sent from the host controller and whether EtherCAT communication is being disturbed.	Check whether the communication line between the host controller and the servo drive is being disturbed.
4.The motor is stalled due to mechanical factors.	Check the reference and motor speed (H0b.00) through the software tool or keypad. <ul style="list-style-type: none"> ● References in the position control mode: H0b.13 (Position reference counter) ● References in the speed control mode: H0b.01 (Speed reference) ● References in the torque control mode: H0b.02 (Internal torque reference) Check whether the reference value is not 0 but the motor speed is 0 rpm in the corresponding mode. Check the current feedback (torque reference) waveform.	Check whether any mechanical part gets stuck or eccentric.

Note

When E620.0 occurs, stop the servo drive for at least 30s before further operations.

- E640.0: IGBT junction overtemperature

Cause:

The IGBT junction temperature reaches the fault threshold defined by H0A.18.

Possible Causes	Confirming Method	Solutions
1.The ambient temperature is too high.	Measure the ambient temperature.	Improve the cooling conditions of the servo drive to lower down the ambient temperature.
2.The drive has been restarted several times to reset the overload fault.	Check the fault records (set H0b.33 and check H0b.34) for any overload fault/warning (E620.0, E630.0, E650.0, E909.0, E920.0, E922.0).	Change the fault reset method. After overload occurs, wait for 30s before reset. Increase the capacities of the servo drive and servo motor. Increase the acceleration/ deceleration time and reduce the load.
3.The fan is damaged.	Check whether the fan works properly during operation.	Replace the servo drive.
4.The drive is installed in a wrong direction and the clearance between servo drives is improper.	Check whether the servo drive is installed properly.	Install the servo drive according to the requirements.
5.The servo drive is faulty.	The fault persists even though the servo drive is restarted five minutes after power-off.	Replace the servo drive.

Note

When E620.0 occurs, stop the servo drive for at least 30s before further operations.

- E640.1: Flywheel diode overtemperature

Cause:

The temperature of the flywheel diode reaches the fault threshold defined by H0A.18.

Possible Causes	Confirming Method	Solutions
1.The ambient temperature is too high.	Measure the ambient temperature.	Improve the cooling conditions of the servo drive to lower down the ambient temperature.
2.The drive has been restarted several times to reset the overload fault.	Check the fault records (set H0b.33 and check H0b.34) for any overload fault/warning (E620.0, E630.0, E650.0, E909.0, E920.0, E922.0).	Change the fault reset method. After overload occurs, wait for 30s before reset. Increase the capacities of the servo drive and servo motor. Increase the acceleration/ deceleration time and reduce the load.
3.The fan is damaged.	Check whether the fan works properly during operation.	Replace the servo drive.
4.The drive is installed in a wrong direction and the clearance between servo drives is improper.	Check whether the servo drive is installed properly.	Install the servo drive according to the requirements.
5.The servo drive is faulty.	The fault persists even though the servo drive is restarted five minutes after power-off.	Replace the servo drive.

Note

When E620.0 occurs, stop the servo drive for at least 30s before further operations.

- E650.0: Heatsink overtemperature

Cause:

The temperature of the servo drive power module is higher than the overtemperature threshold.

Possible Causes	Confirming Method	Solutions
1.The ambient temperature is too high.	Measure the ambient temperature.	Improve the cooling conditions of the servo drive to lower down the ambient temperature.
2.The drive has been restarted several times to reset the overload fault.	Check the fault records (set H0b.33 and check H0b.34) for any overload fault/warning (E620.0, E630.0, E650.0, E909.0, E920.0, E922.0).	Change the fault reset method. After overload occurs, wait for 30s before reset. Increase the capacities of the servo drive and servo motor. Increase the acceleration/ deceleration time and reduce the load.
3.The fan is damaged.	Check whether the fan works properly during operation.	Replace the servo drive.
4.The drive is installed in a wrong direction and the clearance between servo drives is improper.	Check whether the servo drive is installed properly.	Install the servo drive according to the requirements.
5.The servo drive is faulty.	The fault persists even though the servo drive is restarted five minutes after power-off.	Replace the servo drive.

Note

When E620.0 occurs, stop the servo drive for at least 30s before further operations.

- E660.0: The motor temperature is too high

Cause:

The temperature of the air-cooled motor is too high.

Possible Causes	Confirming Method	Solutions
The temperature of the air-cooled motor is too high.	Measure whether the temperature of the air-cooled motor is too high.	Cool the motor down.

- E661.0: STune failure

Cause:

The gain values fall below the lower limit during ETune operation.

Possible Causes	Confirming Method	Solutions
<p>1. During STune operation, the gain drops to the lower limit, stiffness ≤ 10.</p>	<p>Check if vibration resonance is properly suppressed in the system. The torque vibration amplitude exceeds the setpoint of H09.11.</p>	<p>Set the notch manually when vibration cannot be suppressed automatically. Modify the electronic gear ratio to improve the command resolution, or increase the command filter time constant in the "Parameter configuration" interface. Check whether the current of the machine fluctuates periodically.</p>
<p>Check whether resonance that occurred during ITune operation cannot be suppressed.</p>	<p>Check whether there is abnormal noise or torque fluctuation during operation.</p>	<ol style="list-style-type: none"> 1. Set the notch manually. 2. Modify the electronic gear ratio to improve the command resolution, increase the command filter time constant in the parameter configuration interface. 3. Check whether the machine suffers from periodic fluctuation. 4. Set H09.58 to 1 to clear resonance suppression parameters, and perform STune again.

- E662.0: ETune failure

Cause:

Check whether resonance that occurred during ETune operation cannot be suppressed.

Possible Causes	Confirming Method	Solutions
<p>1. During ETtune operation, the gain drops to the lower limit: Position loop gain < 5 Velocity loop gain < 5 Model loop gain < 10</p>	<p>Check if vibration resonance is properly suppressed in the system. The torque vibration amplitude exceeds the setpoint of H09.11.</p>	<ol style="list-style-type: none"> 1. Set the notch manually when vibration cannot be suppressed automatically. 2. Modify the electronic gear ratio to improve the command resolution, increase the command filter time constant or in the parameter configuration interface. 3. Increase the value of H09.11 as appropriate. 4. Check whether the machine suffers from periodic fluctuation. 5. Check whether the positioning threshold is too low. Increase the reference acceleration/ deceleration time.
<p>Check whether resonance that occurred during ETune operation cannot be suppressed.</p>	<p>Check whether there is abnormal noise or torque fluctuation during operation.</p>	<ol style="list-style-type: none"> 1. Set the notch manually. 2. Modify the electronic gear ratio to improve the command resolution, increase the command filter time constant in the parameter configuration interface. 3. Check whether the current of the machine fluctuates periodically.

- E663.0: ITune failure
Cause:

Check whether resonance that occurred during ITune operation cannot be suppressed.

Possible Causes	Confirming Method	Solutions
Check whether resonance that occurred during ITune operation cannot be suppressed.	Check if vibration resonance is properly suppressed in the system. The torque vibration amplitude exceeds the setpoint of H09.11.	<ol style="list-style-type: none"> 1. Set the notch manually when vibration cannot be suppressed automatically. 2. Modify the electronic gear ratio to improve the command resolution, increase the command filter time constant or in the parameter configuration interface. 3. Check whether the machine suffers from periodic fluctuation. 4. Increase the value of H09.11 as appropriate.

- E664.0: Resonance too strong
Cause:

Resonance occurs on the servo system and the torque fluctuation amplitude is higher than the value of H09.54.

Possible Causes	Confirming Method	Solutions
Resonance occurs on the servo system and the torque fluctuation amplitude is higher than the value of H09.54.	<ol style="list-style-type: none"> 1. Check whether the torque fluctuation range is greater than the setpoint of H09.54. 2. Check whether there is abnormal noise or torque fluctuation during operation. 	<ol style="list-style-type: none"> 1. Check whether the inertia ratio or loop gain parameters are set properly. 2. Check whether resonance parameters are set properly. 3. Increase the value of H09.54 or set H09.54 to 0 to disable this function.

- E731.0: Encoder battery failure
Cause:

The voltage of the absolute encoder battery is lower than 2.9 V.

Possible Causes	Confirming Method	Solution
1.The battery is not connected during power-off.	Check whether the battery is connected during power-off.	Set H0d.20 to 1 to clear the fault.
2.The encoder battery voltage is too low.	Measure the battery voltage.	Use a new battery with the matching voltage.

- E733.0: An encoder multi-turn counting error occurs.

Cause:

An encoder multi-turn counting error occurs.

Possible Causes	Confirming Method	Solutions
The encoder is faulty.	Set H0d.20 to 2 to clear the fault, but E733.0 persists after restart.	Replace the motor.

- E735.0: Encoder multi-turn counting overflow

Cause:

A multi-turn counting overflow occurs on the absolute encoder.

Possible Causes	Confirming Method	Solutions
The number of forward revolutions exceeds 32767 or the number of reverse revolutions exceeds 32768.	Check whether the value of H0b.70 (Number of absolute encoder revolutions) reach 32767 or 32768 when the servo drive works in the absolute linear mode (H02.01 = 1).	<ol style="list-style-type: none"> 1. This fault can be hidden in cases where no multi-turn absolute position is needed but the absolute position during running needs to be recorded. 2. The rotation mode applies to occasions where only single-turn absolute position needs to be recorded. 3. Set H0d.20 to 2 to power on again. Perform homing if necessary.

- E740.0: Encoder communication timeout

Cause:

Absolute encoder communication timeout

Possible Causes	Confirming Method	Solutions
The encoder cable is not connected reliably. The communication between the servo drive and the encoder times out.	Check the wiring of the encoder and power on the servo drive again.	<ol style="list-style-type: none"> 1. Check the encoder cable connections. 2. Check whether vibration on site is too strong, which loosens the encoder cable and even damages the encoder. 3. Replace with a new encoder cable. If the fault no longer occurs after cable replacement, the original encoder cable is damaged. 4. Check whether the encoder version (H00.04) is set properly. 5. Check whether the servo drive software version (H01.00). 6. Replace the servo motor.

- E740.2: Absolute encoder communication error
Cause:

A communication error occurs on the RX side of the encoder.

Possible Causes	Confirming Method	Solutions
1The encoder cable is connected improperly.	Check the wiring of the encoder.	Connect the encoder cables according to the correct wiring diagram.
2.The encoder cable is connected loosely.	Check whether vibration on site is too strong, which loosens the encoder cable and even damages the encoder.	Re-connect encoder cables and ensure encoder terminals are connected securely.

Possible Causes	Confirming Method	Solutions
3.The encoder Z signal suffers from interference.	Check the cable layout on site: Check whether ambient devices are generating disturbance and whether multiple disturbance sources such as variable-frequency devices are present inside the cabinet. Make servo drive stay in "Rdy" status and rotate motor shaft counterclockwise (CCW) manually and observer whether H0b.17 increases/ decreases smoothly. Turning one circle corresponds to five 0–360° (for Z series motors). For X series motors, turning one circle corresponds to four 0–360°. If H0b.17 changes abnormally during motor rotating, the encoder is faulty. If no warning is reported during rotation but the servo drive reports a warning during operation, disturbance may be present.	It is recommended to use the cables provided by Inovance. For use of customized cables, check whether the customized cable complies with specifications and whether it is a shielded twisted pair cable. Route the motor cables and encoder cables through different routes. Ensure the servo motor and servo drive are grounded properly. Check whether the connectors at both ends of the encoder are in good contact and whether any pin retracts.
4.The encoder is faulty.	Replace with a new encoder cable. If the fault no longer occurs after cable replacement, it indicates the original encoder cable is damaged. Keep the motor in a certain position, power on the system several times and observe the change of H0b.17 (Electrical angle). The electrical angle deviation should be within $\pm 30^\circ$ when the motor position does not change.	Replace with a new encoder cable. If the fault persists after the encoder cable is replaced, the encoder may be faulty. In this case, replace the servo motor.

Possible Causes	Confirming Method	Solutions
5. An error occurs on the communication between the servo drive and the encoder.	Check whether the value of H0b.28 is not 0.	<ol style="list-style-type: none"> 1. Check whether H00.00 (Motor code) is set properly. 2. Check whether the encoder cable is connected properly. 3. Check whether the servo drive and motor are grounded properly. You can wind a magnetic ring on the encoder cable to reduce interference.

- E740.3: Absolute encoder single-turn calculation error

Cause:

The encoder is faulty.

Possible Causes	Confirming Method	Solutions
The encoder is faulty.	Replace with a new encoder cable. If the fault no longer occurs after cable replacement, it indicates the original encoder cable is damaged. Keep the motor in a certain position, power on the system several times and observe the change of H0b.17 (Electrical angle). The electrical angle deviation should be within $\pm 30^\circ$ when the motor position does not change.	<ol style="list-style-type: none"> 1. Check whether the encoder version (H00.04) is proper. 2. Check whether the encoder cable is proper. 3. Replace the motor.

- E740.6: Encoder write error

Cause:

The attempt to write the encoder data fails.

Possible Causes	Confirming Method	Solutions
An error occurs when writing the position offset after angle auto-tuning.	Replace with a new encoder cable. If the fault no longer occurs after cable replacement, it indicates the original encoder cable is damaged. Keep the motor in a certain position, power on the system several times and observe the change of H0b.17 (Electrical angle). The electrical angle deviation should be within $\pm 30^\circ$ when the motor position does not change.	Replace with a new encoder cable. If the fault persists after the encoder cable is replaced, the encoder may be faulty. In this case, replace the servo motor.

- E760.0: Encoder over-temperature

Cause:

The temperature of the absolute encoder is too high.

Possible Causes	Confirming Method	Solutions
The temperature of the absolute encoder is too high.	Measure the encoder or motor temperature.	Switch off the S-ON signal to wait for the encoder to cool down.

- E765.0: Nikon encoder over-temperature or overspeed

Cause:

The temperature of the absolute encoder is too high.

Possible Causes	Confirming Method	Solutions
The temperature of the absolute encoder is too high.	Measure the encoder or motor temperature.	Switch off the S-ON signal to wait for the encoder to cool down.

- E939.0: Motor power cable disconnected

Cause:

Motor three phase cable breakage

Possible Causes	Confirming Method	Solutions
Motor power cables are broken or not connected.	Check the wiring of U/V/W power cables.	1. Check whether the power cables are disconnected or in poor contact. Re-connect the power cables. 2. Replace the servo motor.

- E994.0: Station number conflict

Possible Causes	Confirming Method	Solutions
CANlink station No. conflict	Check the setpoint of H0E.00.	Rectify the value of H0E.00.

- EA33.0: Encoder read/write check error

Cause:

Encoder parameters are abnormal.

Possible Causes	Confirming Method	Solutions
1.The serial incremental encoder cable is disconnected or loose.	Check the wiring.	Check for wrong connection, disconnection and poor contact of the encoder cable. Route the motor cable and encoder cable through different routes.
2.An error occurs when reading/writing the serial incremental encoder parameters.	If the fault persists after the servo drive is powered off and on repeatedly, the encoder is faulty.	Replace the servo motor.

- EB00.0: Position deviation too large

Cause:

The position deviation is larger than the value of 6065h in position control mode.

Possible Causes	Confirming Method	Solutions
1U/V/W output phase loss or incorrect phase sequence occurs on the servo drive.	Perform a no-load trial run on the motor and check the wiring.	Connect cables again according to the correct wiring diagram or replace the cables.
2.The servo drive U/V/W cables or the encoder cable is disconnected.	Check the wiring.	Connect the cables again. The servo drive power cables must be connected in the correct order at both ends. Replace with new cables if necessary and ensure cables are connected properly.

Possible Causes	Confirming Method	Solutions
3.The motor is stalled due to mechanical factors.	<p>Check the reference and motor speed (H0b.00) through the software tool or keypad.</p> <ul style="list-style-type: none"> References in the position control mode: H0b.13 (Position reference counter) References in the speed control mode: H0b.01 (Speed reference) References in the torque control mode: H0b.02 (Internal torque reference) <p>Check whether the reference value is not 0 but the motor speed is 0 rpm in the corresponding mode.</p>	Eliminate the mechanical factors.
4.The gain values are too low.	<p>Check the position loop gain and speed loop gain of the servo drive.</p> <p>1st gain set: H08.00–H08.02; 2nd gain set: H08.03–H08.05.</p>	Adjust the gain values manually or perform gain auto-tuning.
5.The position reference increment is too large.	<p>Position control mode:</p> <ul style="list-style-type: none"> In CSP mode, check the gear ratio 6091.01h/6091.02h to determine the position reference increment for an individual synchronization period and convert it to the speed information. In PP mode, check the gear ratio 6091.01h/6091.02h and determine the 6081h (Profile velocity). In HM mode, check the gear ratio 6091.01h/6091.02h, and determine 6099.01h and 6099.02h. 	<ul style="list-style-type: none"> CSP: Decrease the position reference increment per synchronization cycle. The host controller should cover the position ramp when generating references. PP: Decrease the value of 6081h or increase the acceleration/deceleration ramp (6083h, 6084h). HM: Decrease the values of 6099.01h and 6099.02h or increase the acceleration/deceleration ramp (609Ah). Decrease the gear ratio according to actual conditions.

Possible Causes	Confirming Method	Solutions
6. Given the operating condition, the value of 6065h (H0A.10) is too low.	Check whether the setpoint of 6065h is too low.	Increase the setpoint of 6065h.
7. The drive/motor is faulty.	Monitor the operating waveforms using the oscilloscope function in the software tool: position reference, position feedback, speed reference, torque reference	If the position reference is not 0, but the position feedback is always 0, replace the servo drive or motor.

- EB00.1: Position deviation overflow

Cause:

The position deviation is too large.

Possible Causes	Confirming Method	Solutions
1. U/V/W output phase loss or incorrect phase sequence occurs on the servo drive.	Perform a no-load trial run on the motor and check the wiring.	Connect cables again according to the correct wiring diagram or replace the cables.
2. The servo drive U/V/W cables or the encoder cable is disconnected.	Check the wiring.	Connect the cables again. The servo drive power cables must be connected in the correct order at both ends. Replace with new cables if necessary and ensure cables are connected properly.
3. The motor is stalled due to mechanical factors.	Check the reference and motor speed (H0b.00) through the software tool or keypad. <ul style="list-style-type: none"> ● References in the position control mode: H0b.13 (Position reference counter) ● References in the speed control mode: H0b.01 (Speed reference) ● References in the torque control mode: H0b.02 (Internal torque reference) Check whether the reference value is not 0 but the motor speed is 0 rpm in the corresponding mode.	Eliminate the mechanical factors.

Possible Causes	Confirming Method	Solutions
4.The gain values are too low.	Check the position loop gain and speed loop gain of the servo drive. <ul style="list-style-type: none"> • 1st gain set: H08.00–H08.02; • 2nd gain set: H08.03–H08.05. 	Adjust the gain values manually or perform gain auto-tuning.
5.The position reference increment is too large.	Position control mode: <ul style="list-style-type: none"> • In CSP mode, check the gear ratio 6091.01h/6091.02h to determine the position reference increment for an individual synchronization period and convert it to the speed information. • In PP mode, check the gear ratio 6091.01h/6091.02h and determine the 6081h (Profile velocity). • In HM mode, check the gear ratio 6091.01h/6091.02h, and determine 6099.01h and 6099.02h. 	<ul style="list-style-type: none"> • CSP: Decrease the position reference increment per synchronization cycle. The host controller should cover the position ramp when generating references. • PP: Decrease the value of 6081h or increase the acceleration/deceleration ramp (6083h, 6084h). • HM: Decrease the values of 6099.01h and 6099.02h or increase the acceleration/deceleration ramp (609Ah). Decrease the gear ratio according to actual conditions.
6.Given the operating condition, the value of 6065h (H0A.10) is too low.	Check whether the setpoint of 6065h is too low.	Increase the setpoint of 6065h.
7.The drive/motor is faulty.	Monitor the operating waveforms using the oscilloscope function in the software tool: position reference, position feedback, speed reference, torque reference	If the position reference is not 0, but the position feedback is always 0, replace the servo drive or motor.

- EB01.0: The position reference increment is too large.
Cause:

The pulse reference increment exceeds the excessive reference threshold three times consecutively.

Possible Causes	Confirming Method	Solutions
The pulse reference increment exceeds the excessive reference threshold three times consecutively.	Check whether the baud rate of pulse reference input exceeds the value of H0A.09.	<ol style="list-style-type: none"> 1. Increase the value of H0A.09. 2. Reduce the baud rate of pulse input.

- EB01.1: Individual position reference increment too large
Cause:

The target position increment is too large.

Possible Causes	Confirming Method	Solutions
The target position increment is too large.	Check the variation between two adjacent target positions using the software tool.	<ol style="list-style-type: none"> 1. Check whether the maximum speed of the motor fulfills the application requirement. If yes, reduce the target position reference increment, which is to lower the profile reference speed. If not, replace the servo motor. 2. Before switching the mode or enabling the servo drive, check whether the target position is aligned with current position feedback. 3. The communication sequence of the host controller is abnormal, leading to slave data error. Check the communication sequence of the host controller.

- EB01.3: Reference overflow
Cause:

The target position is still in the process of transmission when the servo limit or software position limit signal is activated and the 32-bit upper/lower limit is reached.

Possible Causes	Confirming Method	Solutions
The target position is still in the process of transmission when the servo limit or software position limit signal is activated and the 32-bit upper/lower limit is reached.	Check whether the host controller continues sending commands after overtravel warning is reported by the servo drive.	<ol style="list-style-type: none"> 1. Detect the servo limit signal (bit0 and bit1 of 60FD is recommended) through the host controller. 2. Stop sending limit direction commands when an active servo limit signal is detected by the host controller.

- EB03.0: Electronic gear ratio beyond the limit - H05.02

Cause:

H05.02 electronic gear ratio exceeds limit: $(0.001-4000 \times \text{Encoder resolution}/10000)$.

Possible Causes	Confirming Method	Solutions
The electronic gear ratio converted by converted exceeds the maximum gear ratio or is less than the minimum gear ratio.	Check if the electronic gear ratio is within the range of $0.001-4000 \times \text{Encoder resolution}/10000$.	Adjust the value of H05.02.

- EB03.1: Electronic gear ratio beyond the limit - 1st group of electronic gear ratio

Cause:

1st electronic gear ratio exceeds limit: $(0.001-4000 \times \text{Encoder resolution}/10000)$.

Possible Causes	Confirming Method	Solutions
The group 1 electronic gear ratio exceeds the maximum gear ratio or is less than the minimum gear ratio.	Check if the electronic gear ratio is within the range of $0.001-4000 \times \text{Encoder resolution}/10000$.	The electronic gear ratio 1 is used (H05.07/H05.09).

- EB03.2: Electronic gear ratio beyond the limit - 2nd group of electronic gear ratio

Cause:

2nd electronic gear ratio exceeds limit: $(0.001-4000 \times \text{Encoder resolution}/10000)$.

Possible Causes	Confirming Method	Solutions
The group 2 electronic gear ratio exceeds the maximum gear ratio or is less than the minimum gear ratio.	Check if the group 2 electronic gear ratio is within the range of $0.001-4000 \times \text{Encoder resolution}/10000$.	Adjust electronic gear ratio 2 (H05.11/H05.13).

- ED02.0: Modbus communication timeout

Cause:

Modbus communication timeout

Possible Causes	Confirming Method	Solutions
Modbus communication timeout	Increase the value of H0E.83.	Determine the Modbus access cycle by frame grab.

- ED03.0: CANLink communication failure

Cause:

The master is offline.

Possible Causes	Confirming Method	Solutions
The master is offline.	1.Increase the master heartbeat threshold. 2.Check hardware wiring.	Capture frames to ensure that the master station is online.

- ED04.0: CANopen communication timeout

Cause:

The slave reaches the time configured by the consumer or the node guarding time.

Possible Causes	Confirming Method	Solutions
The slave reaches the time configured by the consumer or the node guarding time.	Check whether the heartbeat frame cycle of the host controller is normal by frame grab.	Check whether all CAN nodes are online, or check the CANopen configuration, reset the node or communication.

- ED05.0: CANopen communication initialized

Cause:

After the motor is enabled, errors such as slave offline, heartbeat abnormal, load ratio too high, data frame loss, and false master reset occurred when NMT changes to the initialization state.

Possible Causes	Confirming Method	Solutions
After the motor is enabled, errors such as slave offline, heartbeat abnormal, load ratio too high, data frame loss, and false master reset occurred when NMT changes to the initialization state.	Check whether the reset frame is received during operation by frame grab.	<p>Reset the NMT node. When changing the NMT, disable the output stage.</p> <ol style="list-style-type: none"> 1. Use shielded cables to prevent interference. 2. Ground the servo drive properly. 3. Ensure the load rate is proper. 4. If asynchronous transmission is configured, ensure the suppression time is set properly. 5. Ensure no false reset frame is triggered by the host controller. 6. Ensure the termination resistor is installed.

- ED08.0: CANopen bus PDO transmission length error
Cause:

The length of the content transmitted by PDO is inconsistent with the configured mapping length.

Possible Causes	Confirming Method	Solutions
The length of the content transmitted by PDO is inconsistent with the configured mapping length.	Check whether the PDO transmission length is consistent with the configuration by frame grab.	Re-configure the PDO and reset the node or communication.

- ED11.0: CANopen sync period error too large
Cause:

The SYNC period error exceeds the setpoint

Possible Causes	Confirming Method	Solutions
The SYNC period error exceeds the setpoint	Collect the synchronization signal using the software tool and calculate whether the cycle is higher than the fault threshold.	Check the settings of 60C2.01h and 60C2.02h and ensure the synchronization period is set properly. Ensure the synchronization period of the host controller is set correctly and consistent with the setting of 60C2h. Check the wiring between the slave and the master.

5.2 Internal fault

When any one of the following fault occurs, contact Inovance for technical support.

- E602.0: Angle auto-tuning failure
- E220.0: Phase sequence incorrect
- EA40.0: Parameter auto-tuning failure
- E111.0: Internal parameters of the servo drive are abnormal.

6 List of Warning Codes

Table 6-1 No. 3 resettable warning list

Fault code	Fault subcode	Alarm Name	Fault Level	Resettable
E108	E108.0	Parameter write error	No. 3	Yes
	E108.1	Parameter read error	No. 3	Yes
	E108.2	Invalid check on data written in EEPROM	No. 3	Yes
	E108.3	Invalid check on data read in EEPROM	No. 3	Yes
	E108.4	Single data is stored too many times	No. 3	Yes
E110	E110.0	Frequency-division pulse output setting error	No. 3	Yes
E121	E121.0	Invalid S-ON command	No. 3	Yes
E122	E122.0	Multi-turn absolute encoder setting error	No. 3	Yes
E510	E510.0	Frequency division pulse output overspeed	No. 3	Yes
E600	E600.0	Inertia auto-tuning failure	No. 3	Yes
E601	E601.0	Homing warning	No. 3	Yes
	E601.1	Homing switch error	No. 3	Yes
	E601.2	Homing mode setting error	No. 3	Yes
E730	E730.0	Encoder battery warning	No. 3	Yes
E731	E731.0	Encoder battery failure	No. 3	Yes
E831	E831.1	A11 zero offset too large	No. 3	Yes
E834	E834.1	A11 overvoltage	No. 3	Yes
E900	E900.0	DI emergency braking	No. 3	Yes
E902	E902.0	DI setting invalid	No. 3	Yes
	E902.1	DO setting invalid	No. 3	Yes
	E902.2	Torque reach setting invalid	No. 3	Yes
E908	E908.0	Model identification failure	No. 3	Yes
E909	E909.0	Motor overload	No. 3	Yes
E910	E910.0	Control circuit overvoltage	No. 3	Yes
E920	E920.0	The regenerative resistor is overloaded.	No. 3	Yes
E922	E922.0	Resistance of the external regenerative resistor too small	No. 3	Yes
E924	E924.0	Regenerative transistor over-temperature	No. 3	Yes
E941	E941.0	Modified parameters activated at next power-on	No. 3	Yes
E942	E942.0	Parameters saved frequently	No. 3	Yes
E950	E950.0	Forward overtravel warning	No. 3	Yes
E952	E952.0	Reverse overtravel warning	No. 3	Yes

List of Warning Codes

Fault code	Fault subcode	Alarm Name	Fault Level	Resettable
E980	E980.0	Encoder algorithm error	No. 3	Yes
E990	E990.1	Pulse input overspeed warning	No. 3	Yes
EA41	EA41.0	Torque fluctuation compensation failure	No. 3	Yes

7 Fault Code Table

No. 1 non-resettable faults:

Table 7-1 List of No. 1 non-resettable faults

Fault code	Fault subcode	Name	Fault Level	Resettable
E101	E101.0	Abnormal parameters in groups H02 and above	No. 1	No
	E101.1	Parameter error in group H00/H01	No. 1	No
	E101.2	Address error in read/write operation after the number of parameters changes	No. 1	No
	E101.9	Parameter attribute initialization check error.	No. 1	No
E102	E102.0	FPGA communication establishment error	No. 1	No
	E102.1	FPGA initialization start error	No. 1	No
	E102.8	FPGA and MCU version mismatch	No. 1	No
E104	E104.1	MCU running timeout (MCU break down)	No. 1	No
	E104.2	FPGA running timeout (FPGA break down).	No. 1	No
	E104.4	MCU command update timeout	No. 1	No
E120	E120.0	Unknown encoder model	No. 1	No
	E120.1	Unknown motor model	No. 1	No
	E120.2	Unknown drive model	No. 1	No
	E120.5	Motor and drive current mismatch	No. 1	No
	E120.6	FPGA and motor model mismatch	No. 1	No
	E120.7	Model check error	No. 1	No
E136	E120.8	Junction temperature parameter check error	No. 1	No
	E136.0	Encoder ROM motor parameter check error	No. 1	No
E136	E136.1	Encoder ROM motor parameter read error	No. 1	No
	E201	E201.0	Phase-P overcurrent	No. 1
E201.1		Phase-U overcurrent	No. 1	No
E201.2		Phase-V overcurrent	No. 1	No
E201.4		Phase-N overcurrent	No. 1	No
E210	E210.0	Output short circuited to ground	No. 1	No
E234	E234.0	Runaway	No. 1	No
E740	E740.0	Encoder communication timeout	No. 1	No
	E740.2	Absolute encoder error	No. 1	No
	E740.3	Absolute encoder single-turn calculation error	No. 1	No
	E740.6	Encoder write error	No. 1	No

Fault code	Fault subcode	Name	Fault Level	Resettable
E765	E765.0	Nikon encoder over-temperature or overspeed	No. 1	No
EA33	EA33.0	Encoder read/write check error	No. 1	No

No. 1 resettable faults

Table 7-2 List of No. 1 resettable faults

Fault code	Fault subcode	Name	Fault Level	Resettable
E150	E150.0	STO safety state applied	No. 1	Yes
	E150.1	STO input state abnormal	No. 1	Yes
	E150.2	Abnormal measured buffer 5 V voltage	No. 1	Yes
	E150.3	STO input circuit hardware diagnosis failure	No. 1	Yes
	E150.4	PWM Buffer hardware diagnosis failure	No. 1	Yes
E208	E208.2	Encoder communication timeout	No. 1	Yes
	E208.4	FPGA current loop operation timeout	No. 1	Yes
E320	E320.0	The regenerative resistor is overloaded.	No. 1	Yes
E400	E400.0	Main circuit overvoltage	No. 1	Yes
E410	E410.0	Main circuit undervoltage	No. 1	Yes
	E410.1	Main circuit de-energized	No. 1	Yes
E500	E500.0	Motor overspeed	No. 1	Yes
	E500.1	Speed feedback overflow	No. 1	Yes
	E500.2	FPGA position feedback pulse overspeed	No. 1	Yes
E602	E602.0	Angle auto-tuning failure	No. 1	Yes
	E602.2	U/V/W phase sequence reversed	No. 1	Yes
E605	E605.0	Speed too fast upon S-ON	No. 1	Yes
E620	E620.0	Motor overload	No. 1	Yes
E625	E625.0	Brake abnormality enabled	No. 1	Yes
E626	E626.0	Brake abnormality disabled	No. 1	Yes
E630	E630.0	Motor stall overtemperature protection	No. 1	Yes
E640	E640.0	IGBT junction overtemperature	No. 1	Yes
	E640.1	Flywheel diode overtemperature	No. 1	Yes
E650	E650.0	Heatsink overtemperature	No. 1	Yes
E660	E660.0	The motor temperature is too high	No. 1	Yes
E939	E939.0	Motor power cables disconnected	No. 1	Yes

No. 2 resettable faults

Table 7-3 List of No. 2 resettable faults

Fault code	Fault subcode	Name	Fault Level	Resettable
E122	E122.1	Different DIs assigned with the same function	No. 2	Yes
	E122.2	Different DOs assigned with the same function	No. 2	Yes
	E122.3	Upper limit in the rotation mode too high	No. 2	Yes
	E122.4	Different VDIs assigned with the same function	No. 2	Yes
	E122.5	DI and VDI assigned with the same function	No. 2	Yes
E420	E420.0	Main circuit phase loss	No. 2	Yes
E661	E661.0	STune failure	No. 2	Yes
E662	E662.0	ETune failure	No. 2	Yes
E663	E663.0	ITune failure	No. 2	Yes
E664	E664.0	Resonance too strong	No. 2	Yes
E731	E731.0	Encoder battery failure	No. 2	Yes
E733	E733.0	An encoder multi-turn counting error occurs.	No. 2	Yes
E735	E735.0	Encoder multi-turn counting overflow	No. 2	Yes
E760	E760.0	Encoder over-temperature	No. 2	Yes
E994	E994.0	Station number conflict	No. 2	Yes
EB00	EB00.0	Position deviation too large	No. 2	Yes
	EB00.1	Position deviation overflow	No. 2	Yes
EB01	EB01.0	The position reference increment is too large.	No. 2	Yes
	EB01.1	Individual position reference increment too large	No. 2	Yes
	EB01.3	Reference overflow	No. 2	Yes
EB03	EB03.0	Electronic gear ratio beyond the limit - H05.02	No. 2	Yes
	EB03.1	Electronic gear ratio beyond the limit - Electronic gear ratio 1	No. 2	Yes
	EB03.2	Electronic gear ratio beyond the limit -Electronic gear ratio 2	No. 2	Yes
ED02	ED02.0	Modbus communication timeout	No. 2	Yes
ED03	ED03.0	CANLink communication failure	No. 2	Yes
ED04	ED04.0	CANOpen communication timeout	No. 2	Yes
ED05	ED05.0	CANOpen communication initialized	No. 2	Yes
ED08	ED08.0	CANOpen bus PDO transmission length error	No. 2	Yes
ED11	ED11.0	CANOpen sync period error too large	No. 2	Yes



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