

HP Integral Flow

VARIABLE FREQUENCY DRIVE



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Declaration of Conformity

Lafert Group hereby states that the HPI Eco product range conforms to the relevant safety provisions of the following council directives: 2014/30/EU (EMC) and 2014/35/EU (LVD)

Design and manufacture is in accordance with the following harmonised European standards:

EN 61800-5-1:2007:A11:2021	Adjustable speed electrical power drive systems. Safety requirements. Electrical, thermal and energy.
EN 61800-3:2018	Adjustable speed electrical power drive systems. EMC requirements and specific test methods.
EN61000-3-12:2021	Limits for harmonic currents produced by equipment connected to public low-voltage systems with input current > 16 A and ≤ 75 A per phase. Three phase 200V and three phase 400V HPI Eco products comply with IEC 61000-3-12 with respect to the THD without the need for Line Reactors, provided that the short-circuit power S_{SC} is greater than or equal to $S_{SC(min)}$ at the interface point between the user's supply and the public system. It is the responsibility of the installer or user of the equipment to ensure, by consultation with the distribution network operator if necessary, that the equipment is connected only to a supply with a short-circuit power S_{SC} greater than or equal to $S_{SC(min)}$ calculated as: $S_{SC(min)} = 320 \times V_{rated} \times I_{rated}$ Where V_{rated} is the drive rated voltage (phase to phase) and I_{rated} is the drive rated current (per phase)
EN 55011:2007	Limits and Methods of measurement of radio disturbance characteristics of industrial, scientific and medical (ISM) radio-frequency equipment (EMC).
EN60529: 992	Specifications for degrees of protection provided by enclosures.
EN60034	Text to come

Safe Torque OFF ("STO") Function

HPI Eco incorporates a hardware STO (Safe Torque Off) Function, designed in accordance with the standards listed below.

Standard	Classification	Independent Approval
EN 61800-5-2:2016	Type 2	*TUV
EN ISO 13849-1:2015	PL "d"	
EN 61508 (Part 1 to 7):2010	SIL 2	
EN60204-1:2018	Uncontrolled Stop "Category 0"	
EN 62061:2005/A2:2015	SIL CL 2	

Electromagnetic Compatibility

All HPI Ecos are designed with high standards of EMC in mind. All versions intended for use within the European Union are fitted with an internal EMC filter. This EMC filter is designed to reduce the conducted emissions back into the supply via the power cables for compliance with harmonised European standards.

It is the responsibility of the installer to ensure that the equipment or system into which the product is incorporated complies with the EMC legislation of the country of use. Within the European Union, equipment into which this product is incorporated must comply with the EMC Directive 2014/30/EU. This User Guide provides guidance to ensure that the applicable standards may be achieved.

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2 Year Warranty: All Lafert Group HPI Eco units carry a 2 year warranty against manufacturing defects from the date of manufacture. The manufacturer accepts no liability for any damage caused during or resulting from transport, receipt of delivery, installation or commissioning. The manufacturer also accepts no liability for damage or consequences resulting from inappropriate, negligent or incorrect installation, incorrect adjustment of the operating parameters of the drive, incorrect matching of the drive to the motor, incorrect installation, unacceptable dust, moisture, corrosive substances, excessive vibration or ambient temperatures outside of the design specification.

This user guide is the "original instructions" document. All non-English versions are translations of the "original instructions".

The contents of this User Guide are believed to be correct at the time of printing. In the interest of a commitment to a policy of continuous improvement, the manufacturer reserves the right to change the specification of the product or its performance or the contents of the User Guide without notice.

This User Guide is for use with version 2.50 Firmware. The firmware version can be viewed in parameter P0-28. User Guide Revision 3.11

Lafert Group adopts a policy of continuous improvement and whilst every effort has been made to provide accurate and up to date information, the information contained in this User Guide should be used for guidance purposes only and does not form the part of any contract.

	When installing the drive on any power supply where the phase-ground voltage may exceed the phase-phase voltage (typically IT supply networks or Marine vessels) it is essential that the internal EMC filter ground and surge protection varistor ground (where fitted) are disconnected. If in doubt, refer to your Sales Partner for further information.
	This manual is intended as a guide for proper installation. Lafert Group cannot assume responsibility for the compliance or the non-compliance to any code, national, local or otherwise, for the proper installation of this drive or associated equipment. A hazard of personal injury and/or equipment damage exists if codes are ignored during installation.
	This HPI Eco contains high voltage capacitors that take time to discharge after removal of the main supply. Before working on the drive, ensure isolation of the main supply from line inputs. Wait ten (10) minutes for the capacitors to discharge to safe voltage levels. Failure to observe this precaution could result in severe bodily injury or loss of life.
	Only qualified electrical personnel familiar with the construction and operation of this equipment and the hazards involved should install, adjust, operate, or service this equipment. Read and understand this manual and other applicable manuals in their entirety before proceeding. Failure to observe this precaution could result in severe bodily injury or loss of life.

1. Introduction

1.1. Important Safety Information

Please read the IMPORTANT SAFETY INFORMATION below, and all Warning and Caution information elsewhere.



Danger: Indicates a risk of electric shock, which, if not avoided, could result in damage to the equipment and possible injury or death.

This variable speed drive product (HPI Eco) is intended for professional incorporation into complete equipment or systems as part of a fixed installation. If installed incorrectly it may present a safety hazard. The HPI Eco uses high voltages and currents, carries a high level of stored electrical energy, and is used to control mechanical plant that may cause injury. Close attention is required to system design and electrical installation to avoid hazards in either normal operation or in the event of equipment malfunction. Only qualified electricians are allowed to install and maintain this product.

System design, installation, commissioning and maintenance must be carried out only by personnel who have the necessary training and experience. They must carefully read this safety information and the instructions in this Guide and follow all information regarding transport, storage, installation and use of the HPI Eco, including the specified environmental limitations.

Do not perform any flash test or voltage withstand test on the HPI Eco. Any electrical measurements required should be carried out with the HPI Eco disconnected. Internal surge arrestors are fitted, intended to protect against damage due to mains borne spikes, which will result in the product failing the flash test.

Electric shock hazard! Disconnect and ISOLATE the HPI Eco before attempting any work on it. High voltages are present at the terminals and within the drive for up to 10 minutes after disconnection of the electrical supply. Always ensure by using a suitable multimeter that no voltage is present on any drive power terminals prior to commencing any work.

Where supply to the drive is through a plug and socket connector, do not disconnect until 10 minutes have elapsed after turning off the supply.

Ensure correct earthing connections and cable selection as per defined by local legislation or codes. The drive may have a leakage current of greater than 3.5mA; furthermore the earth cable must be sufficient to carry the maximum supply fault current which normally will be limited by the fuses or MCB. Suitably rated fuses or MCB should be fitted in the mains supply to the drive, according to any local legislation or codes.

Do not carry out any work on the drive control cables whilst power is applied to the drive or to the external control circuits.



Danger: Indicates a potentially hazardous situation other than electrical, which if not avoided, could result in damage to property.

Within the European Union, all machinery in which this product is used must comply with Directive 98/37/EC, Safety of Machinery. In particular, the machine manufacturer is responsible for providing a main switch and ensuring the electrical equipment complies with EN60204-1.

The level of integrity offered by the HPI Eco control input functions – for example stop/start, forward/reverse and maximum speed, is not sufficient for use in safety-critical applications without independent channels of protection. All applications where malfunction could cause injury or loss of life must be subject to a risk assessment and further protection provided where needed.

The driven motor can start at power up if the enable input signal is present.

The STOP function does not remove potentially lethal high voltages. ISOLATE the drive and wait 10 minutes before starting any work on it. Never carry out any work on the Drive, Motor or Motor cable whilst the input power is still applied.

Do not activate the automatic fault reset function on any systems whereby this may cause a potentially dangerous situation.

IP66 outdoor drives can be installed in a pollution degree 4 environment.

HPI Ecos are intended for indoor use only, unless specifically stated as being suitable for installation outdoors and installed in accordance with the Manufacturers guidelines.

When mounting the drive, ensure that sufficient cooling is provided. Do not carry out drilling operations with the drive in place, dust and swarf from drilling may lead to damage.

The entry of conductive or flammable foreign bodies should be prevented. Flammable material should not be placed close to the drive.

Relative humidity must be less than 95% (non-condensing).

Ensure that the supply voltage, frequency and 3 Phase Voltage corresponds to the rating of the HPI Eco.

Never connect the mains power supply to the Output terminals U, V, W.

Do not install any type of automatic switchgear between the drive and the motor. This may cause the drive protection to activate, resulting in a trip and loss of operation.

Wherever control cabling is close to power cabling, maintain a minimum separation of 100 mm and arrange crossings at 90 degrees.

Ensure that all terminals are tightened to the appropriate torque setting.

Do not attempt to carry out any repair of the HPI Eco. In the case of suspected fault or malfunction, contact the Lafert Group Technical Department for further assistance.

2. General Information and Ratings

2.1. Identifying the Drive by Model Number

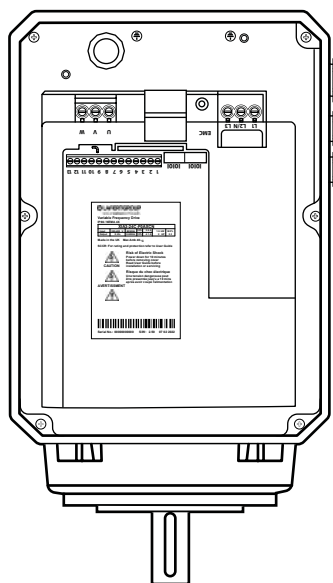
Each drive can be identified by its model number, shown below. The model number is on the shipping label and the drive nameplate. The model number includes the drive and factory fitted options.

	X	I	F	3	-	2	4	B	-	F	O	#	X	C	#	
Drive																Cable Glands Thread N: NPT gland holes M: Metric gland holes W: Gland plate window
Product I: Motor Mount																Lid Option C: Plain lid
Family F: Flow (Eco)																Display X: No display
Generation 3																IP Version A: IP66 Non-Switched E: IP66 With Disconnect
Size 2: 90 Frame 3: 112 Frame																Brake O: No Brake Chopper
Voltage 2: 3x200V 4: 3x400V 6: 3x600V																EMC Filter O: Non-Filtered F: Filtered
Power B: 0.75kW E: 3.0kW H: 7.5kW C: 1.5kW F: 4.0kW I: 11kW D: 2.2kW G: 5.5kW J: 15kW																

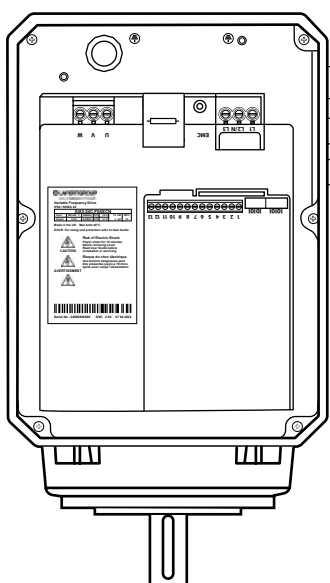
2.2. Product Rating Label Location

All HPI Eco models carry a rating label, which can be located as follows:

HPI 90 Models



HPI 112 Models



2.3. Understanding the Rating Label

The product rating label provides the following information.

	Key
1	Model Code
2	Enclosure Type and IP Rating
3	Firmware Version
4	Serial Number
5	Technical Data – Supply Voltage
6	Technical Data – Maximum continuous output current

IP66 Label

LAFERTGROUP
Member of Sumitomo Drive Technologies

Variable Frequency Drive
IP66 / NEMA 4X

XIA3-24C-F0AXCN

Input	380-480 V	50/60Hz	3 Ph	3.5 A	1.5 kW	IE2%
Output	0-Vin	0-500Hz	3 Ph	4.1 A	2 HP	2.3

Made in the UK Max Amb 40°C

SCCR: For rating and protection refer to User Guide

CAUTION
Risk of Electric Shock
Power down for 10 minutes before removing cover
Read User Guide before installation or servicing

AVERTISSEMENT
Risque du choc électrique
Une tension dangereuse peut être présentée jusqu'à 10 mins après avoir coupé l'alimentation

Serial No.: 00000000000 S/W: 2.50 07 02 2022

2.4. Drive Model Numbers

2.4.1. IP66 Outdoor Rated Enclosed Units

3ph 200-240V IP66 with Windows				
EMC filter & disconnect	EMC filter	Power [kW]	Output Current [A]	Frame Size
XIF3-22B-FOEXCW	XIF3-22B-FOAXCW	0.75	4.3	2
XIF3-22C-FOEXCW	XIF3-22C-FOAXCW	1.5	7	2
XIF3-22D-FOEXCW	XIF3-22D-FOAXCW	2.2	10.5	2
XIF3-22E-FOEXCW	XIF3-22E-FOAXCW	3	14	2
XIF3-32F-FOEXCW	XIF3-32F-FOAXCW	4	18	3
XIF3-32G-FOEXCW	XIF3-32G-FOAXCW	5.5	24	3
XIF3-32H-FOEXCW	XIF3-32H-FOAXCW	7.5	30	3
3ph 380-480V with Windows				
EMC filter & disconnect	EMC filter	Power [kW]	Output Current [A]	Frame Size
XIF3-24B-FOEXCW	XIF3-24B-FOAXCW	0.75	2.2	2
XIF3-24C-FOEXCW	XIF3-24C-FOAXCW	1.5	4.1	2
XIF3-24D-FOEXCW	XIF3-24D-FOAXCW	2.2	5.8	2
XIF3-24F-FOEXCW	XIF3-24F-FOAXCW	4	9.5	2
XIF3-24G-FOEXCW	XIF3-24G-FOAXCW	5.5	14	2
XIF3-34G-FOEXCW	XIF3-34G-FOAXCW	5.5	14	3
XIF3-34H-FOEXCW	XIF3-34H-FOAXCW	7.5	18	3
XIF3-34I-FOEXCW	XIF3-34I-FOAXCW	11	24	3
XIF3-34J-FOEXCW	XIF3-34J-FOAXCW	15	30	3

3ph 500-600V IP66 Plain without filter				
Non-filtered & disconnecter	Non-filtered	Power [kW]	Output Current [A]	Frame Size
XIA3-26B-00AXCN	90	0.75	2.1	No
XIA3-26C-00AXCN	90	1.5	3.1	No
XIA3-26D-00AXCN	90	2.2	4.1	No
XIA3-26F-00AXCN	90	4	6.5	No
XIA3-26G-00AXCN	90	5.5	9	No
XIA3-36H-00AXCN	112	7.5	12	No
XIA3-36I-00AXCN	112	11	17	No
XIA3-36J-00AXCN	112	15	22	No

2.4.2. Low Harmonic Variants

The majority of the HPI Eco product range is based on a low harmonic solution using film capacitor technology to achieve compliance with EN 61000-3-12 without the need for any additional equipment. This standard specifies limits for harmonic currents for equipment connected to public low-voltage systems with input current > 16A and ≤ 75A per phase. It is important to understand which models from the product range are of the low harmonic technology which is detailed below.

The HPI Eco three phase 200V (200-240V) input and three phase 400V (380-480V) input drives frame sizes 2 and 3 are a lower harmonic drive using film capacitor technology. Please refer to the product rating tables in section 2.4. *Drive Model Numbers* for confirmation.

In short, this means that the low harmonic drives do not require an input choke and should not have one installed.

3. Mechanical Installation

3.1. General

- Do not mount flammable material close to the HPI Eco.
- Ensure that the minimum cooling air gaps, as detailed in sections 3.6. *Guidelines for Mounting (IP66 Units) on page 10* are left clear.
- Ensure that the ambient temperature range does not exceed the permissible limits for the HPI Eco given in section 10.1. *Environmental*.
- Provide suitable clean, moisture and contaminant free cooling air sufficient to fulfil the cooling requirements of the HPI Eco.

3.2. Before Installation

- Carefully unpack the HPI Eco and check for any signs of damage. Notify the shipper immediately if any exist.
- Check the drive rating label to ensure it is of the correct type and power requirements for the application.
- To prevent accidental damage always store the HPI Eco in its original box until required. Storage should be clean and dry and within the temperature range -40°C to $+60^{\circ}\text{C}$.

3.3. UL Compliant Installation

Note the following for UL-compliant installation:

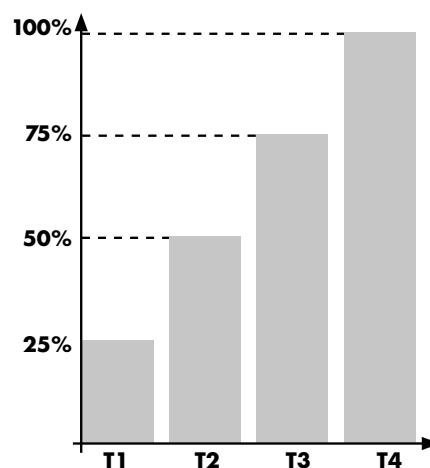
- For an up to date list of UL compliant products, please refer to UL listing NMMS.XXXXXX.
- The drive can be operated within an ambient temperature range as stated in section 10.1. *Environmental on page 43*.
- UL Listed ring terminals / lugs must be used for all bus bar and grounding connections.

Refer to section 10.6. *Additional Information for UL Compliance on page 45*.

3.4. Installation Following a Period of Storage

Where the drive has been stored for some time prior to installation, or has remained without the main power supply present for an extended period of time, it is necessary to reform the DC capacitors within the drive according to the following table before operation. For drives which have not been connected to the main power supply for a period of more than 2 years, this requires a reduced mains voltage mains voltage to be applied for a time period, and gradually increased prior to operating the drive. The voltage levels relative to the drive rated voltage, and the time periods for which they must be applied are shown in the following table. Following completion of the procedure, the drive may be operated as normal.

NOTE This is only valid for non low harmonic version - see section 2.4.2. *Low Harmonic Variants on page 7*.

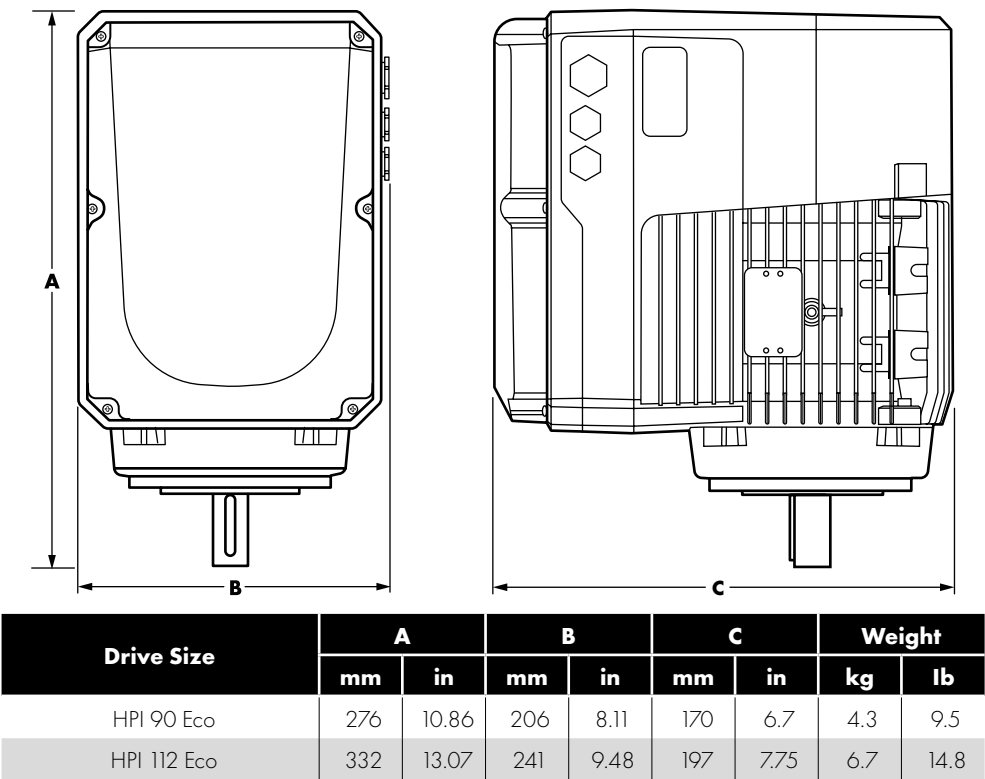


Storage Period /Power-OFF Period	Initial Input Voltage Level	Time Period T1	Secondary Input Voltage Level	Time Period T2	Third Input Voltage Level	Time Period T3	Final Input Voltage Level	Time Period T4
Up to 1 Year	100%	N/A						
1 – 2 Years	100%	1 Hour	N/A					
2 – 3 Years	25%	30 Minutes	50%	30 Minutes	75%	30 Minutes	100%	30 Minutes
More than 3 Years	25%	2 Hours	50%	2 Hours	75%	2 Hours	100%	2 Hours

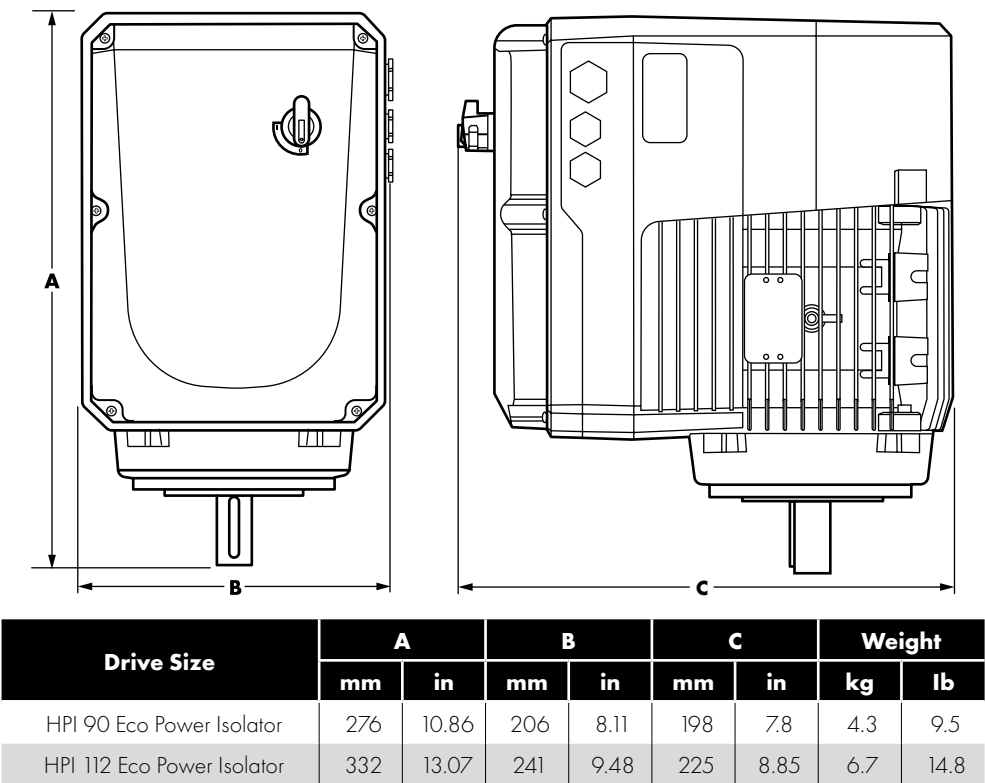
3.5. Mechanical Dimensions and Weight

3.5.1. IP66 Units

HPI



HPI Power Isolator

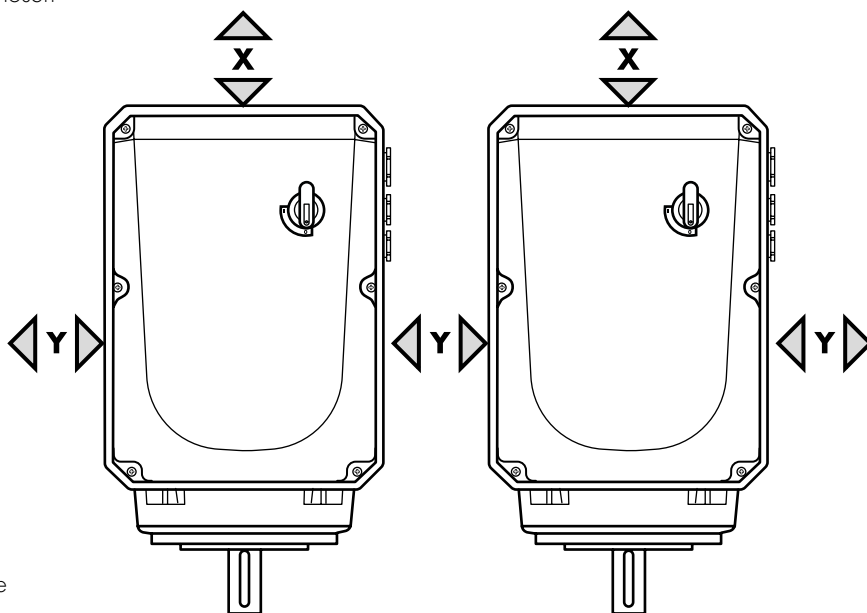


Mounting Bolts		
Frame Size	Metric	UNF
All Sizes	M4	#8

Tightening Torques			
	Frame Size	Required Torque	
Control Terminals	HPI 90 & 112	0.5 Nm	4.5 lb-in
Power Terminals	HPI 90 & 112	0.8 Nm	7 lb-in

3.6. Guidelines for Mounting (IP66 Units)

- Before mounting the drive, ensure that the chosen location meets the environmental condition requirements for the drive shown in section 10.1. *Environmental* on page 43.
- Suitable cable glands to maintain the ingress protection of the drive are required. Gland holes for power are pre-moulded into the drive enclosure, recommended gland sizes are shown below. Gland holes for control cables may be cut as required.
- The mounting location should be free from vibration that exceed 1g.
- Do not mount the drive in any area with excessive humidity, corrosive airborne chemicals or potentially dangerous dust particles.
- Avoid mounting close to high heat sources.
- The drive must not be mounted in direct sunlight. If necessary, install a suitable shade cover.
- The mounting location must be free from frost.
- Do not restrict the flow of air through the drive heatsink. The drive generates heat which must be naturally allowed to dissipate. Correct air clearance around the drive must be observed.
- If the location is subject to wide ambient temperature and air pressure variation, install a suitable pressure compensation valve in the drive gland plate.



NOTE If the drive has been in storage for a period longer than 2 years, the DC link capacitors must be reformed.

Drive Size	X Above		Y Either Side	
	mm	in	mm	in
90	200	7.87	200	7.87
112	200	7.87	200	7.87
NOTE	Above are guidelines only and the operating ambient temperature of the drive MUST be maintained within the limits shown in section 10.1. <i>Environmental</i> at all times.			

3.7. Routine Maintenance

The drive should be included within the scheduled maintenance program so that the installation maintains a suitable operating environment, this should include:

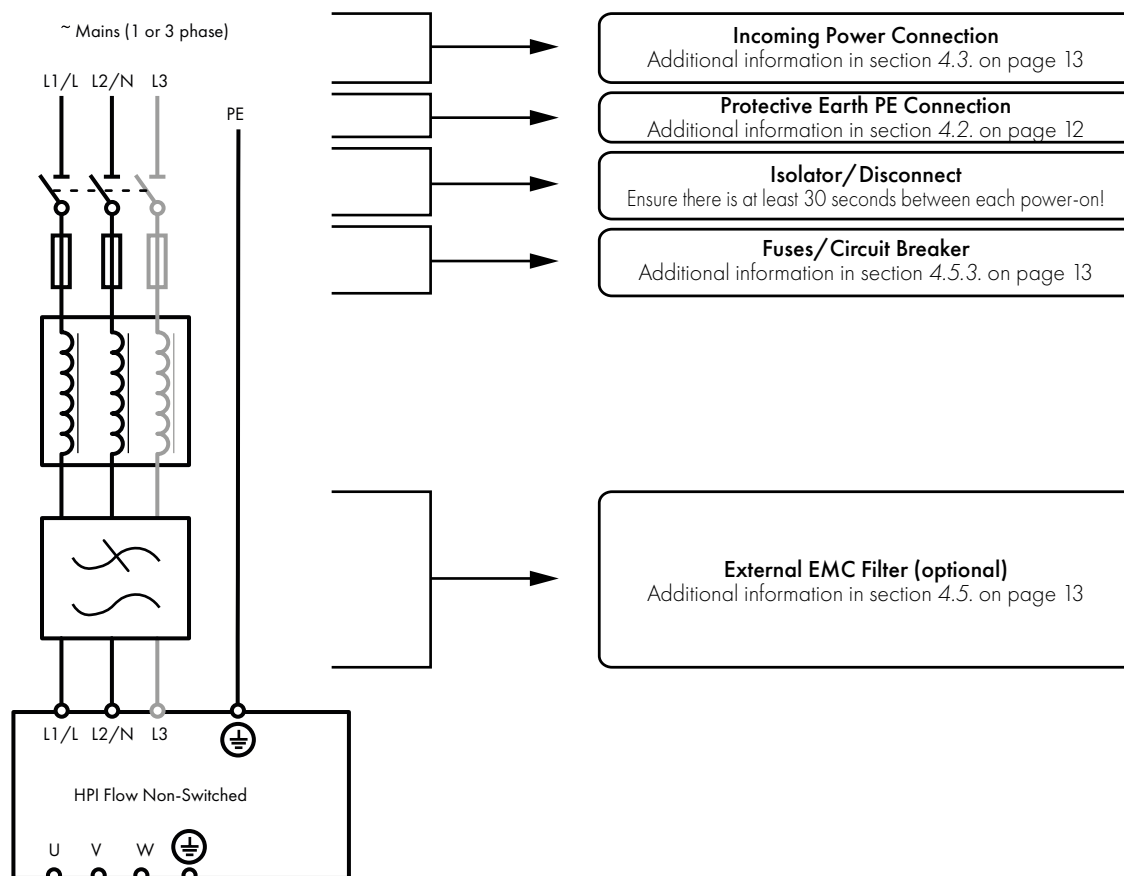
- Ambient temperature is at or below that set out in the section 10.1. *Environmental* on page 43, with any relevant derating applied.
- If the drive is mounted within an enclosure:
 - Ensure this is free from dust and condensation.
 - Ensure sufficient ventilation of clean cooling air is provided.
 - Ensure any panel ventilation fans and air filters are clean and provide the correct required air flow.
- Checks should also be made on all electrical connections, ensuring screw terminals are correctly torqued; and that power cables have no signs of heat damage.

4. Electrical Installation

4.1. Connection Diagram

All power terminal locations are marked directly on the product.

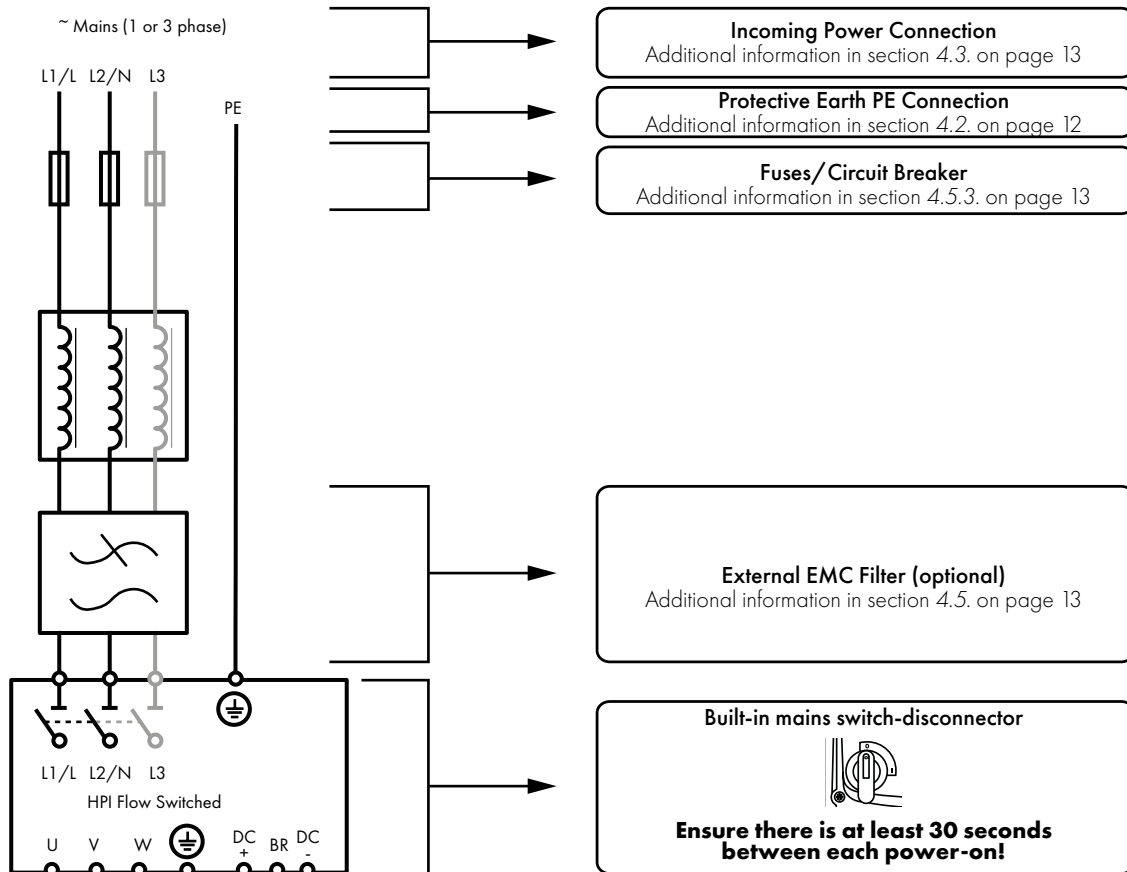
4.1.1. Electrical Power Connections



NOTE Enclosed drives are not suitable for rigid conduit system connection.

	This manual is intended as a guide for proper installation. Lafert Group cannot assume responsibility for the compliance or the non-compliance to any code, national, local or otherwise, for the proper installation of this drive or associated equipment. A hazard of personal injury and/or equipment damage exists if codes are ignored during installation.
	This HPI Eco contains high voltage capacitors that take time to discharge after removal of the main supply. Before working on the drive, ensure isolation of the main supply from line inputs. Wait ten (10) minutes for the capacitors to discharge to safe voltage levels. Failure to observe this precaution could result in severe bodily injury or loss of life.
	Only qualified electrical personnel familiar with the construction and operation of this equipment and the hazards involved should install, adjust, operate, or service this equipment. Read and understand this manual and other applicable manuals in their entirety before proceeding. Failure to observe this precaution could result in severe bodily injury or loss of life.

4.1.2. Electrical Power Connections – IP66 (NEMA 4X) Switched Models



4.2. Protective Earth (PE) Connection

4.2.1. Grounding Guidelines

Adequate safety earthing must be provided in accordance with local wiring rules and codes of practice. The ground terminal of each HPI Eco should be connected back to the common safety earth bar to maintain touch potentials within safe limits. The ground terminal of each HPI Eco should be individually connected DIRECTLY to the site ground bus bar (through the EMC filter if installed). HPI Eco ground connections should not loop from one drive to another, or to, or from any other equipment. Ground impedance must conform to local industrial safety regulations and/or electrical codes.

To meet UL regulations, UL approved ring crimp terminals should be used for all ground wiring connections.

The integrity of all ground connections should be checked periodically.

4.2.2. Protective Earth Conductor

The Cross sectional area of the PE Conductor must be at least equal to that of the incoming supply conductors.

4.2.3. Ground Fault Monitoring

As with all inverters, a leakage current to earth can exist. The HPI Eco is designed to produce the minimum possible leakage current whilst complying with worldwide standards. The level of current is affected by motor cable length and type, the effective switching frequency, the earth connections used and the type of RFI filter installed. If an ELCB (Earth Leakage Circuit Breaker) is to be used, the following conditions apply:

- A Type B Device must be used.
- Individual device should be used for each HPI Eco.
- The device must be suitable for protecting equipment with a DC component in the leakage current.
- The device should not be sensitive to high frequency leakage current.

4.3. Incoming Power Connection

- Power should be connected to the L1 and L2 terminals for single phase drives, L1, L2 and L3 for three phase drives. Phase sequence is not important.
- For compliance with CE and C Tick EMC requirements, a symmetrical shielded cable is recommended.
- A fixed installation is required according to IEC61800-5-1.
- For units without an internal isolator / disconnect, a suitable disconnecting device should be installed between the HPI Eco and the AC Power Source. The disconnecting device must conform to the local safety code / regulations (e.g. within Europe, EN60204-1, Safety of machinery).
- The cables should be dimensioned according to any local codes or regulations.
- Suitable fuses to provide wiring protection of the input power cable should be installed in the incoming supply line, according to the data in section 10.5. *Output Power and Current ratings*. The fuses must comply with any local codes or regulations in place. In general, type gG (IEC 60269) or UL type J, T or CC fuses are suitable; however in some cases type aR fuses may be required. The operating time of the fuses must be below 0.5 seconds.
- Where allowed by local regulations, suitably dimensioned type B MCB circuit breakers of equivalent rating may be utilised in place of fuses, providing that the clearing capacity is sufficient for the installation.
- When the power supply is removed from the drive, a minimum of 30 seconds should be allowed before re-applying the power. A minimum of 10 minutes should be allowed before removing the terminal covers or connection.
- The maximum permissible short circuit current at the HPI Eco Power terminals as defined in IEC60439-1 is 100kA.

4.4. EMC Compliant Installation

4.4.1. Recommended Cable Types by EMC Category

Number of Input Phases	Rated Supply Voltage	Frame Size	IP rating
3	400	90, 112	IP66

NOTE

- Data in brackets shows permissible cable length with additional external EMC filter.
- The 500 – 600V drives are not equipped with the internal EMC filter and are intended for use on second environment only.

General

- ¹ Compliance with category C1 conducted emissions only is achieved.

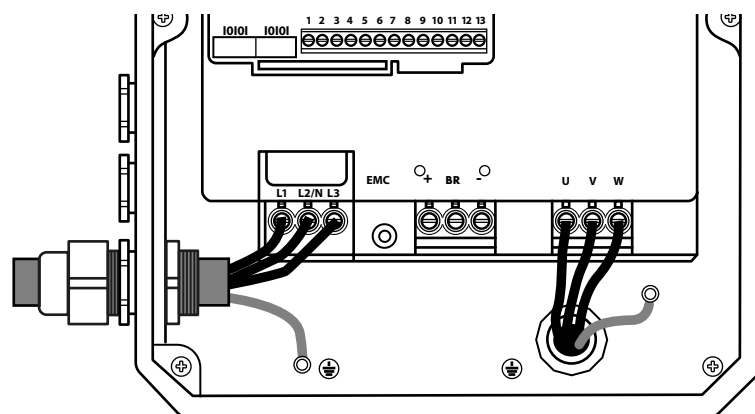
Supply Cable

- ² A screened (shielded) cable suitable for fixed installation with the relevant mains voltage in use. Braided or twisted type screened cable where the screen covers at least 85% of the cable surface area, designed with low impedance to HF signals. Installation of a standard cable within a suitable steel or copper tube is also acceptable - in this case, ensure that metal tube is adequately grounded.
- ³ A cable suitable for fixed installation with relevant mains voltage with a concentric protection wire. Installation of a standard cable within a suitable steel or copper tube is also acceptable.
- ⁴ A cable suitable for fixed installation with relevant mains voltage. A shielded type cable is not necessary.

Control Cable

- ⁵ A shielded cable with low impedance shield. Twisted pair cable is recommended for analog signals.

4.4.2. Recommended Cable Connections



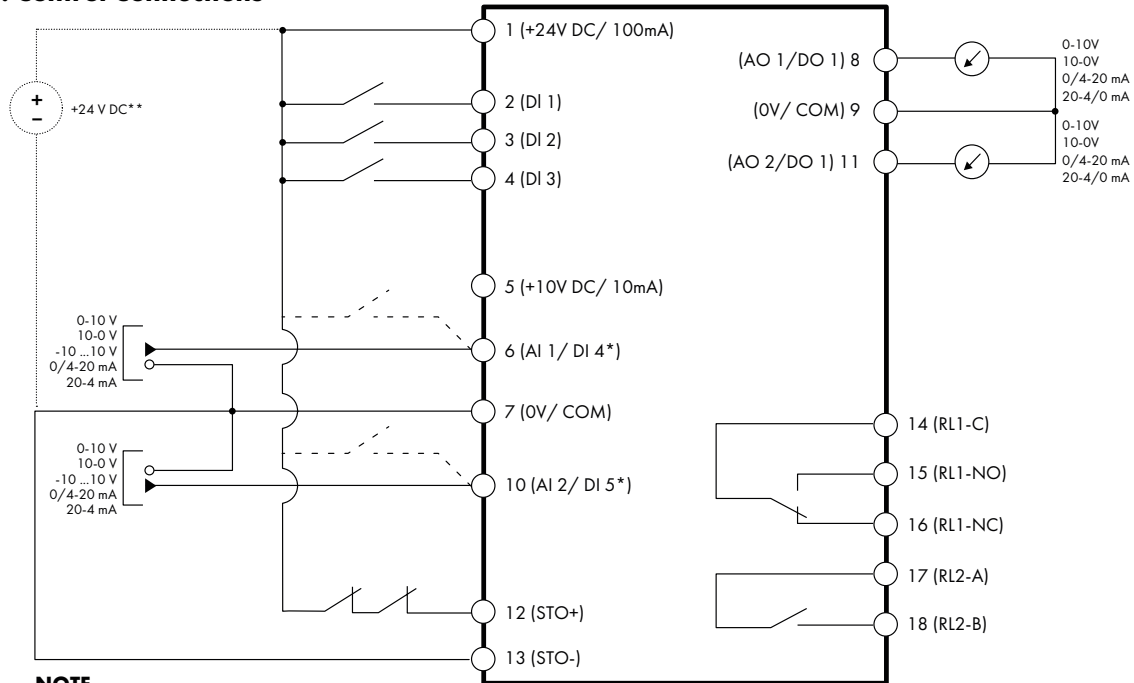
4.4.3. Wiring Precautions

Connect the HPI according to section 4.5. *Control Terminal Wiring*, ensuring that motor terminal box connections are correct. It is recommended that the power cabling should be 4-core PVC-insulated screened cable, laid in accordance with local industrial regulations and codes of practice.

4.5. Control Terminal Wiring

- All analog signal cables should be suitably shielded. Twisted pair cables are recommended.
- Power and Control Signal cables should be routed separately where possible, and must not be routed parallel to each other.
- Signal levels of different voltages e.g. 24 Volt DC and 110 Volt AC, should not be routed in the same cable.
- Maximum control terminal tightening torque is 0.5Nm.
- Control Cable entry conductor size: 0.05 – 2.5mm² / 30 – 12 AWG.

4.5.1. Control Connections



NOTE

* Dashed lines shows connection for analog inputs in digital mode ** Optional external 24 V DC power supply

Key			Default Function		Sec.	Page
			Open	Closed		
1	+24V DC	24 Volt DC Input / Output	On-board +24V DC Supply (100mA) or External 24V DC Input		4.10.1	15
2	DI 1	Digital Input 1 (Run Enable)	STOP	RUN	4.10.2	15
3	DI 2	Digital Input 2	Analog Input Reference	Preset Speed 1	4.10.2	15
4	DI 3	Digital Input 3	Analog Input 1 Reference	Analog Input 2 Reference	4.10.2	15
5	+10V DC	+10Volt DC Output	On-board +10V DC Supply (10 mA)			
6	AI 1 / DI 4	Analog Input 1 / Digital Input 4	Speed Reference 1 (0-10V)		4.10.3	15
7	0V / COM	0 Volt Common	0V Common for AI/AO/DI/DO			
8	AO 1	Analog Output 1	Motor Speed (0-10V)		4.10.4	16
9	0V / COM	0 Volt Common	0V Common for AI/AO/DI/DO			
10	AI 2 / DI 5	Analog Input 2 / Digital Input 5	Speed Reference 2 (0-10V)		4.10.3	15
11	AO2	Analog Output 2	Motor Current (0-10V)		4.10.4	16
12	STO+	STO + 24V DC Connection	InHibit	Run Permit	4.14	
13	STO-	STO 0 Volt Connection				
14	RL1-COM	Auxiliary Relay Output 1 Common			4.10.5	16
15	RL1-NO	Auxiliary Relay Output 1 Normally Open	Drive Healthy	Drive Faulty	4.10.5	16
16	RL1-NC	Auxiliary Relay Output 2 Normally Closed	Drive Faulty	Drive Healthy	4.10.5	16
17	RL2-A	Auxiliary Relay Output 2	Drive Stopped	Drive Running	4.10.5	16
18	RL2-B	Auxiliary Relay Output 2			4.10.5	16

NOTE

Digital Inputs: Logic High = 8-30V DC (30 V DC max)

Analog Outputs: 0 – 10 Volt / 4-20mA (20mA max)

SAFE TORQUE OFF input: Logic High = 18-30 Vdc (Also refer to section 4.8. Safe Torque Off on page 17)

4.6. Control Terminal Connections

4.6.1. +24VDC Input / Output

When the mains power is applied to the drive, terminal 1 provides a +24VDC output, maximum load 100mA. This may be used to activate digital inputs or provide power to sensors.

When no mains power is applied to the drive, the drive control electronics may be powered from an external +24VDC source. When powered in this way, all analog and digital I/O and communication functions remain operative, however the motor may not be operated, which allows safe testing and commissioning of the installation without risk of high voltage being present. When powered in this way, the drive requires up to 100mA.

4.6.2. Digital Inputs

Up to five digital inputs are available. The function of the inputs is defined by parameters P1-12 and P1-13, which are explained in section 7. *Control Terminal Functions* on page 23.

4.6.3. Analog Inputs

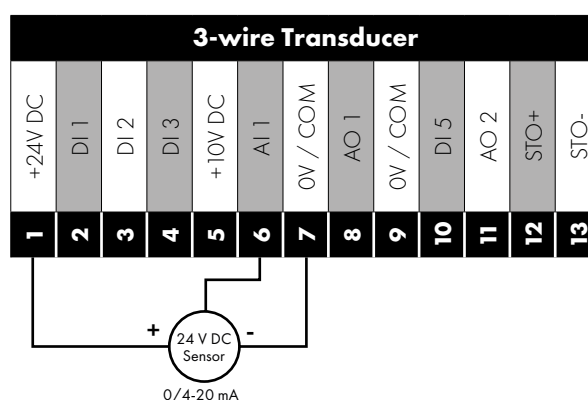
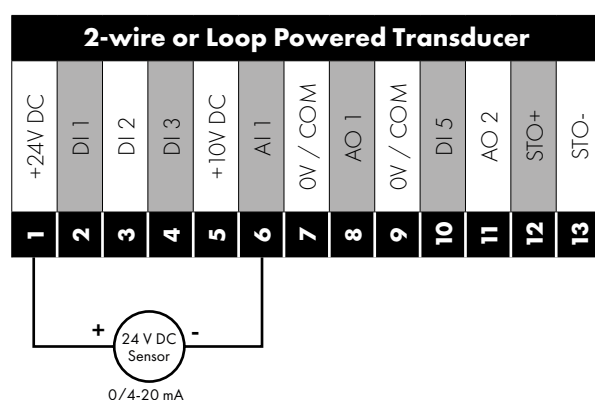
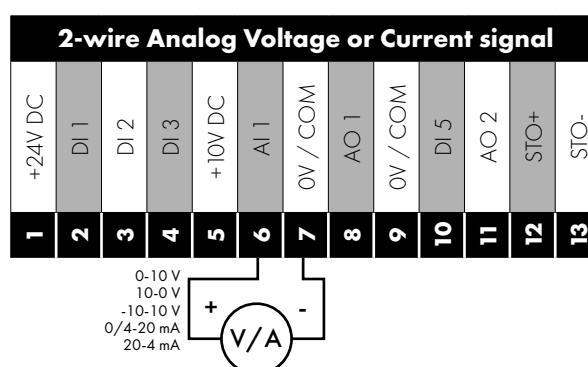
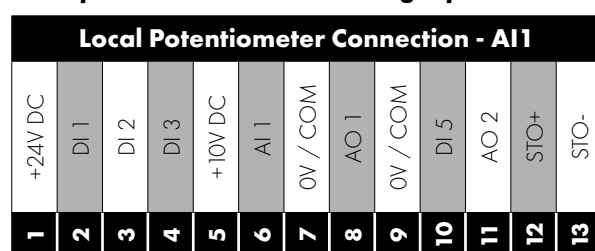
Two analog inputs are available, which may also be used as digital Inputs if required. The signal formats are selected by parameters as follows:

- Analog Input 1 Format Selection Parameter P2-30.
- Analog Input 2 Format Selection Parameter P2-33.

These parameters are described more fully in section 7.1. *Digital Input Configuration Parameter P1-13* on page 23.

The function of the analog input, e.g. for speed reference or PID feedback for example is defined by parameters P1-12 and P1-13. The function of these parameters and available options are described in section 7. *Control Terminal Functions* on page 23.

Example Connections for Analog Input



4.6.4. Analog Outputs

Two analog outputs are available, and may be used for 0 – 10 Volt Signal (max load 20mA), 0 – 20mA, 4 – 20mA or a digital +24Volt DC, 20mA output. The parameters to select function and format are as follows.

Analog Output	Function selected by	Format selected by
Analog Output 1	P2-11	P2-12
Analog Output 2	P2-13	P2-14

These parameters are described more fully in section 7.1. *Digital Input Configuration Parameter P1-13* on page 23.

4.6.5. Auxiliary Relay Outputs

Two relay outputs are available, which are intended to be used to switch external resistive loads up to 5A at 230 VAC or 30VDC.

Relay 1 has both normally open and normally closed contacts available. Relay 2 provides a simple open or closed contact.

The relay output function may be configured using parameters P2-15 and P2-18, which are described in section 7.1. *Digital Input Configuration Parameter P1-13* on page 23.

4.7. Motor Thermal Overload Protection

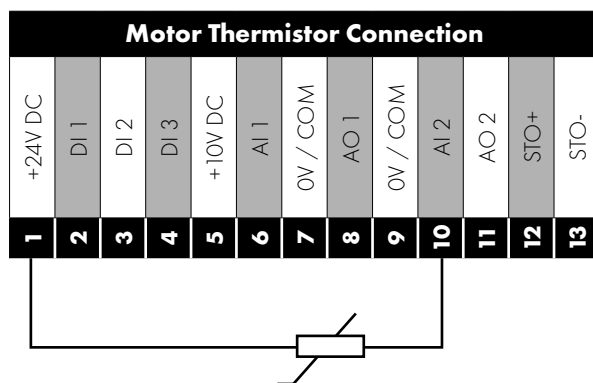
4.7.1. Internal Thermal Overload Protection

HPI Eco has internal motor overload protection (current limit) set at 150% of FLC. This level may be adjusted using P4-07.

The drive has an in-built motor thermal overload function; this is in the form of an "I.t-trP" trip after delivering >100% of the value set in P1-08 for a sustained period of time (e.g. 150% for 60 seconds).

4.7.2. Motor Thermistor Connection

Where a motor thermistor is to be used, it should be connected as follows:



Additional Information
<ul style="list-style-type: none"> Compatible Thermistor: PTC Type, 2.5kΩ trip level. Use a setting of P1-13 that has DI5/AI2 function as E-TRIP "External Trip", e.g. P1-13 = 6. Refer to section 7.2. <i>Digital Input Configuration Parameter P1-13</i> on page 38 for further details. Enable the Motor PTC Thermistor Input function in parameter P2-33.

4.8. Safe Torque Off

Safe Torque OFF will be referred to as "STO" through the remainder of this section.

4.8.1. Responsibilities

The overall system designer is responsible for defining the requirements of the overall "Safety Control System" within which the drive will be incorporated; furthermore the system designer is responsible for ensuring that the complete system is risk assessed and that the "Safety Control System" requirements have been entirely met and that the function is fully verified, this must include confirmation testing of the "STO" function before drive commissioning.

The system designer shall determine the possible risks and hazards within the system by carrying out a thorough risk and hazard analysis, the outcome of the analysis should provide an estimate of the possible hazards, furthermore determine the risk levels and identify any needs for risk reduction. The "STO" function should be evaluated to ensure it can sufficiently meet the risk level required.

4.8.2. What STO Provides

The purpose of the "STO" function is to provide a method of preventing the drive from creating torque in the motor in the absence of the "STO" input signals (Terminal 12 with respect to Terminal 13), this allows the drive to be incorporated into a complete safety control system where "STO" requirements need to be fulfilled.¹

The "STO" function can typically eliminate the need for electro-mechanical contactors with cross-checking auxiliary contacts as per normally required to provide safety functions.²


The drive has the "STO" Function built-in as standard and complies with the definition of "Safe torque off" as defined by IEC 61800-5-2:2007.

The "STO" Function also corresponds to an uncontrolled stop in accordance with category 0 (Emergency Off), of IEC 60204-1. This means that the motor will coast to a stop when the "STO" function is activated, this method of stopping should be confirmed as being acceptable to the system the motor is driving.

The "STO" function is recognised as a failsafe method even in the case where the "STO" signal is absent and a single fault within the drive has occurred, the drive has been proven in respect of this by meeting the following safety standards:

	SIL (Safety Integrity Level)	PFHD (Probability of dangerous Failures per Hour)	SFF (Safe failure fraction %)	Lifetime assumed
EN 61800-5-2	2	1.23E-09 1/h (0.12 % of SIL 2)	50	20 Yrs
	PL (Performance Level)	CCF (%) (Common Cause Failure)	MTTFd	Category
EN ISO 13849-1	PL d	1	4525a	3
	SILCL			
EN 62061	SILCL 2			

NOTE The values achieved above maybe jeopardised if the drive is installed outside of the Environmental limits detailed in section 10.1. Environmental.

	Disconnect and ISOLATE the drive before attempting any work on it. The "STO" function does not prevent high voltages from being present at the drive power terminals.
	¹ NOTE The "STO" function does not prevent the drive from an unexpected re-start. As soon as the "STO" inputs receive the relevant signal it is possible (subject to parameter settings) to restart automatically, Based on this, the function should not be used for carrying out short-term non-electrical machinery operations (such as cleaning or maintenance work).
	² NOTE In some applications additional measures may be required to fulfil the systems safety function needs: the "STO" function does not provide motor braking. In the case where motor braking is required a time delay safety relay and/or a mechanical brake arrangement or similar method should be adopted, consideration should be made over the required safety function when braking as the drive braking circuit alone cannot be relied upon as a fail safe method.
	When using permanent magnet motors and in the unlikely event of multiple output power devices failing then the motor could effectively rotate the motor shaft by 180/p degrees (Where p denotes number of motor pole pairs).

4.8.3. "STO" Operation

When the "STO" inputs are energised, the "STO" function is in a standby state, if the drive is then given a "Start signal/command" (as per the start source method selected in P1-13) then the drive will start and operate normally.

When the "STO" inputs are de-energised then the STO Function is activated and stops the drive (Motor will coast), the drive is now in "Safe Torque Off" mode.

4.8.4. "STO" Status and Monitoring

There are a number of methods for monitoring the status of the "STO" input, these are detailed below:

Drive Display

In Normal drive operation (Mains AC power applied), when the drives "STO" input is de-energised ("STO" Function activated) the drive will highlight this by displaying "InHibit", (**NOTE** If the drive is in a tripped condition then the relevant trip will be displayed and not "InHibit").

Drive Output Relay

- Drive relay 1: Setting P2-15 to a value of "13" will result in relay opening when the "STO" function is activated.
- Drive relay 2: Setting P2-18 to a value of "13" will result in relay opening when the "STO" function is activated.

"STO" Fault Codes

Fault Code	Code Number	Description	Corrective Action
"Sto-F"	29	A fault has been detected within either of the internal channels of the "STO" circuit.	Refer to the Lafert Group Technical Department

4.8.5. "STO" Function response time

The total response time is the time from a safety related event occurring to the components (sum of) within the system responding and becoming safe. (Stop Category 0 in accordance with IEC 60204-1).

- The response time from the "STO" inputs being de-energised to the output of the drive being in a state that will not produce torque in the motor ("STO" active) is less than 1ms.
- The response time from the "STO" inputs being de-energised to the "STO" monitoring status changing state is less than 20ms.
- The response time from the drive sensing a fault in the STO circuit to the drive displaying the fault on the display/Digital output showing drive not healthy is less than 20ms.

4.8.6. "STO" Electrical Installation



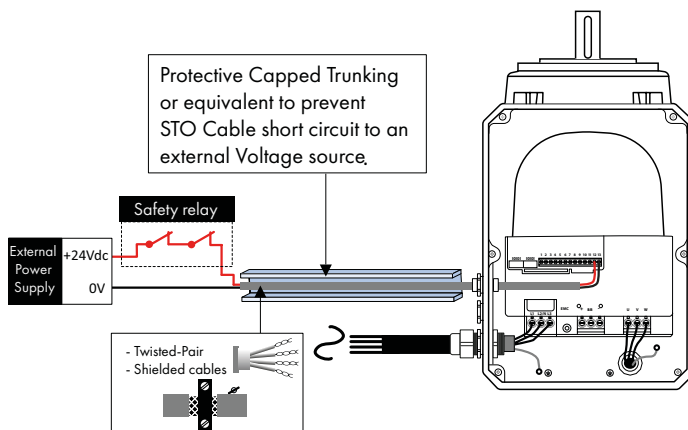
The "STO" wiring shall be protected from inadvertent short circuits or tampering which could lead to failure of the "STO" input signal, further guidance is given in the diagrams below.

In addition to the wiring guidelines for the "STO" circuit below, section 4.4. *EMC Compliant Installation* should also be followed.

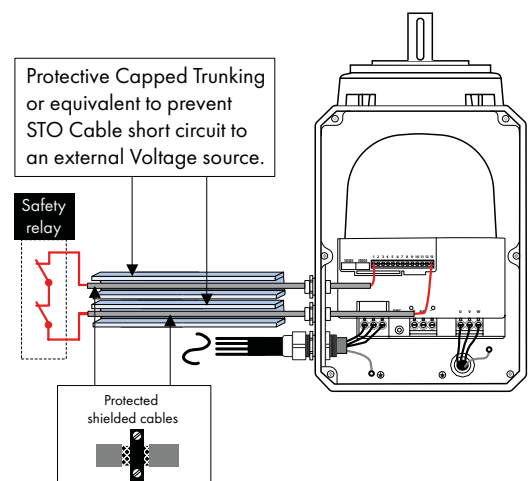
The drive should be wired as illustrated below; the 24Vdc signal source applied to the "STO" input can be either from the 24Vdc on the drive or from an External 24Vdc power supply.

4.8.7. Recommended "STO" Wiring

Using an External 24V DC Power Supply



Using the Drives On-board 24V DC Supply





NOTE The Maximum cable length from Voltage source to the drive terminals should not exceed 25 metres.

4.8.8. External Power Supply Specification

Voltage Rating (Nominal)	24V DC
STO Logic High	18-30V DC (Safe torque off in standby)
Current Consumption (Maximum)	100mA

4.8.9. Safety Relay Specification

The safety relay should be chosen so that at minimum it meets the safety standards in which the drive meets.

Standard Requirements	SIL2 or PLd SC3 or better (with forcibly guided contacts)
Number of Output Contacts	2 independent
Switching Voltage Rating	30V DC
Switching Current	100mA

4.8.10. Enabling the “STO” Function

The “STO” function is always enabled in the drive regardless of operating mode or parameter changes made by the user. In order to ensure that the drive does not immediately re-start when the STO is energised, the 'start mode' (P2-36) should be set to 'Edge-r' as opposed to the default value of 'Auto-O'. This means that when the drive is ready to run (STO active and drive healthy), it will only start when it sees a rising edge on the run command.

4.8.11. Testing the “STO” Function

Before commissioning the system the “STO” function should always be tested for correct operation, this should include the following tests:

- With the motor at standstill, and a stop command given to the drive (as per the start source method selected in P1-13):
 - De-energise the “STO” inputs (Drive will display “InHibit”).
 - Give a start command (as per the start source method selected in P1-13) and check that the drive still displays “Inhibit” and that the operation is in line with the section 4.8.3. “STO” Operation and 4.8.4. “STO” Status and Monitoring on page 18.
- With the motor running normally (from the drive):
 - De-energise the “STO” inputs.
 - Check that the drive displays “InHibit” and that the motor stops and that the operation is in line with the section 4.8.3. “STO” Operation and 4.8.4. “STO” Status and Monitoring “STO” Function Maintenance.

The “STO” function should be included within the control systems scheduled maintenance program so that the function is regularly tested for integrity (Minimum once per year), furthermore the function should be integrity tested following any safety system modifications or maintenance work.

If drive fault messages are observed refer to section 11.1. Fault Messages for further guidance.

5. Commissioning

5.1. General

The following guidelines apply to all applications:

5.1.1. Entering the Motor Nameplate Information

HPI Eco uses the information from the motor nameplate to:

- Operate the motor with the best possible efficiency level.
- Protect the motor against possible damage due to operation in overload condition.

In order to achieve this, the HPI Eco requires that the following information from the motor nameplate is entered into the parameters:

P1-07 Motor Rated Voltage.

P1-08 Motor Rated Current. This is the full load current of the motor from the nameplate.

P1-09 Motor Rated Frequency. This is the standard operating frequency of the motor, generally 50 or 60Hz.

P1-10 Motor Rated Speed. This parameter can optionally be set to the Rpm shown on the motor nameplate. When this parameter is entered, all speed related parameters in the drive are displayed in Rpm. When the parameter is set to zero, all speed related parameters are displayed in Hz.

5.1.2. Minimum and Maximum Frequencies / Speeds

HPI Eco units are factory set to operate the motor from zero up to base speed. In general, this operating range is suitable for a wide range of requirements, however in some cases it may be desired to adjust these limits, e.g. where the maximum speed of a fan or pump may provide excessive flow, or where operation below a certain speed is never required. In this case, the following parameters can be adjusted to suit the application:

P1-01 Maximum Frequency. In general this should match the motor rated frequency. If operation above this frequency is desired, confirmation from the motor manufacturer, and the manufacturer of any connected fan or pump should be sought that this is permissible, and will not cause damage to the equipment.

P1-02 Minimum Frequency. A suitable minimum can be set to prevent the motor operating at low speed, which may cause the motor to overheat. In some applications, such as a pump circulating water through a boiler, it may be necessary to set a speed to ensure the boiler does not run dry during operation.

5.1.3. Acceleration and Deceleration Ramp Times

HPI Eco units are factory set with acceleration and deceleration ramp rates set to 30 seconds. The default value is suitable for the majority of applications but can be altered by changing the values in parameters P1-03 and P1-04. Care must be taken to ensure the driven load is capable of performing the specified ramps and that nuisance trips due to excessively short ramp times are not produced.

The ramp times entered in the parameter set always specify the time taken to ramp between 0Hz and motor rated speed P1-09.

For example: If ramp rate = 30 seconds and P1-09 (motor base speed) = 150Hz, and assuming the motor is currently running at 50Hz and the drive is commanded to accelerate to 150Hz. The time taken to reach 150Hz would be 30 seconds (P1-03) / 150 (P1-09) * 50 (required change in speed) = 10(s).

P1-03 Acceleration Ramp Rate: Time taken for the drive to accelerate the motor from 0Hz to Motor base speed, P1-09 in seconds.

P1-04 Deceleration Ramp Rate: Time taken for the drive to decelerate the motor from Motor base speed, P1-09 to 0Hz in seconds.

5.1.4. Stop Mode Selection

HPI Eco units can be programmed to either apply a fixed deceleration to the motor during stopping, or to release control of the motor and allow it to coast or free-wheel to a stop. The default selection is for the drive is ramp to stop and behaviour is programmed using parameter P1-05.

P1-05 Stop Mode Select: Defines how the motor will be stopped in the event of the enable input being removed from the drive. Ramp to stop (P1-05 = 0) will ramp the drive to stop using the value for deceleration entered in P1-04. Coast to stop (P1-05 = 1) will allow the motor to coast to stop (uncontrolled).

5.1.5. Voltage Boost

Voltage boost is used to increase the applied motor voltage at low output frequencies, in order to improve low speed and starting torque. Excessive boost levels may result in increased motor current and temperature, and force ventilation of the motor may be required.

The default value for Torque boost is set 0.0%, and this should only be increased if the starting torque is insufficient. Ensure that the correct Constant or Variable Torque mode is set in P4-01 before adjusting the boost.

P1-11 Torque Boost: Set as a percentage of motor rated voltage P1-07.

6. Parameters

6.1. Parameter Set Overview

The HPI Eco Extended Parameter set consists of 7 groups as follows:

- Group 1 – Basic Parameter Set
- Group 2 – Extended Parameter Set
- Group 3 – User PID Control Parameter Set
- Group 4 – Motor Control Parameters
- Group 5 – Field Bus Communications Parameter Set
- Group 8 – Application Specific Functions Parameter Set
- Group 0 – Monitoring and Diagnostic Parameters (Read Only).

When the HPI Eco is reset to factory defaults, or is in its factory supplied state, only Group 1 Parameters can be accessed. In order to allow access to parameters from the higher level groups, P1-14 must be set to the same value as P2-40 (Default setting = 101). With this setting, parameter groups 1 – 5 and group 8 can be accessed, along with the first 39 parameters in Group 0. These parameters are listed in the tables below.

For advanced parameter access, P1-14 can be set to the same value as P6-30 (Default setting = 201), which allows access to all parameter groups and ranges.

6.2. Parameter Group 1 – Basic Parameters

Par.	Parameter Name	Minimum	Maximum	Default	Units	
P1-01	Maximum Frequency/Speed Limit	Motor Rating Dependent			Hz / Rpm	
	Maximum output frequency or motor speed limit – Hz or Rpm. If P1-10 >0, the value entered / displayed is in Rpm.					
	NOTE The maximum possible setting is limited to the lowest value of: <ul style="list-style-type: none">▪ 5 x P1-09▪ 5 x P1-10▪ P2-24 / 16▪ 500.0Hz					
P1-02	Minimum Frequency/Speed Limit	Motor Rating Dependent			Hz / Rpm	
	Minimum speed limit – Hz or Rpm. If P1-10 >0, the value entered / displayed is in Rpm.					
P1-03	Acceleration Ramp Time	0.0	6000.0	30.0	Seconds	
	Acceleration ramp time from 0 to base speed (P1-09) in seconds.					
P1-04	Deceleration Ramp Time	0.0	6000.0	30.0	Seconds	
	Deceleration ramp time from base speed (P1-09) to standstill in seconds.					
P1-05	Stop Mode		0	2	0	-
	0	Ramp	When the enable signal is removed, the drive will ramp to stop, with the rate controlled by P1-04 as described above.			
	1	Coast	When the enable signal is removed the motor will coast (freewheel) to stop.			
	2	AC Flux Braking	Provides additional braking torque capability when decelerating.			
P1-07	Motor Rated Voltage / kE	0	Motor Rating Dependent		Volts	
	For PM Motors - Enter the back EMF at rated motor speed.					
P1-08	Motor Rated Current	Motor Rating Dependent			Amps	
	This parameter should be set to the rated (nameplate) current of the motor.					
P1-09	Motor Rated Frequency	Motor Rating Dependent			Hz	
	This parameter should be set to the rated (nameplate) current of the motor.					
P1-10	Motor Rated Speed	Motor Rating Dependent			Rpm	
	This parameter can optionally be set to the rated (nameplate) Rpm of the motor. When set to the default value of zero, all speed related parameters are displayed in Hz, and the slip compensation for the motor is disabled. Entering the value from the motor nameplate enables the slip compensation function, and the HPI Eco display will now show motor speed in estimated Rpm. All speed related parameters, such as Minimum and Maximum Speed, Preset Speeds etc. will also be displayed in Rpm.					

Par.	Parameter Name	Minimum	Maximum	Default	Units	
P1-11	Torque Boost	Motor Rating Dependent			%	
	Torque Boost is used to increase the applied motor voltage and hence current at low output frequencies. This can improve low speed and starting torque. Increasing the boost level will increase motor current at low speed, which may result in the motor temperature rising - force ventilation of the motor may then be required. In general, the lower the motor power, the higher the boost setting that may be safely used.					
P1-12	Primary Command Source		0	6	0	-
	0	Terminal Control	The drive responds directly to signals applied to the control terminals.			
	1	Keypad control - uni-directional	The drive can be controlled in the forward direction only using an internal or remote Keypad.			
	2	Keypad control - uni-directional	As above.			
	3	PID Control	The output frequency is controlled by the internal PID controller.			
	4	Fieldbus Control	By the selected Fieldbus (Group 5 Parameters) – Excludes BACnet (see option 6).			
	5	Slave Mode	The drive acts as a Slave to a connected HPI Eco operating in Master Mode.			
	6	BACNet MS/TP Mode	Drive communicates / responds as a slave within a BACnet network.			
P1-13	Digital Input Function	0	14	1	-	
	Defines the function of the digital inputs. When set to 0 the inputs are user defined using group 9 parameters or the PLC software function in the software package. When set to a value other than 0 the digital input configuration is defined by digital input definition table (see section 7.1. <i>Digital Input Configuration Parameter P1-13</i>).					
P1-14	Extended Menu Access	0	30000	0	-	
	Parameter Access Control. The following settings are applicable:					
	P1-14 <> P2-40 and P1-14 <> P6-30: Allows access to Parameter Group 1 only. P1-14 = P2-40 (101 default): Allows access to Parameter Groups 0 - 5 and group 8. P1-14 = P6-30 (201 default): Allows access to Parameter Groups 0 - 9.					

7. Control Terminal Functions

7.1. Digital Input Configuration Parameter P1-13

P1-13 *(2)	Local (Hand) Control Function	Digital Input 1 (Terminal 2)	Digital Input 2 (Terminal 3)	Digital Input 3 (Terminal 4)	Analog Input 1 (Terminal 6)	Analog Input 2 (Terminal 10)	Notes	
0	N/A	All functions User defined in Menu 9 or configured through PLC function in HP Drive Tools studio software suite.						
1*(3)	Analog Input 2	O: Stop C: Run/Enable	O: Normal Operation C: Preset 1/ PI Set-point 2	O: Remote Ctrl C: Local Ctrl	Analog In 1	Analog In 2	When Input 3 is Closed: Speed Reference = Analog Input 2 Start Command = Input 1 In PI Mode, Analog Input 1 must be used for feedback	
2		O: No Function C: Momentary Start	O: Stop (Disable) C: Run Permit	O: Remote Ctrl C: Local Ctrl	Analog In 1	Analog In 2		
3		O: Stop C: Run/Enable	O: Forward C: Reverse	O: Remote Ctrl C: Local Ctrl	Analog In 1	Analog In 2		
4		O: Stop C: Run/Enable	O: Fire Mode *(1) C: Normal Operation*(1)	O: Remote Ctrl C: Local Ctrl	Analog In 1	Analog In 2		
5	Preset Speeds	O: Stop C: Run/Enable	O: Preset Speed 1 C: Preset Speed 2	O: Remote Ctrl C: Local Ctrl	Analog In 1	O: Ext Trip C: Normal Operation	When Input 3 is Closed: Speed Reference = Preset Speed 1 / 2 Start Command = Input 1	
6		O: No Function C: Momentary Start	O: Stop (Disable) C: Run Permit	O: Remote Ctrl C: Local Ctrl	Analog In 1	O: Preset 1 C: Preset 2I		
7		O: Stop C: Run/Enable	O: Forward C: Reverse	O: Remote Ctrl C: Local Ctrl	Analog In 1	O: Preset 1 C: Preset 2		
8		O: Stop C: Run/Enable	O: Fire Mode *(1) C: Normal Operation*(1)	O: Remote Ctrl C: Local Ctrl	Analog In 1	O: Preset 1 C: Preset 2		
9*(3)	Keypad Speed Reference	O: Stop C: Run/Enable	O: Normal Operation C: Preset 1/ PI Set-point 2	O: Remote Ctrl C: Local Ctrl	Analog In 1	Analog In 2	When Input 3 is Closed: Speed Reference = Keypad Start Command = Determined by P2-37	
10*(3)		O: Stop C: Run/Enable	O: Normal Operation C: Preset 1/ PI Set-point 2	O: Remote Ctrl C: Local Ctrl	Analog In 1	O: Ext Trip C: Normal Operation		
11		O: No Function C: Momentary Start	O: Stop (Disable) C: Run Permit	O: Remote Ctrl C: Local Ctrl	Analog In 1	Analog In 2		
12		O: Stop C: Run Fwd	O: Forward C: Reverse	O: Remote Ctrl C: Local Ctrl	Analog In 1	Analog In 2		
13		O: Stop C: Run Fwd	O: Fire Mode *(1) C: Normal Operation*(1)	O: Remote Ctrl C: Local Ctrl	Analog In 1	Analog In 2		
14		O: Stop C: Run	O: Forward C: Reverse	Digital input 3	Analog input 1	Analog input 2	Preset Speed	
				Off	Off	Off	Preset Speed 1	
				On	Off	Off	Preset Speed 2	
				Off	On	Off	Preset Speed 3	
				On	On	Off	Preset Speed 4	
				Off	Off	On	Preset Speed 5	
				On	Off	On	Preset Speed 6	
				Off	On	On	Preset Speed 7	
On	On	On	Preset Speed 8					

Notes

*(1): Logic shown is as per the default setting. Fire mode logic can be configured through parameter P8-09.

*(2): Default setting for P1-13 = 1.

*(3): When the drive is in PID control (P1-12 = 3) and digital preset reference is selected (P3-05 = 0) then P1-13 can be set to 1, 9, or 10 to allow selection between two independent digital references using digital input 2. Digital preset reference 1 and 2 are set in P3-06 and P3-15 respectively.

NOTE "Motor thermistor trip" connection is via analog input 2 and is configured by parameter P2-33 (Ptc-Lh).

8. Extended Parameters


8.1. Parameter Group 2 – Extended parameters

Par.	Parameter Name	Minimum	Maximum	Default	Units
P2-01	Preset Frequency / Speed 1	-P1-01	P1-01	Motor Rating Dependent	Hz / Rpm
P2-02	Preset Frequency / Speed 2	-P1-01	P1-01	Motor Rating Dependent	Hz / Rpm
P2-03	Preset Frequency / Speed 3	-P1-01	P1-01	Motor Rating Dependent	Hz / Rpm
P2-04	Preset Frequency / Speed 4	-P1-01	P1-01	Motor Rating Dependent	Hz / Rpm
	Preset speeds can be selected by: <ul style="list-style-type: none"> Configuring P1-13 to an option that permits logic selection via the digital inputs (see section 7.1. <i>Digital Input Configuration Parameter P1-13</i>). Using the user defined logic configuration parameters in Parameter Group 9. Configured through the drive PLC function using the HP Drive Tools Studio PC software. 				
P2-05	Preset Speed 5 / Clean 1	-P1-01	P1-01	0.0	Hz / Rpm
	Preset speed 5 is automatically reference by the Pump Clean function when this is enabled. When the Pump Clean function is disabled, Preset speed 5 can be selected as per preset speeds 1 – 4.				
P2-06	Preset Speed 6 / Clean 2	-P1-01	P1-01	0.0	Hz / Rpm
	Preset speed 6 is automatically reference by the Pump Clean function when this is enabled. When the Pump Clean function is disabled, Preset speed 6 can be selected as per preset speeds 1 – 4.				
P2-07	Preset Speed 7 / Boost 1 / Pump Stir Speed	-P1-01	P1-01	0.0	Hz / Rpm
	Preset speed 7 is automatically referenced by the Start / Stop Boost function, or the Pump Stir Function, when these functions are enabled. When they are disabled, Preset speed 7 can be selected as per preset speeds 1 – 4.				
P2-08	Preset Speed 8 / Boost 2	-P1-01	P1-01	0.0	Hz / Rpm
	Preset speed 8 is automatically reference by the Start / Stop Boost function when this function is enabled. When disabled, Preset speed 8 can be selected as per preset speeds 1 – 4.				
P2-09	Skip Frequency Centre Point	P1-02	P1-01	0.0	Hz / Rpm
	Defines the centre point of the skip frequency band. The width of the skip frequency band is defined by: <ul style="list-style-type: none"> Lower limit = P2-09 - P2-10/2 Upper limit = P2-09 + P2-10/2 All skip frequency bands defined for forward speeds are mirrored for negative speeds.				
P2-10	Skip Frequency Band Width	0.0	P1-01	0.0	Hz / Rpm
	Defines the width of the skip frequency band. The width of the skip frequency band is defined by: <ul style="list-style-type: none"> Lower limit = P2-09 - P2-10/2 Upper limit = P2-09 + P2-10/2 All skip frequency bands defined for forward speeds are mirrored for negative speeds.				

Par.	Parameter Name	Minimum	Maximum	Default	Units	
P2-11	Analog Output 1 Function		0	12	8	-
	Digital Output Mode. Logic 1 = +24V DC					
	0	Drive running	Logic 1 when the HPI Eco is enabled (Running).			
	1	Drive healthy	Logic 1 when no Fault condition exists on the drive.			
	2	At speed	Logic 1 when the output frequency matches the setpoint frequency.			
	3	Motor speed > 0	Logic 1 when the motor runs above zero speed.			
	4	Motor speed >= limit	Logic 1 when the motor speed exceeds the adjustable limit.			
	5	Motor current >=limit	Logic 1 when the motor current exceeds the adjustable limit.			
	6	Motor torque >= Limit	Logic when the motor torque exceeds the adjustable limit.			
	7	Analog input 2 >=limit	Logic when the signal applied to the Analog Input 2 exceeds the adjustable limit.			
	NOTE When using settings 4 – 7, parameters P2-16 and P2-17 must be used together to control the behaviour. The output will switch to Logic 1 when the selected signal exceeds the value programmed in P2-16, and return to Logic 0 when the signal falls below the value programmed in P2-17.					
	Analog Output Mode					
	8	Motor speed	0 to P1-01.			
	9	Motor current	0 to 200% of P1-08.			
	10	Motor torque	0 to 200% of motor rated torque.			
	11	Motor power	0 to 150% of drive rated power.			
	12	PID Output	Output from the internal PID Controller, 0 – 100%.			
P2-12	Analog Output 1 Format		-	-	U 0-10	-
	U 0-10 = 0 to 10V					
	U 10-0 = 10 to 0V					
	A 0-20 = 0 to 20mA					
	A 20-0 = 20 to 0mA					
	A 4-20 = 4 to 20mA					
	A 20-4 = 20 to 4mA					
P2-13	Analog Output 2 Function		0	12	9	-
	Digital Output Mode. Logic 1 = +24V DC					
	0	Drive running	Logic 1 when the HPI Eco is enabled (Running).			
	1	Drive healthy	Logic 1 when no Fault condition exists on the drive.			
	2	At speed	Logic 1 when the output frequency matches the setpoint frequency.			
	3	Motor speed > 0	Logic 1 when the motor runs above zero speed.			
	4	Motor speed >= limit	Logic 1 when the motor speed exceeds the adjustable limit.			
	5	Motor current >= limit	Logic 1 when the motor current exceeds the adjustable limit.			
	6	Motor torque >= limit	Logic when the motor torque exceeds the adjustable limit.			
	7	Analog input 2 >= limit	Logic when the signal applied to the Analog Input 2 exceeds the adjustable limit.			
	NOTE When using settings 4 – 7, parameters P2-19 and P2-20 must be used together to control the behaviour. The output will switch to Logic 1 when the selected signal exceeds the value programmed in P2-19, and return to Logic 0 when the signal falls below the value programmed in P2-20.					
	Analog Output Mode					
	8	Motor speed	0 to P1-01.			
	9	Motor current	0 to 200% of P1-08.			
	10	Motor torque	0 to 200% of motor rated torque.			
	11	Motor power	0 to 150% of drive rated power.			
	12	PID output	Output from the internal PID Controller, 0 – 100%.			

Par.	Parameter Name	Minimum	Maximum	Default	Units
P2-14	Analog Output 2 Format	-	-	U 0-10	-
	U-10 = 0 to 10V U-0 = 10 to 0V R 0-20 = 0 to 20mA R 20-0 = 20 to 0mA R 4-20 = 4 to 20mA R 20-4 = 20 to 4mA				
P2-15	Relay 1 Function	0	15	1	-
	Selects the function assigned to Relay Output 1. The relay has normally open and normally closed contacts. Logic 1 indicates the relay is active, and therefore the normally open contact is closed (terminals 14 and 15 will be linked together) and the normally closed contact is opened (terminals 14 and 16 will no longer be connected together). Settings 4, 5, 6, 7 & 14 use the adjustable limit parameters P2-16 and P2-17. The Output switches to Logic 1 (relay closed) when the chosen analog value exceeds the Upper Threshold (P2-16) and resets to Logic 0 (relay open) when the chosen analog value reduces below the Lower Threshold (P2-17). 0 : Drive running. Logic 1 when the motor is enabled. 1 : Drive healthy. Logic 1 when power is applied to the drive and no fault exists. 2 : At speed. Logic 1 when the output frequency matches the set-point frequency. 3 : Motor speed > 0. Logic 1 when the drive output frequency to the motor exceeds 0.0Hz. 4 : Motor speed >= limit. Logic 1 when the motor speed exceeds the adjustable limit. 5 : Motor current >=limit. Logic 1 when the motor current exceeds the adjustable limit. 6 : Motor Torque >=limit. Logic 1 when the motor torque exceeds the adjustable limit. 7 : Analog input 2 >=limit. Logic 1 when the signal applied to the Analog Input 2 exceeds the adjustable limit. 8 : Reserved. No Function. 9 : Fire mode active. Logic 1 when the drive in running in Fire Mode (Fire Mode input is active). 10 : Maintenance due. Logic 1 when Maintenance Timer expires indicating that Maintenance is now due. 11 : Drive ready to run. Logic 1 when drive is in Auto-mode, no trips are present, and the safety circuit is enabled indicating that drive is ready for automatic control. 12 : Drive tripped. Logic 1 when the drive has tripped and the display shows the fault code. 13 : STO Status. Logic 1 when both Hardware Enable (STO) inputs are present and the drive is able to be operated. 14 : PID error >=limit. The PID Error (difference between setpoint and feedback) is greater than or equal to the programmed limit. 15 : Low & high current warning. Logic 1 when the load monitoring has been enabled using P8-06 to P8-08 and a high load or low load condition has been detected – usually used to signal pump blockage or burst pipe.				
P2-16	Relay 1 / AO1 Upper Limit	P2-17	200.0	100.0	%
	Sets the upper limited value for P2-11 and P2-15, please refer to P2-11 or P2-15.				
P2-17	Relay 1 / AO1 Lower Limit	0	P2-16	0.0	%
	Sets the lower limited value for P2-11 and P2-15, please refer to P2-11 or P2-15.				
P2-18	Relay 2 Function	0	15	0	-
	Selects the function assigned to Relay Output 2. The relay has two output terminals, Logic 1 indicates the relay is active, and therefore terminals 17 and 18 will be linked together. Settings 4, 5, 6, 7 & 14 use the adjustable limit parameters P2-19 and P2-20. The Output switches to Logic 1 (relay closed) when the chosen analog value exceeds the Upper Threshold (P2-19) and resets to Logic 0 (relay open) when the chosen analog value reduces below the Lower Threshold (P2-20). 0 : Drive running. Logic 1 when the motor is enabled. 1 : Drive healthy. Logic 1 when power is applied to the drive and no fault exists. 2 : At speed. Logic 1 when the output frequency matches the set-point frequency. 3 : Motor speed > 0. Logic 1 when the drive output frequency to the motor exceeds 0.0Hz. 4 : Motor speed >= limit. Logic 1 when the motor speed exceeds the adjustable limit. 5 : Motor current >=limit. Logic 1 when the motor current exceeds the adjustable limit. 6 : Motor torque >= limit. Logic 1 when the motor torque exceeds the adjustable limit. 7 : Analog input 2 >=limit. Logic 1 when the signal applied to the Analog Input 2 exceeds the adjustable limit. 8 : Assist pump 1 control (DOL*). Contact your local sales partner for detailed instructions for DOL Cascade operation. 9 : Fire mode active. Logic 1 when the drive in running in Fire Mode (Fire Mode input is active). 10 : Maintenance due. Logic 1 when Maintenance Timer expires indicating that Maintenance is now due. 11 : Drive ready to run. Logic 1 when drive is in Auto-mode, no trips are present, and the safety circuit is enabled indicating that drive is ready for automatic control. 12 : Drive tripped. Logic 1 when the drive has tripped and the display shows the fault code. 13 : STO status. Logic 1 when both Hardware Enable (STO) inputs are present and the drive is able to be operated. 14 : PID error >=limit. The PID Error (difference between setpoint and feedback) is greater than or equal to the programmed limit. 15 : Low & high current warning. Logic 1 when the load monitoring has been enabled using P8-06 to P8-08 and a high load or low load condition has been detected – usually used to signal pump blockage or burst pipe.				

Par.	Parameter Name	Minimum	Maximum	Default	Units
P2-19	Relay 2 / AO2 Upper Limit	P2-20	200.0	100.0	%
	Sets the upper limited value for P2-13 and P2-18, please refer to P2-13 or P2-18.				
P2-20	Relay 2 / AO2 Lower Limit	0.0	P2-19	0.0	%
	Sets the lower limited value for P2-13 and P2-18, please refer to P2-13 or P2-18.				
P2-21	Display Scaling Factor	-30.000	30.000	0.000	-
	Determines the factor for the scaled display value. The variable selected in P2-22 is scaled by the factor set in P2-21.				
P2-22	Display Scaling Source	0	3	0	-
	Source value used when custom units are to be shown on the drive display. 0 : Motor Speed 1 : Motor Current 2 : Analog Input 2 3 : P0-80 Value NOTE P2-21 & P2-22 allow the user to program the HPI Eco display to show an alternative output unit scaled from an existing parameter (for example, to display conveyer speed in metres per second based on the output frequency). This function is disabled if P2-21 is set to 0. If P2-21 is set >0, the variable selected in P2-22 is multiplied by the factor entered in P2-21, and is shown on the drive display whilst the drive is running.				
P2-23	Zero Speed Holding Time	0.0	60.0	0.2	Seconds
	Determines the time for which the drive output frequency is held at zero when stopping, before the drive output is disabled.				
P2-24	Effective Switching Frequency	Motor Rating Dependent			kHz
	Effective power stage switching frequency. Higher frequencies reduce audible noise from the motor, and improve the output current waveform, at the expense of increased drive losses. NOTE De-rating of the drive output current may be required when increasing P2-24 beyond the minimum setting. Refer to section 10.8.3. Derating for Switching Frequency for further information.				
P2-25	Fast Decel Ramp Time	0.00	240.0	0.0	Seconds
	This parameter allows an alternative deceleration ramp down time to be programmed into the HPI Eco. Fast Deceleration ramp is selected Automatically in the case of a mains power loss if P2-38 = 2. When ramp rate in P2-25 is set to 0.0, the drive will coast to stop. Fast deceleration ramp can also be selected using the user defined logic configuration parameters in menu 9 (P9-02), or selection configured through the drive PLC function using the HP Drive Tools Studio PC software. In addition, if P2-25 > 0, P1-02 > 0, P2-10 = 0 and P2-09 = P1-02, this ramp time is applied to both acceleration and deceleration when operating below minimum speed, allowing selection of an alternative ramp when operating outside of the normal speed range, which may be useful in pump and compressor applications.				
P2-26	Spin Start Enable	0	2	1	-
	When Enabled, the drive will attempt to determine if the motor is already rotating on start up, and to detect rotational speed and direction. The drive will begin control of the motor from its present (detected) speed. A short delay may be observed when starting the drive whilst the spin start function is completed. 0 : Disabled 1 : Enabled 2 : Enabled following Trip, Brown Out or Coast Stop				
P2-27	Standby Mode Timer	0.0	250.0	20	Seconds
	This parameter defines the time period, whereby if the drive operates at the frequency / speed set in P3-14 (Standby speed threshold) for greater than the set time period, the HPI Eco output will be disabled, and the display will show Standby . The function is disabled if P2-27 = 0.0.				
P2-28	Slave Speed Scaling Control	0	3	0	-
	Active in Keypad mode (P1-12 = 1 or 2) and Slave mode (P1-12=5) only. The keypad reference can be multiplied by a preset scaling factor or adjusted using an analog trim or offset. 0 : Disabled. No scaling or offset is applied. 1 : Actual Speed = Digital Speed x P2-29 2 : Actual Speed = (Digital Speed x P2-29) + Analog Input 1 Reference 3 : Actual Speed = (Digital Speed x P2-29) x Analog Input 1 Reference				
P2-29	Slave Speed Scaling Factor	-500.0	500.0	%	100.0
	Slave speed scaling factor used in conjunction with P2-28.				

Par.	Parameter Name	Minimum	Maximum	Default	Units
P2-30	Analog Input 1 Format	See Below		U 0-10	-
	U 0-10 = 0 to 10 Volt Signal (Uni-polar). U 10-0 = 10 to 0 Volt Signal (Uni-polar). -10-10 = -10 to +10 Volt Signal (Bi-polar). R 0-20 = 0 to 20mA Signal. t 4-20 = 4 to 20mA Signal, the HPI Eco will trip and show the fault code 4-20F if the signal level falls below 3mA. r 4-20 = 4 to 20mA Signal, the HPI Eco will ramp to preset speed 4 (P2-04) if the signal level falls below 3mA. t 20-4 = 20 to 4mA Signal, the HPI Eco will trip and show the fault code 4-20F if the signal level falls below 3mA. r 20-4 = 20 to 4mA Signal, the HPI Eco will ramp to preset speed 4 (P2-04) if the signal level falls below 3mA.				
P2-31	Analog Input 1 Scaling	0.0	2000.0	100.0	%
	P2-31 is used to scale the analog input prior to being applied as a reference to the drive. For example, if P2-30 is set for 0 – 10V, and the scaling factor is set to 200.0%, a 5 volt input will result in the drive running at maximum speed (P1-01).				
P2-32	Analog Input 1 Offset	-500.0	500.0	0.0	%
	P2-32 defines an offset for the analog input, as a percentage of the full range of the input. A positive offset is deducted from the incoming analog signal and a negative offset is added to the signal. For example, if P2-30 is set for 0 – 10V, and the analog offset is set to 10.0%, then 1 volt (10% of 10V) will be deducted from the incoming analog reference prior to it being applied.				
P2-33	Analog Input 2 Format	See Below		U 0-10	-
	U 0-10 = 0 to 10 Volt Signal (Uni-polar). U 10-0 = 10 to 0 Volt Signal (Uni-polar). Ptc-th = Motor PTC Thermistor Input. R 0-20 = 0 to 20mA Signal. t 4-20 = 4 to 20mA Signal, the HPI Eco will trip and show the fault code 4-20F if the signal level falls below 3mA. r 4-20 = 4 to 20mA Signal, the HPI Eco will ramp to preset speed 4 (P2-04) if the signal level falls below 3mA. t 20-4 = 20 to 4mA Signal, the HPI Eco will trip and show the fault code 4-20F if the signal level falls below 3mA. r 20-4 = 20 to 4mA Signal, the HPI Eco will ramp to preset speed 4 (P2-04) if the signal level falls below 3mA.				
P2-34	Analog Input 2 Scaling	0.0	2000.0	100.0	%
	P2-34 is used to scale the analog input prior to being applied as a reference to the drive. For example, if P2-34 is set for 0 – 10V, and the scaling factor is set to 200.0%, a 5 volt input will result in the drive running at maximum speed (P1-01).				
P2-35	Analog Input 2 Offset	-500.0	500.0	0.0	%
	P2-35 defines an offset for the analog input, as a percentage of the full range of the input. A positive offset is deducted from the incoming analog signal and a negative offset is added to the signal. For example, if P2-33 is set for 0 – 10V, and the analog offset is set to 10.0%, then 1 volt (10% of 10V) will be deducted from the incoming analog reference prior to it being applied.				
P2-36	Start Mode Select / Automatic Restart	See Below		EdSE-r	-
	Defines the behaviour of the drive relating to the enable digital input and also configures the Automatic Restart function. EdSE-r : Following Power on or reset, the drive will not start if Digital Input 1 remains closed. The Input must be closed after a power on or reset to start the drive. Auto-0 : Following a Power On or Reset, the drive will automatically start if Digital Input 1 is closed. Auto-1 to Auto-5 : Following a trip, the drive will make up to 5 attempts to restart at 20 second intervals. The drive must be powered down to reset the counter. The number of restart attempts are counted, and if the drive fails to start on the final attempt, the drive will remain in the fault condition with the last active trip code, and will require the user to manually reset the fault.  DANGER! "Auto" modes allow the drive to Auto-start, therefore the impact on system/Personnel safety needs to be considered.				
P2-37	Keypad Start Mode	0	7	2	-
	Options 0 to 3 are only active when P1-12 = 1 or 2 (keypad Mode). With these settings, the drive waits for the keypad start button to be pressed before running. 0 : Minimum speed, keypad start. Following a stop and restart, the drive will always initially run at the minimum speed P1-02. 1 : Previous speed, keypad start. Following a stop and restart, the drive will return to the last keypad set-point speed used prior to stopping. 2 : Current speed, keypad start. Where the HPI Eco is configured for multiple speed references (typically Hand / Auto control or Local / Remote control), when switched to keypad mode by a digital input, the drive will continue to operate at the last operating speed. 3 : Preset speed 4, keypad start. Following a stop and restart, the HPI Eco will always initially run at Preset Speed 4 (P2-04). Options 4 to 7 are active in all control modes. Drive starting in these modes is controlled by the enable digital input on the control terminals. 4 : Minimum speed, terminal start. Following a stop and restart, the drive will always initially run at the minimum speed P1-02. 5 : Previous speed, terminal start. Following a stop and restart, the drive will return to the last keypad set-point speed used prior to stopping. 6 : Current speed, terminal start. Where the HPI Eco is configured for multiple speed references (typically Hand / Auto control or Local / Remote control), when switched to keypad mode by a digital input, the drive will continue to operate at the last operating speed. 7 : Preset speed 4, terminal start. Following a stop and restart, the HPI Eco will always initially run at Preset Speed 4 (P2-04).				

Par.	Parameter Name	Minimum	Maximum	Default	Units
P2-38	Mains Loss Stop / Ride Through	0	3	0	-
	<p>Controls the behaviour of the drive in response to a loss of mains power supply whilst the drive is enabled.</p> <p>0 : Reserved.</p> <p>1 : Coast to stop. The HPI Eco will immediately disable the output to the motor, allowing the load to coast or free wheel. When using this setting with high inertia loads, the Spin Start function (P2-26) may need to be enabled.</p> <p>2 : Fast ramp to stop. The drive will ramp to stop at the rate programmed in the Fast deceleration time P2-25. NA Coast to stop is the only applicable action on mains loss in the HPI Eco.</p> <p>3 : DC bus supply. NA Coast to stop is the only applicable action on mains loss in the HPI Eco</p>				
P2-39	Parameter Lock	0	1	0	-
	<p>0 : Unlocked. All parameters can be accessed and changed</p> <p>1 : Locked. Parameter values can be displayed, but cannot be changed. Also disables Hand and Auto button on keypad.</p>				
P2-40	Extended Menu Access Code	0	9999	101	-
	Defines the access code which must be entered in P1-14 to access parameter groups above Group 1.				

8.2. Parameter Group 3 – PID Control

Par.	Parameter Name	Minimum	Maximum	Default	Units
P3-01	PID Proportional Gain	0.1	30.0	1.0	-
	PID Controller Proportional Gain. Instantaneous error between the feedback and the set-point in the PID controller is multiplied by P3-01 to produce the output from the PID controller. Higher values of proportional gain produce a larger change in the drive output frequency in response to changes in the PID set-point or feedback signals. Too high a value can cause instability.				
P3-02	PID Integral Time	0.0	30.0	1.0	Seconds
	PID Controller Integral Time. Accumulated error in the PID control. Uses accumulated errors between set-point and feedback signals to influence the output from the PID controller. P3-02 is the time constant for accumulating error. Larger values provide a more damped response. Lower values result in a faster system response but may result in instability.				
P3-03	PID Differential Time	0.00	1.00	0.00	Seconds
	<p>PID Differential Time Constant. The Differential time constant references the rate of change of the feedback signal over time and works to slow the rate of change of the PID controller, particularly as it approaches the set-point. Setting a shorter time will decrease overshoot but slow down response and may lead to instability.</p> <p>NOTE P3-03 is set to 0 by default which disables the differential time constant. Care must be taken when adjusting this value outside of its default value.</p>				
P3-04	PID Operating Mode	0	1	0	-
	<p>0 : Direct operation. Use this mode if an increase in the feedback signal should result in a decrease in the motor speed.</p> <p>1 : Inverse operation. Use this mode if an increase in the feedback signal should result in an increase in the motor speed.</p>				
P3-05	PID Reference Select	0	2	0	-
	<p>Selects the source for the PID Reference / Set-point</p> <p>0 : Digital preset. P3-06 is used.</p> <p>1 : Analog input 1</p> <p>2 : Analog input 2</p>				
P3-06	PID Digital Reference Value	0.0	100.0	0.0	%
	When P3-05 = 0, this parameter sets the preset digital reference (set-point) used for the PID Controller.				
P3-07	PID Output Upper Limit	P3-08	100.0	100.0	%
	Limits the maximum value output from the PID controller.				
P3-08	PID Output Lower Limit	0.0	P3-07	0.0	%
	Limits the minimum output from the PID controller.				
P3-09	PID Output Limit Select	0	3	0	-
	<p>0 : Digital output limits. The output range of the PID controller is limited by the values of P3-07 & P3-08.</p> <p>1 : Upper limit set by analog input 1. The output range of the PID controller is limited by the values of P3-08 & the signal applied to Analog Input 1.</p> <p>2 : Lower limit set by analog input 1. The output range of the PID controller is limited by the signal applied to Analog Input 1 & the value of P3-07.</p> <p>3 : PID output added to analog input 1. The output value from the PID Controller is added to the speed reference applied to the Analog Input 1.</p>				

Par.	Parameter Name	Minimum	Maximum	Default	Units
P3-10	PID Feedback Select	0	5	0	-
	<p>Defines the source of the PID control feedback (location of the feedback sensor).</p> <p>0 : Analog input 2. 0 – 100.0%.</p> <p>1 : Analog input 1. 0 – 100.0%.</p> <p>2 : Motor current. 0 – 100.0% of P1-08 Value.</p> <p>3 : DC bus voltage. 0 – 1000 Volt = 0 – 100.0%.</p> <p>4 : Analog input 1 – Analog input 2. Differential of Analog 1 – Analog 2 = 0 – 100.0%.</p> <p>5 : Largest (analog input 1, analog input 2). The greater of Analog input 1 or Analog Input 2 is always used.</p>				
P3-11	PID Error to Enable Ramp	0.0	25.0	0.0	%
	<p>Defines a threshold PID error level, whereby if the difference between the set-point and feedback value is less than the set threshold, the internal ramp times of the drive are disabled to allow the drive to react quickly to small errors. Where a greater PID error exists, the ramp times are enabled to limit the rate of change of motor speed.</p> <p>Setting to 0.0 means that the drive ramps are always enabled. This parameter is intended to allow the user to disable the drive internal ramps where a fast reaction to the PID control is required, however by only disabling the ramps when a small PID error exists, the risk of possible over current or over voltage trips being generated is reduced.</p>				
P3-12	PID Feedback Display Scaling	0.000	50.000	0.000	-
	<p>Applies a scaling factor to the displayed PID feedback, allowing the user to display the actual signal level from a transducer, e.g. 0 – 10 Bar etc.</p>				
P3-13	PID Error Wake Level	0.0	100.0	5.0	%
	<p>Sets a programmable PID Error Level whereby if the drive enters standby mode whilst operating under PID control, the difference between the PID reference and PID feedback signals must exceed this error level to restart the PID controller.</p>				
P3-14	Standby Speed Threshold	0.0	P1-01	0.0	Hz / Rpm
	<p>Determines the level at which the drive will enter into standby mode. P2-27 must be set with a value (time) for standby function to be active. Drive enters standby mode if motor speed remains below the level set in P3-14 for the time period set in P2-27.</p>				
P3-15	PID Reference 2 Value	0.0	100.0	0.0	%
	<p>When P3-05 = 0, and the 2nd digital reference is selected (see section 7.1. <i>Digital Input Configuration Parameter P1-13</i>) this parameter sets the preset digital reference (set-point) used for the PID Controller.</p>				
P3-16	Pump Prime Time	0	2000	0	Seconds
	<p>A value other than zero in this parameter will automatically enable the burst pipe detection function. Each time the drive is enabled whilst in PID control or is switched to PID control, the drive will monitor the PID feedback level for the time entered in P3-16. If the PID feedback level does not exceed the threshold entered in P3-17 before the time in P3-16 expires then the drive will trip with "Pr-Lo" (pressure low) trip.</p>				
P3-17	Burst Pipe Threshold	0.0	100.0	0.0	%
	<p>PID feedback threshold for the burst pipe detection. In direct PID mode, PID feedback should be equal to or greater than this threshold before the pump prime time (P3-16) expires. In inverse PID mode, PID feedback should be less than or equal to the threshold before the pump prime time (P3-16) expires.</p>				
P3-18	PID Reset Control	0	1	0	-
	<p>0 : Continuous Run. PID loop will continue running as long as P gain (P3-01) is not zero.</p> <p>1 : On drive Enable. PID loop will only run when the drive is enabled. If the drive is not running, PID output will reset to 0 (Including integral result).</p>				
P3-19	Burst Pipe Detection Trip Delay	0	600	0	Seconds
	<p>When burst pipe detection is enabled by configuring parameters P3-16 & P3-17, this parameter adds a delay/filter to the "Pr-Lo" trip. This can be useful in situations where the system has been operating in steady state and sudden closing and then re-opening of valves can cause an overshoot of pressure followed by an undershoot which could trigger the "Pr-Lo" trip unnecessarily.</p>				

8.3. Parameter Group 4 – High Performance Motor Control



Incorrect adjustment of parameters in menu group 4 can cause unexpected behaviour of the motor and any connected machinery. It is recommended that these parameters are only adjusted by experienced users.

Par.	Parameter Name	Minimum	Maximum	Default	Units
P4-01	Motor Control Mode	0	6	3	-
	3 : PM Motor, Vector Speed Control. Control mode for AC Permanent Magnet Motors.				
P4-02	Auto-tune Enable	0	1	0	-
	When set to 1, the drive immediately carries out a non-rotating auto-tune to measure the motor parameters for optimum control and efficiency. Following completion of the auto-tune, the parameter automatically returns to 0.				
P4-03	Vector Speed Controller Proportional Gain	0.1	400.0	50.0	%
	Sets the proportional gain value for the speed controller. Higher values provide better output frequency regulation and response. Too high a value can cause instability or even over current trips. For applications requiring best possible performance, the value should be adjusted to suit the connected load by gradually increasing the value and monitoring the actual output speed of the load until the required dynamic behaviour is achieved with little or no overshoot where the output speed exceeds the setpoint. In general, the factory set value will be suitable for most fan and pump applications, higher friction loads can tolerate higher values of proportional gain, and high inertia, low friction loads may require the gain to be reduced.				
P4-04	Vector Speed Controller Integral Time Constant	0.010	2.000	0.050	Seconds
	Sets the integral time for the speed controller. Smaller values provide a faster response in reaction to motor load changes, at the risk of introducing instability. For best dynamic performance, the value should be adjusted to suit the connected load.				
P4-05	Motor Power Factor Cos Ø	0.00	0.99	-	-
	When operating in Vector Speed motor control mode, this parameter must be set to the motor nameplate power factor.				
P4-07	Maximum Torque / Current Limit	20.0	200	110.0	%
	This parameter defines the maximum current or torque limit used by the drive.				
P4-12	Thermal Overload Retention	0	1	1	-
	0 : Disabled. 1 : Enabled. All HPI Ecos feature electronic thermal overload protection for the connected motor, designed to protect the motor against damage. An internal overload accumulator monitors the motor output current over time, and will trip the drive if the usage exceeds the thermal limit. When P4-12 is disabled, removing the power supply from the drive and re-applying will reset the value of the accumulator. When P4-12 is enabled, the value is retained during power off.				
P4-13	Output Phase Sequence	0	1	0	-
	0 : U,V,W. 1 : U,W,V. Direction of motor rotation when operating in a forward direction will be reversed.				
P4-14	Thermal Overload Reaction	0	2	1	-
	0 : Trip. When the overload accumulator reaches the limit, the drive will trip on lt.trp to prevent damage to the motor. 1 : Current Limit Reduction. When the overload accumulator reaches 90%, the output current limit is internally reduced to 100% of P1-08 in order to avoid an lt.trp. The current limit will return to the setting in P4-07 when the overload accumulator reaches 10%. 2: Current Limit Reduction above minimum speed. This mode is the same as mode 1 above, but is only activated once the motor has ramped up to the minimum speed set in P1-02.				

8.4. Parameter Group 5 – Communication Parameters

Par.	Name	Minimum	Maximum	Default	Units
P5-01	Drive Fieldbus Address	1	63	1	-
	Sets the Fieldbus address for the HPI Eco. When using Modbus RTU, this parameter sets the Node Address. Refer to section 10.2. <i>Modbus RTU Communications</i> for further information. Please note that if a higher Modbus address than 63 is required, P5-16 can be used – see P5-16 for further information. This parameter also determines the Optibus address of the drive for use with HP Drive Tools Studio. When Using BACnet MS/TP, this parameter sets the MAC ID. Refer to section 10.3. <i>BACnet MSTP</i> for further information.				
P5-03	Modbus RTU / BACnet MSTP Baud Rate	9.6	115.2	115.2	kbps
	Sets the baud rate when Modbus/BACnet communications are used. 9.6kbps, 19.2kbps, 38.4kbps, 57.6kbps, 115 kbps, 76.8kbps.				
P5-04	Modbus RTU / BACnet MSTP Data Format	-	-	n-1	-
	Sets the expected Modbus telegram data format as follows: n-1 : No Parity, 1 stop bit. n-2 : No parity, 2 stop bits. O-1 : Odd parity, 1 stop bit. E-1 : Even parity, 1 stop bit.				
P5-05	Communications Loss Timeout	0.0	5.0	1.0	Seconds
	Sets the watchdog time period for the communications channel. If a valid telegram is not received by the HPI Eco within this time period, the drive will assume a loss of communications has occurred and react as selected below (P5-07).				
P5-06	Communications Loss Action	0	3	0	-
	Controls the behaviour of the drive following a loss of communications as determined by the above parameter setting (P5-06). 0 : Trip & Coast To Stop 1 : Ramp to Stop Then Trip 2 : Ramp to Stop Only (No Trip) 3 : Run at Preset Speed 4				
P5-07	Fieldbus Ramp Control	0	1	0	-
	Selects whether the acceleration and deceleration ramps are control directly via the Fieldbus, or by internal drive parameters P1-03 and P1-04. 0 : Disabled. Ramps are control from internal drive parameters. 1 : Enabled. Ramps are controlled directly by the Fieldbus.				
P5-08	Fieldbus PDO4 Data Select	0	7	1	-
	When using an optional Fieldbus interface, this parameter configures the parameter source for the 4th process data word transferred from the drive to the network master during cyclic communications: 0 : Motor torque. Output torque in % to one decimal place, e.g. 500 = 50.0%. 1 : Motor power. Output power in kW to two decimal places, e.g. 400 = 4.00kW. 2 : Digital input status. Bit 0 indicates digital input 1 status, bit 1 indicates digital input 2 status etc. 3 : Analog input 2 signal level. 0 to 1000 = 0 to 100.0%. 4 : Heatsink temperature. 0 to 100 = 0 to 100°C. 5 : User register 1. Can be accessed by PLC program or group 9 parameters. 6 : User register 2. Can be accessed by PLC program or group 9 parameters. 7 : PO-80 value. PO-80 value can be selected by P6-28.				
P5-09	BACnet Device Instance Number (Low)	0	65535	1	-
P5-10	BACnet Device Instance Number (High)	0	63	0	-
	When using BACnet MS/TP, these parameter together allow a unique Device Instance Number to be programmed into the drive.				
P5-11	BACnet Maximum Masters	1	127	127	-
	Parameter defines the maximum address of any BACnet masters that can exist on the current local MSTP BACnet network. When the device is polling for the next master in the network it will not poll about the value set in P5-11. For example, if the value is set to 50 then when the drive finishes communicating and needs to pass control to the next master it will poll up to address 50 looking for a response before rolling back to address 0.				

Par.	Name	Minimum	Maximum	Default	Units
P5-12	Fieldbus PDO-3 Data Select	0	7	0	-
	<p>When using an optional Fieldbus interface, this parameter configures the parameter source for the 3rd process data word transferred from the drive to the network master during cyclic communications:</p> <p>0 : Motor current. With one decimal place, e.g. 100.</p> <p>1 : Motor power. Output power in kW to two decimal places, e.g. 400 = 4.00kW.</p> <p>2 : Digital input status. Bit 0 indicates digital input 1 status, bit 1 indicates digital input 2 status etc.</p> <p>3 : Analog input 2 signal level. 0 to 1000 = 0 to 100.0%.</p> <p>4 : Heatsink temperature. 0 to 100 = 0 to 100°C.</p> <p>5 : User register 1. Can be accessed by PLC program or group 9 parameters.</p> <p>6 : User register 2. Can be accessed by PLC program or group 9 parameters.</p> <p>7 : PO-80 value. PO-80 value can be selected by P6-28.</p>				
P5-13	Fieldbus PDI-4 Function Select	0	1	0	-
	<p>When using an optional Fieldbus interface, this parameter configures the parameter source for the 4th process data word transferred from the network master to the drive during cyclic communications:</p> <p>0 : User ramp time. In second with two decimal places.</p> <p>1 : User Register 4. Can be accessed by PLC program or group 9 parameters.</p>				
P5-14	Fieldbus PDI-3 Function Select	0	2	0	-
	<p>When using an optional Fieldbus interface, this parameter configures the parameter source for the 3rd process data word transferred from the network master to the drive during cyclic communications:</p> <p>0 : Not used. No function.</p> <p>1 : User Reference. 0 to 1000 = 0% to 100.0%.</p> <p>2 : User Register 3. Can be accessed by PLC program or group 9 parameters.</p>				
P5-15	Modbus Response Delay	0	16	0	Chr
	<p>Allows the user to configure an additional delay between the drive receiving a request via the Modbus RTU interface, and transmitting a reply. The value entered represents the delay in addition to the minimum delay permissible according to the Modbus RTU specification, and is expressed as the number of additional characters.</p>				
P5-16	Drive Modbus Address	0	247	0	-
	<p>The drive Modbus (and Optibus) address is set in P5-01 which has a maximum value of 63. If a higher Modbus address is required for a larger network, it can be set in this parameter.</p> <p>If this parameter is set to a value greater than 0, this address will become the Drive Modbus address. If this value is set to 0, P5-01 determines the Drive Modbus address.</p>				

8.5. Advanced Parameters

For Advanced Parameters, basic information only is provided in this guide. The parameter functions are described more fully in HP Drive Tools Studio PC software.

8.5.1. Parameter Group 6 – Advanced Configuration



Par.	Function	Setting Range		Default	Notes
P6-01	Firmware Upgrade Enable	0	Disabled	0	This parameter should not be adjusted by the user.
		1	Update I/O & P/S		
		2	Update I/O		
		3	Update P/S		
P6-02	Thermal Overload Management	4 – 32kHz (Model Dependent)		Motor Rating Dependent	Minimum Effective Switching Frequency.
P6-03	Auto Reset Time Delay	1 – 60 Seconds		20s	
P6-04	Relay Output Hysteresis	0.0 – 25.0%		0.3%	
P6-08	Max Speed Reference Frequency	0 – 20kHz		0 kHz	
P6-10	Function Block Program Enable	0	Disabled	0	
		1	Enabled		
P6-11	Speed Hold Time on Enable	0 – 600s		0s	
P6-12	Speed Hold / DC Injection Time on Disable	0 – 250s		0s	
P6-18	DC Injection Current	0.0 – 100.0%		0.0%	
P6-22	Reset Fan Run Time	0	No Reset	0	
		1	Reset		
P6-23	Reset Energy Meters	0	No Reset	0	
		1	Reset		
P6-24	Maintenance Time Interval	0 – 60000 Hours		0 Hours	
P6-25	Reset Maintenance Indicator	0	No Reset	0	
		1	Reset		
P6-26	Analog Output 1 Scaling	0.0 – 500.0%		100.0%	
P6-27	Analog Output 1 Offset	-500.0 – 500.0%		0.0%	
P6-28	P0-80 Display Index	0 - 200		0	
P6-29	User Default Parameters	0	No Function	0	
		1	Save user parameters		
		2	Clear user parameters		
P6-30	Level 3 (Advanced) Access Code	0 – 9999		201	

8.5.2. Parameter Group 7 – Motor Control

Par.	Function	Setting Range	Default	Notes
P7-01	Motor Stator Resistance	0.000 – 65.535	Motor Rating Dependent	Motor data, measured or calculated during the autotune. P7-06 is used only for PM motors.
P7-03	Motor Stator Inductance (d)	0.0000 – 1.0000		
P7-04	Magnetising Current (id)	Drive Dependent		
P7-05	Motor Leakage Coefficient (Sigma)	0.000 – 0.250		
P7-06	Motor Q Axis Inductance (Lsq)	0.0000 – 1.0000		
P7-09	Over Voltage Current Limit	0.0 – 100.0%	5.0%	
P7-10	Load Inertia Constant	0 - 600	10	
P7-11	Pulse Width Minimum Limit	0 - 500		
P7-12	V/F Mode Magnetising Delay Time	0 – 5000ms	Motor Rating Dependent	Sets the motor alignment time in PM modes.
P7-14	Low Frequency Torque Boost	0.0 – 100.0%	Motor Rating Dependent	For PM Motors, applies a torque boost current at low frequency, % x P1-08.
P7-15	Torque Boost Frequency Limit	0.0 – 50.0%	Motor Rating Dependent	For PM motors, determines the frequency, % x P1-09 when the boost current is removed.
P7-18	Over Modulation	0	0	
		1		
		2		
P7-19	BLDC Light Load Optimization	0	1	
		1		
P7-20	Modulation Mode	0	1	
		1		

8.6. Parameter Group 8 – Application Function Specific Parameters

Par.	Name	Minimum	Maximum	Default	Units
P8-01	Pump Stir Interval Duration	0	60000	0	Minutes
	This parameter can be used to set a pre-defined period of inactivity, whereby if the drive remains in standby mode for a period of time exceeding the limit, stir function is activated, and the drive will operate at preset speed 7 (P2-07) for the time set in P8-02. This allows the pump to stir, preventing sediment from settling and avoiding a blockage.				
P8-02	Pump Stir Activation Time	1	6000	10	Seconds
	Set the time period that the stir function will be active once triggered (excludes time for deceleration to stop).				
P8-03	Pump Clean Function Select	0	3	-	-
	<p>This parameter configures the drive conditions that will cause activation of the automatic pump clean function. When activated, the pump clean will operate the pump at preset speed 5 (P2-05) for the time period set in P8-04, followed by Preset Speed 6 (P2-06) (Providing P2-06 > 0) for the time set in P8-04, before resuming normal operation. During the cleaning cycle, the ramp time set in P8-05 is used for both acceleration and deceleration, and overrides P1-03 and P1-04.</p> <p>Where possible, P2-05 and P2-06 may be set to negative values, to allow the pump to be reversed. For best results, it is recommended to use as high a speed as possible, and to adjust P8-05 to allow a short acceleration time whilst avoiding over current trips.</p> <p>0 : Disabled.</p> <p>1 : Active on start-up only. The pump cleaning function operates every time the pump is started.</p> <p>2 : Active on start-up and high current detection. The pump cleaning function operates every time the pump is started, and also in the event that the drive detects a possible pump blockage during normal operation. This requires the Motor Current Profile Monitoring function to be active and commissioned for correct operation, see parameter P8-06.</p> <p>3 : Active on high current detection only. The pump cleaning function operates only when a possible pump blockage is detected during normal operation. This requires the Motor Current Profile Monitoring function to be active and commissioned for correct operation, see parameter P8-06.</p> <p>NOTE The pump clean function can also be activated by digital input configured in group 9 parameters.</p>				
P8-04	Pump Clean Time	0	600	0	Seconds
	Sets the time period for the operation of the pump cleaning cycle. When bi-directional pump cleaning is selected, the time interval is used twice, once in each direction.				
P8-05	Pump Clean Function Ramp Time	0	6000	30	Seconds
	Independent ramp rate used only for the pump automatic cleaning function (see P8-03) when the motor is Accelerated as part of the cleaning cycle.				

Par.	Name	Minimum	Maximum	Default	Units
P8-06	Load Monitor Enable	0	4	0	-
	<p>This parameter enables the Total Motor Current Profile Monitoring Function, which can be used to detect belt failure in belt driven fan applications, or Dry Pump, Pump Blockage or broken impeller in Pump applications.</p> <p>0 : Disabled 1 : Low Current Detection Enabled (Belt Failure / Dry Pump / Broken Impeller) 2 : High Current Detection Enabled (Pump Blockage) 3 : Low and High Current Detection 4 : Low and High Current Detection, warning only. Bit 7 of the status word goes high in the event of a high or low current being detected but the drive will not trip.</p>				
	<p>Adjustment of parameter P8-06 (<>0) will cause the drive to automatically run the motor through its programmed frequency range upon the next drive enable (input enable). Ensure the application is in a suitable condition to allow the motor to run safely through its frequency range prior to enabling this feature.</p>				
P8-07	Load Profile Bandwidth	0.1	50.0	1.0	Amps
	<p>This parameter sets a bandwidth around the Motor Current profile generated by P8-06. If P8-06 has been set to an appropriate value to detect a high /low current condition and the drive operates outside of the bandwidth set in P8-07 for a period longer than that defined by P8-08 then the drive will trip. Value entered in P8-07 is the value between the normal current and the trip level, hence total bandwidth for the function is 2 x P8-07.</p>				
P8-08	Load Monitor Trip Delay	0	60	0	Seconds
	<p>This parameter sets a time limit for the Motor Current profile generated by P8-06. If P8-06 has been set to an appropriate value to detect a high /low current condition and the drive operates outside of the bandwidth set in P8-07 for a period longer than that defined by P8-08 and then the drive will trip.</p>				
P8-09	Fire Mode Logic	0	1	0	-
	<p>When Fire mode is assigned to a digital input on the drive then the logic configuration for the input is set by P8-09 to allow normally open or normally closed activation. Default behaviour is for Input logic off (0) to activate fire mode (Open activation). Input configuration for Fire mode is set by parameter P1-13 or can be user defined by the setting of P9-32.</p> <p>0 : Open Activation 1 : Closed Activation</p>				
P8-10	Fire Mode Speed	-P1-01	P1-01	0	Hz / Rpm
	<p>When set to a non-zero value, this parameter sets an operational fixed frequency / speed used when Fire Mode is selected. The drive will maintain operation at this frequency until the fire mode signal is removed or the drive is no longer able to sustain operation. When P8-10 is zero, and fire mode is activated, the drive will continue to operate under the control of the selected speed reference, dependent on parameter settings and digital input selection.</p>				
P8-11	Bypass Mode on Fault	0	1	0	-
	<p>Parameter configures the drive to switch to bypass mode automatically should a trip occur on the drive. When enabled the drive standard relays 1 and 2 are dedicated to bypass control and cannot be assigned other functions.</p> <p>0 : Disabled 1 : Enabled</p>				
P8-12	Bypass In Fire Mode	0	1	0	-
	<p>Parameter configures the drive to switch to bypass mode automatically should an input to the drive be configured for Fire Mode operation and that input becomes active. When enabled the drive standard relays 1 and 2 are dedicated to bypass control and cannot be assigned other functions.</p> <p>0 : Disabled 1 : Enabled</p>				
P8-13	Bypass Contactor Change Over Time	0	30	2	Seconds
	<p>Parameter active when Bypass function is enabled. Parameter P8-05 sets a time delay or changeover time between the switching of the drive relays controlling the bypass circuitry.</p>				
	<p>Care must be taken when setting P8-13 to ensure that drive and DOL contactors are not switched in circuit simultaneously. Both Mechanical and Electrical interlocking of drive and DOL contactors to regional standards are recommended in configuring the Bypass function.</p>				

Par.	Name	Minimum	Maximum	Default	Units
P8-14	Pump Staging Function Select	0	5	0	-
	Parameter enables the pump staging (cascade) function on the drive. Contact your local sales partner for full detailed application notes concerning this parameter. 0 : Disabled 1 : Single VFD with DOL Cascade (max 4 DOL pumps) 2 : Multiple Drive Cascade (Optiflow) Master Drive. (Only valid when drive set to Optibus master address, P5-01 = 1). 3 : Multiple Drive Cascade with Jockey Pump (Optiflow). Master Drive (Only valid when drive set to Optibus master address, P5-01 = 1) In this instance, the Master drive (with address P5-01 = 1) will remain active and will not be switched off to support the pump rotation ordinarily used for the purpose of sharing operating hours across all pumps. 4 : Multiple Drive Cascade Mode 2 (Optiflow) Master Drive. (Only valid when drive set to Optibus master address, P5-01 = 1) This mode is similar to mode 2 but the settling time is active on first start-up before introducing the first assist pump, which can prevent multiple pumps starting simultaneously when waking up from PID Standby mode. 5 : Multiple Drive Cascade with Jockey Pump Mode 2 (Optiflow) Master Drive. (Only valid when drive set to Optibus master address, P5-01 = 1) This mode is the same as mode 3 except that when an assist pump starts, the lead pump (jockey pump) will stop. When the assist pump goes into standby mode, the lead pump (jockey pump) will start again.				
P8-15	Number of Assist Pumps	1	4	1	-
	Parameter valid when P8-14 is set greater than 0 to enable Pump Staging Function. P8-15 set the number of assist pumps (P8-14 = 1) or network slave drives (P8-14 = 2) that are available in the Pump Staging application.				
P8-16	Pump Duty Changeover Time	0	1000	0	Hours
	In order to balance run time (duty) on each pump in the Pump staging application and to ensure periodic operation of each pump P8-16 can be set with a time limit for pump switch over. When set to a value other than 0 (disabled) the operation of each staging pump will be cycled to ensure the difference in duty between each pump does not exceed the time set in P8-16.				
P8-17	Assist Pump Start Speed	P8-18	P1-01	49.0	Hz / Rpm
	This parameter defines the speed at which an "Assist" Pump is started when using the Pump Cascade or Optiflow feature. When the drive output increases beyond this threshold the next Staging pump is switch on. The Pump staging settle time must then expire before additional staging pumps can be brought on or off line. Priority for Staging pump switch on is always given to the pump with lowest run time accumulated.				
P8-18	Assist Pump Stop Speed	0	P8-17	30.0	Hz / Rpm
	This parameter defines the speed at which an "Assist" Pump is stopped when using the Pump Cascade or Optiflow feature. When the drive output decreases below this threshold one of the Staging pumps currently operating is switch off. The Pump staging settle time must then expire before additional staging pumps can be brought on or off line. Priority for Staging pump switch off is always given to the pump with highest run time accumulated.				
P8-19	Pump Settling Time	2	600	60	Seconds
	Parameter sets a time delay for pump staging whereby, following switch in or switch out of a staging pump, further pumps are not permitted to be switched in or out until this time period has elapsed. This parameter should be set to allow adequate settle time between staging pump transitions.				
P8-20	Pump Master Clock Reset	0	1	0	-
	Master drive in pump staging monitors and maintains duty run times for all available staging pumps. All clocks are available to view in PO-20. P8-20 provides the master reset to all run time clocks used for Pump Staging Function (all clocks set to 0).				

8.7. Fire Mode

The Fire Mode function is designed to ensure continuous operation of the drive in emergency conditions until the drive is no longer capable of sustaining operation.

The Fire Mode input may be Normally Open (Close to Activate Fire Mode) or Normally Closed (Open to Activate Fire Mode) according to the setting of P8-09. This input may be linked to a fire control system to allow maintained operation in emergency conditions, e.g. to clear smoke or maintain air quality within the building. The fire mode function is enabled when P1-13 = 4, 8 or 13 with Digital Input 2 assigned to activate fire mode or can be user defined by the setting of P9-32 when P1-13 = 0.

Fire Mode disables the following protection features in the drive: O-t (Heat-sink Over-Temperature), U-t (Drive Under Temperature), Th-Flt (Faulty Thermistor on Heat-sink), E-trip (External Trip), 4-20 F (4-20mA fault), Ph-Ib (Phase Imbalance), P-Loss (Input Phase Loss Trip), SC-trp (Communications Loss Trip), I.t-trp (Accumulated overload Trip). The following faults will result in a drive trip, auto reset and restart: O-Volt (Over Voltage on DC Bus), U-Volt (Under Voltage on DC Bus), h O-I (Fast Over-current Trip), O-I (Instantaneous over current on drive output), Out-F (Drive output fault, Output stage trip).

When Fire Mode is activated, the drive will enter Fire Mode but will run from the existing control source selected – it will require the run signal and relevant speed reference.

If Fire Mode speed is set (<>0) in P8-10, when fire mode is activated, the drive will enter Fire Mode and run at the speed set in P8-10 and will ignore all other terminals with the exception of the STO.

8.8. Parameter Group 9 – User Inputs and Output Programming

Par.	Function	Setting Range		Default	Notes	
P9-01	Enable Input Source	These parameters allow the user to directly select the source of the various command points. Parameters are only adjustable if P1-13 = 0. This allows complete flexibility over the drive control functions, and interaction with the internal Function Block programming environment.				
P9-02	Fast Stop Input Source					
P9-03	Run Forward Input Source					
P9-04	Run Reverse Input Source					
P9-05	Latch Function Enable	0	OFF	0		
		1	ON			
P9-06	Reverse Input Source	See above				
P9-07	Reset Input Source					
P9-08	External Trip Input Source					
P9-09	Terminal Control Select Source					
P9-10	Speed Reference Source 1	In combination with P9-18 – P9-20, allow selection of several speed reference sources for common applications.				
P9-11	Speed Reference Source 2					
P9-12	Speed Reference Source 3					
P9-13	Speed Reference Source 4					
P9-14	Speed Reference Source 5					
P9-15	Speed Reference Source 6					
P9-16	Speed Reference Source 7					
P9-17	Speed Reference Source 8					
P9-18	Speed Reference Select Input 0	See above				
P9-19	Speed Reference Select Input 1					
P9-20	Speed Reference Select Input 2					
P9-21	Preset Speed Select Input 0					
P9-22	Preset Speed Select Input 1					
P9-23	Preset Speed Select Input 2					
P9-28	Motorised Pot Up Input Source					
P9-29	Motorised Pot Down Inpt Source					
P9-32	Fire Mode Input Select					
P9-33	Analog Output 1 Source	0	Defined by P2-11	0	These parameters allow the user to override the normal parameter control source for the associated function, allowing interaction with the internal Function Block programming environment.	
		1	Function block program - digital			
		2	Function block program - analog			
P9-34	Analog Output 2 Source	0	Defined by P2-13	0		
		1	Function block program - digital			
		2	Function block program - analog			
P9-35	Relay 1 Control Source	0	Defined by P2-15	0		
		1	Function block program - digital			
P9-36	Relay 2 Control Source	0	Defined by P2-18	0		
		1	Function block program - digital			
P9-37	Display Scaling Source Control	0	Defined by P2-21	0		
		1	Function block program - digital			
P9-38	PID Reference Source	0	Defined by P3-05	0		
		1	Function block program - digital			
P9-39	PID Feedback Source	0	Defined by P3-10	0		
		1	Function block program - digital			
P9-41	Relay 3,4,5 Function	0	Healthy : Tripped : Running	0		
		1	Function block program - digital			
P9-42	Clean Trigger Source (edge)					
P9-43	Bypass Mode Trigger Source					
P9-44	PID Second Digital Ref Select					

8.9. Parameter Group 0 – Monitoring Parameters (Read Only)

Par.	Parameter Name	Units
P0-01	Analog Input 1 Value	%
	Displays the signal level applied to analog input 1 (Terminal 6) after scaling and offsets have been applied.	
P0-02	Analog Input 2 Value	%
	Displays the signal level applied to analog input 2 (Terminal 10) after scaling and offsets have been applied.	
P0-03	Digital Input Status	Binary
	Displays the status of the drive inputs, including the extended I/O module (if fitted). 1st Entry: 00000 ... 11111. Drive digital Input status. MSB represents digital input 1 / LSB representing digital input 5. 2nd Entry: E 000 ... E 111. Drive Extended (option) Input status. MSB represents digital input 6 / LSB representing digital input 8.	
P0-04	Speed Controller Reference	Hz / Rpm
	Displays the set point reference input applied to the drive internal speed controller.	
P0-06	Digital Speed Reference	Hz / Rpm
	Displays the value of the drive internal Motorised Pot (used for keypad) speed reference.	
P0-07	Fieldbus Speed Reference	Hz / Rpm
	Displays the set-point being received by the drive from the currently active Fieldbus interface.	
P0-08	PID Reference	%
	Displays the set-point input to the PID controller.	
P0-09	PID Feedback	%
	Displays the Feedback input signal to the PID controller.	
P0-10	PID Output	%
	Displays the output level of the PID controller.	
P0-11	Motor Voltage	Volts
	Displays the instantaneous output voltage from the drive to the motor.	
P0-12	Output Torque	Nm
	Displays the instantaneous output torque level produced by the motor.	
P0-13	Trip Log	-
	Displays the last four fault codes for the drive. Refer to section 11.1. <i>Fault Messages</i> for further information.	
P0-14	Magnetising Current (Id)	Amps
	Displays the motor magnetising Current, providing an auto tune has been successfully completed.	
P0-16	DC Bus Voltage Ripple	Volts
	Displays the level of ripple present on the DC Bus Voltage. This parameter is used by the HPI Eco for various internal protection and monitoring functions.	
P0-17	Motor Stator Resistance (Rs)	Ohms
	Displays the measured motor stator resistance, providing an auto tune has been successfully completed.	
P0-19	Cascade Run Time Log	Hours
	Run Time values for variable speed and DOL pumps used in cascade function. 5 entry log. 0 = Master, 1 = DOL1, 2 = DOL2, 3 = DOL3, 4 = DOL4. Clocks can be reset through P8-20, Master Clock Reset.	
P0-20	DC Bus Voltage	Volts
	Displays the instantaneous DC Bus Voltage internally within the drive.	
P0-21	Heatsink Temperature	°C
	Displays the Instantaneous Heatsink Temperature measured by the drive.	
P0-22	Time Left to Next Service	Hours
	Displays the current time period remaining before the next maintenance becomes due. Maintenance interval is based on the value entered in P6-24 (Maintenance Time Interval) and the elapsed time since the maintenance interval was enabled or reset.	

Par.	Parameter Name	Units
P0-23	Time Heatsink >85°C	HH:MM:SS
	Two entry display: First display shows hours. Second display shows minutes and seconds. Displays the amount of time in hours and minutes that the HPI Eco has operated for during its lifetime with a heatsink temperature in excess of 85°C. This parameter is used by the HPI Eco for various internal protection and monitoring functions.	
P0-24	Time Internal >80°C	HH:MM:SS
	Two entry display: First display shows hours. Second display shows minutes and seconds. Displays the amount of time in hours and minutes that the HPI Eco has operated for during its lifetime with an ambient temperature in excess of 80°C. This parameter is used by the HPI Eco for various internal protection and monitoring functions.	
P0-25	Estimated Rotor Speed	Hz
	Displays the estimated rotor speed of the motor.	
P0-26	kWh Meter	kWh
	Two entry display: First display shows user resettable meter (reset with P6-23). Second display shows none resettable value. Displays the amount of energy consumed by the drive in kWh. When the value reaches 1000, it is reset back to 0.0, and the value of P0-27 (MWh meter) is increased.	
P0-27	MWh Meter	MWh
	Two entry display: First display shows user resettable meter (reset with P6-23). Second display shows none resettable value. Displays the amount of energy consumed by the drive in MWh.	
P0-28	Software Version	-
	Displays the software version of the drive: Four entry display: First display = IO Version, Second display = IO Checksum, Third display = DSP Version, Fourth display = DSP Checksum	
P0-29	Drive Type	-
	Displays the type details of the drive: Three entry display: First display = Frame size and input voltage level. Second display = Power rating. Third display = Output phase count.	
P0-30	Drive Serial Number	-
	Displays the unique serial number of the drive. Dual entry display: First display = Serial number (MSB), Second display = Serial number (LSB).	
P0-31	Total Run Time	HH:MM:SS
	Two entry display: First display shows hours. Second display shows minutes and seconds. Displays the total operating time of the drive.	
P0-32	Run Time Since Last Trip 1	HH:MM:SS
	Two entry display: First display shows hours. Second display shows minutes and seconds. Displays the total operating time of the drive since the last fault occurred. Run-time clock stopped by drive disable (or trip), reset on next enable only if a trip occurred. Reset also on next enable after a drive power down.	
P0-33	Run Time Since Last Trip 2	HH:MM:SS
	Two entry display: First display shows hours. Second display shows minutes and seconds. Displays the total operating time of the drive since the last fault occurred. Run-time clock stopped by drive disable (or trip), reset on next enable only if a trip occurred (under-volts not considered a trip) – not reset by power down / power up cycling unless a trip occurred prior to power down.	
P0-34	Run Time Since Last Enable	HH:MM:SS
	Two entry display: First display shows hours. Second display shows minutes and seconds. Displays the total operating time of the drive since the last Run command was received.	
P0-35	Cooling Fan Operating Lifetime	HH:MM:SS
	Displays the total operating time of the HPI Eco internal cooling fans. Two entry display: First display shows user resettable time (reset with P6-22). Second display shows none resettable time. This is used for scheduled maintenance information.	
P0-36	DC Bus Voltage Log (256ms)	Volts
	Diagnostic log for DC bus voltage. Values logged every 256ms with 8 samples total. Logging suspended on drive trip.	
P0-37	DC Bus Voltage Ripple Log (20ms)	Volts
	Diagnostic log for DC bus voltage ripple. Values logged every 20ms with 8 samples total. Logging suspended on drive trip.	
P0-38	Heatsink Temperature Log (30s)	°C
	Diagnostic log for heatsink temperature. Values logged every 30s with 8 samples total. Logging suspended on drive trip.	

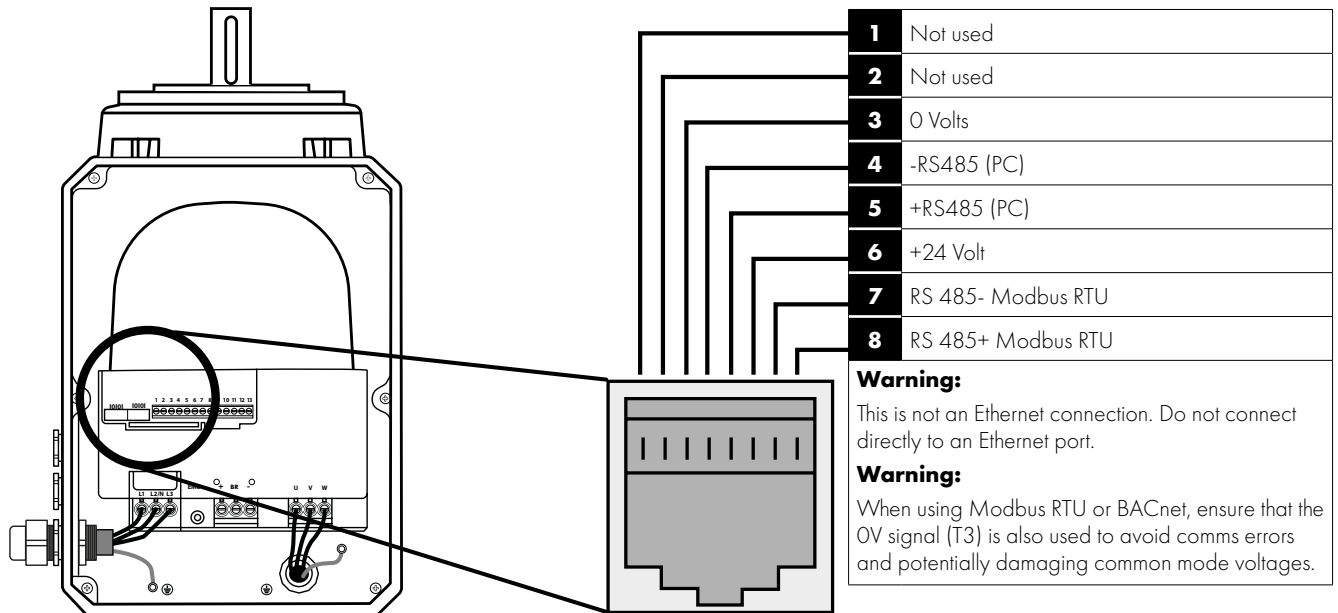
Par.	Parameter Name	Units
P0-39	Internal Temperature Log (30s)	°C
	Diagnostic log for drive ambient temperature. Values logged every 30s with 8 samples total. Logging suspended on drive trip.	
P0-40	Motor Current Log (256ms)	Amps
	Diagnostic log for Motor Current. Values logged every 256ms with 8 samples total. Logging suspended on drive trip.	
NOTE The above parameters (P0-36 to P0-40) are used to store the history of various measured levels within the drive at various regular time intervals prior to a trip. The values are frozen when a fault occurs and can be used for diagnostic purposes.		
P0-41	Over Current Fault Counter	-
P0-42	Over Voltage Fault Counter	-
P0-43	Under Voltage Fault Counter	-
P0-44	Heatsink Over Temperature Fault Counter	-
P0-45	Reserved	-
P0-46	Ambient Over Temperature Fault Counter	-
NOTE These parameters (P0-41 to P0-46) contain a record of how many times certain critical faults have occurred during a drives operating lifetime. This provides useful diagnostic data.		
P0-47	I/O Comms Fault Counter	-
	Displays the number of communication errors detected by the I/O processor in messages received from the power stage processor since the last power up.	
P0-48	DSP Comms Fault Counter	-
	Displays the number of communication errors detected by the Power Stage processor in messages received from the I/O processor since the last power up.	
P0-49	Modbus RTU / BACnet MSTP Fault Counter	-
	This parameter is incremented every time an error occurs on the Modbus RTU communication link. This information can be used for diagnostic purposes.	

9. Serial Communications

9.1. RS-485 Communications

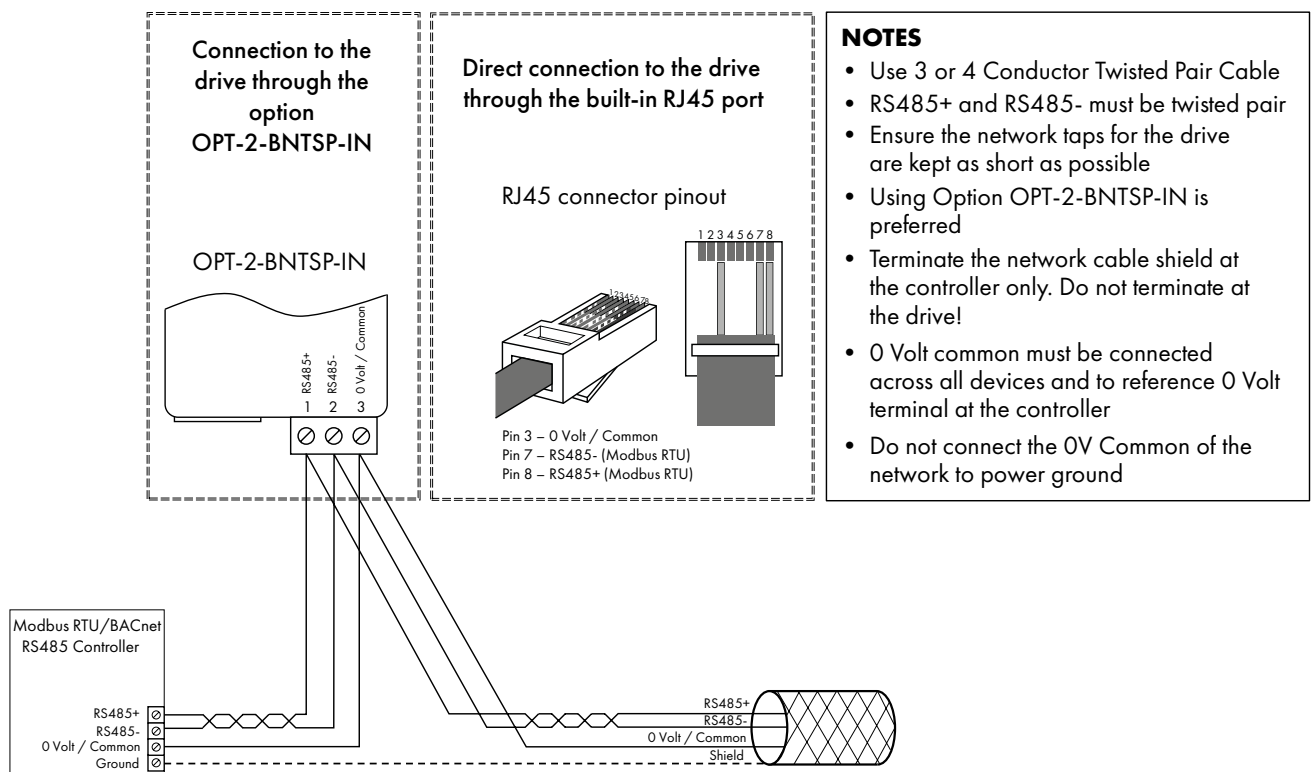
HPI Eco has an RJ45 connector located within the wiring enclosure of the drive. This connector allows the user to set up a drive network via a wired connection. The connector contains two independent RS485 connections, one for Lafert Group's Optibus Protocol and one for Modbus RTU / BACnet MSTP. Both connections can be used simultaneously.

The electrical signal arrangement of the RJ45 connector is shown as follows:



- There are two RJ45 ports present in the IP66 outdoor rated drive. The two RJ45 ports are connected in parallel internally to help support a network connection without the need for a splitter. Either port can be used.

9.1.1. RS-485 Communications Electrical Connections



10. Technical Data

10.1. Environmental

Ambient Temperature Range	Storage	All	-40 °C ... 60 °C
		IP66	-20 ... 40°C without derating
Maximum Altitude	Operational	All	1000m without derating
Relative Humidity	Operational	All	=< 95% (no condensation permitted)
Environmental Conditions	IP66 HPI Eco products are designed to operate in 3S3/3C3 environments in accordance with IEC 60721-3-3.		

Refer to section 10.8. *Derating Information* on page 46 for derating information.

10.2. Input Power Supply Requirements

Input Power Supply Requirements	
Supply Voltage	200 – 240 RMS Volts for 230 Volt rated units, + / - 10% variation allowed. 240 Volt RMS Maximum
	380 – 480 RMS Volts for 400 Volt rated units, + / - 10% variation allowed. 500 Volt RMS Maximum
	500 – 600 RMS Volts for 600 Volt rated units, + / - 10% variation allowed.
Imbalance	Maximum 3% voltage variation between phase – phase voltages allowed.
	All HPI Eco units have phase imbalance monitoring. A phase imbalance of > 3% will result in the drive tripping.
Frequency	50 – 60Hz + / - 5% Variation.

10.3. Input Voltage Ranges

Depending upon model and power rating, the drives are designed for direct connection to the following supplies:

Model Number	Supply Voltage	Phases	Frequency
XCF3-x2x-x0xxMXX	200 – 240 Volts + / - 10%	3	50 – 60 Hz
XCF3-x4x-x0xxMXX	380 – 480 Volts + / - 10%	3	50 – 60 Hz
XCF3-x6x-x0xxMXX	500 – 600 Volts + / - 10%	3	50 – 60 Hz

10.4. Phase Imbalance

All three phase HPI Eco units have phase imbalance monitoring. The maximum permissible voltage imbalance between any two phases is 3% for full load operation.

10.5. Output Power and Current ratings

The following tables provide the output current rating information for the various HPI Eco models. Lafert Group always recommend that selection of the correct HPI Eco is based upon the motor full load current at the incoming supply voltage.

Please note that the maximum cable length stated in the following tables indicate the maximum permissible cable length for the drive hardware and does not take into consideration EMC compliance.

10.5.1. IP66 200-240V 3 Phase Input, 3 Phase Output

Frame Size	Power Rating		Input Current	Fuse or MCB (Type B)		Maximum Cable Size		Rated Output Current	Maximum Motor Cable Length	
	kW	HP		Non UL	UL	mm ²	AWG/kcmil		m	ft
90	0.75	1	3.3	6	6	8	8	4.3	100	330
90	1.5	1.5	5.3	10	10	8	8	7	100	330
90	2.2	3	8	10	10	8	8	10.5	100	330
112	4	5	14.2	25	17.5	8	8	18	100	330
112	5.5	7.5	19.3	25	25	8	8	24	100	330
112	7.5	10	24.6	32	30	8	8	30	100	330

10.5.2. IP66 380-480V 3 Phase Input, 3 Phase Output

Frame Size	Power Rating		Input Current	Fuse or MCB (Type B)		Maximum Cable Size		Rated Output Current
	kW	HP	A	Non UL	UL	mm ²	AWG/kcmil	A
90	0.75	1	1.8	6	6	8	8	2.2
90	1.5	2	3.3	6	6	8	8	4.1
90	2.2	3	4.7	6	6	8	8	5.8
90	4	5	7.7	10	10	8	8	9.5
90	5.5	7.5	11.4	16	15	8	8	14
112	7.5	10	15	25	20	8	8	18
112	11	15	20.5	25	25	8	8	24
112	15	20	25.3	32	35	8	8	30

10.5.3. IP66 500-600V 3 Phase Input, 3 Phase Output

Frame Size	Power Rating		Input Current	Fuse or MCB (Type B)		Maximum Cable Size		Rated Output Current
	kW	HP	A	Non UL	UL	mm ²	AWG/kcmil	A
90	0.75	1	2.2	6	6	8	8	2.1
90	1.5	2	4	6	6	8	8	3.1
90	2.2	3	3.9	6	6	8	8	4.1
90	4	5	6.5	16	15	8	8	6.5
90	5.5	7.5	9.1	16	15	8	8	9
112	7.5	10	10.5	25	20	8	8	12
112	11	15	15.2	32	30	8	8	17
112	15	20	19.9	32	35	8	8	22

NOTE

- Ratings shown above apply to 40°C Ambient temperature. For derating information, refer to section 10.8.1. *Derating for Ambient Temperature*.
- The drive is protected against short-circuit from power output to protective earth for all rated cable lengths, cable sizes and cable types.
- The maximum cable lengths stated here are based on hardware limitations and do NOT take into consideration any requirements for compliance to any EMC standards. Please see section 4.4. *EMC Compliant Installation* for further information.
- Supply and motor cable sizes should be dimensioned according to local codes or regulations in the country or area of installation.
- For UL compliant installation, use Copper wire with a minimum insulation temperature rating of 70°C, UL Class CC or Class J Fuses.

10.6. Additional Information for UL Compliance

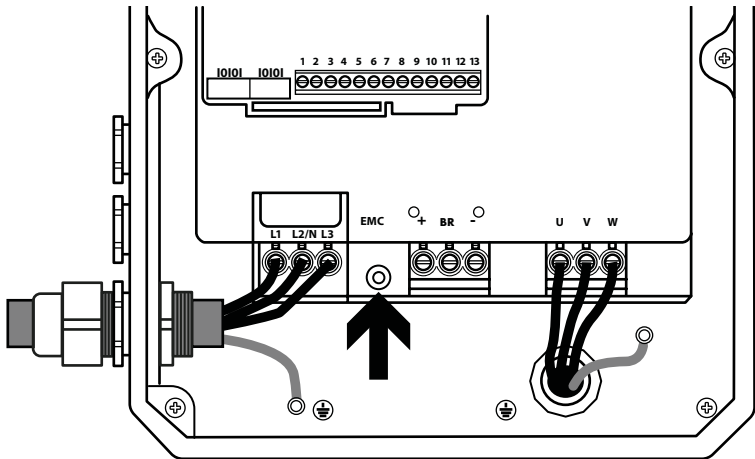
HPI Eco is designed to meet the UL requirements. For an up to date list of UL compliant products, please refer to UL listing NMMS. XXXXXXXX. In order to ensure full compliance, the following must be fully observed.

Input Power Supply Requirements		
Short Circuit Capacity		All the drives in the HPI Eco range are suitable for use on a circuit capable of delivering not more than 100kA rms (AC) short-circuit Amperes symmetrical with the specified maximum supply voltage when protected by UL type J, T or CC fuses.
Mechanical Installation Requirements		
Unless otherwise stated,all HPI Eco units are intended for indoor installation within controlled environments which meet the condition limits shown in section 10.1. <i>Environmental</i> .		
The drive can be operated within an ambient temperature range as stated in section 10.1. <i>Environmental</i> .		
Electrical Installation Requirements		
Incoming power supply connection must be according to section 4.3. Incoming Power Connection.		
Suitable Power and motor cables should be selected according to the data shown in section 10.5. <i>Output Power and Current ratings</i> and the National Electrical Code or other applicable local codes.		
Motor Cable		75°C Copper must be used.
Power cable connections and tightening torques are shown in sections 3.6. <i>Guidelines for Mounting (IP66 Units)</i> .		
Integral Solid Sate short circuit protection does not provide branch circuit protection. Branch circuit protection must be provided in accordance with the National Electrical Code and any additional local codes. Ratings are shown in section 10.5. <i>Output Power and Current ratings</i> .		
UL Listed ring terminals / lugs must be used for all bus bar and grounding connections.		
General Requirements		
HPI Eco provides motor overload protection in accordance with the National Electrical Code (US).		
<ul style="list-style-type: none">Where a motor thermistor is not fitted, or not utilised, Thermal Overload Memory Retention must be enabled by setting P4-12 = 1.Where a motor thermistor is fitted and connected to the drive, connection must be carried out according to the information shown in section 4.7.2. <i>Motor Thermistor Connection</i>.		
For Canadian Installations:		
Transient surge suppression shall be installed on the line side of this equipment and shall be rated as shown below, suitable for over voltage category III and shall provide protection for a rated impulse withstand voltage peak of 2.5kV.		
Supply Voltage Rating of the Drive	Phase-Phase Surge Protection Voltage Rating	Phase-Ground Surge Protection Voltage Rating
200 - 240VAC + / - 10%	230VAC	230VAC
380 - 480VAC + / - 10%	480VAC	480VAC
500 - 600VAC + / - 10%	600VAC	600VAC

10.7. Internal EMC Filter and Varistors – Disconnection Procedure

10.7.1. IP66 Outdoor Rated Models

Remove the terminal cover and then disconnect the EMC filter as shown in the illustration opposite.



10.8. Derating Information

Derating of the drive maximum continuous output current capacity is required when:

- Operating at ambient temperature in excess of 40°C / 104°F.
- Operating at Altitude in excess of 1000m / 3281 ft.
- Operation with Effective Switching Frequency higher than default.

The following derating factors should be applied when operating drives outside of these conditions.

10.8.1. Derating for Ambient Temperature

Enclosure Type	Maximum Temperature Without Derating	Derate by	Maximum Permissible
IP66	40°C / 104°F	2.5% per °C (1.8°F)	50°C / 122°F

10.8.2. Derating for Altitude

Enclosure Type	Maximum Temperature Without Derating	Derate by	Maximum Permissible
IP66	1000m / 3281ft	1% per 100m / 328 ft	4000m / 13123 ft

10.8.3. Derating for Switching Frequency

Enclosure Type	Switching Frequency (Where available)										
	Frame Size	4kHz	8kHz	10kHz	12kHz	14kHz	16kHz	18kHz	20kHz	24kHz	32kHz
IP66	90	N/A	N/A	0%	0%	0%	0%	0%	0%	N/A	N/A
	112	N/A	N/A	0%	0%	0%	6%	N/A	N/A	N/A	N/A

10.8.4. Example of Applying Derating Factors

A 4kW, IP66 drive is to be used at an altitude of 2000 metres above sea level, with 16 kHz switching frequency and 45°C ambient temperature.

From the table above, we can see that the rated current of the drive is 9.5 Amps at 40°C,

Firstly, apply the switching frequency derating (if any), 16 kHz, 0% derating.

Now, apply the derating for higher ambient temperature, 2.5% per °C above 40°C = 5 x 2.5% = 12.5%

9.5 Amps x 87.5% = 8.3 Amps.

Now apply the derating for altitude above 1000 metres, 1% per 100m above 1000m = 10 x 1% = 10%

8.3 Amps x 90% = 7.5 Amps continuous current available.

If the required motor current exceeds this level, it will be necessary to either:

- Reduce the switching frequency selected; or
- Use a higher power rated drive and repeat the calculation to ensure sufficient output current is available.

11. Troubleshooting

11.1. Fault Messages

Fault Code	No.	Message	Description	Corrective Action
no-FLT	00	No Fault	No Fault	Displayed in PO-13 if no faults are recorded in the log.
O-I	03	Over current trip	Instantaneous over current on drive output	Fault Occurs on Drive Enable Check the motor and motor connection cable for phase – phase and phase – earth short circuits. Check the load mechanically for a jam, blockage or stalled condition. Ensure the motor nameplate parameters are correctly entered, P1-07, P1-08, P1-09. Reduced the Boost voltage setting in P1-11. Increase the ramp up time in P1-03. If the connected motor has a holding brake, ensure the brake is correctly connected and controlled, and is releasing correctly. Fault Occurs When Running Reduce the speed loop gain in P4-03 and P4-04.
I-LOTP	04	Over load trip	Drive has tripped on overload after delivering >100% of value in P1-08 for a period of time	Check to see when the decimal points are flashing (drive in overload) and either increase acceleration rate or reduce the load. Check motor cable length is within the limit specified for the relevant drive in section 10.5. <i>Output Power and Current ratings</i> . Ensure the motor nameplate parameters are correctly entered in P1-07, P1-08, and P1-09. Check the load mechanically to ensure it is free, and that no jams, blockages or other mechanical faults exist. For a centrifugal fan or pump, a small reduction in output frequency could significantly reduce the load.
P5-LOTP	05	Hardware Over Current	Instantaneous over current on drive output	Check the motor wiring and motor itself for phase to phase and phase to earth short circuits. Disconnect the motor and motor cable and retest. If the drive trips with no motor connected, it must be replaced and the system fully checked and retested before a replacement unit is installed.
O-VOLT	06	Over voltage	Over voltage on DC bus	The value of the DC Bus Voltage can be displayed in PO-20. A historical log is stored at 256ms intervals prior to a trip in parameter PO-36. This fault is generally caused by excessive regenerative energy being transferred from the load back to the drive. When a high inertia or over hauling type load is connected. If the fault occurs on stopping or during deceleration, increase the deceleration ramp time P1-04. If operating in PID control, ensure that ramps are active by reducing P3-11.
U-VOLT	07	Under voltage	Under voltage on DC bus	This occurs routinely when power is switched off. If it occurs during running, check the incoming supply voltage, and all connections into the drive, fuses, contactors etc.
O-T	08	Over temperature trip	Heatsink over temperature	The heatsink temperature can be displayed in PO-21. A historical log is stored at 30 second intervals prior to a trip in PO-38. Check the drive ambient temperature. Ensure the drive internal cooling fan is operating. Ensure that the required space around the drive as shown in section 3.6. <i>Guidelines for Mounting (IP66 Units)</i> has been observed, and that the cooling airflow path to and from the drive is not restricted. Reduce the effective switching frequency setting in parameter P2-24. Reduce the load on the motor / drive.
U-T	09	Under temperature trip	Drive Under temperature	Trip occurs when ambient temperature is less than -10°C. The temperature must be raised over -10°C in order to start the drive.
P-DEF	10	Load default parameters	Factory Default parameters have been loaded	Press STOP key, the drive is now ready to be configured for the required application. Four button defaults.
E-LOTP	11	External trip	Digital Input External trip	E-trip requested on control input terminals. Some settings of P1-13 require a normally closed contact to provide an external means of tripping the drive in the event that an external device develops a fault. If a motor thermistor is connected check if the motor is too hot.
SC-COMM	12	Optibus serial comms fault	Communications Fault	Communications lost with PC or remote keypad. Check the cables and connections to external devices.

Fault Code	No.	Message	Description	Corrective Action
F _{LT-DC}	13	Excessive DC ripple	Excessive DC Ripple on Internal DC bus	The DC Bus Ripple Voltage level can be displayed in parameter PO-16. A historical log is stored at 20ms intervals prior to a trip in parameter PO-37. Check all three supply phases are present and within the 3% supply voltage level imbalance tolerance. Reduce the motor load. If the fault persists, contact the Lafert Group Technical Department.
P-LOSS	14	Input phase loss	Input phase missing trip	Drive intended for use with a 3 phase supply, one input phase has been disconnected or lost.
h O-I	15	Hardware detected Instant over current	Instantaneous over current on drive output	Refer to fault 3 above.
th-F _{LT}	16	Thermistor Fault	Faulty thermistor on heat-sink	Refer to the Lafert Group Technical Department.
dRtR-F	17	I/O processor data error	Internal memory fault	Parameters not saved, defaults reloaded. If problem reoccurs, refer to the Lafert Group Technical Department.
4-20F	18	4-20mA signal out of range	4-20mA Signal Lost	The reference signal on Analog Input 1 or 2 (Terminals 6 or 10) has dropped below the minimum threshold of 3mA when signal format is set to 4-20mA. Check the signal source and wiring to the HPI Eco terminals.
dRtR-E	19	M/C processor data error	Internal memory fault	Parameters not saved, factory defaults are reloaded. If problem reoccurs, refer to the Lafert Group Technical Department.
U-dEF	20	User Parameter Default	User Parameter Defaults	User Parameter default has been loaded. Press the Stop key. Three button default.
F-Ptc	21	Motor PTC over heat	Motor PTC Over Temperature	The connected motor PTC device has caused the drive to trip (analog input 2 configured for PTC device).
FRn-F	22	Cooling Fan Fault	Cooling Fan Fault	Check and if necessary, replace the drive internal cooling fan.
O-hEAt	23	Ambient Temperature High	Ambient Temperature too High	Ensure the drive internal cooling fan is operating. Ensure that the required space around the drive as shown in section 3.6. <i>Guidelines for Mounting (IP66 Units)</i> has been observed, and that the cooling airflow path to and from the drive is not restricted. Increase the cooling airflow to the drive. Reduce the effective switching frequency setting in parameter P2-24. Reduce the load on the motor / drive.
O-tor9	24	High motor current	Motor current above configured profile	Current Monitoring Function has detected motor current levels above the normal operating condition for the application. Check mechanical load has not changed and that the load is not jammed or stalling. For pump application check for potential pump blockage. For fan applications check airstream to and from the fan is not restricted.
U-tor9	25	Low motor current	Motor current below configured profile	Current Monitoring Function has detected motor current levels below the normal operating condition for the application. Check for mechanical breakages causing loss of load (e.g. belt break). Check motor has not become disconnected from the drive.
OUt-F	26	Drive Output Fault	Drive output fault	Drive output fault. Check for loose motor cables at the drive and at the motor or any termination in between. Otherwise refer to the Lafert Group Technical Department.
Sto-F	29	Internal STO circuit Error	Refer to the Lafert Group Technical Department	
RtF-O1	40	Autotune fail 1	Autotune Failed	Measured motor stator resistance varies between phases. Ensure the motor is correctly connected and free from faults. Check the windings for correct resistance and balance.
RtF-O2	41	Autotune fail 2		Measured motor stator resistance is too large. Ensure the motor is correctly connected and free from faults. Check that the power rating corresponds to the power rating of the connected drive.
RtF-O3	42	Autotune fail 3		Measured motor inductance is too low. Ensure the motor is correctly connected and free from faults.
RtF-O4	43	Autotune fail 4		Measured motor inductance is too large. Ensure the motor is correctly connected and free from faults. Check that the power rating corresponds to the power rating of the connected drive.
RtF-O5	44	Autotune fail 5		Measured motor parameters are not convergent. Ensure the motor is correctly connected and free from faults. Check that the power rating corresponds to the power rating of the connected drive.

Fault Code	No.	Message	Description	Corrective Action
Pr-Lo	48	Feedback Pressure Low	Low Pressure Detected by Pipe Fill Function	Check the pump system for leaks or burst pipes. Check the Pipe fill function has been commissioned correctly (P3-16 & P3-17).
OUT-Ph	49	Output Phase Loss	Output (Motor) Phase Loss	One of the motor output phases is not connected to the drive.
Sc-F01	50	Modbus Comms fault	Built-in Modbus RTU communication timeout or Communication Option Module Fault	When using Modbus RTU: Valid Modbus telegram has not been received within the watchdog time limit set in P5-05. Check the network master / PLC is still operating. Check the connection cables. Increase the value of P5-05 to a suitable level. When using an optional fieldbus Interface: Internal communication to the inserted Communication Option Module has been lost. Check the module is correctly inserted.
Sc-F03	52	Plug-in communication option module timeout	Fitted communication Module Fault	A telegram containing a valid Control Word from the network master has not been received within the watchdog time limit set in P5-05. Check the network master / PLC is still operating. Check the connection cables. Increase the value of P5-05 to a suitable level.
Sc-F04	53	IO Card Comms fault	IO card comms trip	Internal communication to the inserted I/O Option Module has been lost. Check the module is correctly inserted.
Sc-F05	54	BACnet Comms fault	BACnet comms loss trip	A valid BACnet telegram has not been received within the watchdog time limit set in P5-05. Check the network master / PLC is still operating. Check the connection cables. Increase the value of P5-05 to a suitable level.

11.2. Resetting a Fault

When the drive trips, and a fault message is displayed, it can be reset in one of the following ways:

- Completely remove the incoming power supply, and allow the power to power off completely. Re-apply the power.
- Remove and reapply the enable input.
- Press the stop / Reset button.
- If Fieldbus is being used, set the reset bit in the control word from 0 to 1.

In the event of O-I, hO-I or I.t-trp faults, in order to prevent damage that may occur through repeatedly enabling the drive into a fault condition, these trips cannot be reset immediately. A delay time according to the following table must be allowed before reset is possible.

First Trip	2 seconds delay before reset is possible
Second Trip	4 seconds delay before reset is possible
Third Trip	8 seconds delay before reset is possible
Fourth Trip	16 seconds delay before reset is possible
Fifth Trip	32 seconds delay before reset is possible
Subsequent Trips	64 seconds delay before reset is possible



82-HEMAN-LFT_V3.11

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