

Kinetix 5700 Servo Drives

Catalog Numbers 2198-P031, 2198-P070, 2198-P141, 2198-P208, 2198-RP088, 2198-RP200, 2198-RP263, 2198-RP312, 2198-D006-ERS3, 2198-D012-ERS3, 2198-D020-ERS3, 2198-D032-ERS3, 2198-D057-ERS3, 2198-S086-ERS3, 2198-S130-ERS3, 2198-S160-ERS3, 2198-S263-ERS3, 2198-S312-ERS3, 2198-D006-ERS4, 2198-D012-ERS4, 2198-D020-ERS4, 2198-D032-ERS4, 2198-D057-ERS4, 2198-S086-ERS4, 2198-S130-ERS4, 2198-S160-ERS4, 2198-S263-ERS4, 2198-S312-ERS4, 2198T-W25K-ER, 2198-CAPMOD-2240, 2198-CAPMOD-DCBUS-IO, 2198-DCBUSCOND-RP312



Important User Information

Read this document and the documents listed in the additional resources section about installation, configuration, and operation of this equipment before you install, configure, operate, or maintain this product. Users are required to familiarize themselves with installation and wiring instructions in addition to requirements of all applicable codes, laws, and standards.

Activities including installation, adjustments, putting into service, use, assembly, disassembly, and maintenance are required to be carried out by suitably trained personnel in accordance with applicable code of practice.

If this equipment is used in a manner not specified by the manufacturer, the protection provided by the equipment may be impaired.

In no event will Rockwell Automation, Inc. be responsible or liable for indirect or consequential damages resulting from the use or application of this equipment.

The examples and diagrams in this manual are included solely for illustrative purposes. Because of the many variables and requirements associated with any particular installation, Rockwell Automation, Inc. cannot assume responsibility or liability for actual use based on the examples and diagrams.

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Throughout this manual, when necessary, we use notes to make you aware of safety considerations.



WARNING: Identifies information about practices or circumstances that can cause an explosion in a hazardous environment, which may lead to personal injury or death, property damage, or economic loss.



ATTENTION: Identifies information about practices or circumstances that can lead to personal injury or death, property damage, or economic loss. Attentions help you identify a hazard, avoid a hazard, and recognize the consequence.

IMPORTANT Identifies information that is critical for successful application and understanding of the product.

Labels may also be on or inside the equipment to provide specific precautions.



SHOCK HAZARD: Labels may be on or inside the equipment, for example, a drive or motor, to alert people that dangerous voltage may be present.



BURN HAZARD: Labels may be on or inside the equipment, for example, a drive or motor, to alert people that surfaces may reach dangerous temperatures.



ARC FLASH HAZARD: Labels may be on or inside the equipment, for example, a motor control center, to alert people to potential Arc Flash. Arc Flash will cause severe injury or death. Wear proper Personal Protective Equipment (PPE). Follow ALL Regulatory requirements for safe work practices and for Personal Protective Equipment (PPE).

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This manual provides detailed installation instructions for mounting and wiring your Kinetix® 5700 power supplies, single-axis inverters, dual-axis inverters, and accessory modules. Also included is system configuration with the Studio 5000 Logix Designer® application, integration of your drive modules with a Logix 5000™ controller, system startup, and troubleshooting.

Also provided in this manual are installation instructions for mounting and wiring input power for your iTRAK® power supply. For wiring iTRAK digital inputs, outputs to the motor modules, and startup, troubleshooting, and commissioning with the AOI, see the iTRAK System User Manual, publication [2198T-UM001](#).

This manual is intended for engineers or technicians directly involved in the installation and wiring of the Kinetix 5700 drive modules, and programmers directly involved in the operation, field maintenance, and integration of these modules with the EtherNet/IP™ communication module or controller.

If you do not have a basic understanding of Kinetix 5700 drive modules, contact your local Rockwell Automation sales representative for information on available training courses.

Summary of Changes

This manual contains new and updated information as indicated in the following table.

| Topic | Page |
|---|------------|
| Added references to Knowledgebase Answer ID: 1091727 , for fault codes and descriptions. | 12, 277 |
| Added Kinetix 5700 drive compatibility with 2090-CSxM1xx-xxVAxx (PVC) and 2090-CSBM1xx-xxLFxx (Halogen-free PUR) single motor-cables. | Throughout |
| Added Kinetix 5700 drive compatibility with VPC-B3004x-M servo motors with multi-turn encoder. | |

Conventions Used in This Manual

These conventions are used throughout this manual:

- Bulleted lists such as this one provide information, not procedural steps
- Numbered lists provide sequential steps or hierarchical information
- When catalog number 2198-xxxx-ERS3 appears in this publication without series designation, the topic applies to series A and B drives

IMPORTANT Throughout this publication, when the Kinetix 5700 inverter catalog number ends in -ERSx, for example 2198-D057-ERSx, the variable (x) indicates that the inverter (using this example) can be 2198-D057-ERS3 or 2198-D057-ERS4.

- The 2198-CAPMOD-2240 capacitor module, 2198-CAPMOD-DCBUS-IO extension module, and 2198-DCBUSCOND-RP312 DC-bus conditioner module are collectively referred to as accessory modules

Accessing Fault Codes

For Kinetix 5700 fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

CIP Security

CIP Security™ is a standard, open-source communication method that helps to provide a secure data transport across an EtherNet/IP network. It lets CIP-connected devices authenticate each other before transmitting and receiving data.

CIP Security uses the following security properties to help devices protect themselves from malicious communication:

- Device Identity and Authentication
- Data Integrity and Authentication
- Data Confidentiality

Rockwell Automation uses the following products to implement CIP Security:

- FactoryTalk® Services Platform, version 6.11 or later, with the following components enabled:
 - FactoryTalk Policy Manager
 - FactoryTalk System Services
- FactoryTalk Linx, version 6.11 or later
- Studio 5000® Design Environment, version 32.00.00 or later
- CIP Security-enabled Rockwell Automation® products, for example, the product described in this publication

For more information on CIP Security, including which products support CIP Security, see the CIP Security with Rockwell Automation Products Application Technique, publication [SECURE-AT001](#).

Additional Resources

These documents contain additional information concerning related products from Rockwell Automation.

Table 1 - Additional Resources

| Resource | Description |
|--|--|
| Kinetix Rotary Motion Specifications Technical Data, publication KNX-TD001 | Provides product specifications for Kinetix VPL, VPC, VPF, VPH, and VPS motors, Kinetix MPL, MPM, MPF, and MPS motors, and Kinetix HPK rotary motors. |
| Kinetix Linear Motion Specifications Technical Data, publication KNX-TD002 | Provides product specifications for Kinetix MPAS and MPMA linear stages, Kinetix VPAR, MPAR, and MPAL electric cylinders, LDAT-Series linear thrusters, and LDC-Series™ linear motors. |
| Kinetix Servo Drives Specifications Technical Data, publication KNX-TD003 | Provides product specifications for Kinetix Integrated Motion over the EtherNet/IP network, Integrated Motion over sercos interface, EtherNet/IP networking, and component servo drive families. |
| Kinetix Motion Accessories Specifications Technical Data, publication KNX-TD004 | Provides product specifications for Bulletin 2090 motor and interface cables, low-profile connector kits, drive power components, and other servo drive accessory items. |
| Kinetix 5700 Capacitor Modules Installation Instructions, publication 2198-IN008 | Provides information on how to install and wire the Kinetix 5700 capacitor modules. |
| Kinetix 5700 DC-bus Power Supply Installation Instructions, publication 2198-IN009 | Provides information on how to install and wire the Kinetix 5700 DC-bus power supply. |
| Kinetix 5700 Regenerative Bus Supply Installation Instructions, publication 2198-IN014 | Provides information on how to install and wire the Kinetix 5700 regenerative bus supply. |
| AC Line Filter Installation Instructions, publication 2198-IN003 | Provides information on how to install and wire the Kinetix 5500 and Kinetix 5700 AC line filters. |
| Kinetix 5700 DC-bus Conditioner Module Installation Instructions, publication 2198-IN016 | Provides information on how to install and wire the Kinetix 5700 DC-bus conditioner module. |
| Kinetix 5700 Shunt Passive Modules Installation Instructions, publication 2198-IN011 | Provides information on how to install and wire Kinetix 5700 passive shunts. |
| Replacement Fan Kit Installation Instructions, publication 2198-IN015 | Provides information on removal and replacement of cooling fans used in 2198-RPxxx regenerative bus supplies and 2198-S263-ERSx and 2198-S312-ERSx single-axis inverters. |
| Kinetix 5700 Safe Monitor Functions Safety Reference Manual, publication 2198-RM001 | Provides a description of integrated stopping functions and safe monitoring functions with a GuardLogix® controller and Kinetix 5700 servo drives. |
| iTRAK System User Manual, publication 2198T-UM001 | Provides information on how to install the Kinetix 5700 iTRAK power supply with an iTRAK system and programming the iTRAK system. |
| 1321 Power Conditioning Products Technical Data, publication 1321-TD001 | Provides information on typical use cases, specifications, terminations, and dimensions of Bulletin 1321 line reactors. |
| 8720MC Regenerative Power Supply Installation Manual, publication 8720MC-RM001 | Provides information on how to install, wire, and startup the 8720MC regenerative power supply with 380...460V AC operation. |
| System Design for Control of Electrical Noise Reference Manual, publication GMC-RM001 | Provides information, examples, and techniques designed to minimize system failures caused by electrical noise. |
| Kinetix Motion Control Selection Guide, publication KNX-SG001 | Overview of Kinetix servo drives, motors, actuators, and motion accessories designed to help make initial decisions for the motion control products best suited for your system requirements. |
| Kinetix 5700 Drive Systems Design Guide, publication KNX-RM010 | System design guide to select the required (drive specific) drive module, power accessory, feedback connector kit, and motor cable catalog numbers for your Kinetix 5700 drive system. |
| Motor Nameplate Datasheet Entry for Custom Motor Applications Application Technique, publication 2198-AT002 | Provides information on the use of nameplate data entry for custom induction motors and permanent-magnet motors that are used in applications with Kinetix 5700 servo drives. |
| Vertical Load and Holding Brake Management Application Technique, publication MOTION-AT003 | Provides information on vertical loads and how the servo motor holding-brake option can be used to help keep a load from falling. |
| Motion System Tuning Application Technique, publication MOTION-AT005 | Provides information on tuning a Kinetix drive system. |
| Integrated Motion on the EtherNet/IP Network Configuration and Startup User Manual, publication MOTION-UM003 | Provides information on configuring and troubleshooting your ControlLogix® and CompactLogix™ EtherNet/IP network modules. |

Table 1 - Additional Resources (continued)

| Resource | Description |
|---|--|
| Integrated Motion on the EtherNet/IP Network Reference Manual, publication MOTION-RM003 | Provides information on the AXIS_CIP_DRIVE attributes and the Studio 5000 Logix Designer application Control Modes and Methods. |
| GuardLogix 5570 Controllers User Manual, publication 1756-UM022 | Provides information on how to install, configure, program, and use ControlLogix controllers and GuardLogix controllers in Studio 5000 Logix Designer projects. |
| GuardLogix 5580 Controllers User Manual, publication 1756-UM543 | |
| Compact GuardLogix 5370 Controllers User Manual, publication 1769-UM022 | Provides information on how to install, configure, program, and use CompactLogix and Compact GuardLogix controllers. |
| Compact GuardLogix 5380 Controllers User Manual, publication 5069-UM001 | |
| GuardLogix 5570 and Compact GuardLogix 5370 Controller Systems Safety Reference Manual, publication 1756-RM099 | Provides information on how to achieve and maintain Safety Integrity Level (SIL) and Performance Level (PL) safety application requirements for GuardLogix and Compact GuardLogix controllers. |
| GuardLogix 5580 and Compact GuardLogix 5380 Controller Systems Safety Reference Manual, publication 1756-RM012 | |
| ControlFLASH Firmware Upgrade Kit User Manual, publication 1756-UM105 | Provides information on how to upgrade your drive firmware by using ControlFLASH™ software. |
| Rockwell Automation Product Selection website http://www.rockwellautomation.com/global/support/selection.page | Online product selection and system configuration tools, including AutoCAD (DXF) drawings. |
| Motion Analyzer System Sizing and Selection Tool website https://motionanalyzer.rockwellautomation.com/ | Comprehensive motion application sizing tool used for analysis, optimization, selection, and validation of your Kinetix Motion Control system. |
| Product Certifications website, rok.auto/certifications | Provides declarations of conformity, certificates, and other certification details. |
| Rockwell Automation Industrial Automation Glossary, publication AG-7.1 | A glossary of industrial automation terms and abbreviations. |
| Industrial Automation Wiring and Grounding Guidelines, publication 1770-4.1 | Provides general guidelines for installing a Rockwell Automation industrial system. |

You can view or download publications at
<http://www.rockwellautomation.com/global/literature-library/overview.page>.

Start

Use this chapter to become familiar with the Kinetix® 5700 drive system and obtain an overview of installation configurations.

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Kinetix 5700 Servo Drives Series Change

Single-axis and dual-axis inverters, catalog numbers 2198-xxxx-ERS3 (series B), include an enhancement that is not included in series A drives, but that is included in 2198-xxxx-ERS4 drives.

- The drive-based (Monitored SS1 and Timed SS1) stopping functions and controller-based monitoring functions apply to the 2198-xxxx-ERS4 drives
- The drive-based Timed SS1 stopping function and STO with configurable delay applies to the 2198-xxxx-ERS3 (series B) drives
- When catalog number 2198-xxxx-ERS3 appears in this publication without series designation, the topic applies to series A and B drives

Table 2 - Integrated Functional Safety Support

| Integrated Safety Over the EtherNet/IP™ Network | Safety Function | Dual-axis Inverters Cat. No. | Single-axis Inverters Cat. No. | Minimum Controller ⁽¹⁾ Required |
|---|---|---|---|--|
| Drive-based stopping functions | Timed Safe Stop 1 (SS1) | 2198-Dxxx-ERS3 (series B) 2198-Dxxx-ERS4 | 2198-Sxxx-ERS3 (series B) 2198-Sxxx-ERS4 | <ul style="list-style-type: none">• GuardLogix® 5580• CompactLogix™ 5380 |
| | Monitored Safe Stop 1 (SS1) | 2198-Dxxx-ERS4 | 2198-Sxxx-ERS4 | |
| Controller-based stopping functions | <ul style="list-style-type: none">• Monitored Safe Stop 1 (SS1)• Safe Stop 2 (SS2) | | | |
| Controller-based monitoring functions | <ul style="list-style-type: none">• Safe Operational Stop (SOS)• Safely Limited Speed (SLS)• Safety Limited Position (SLP)• Safe Direction (SDI) | | | |
| Safety feedback function | Safety Feedback Interface (SFX) | | | |
| Integrated STO mode | Safe Torque-off (STO) | 2198-Dxxx-ERS4 | 2198-Sxxx-ERS4 | |
| | | 2198-Dxxx-ERS3 | 2198-Sxxx-ERS3 | <ul style="list-style-type: none">• ControlLogix® 5570• CompactLogix 5370 |

(1) Where a ControlLogix or CompactLogix (non-safety) controller is specified, a GuardLogix or Compact GuardLogix controller is backwards compatible. Also, GuardLogix 5580 and Compact GuardLogix 5380 controllers are backwards compatible with GuardLogix 5570 and Compact GuardLogix 5370 controllers.

About the Kinetix 5700 Servo Drive System

The Kinetix 5700 drive modules are zero-stacked and use the shared-bus connection system to extend power from one drive module to another. Systems are designed to support Integrated Motion over the EtherNet/IP network.

Table 3 - Kinetix 5700 Drive System Overview

| Drive System Component | Cat. No. | Description |
|---------------------------------------|----------------|--|
| Kinetix 5700 DC-bus Power Supply | 2198-Pxxx | Converter power supply with 400V-class (three-phase) AC input. Provides power in a range of 7...46 kW and 10.5...69.2 A output current. Systems typically consist of one module, however, up to three modules in parallel is possible. Parallel modules increase available power for Bulletin 2198 single-axis and dual-axis inverters. |
| Kinetix 5700 Regenerative Bus Supply | 2198-RPxxx | Regenerative bus supply with 400V-class (three-phase) AC input provides continuous output power and current to Bulletin 2198 single-axis and dual-axis inverters for applications with requirements in the range of 24...140 kW and 35...207 A, output current. |
| Kinetix 5700 Single-axis Servo Drives | 2198-Sxxx-ERS3 | Single-axis inverters with current ratings up to 192 A rms. Drives feature TÜV Rheinland certified safe torque-off function with hardwired and integrated safety connection options, PL e and SIL 3 safety ratings, and support for DSL, Hyperface, and Heidenhain EnDat encoder feedback. 2198-Sxxx-ERS3 (series B) drives also support Timed SS1 drive-based stopping functions. |
| | 2198-Sxxx-ERS4 | Single-axis inverters with the same power structure and encoder feedback support as -ERS3 inverters, plus support for Monitored SS1 and Timed SS1 drive-based stopping functions. Also, support for controller-based safe stop and safe monitor functions over the EtherNet/IP network. |

Table 3 - Kinetix 5700 Drive System Overview (continued)

| Drive System Component | Cat. No. | Description |
|--|---|--|
| Kinetix 5700 Dual-axis Servo Drives | 2198-Dxxx-ERS3 | Dual-axis inverters with current ratings up to 23 A rms. Drives feature TÜV Rheinland certified safe torque-off function with hardwired and integrated safety connection options, PL e and SIL 3 safety ratings, and support for DSL, Hiperface, and Heidenhain EnDat encoder feedback. 2198-Dxxx-ERS3 (series B) drives also support Timed SS1 drive-based stopping functions. |
| | 2198-Dxxx-ERS4 | Dual-axis inverters with the same power structure and encoder feedback support as -ERS3 inverters, plus support for Monitored SS1 and Timed SS1 drive-based stopping functions. Also, support for controller-based safe stop and safe monitor functions over the EtherNet/IP network. |
| Kinetix 5700 iTRAK Power Supply | 2198T-W25K-ER | DC-DC converter that generates DC-bus power for iTRAK® systems. |
| Kinetix 5700 Capacitor Module | 2198-CAPMOD-2240 | Use for energy storage, external active-shunt connection, and to extend the DC-bus voltage to another inverter cluster. Modules are zero-stacked with servo drives and use the shared-bus connection system to extend the external DC-bus voltage in applications up to 104 A. Can parallel with itself or with another accessory module for up to 208 A with required 2198-KITCON-CAPMOD2240 kit that includes flexible bus-bars. |
| Kinetix 5700 Extension Module | 2198-CAPMOD-DCBUS-IO | The extension module, paired with a capacitor module or DC-bus conditioner module, is used to extend the DC-bus voltage to another inverter cluster in systems with ≥ 104 A current and up to 208 A. |
| Kinetix 5700 DC-bus Conditioner Module | 2198-DCBUSCOND-RP312 | Decreases the voltage stress on insulation components in an inverter system and used to extend the DC-bus voltage to another inverter cluster. Modules are zero-stacked with servo drives and use the shared-bus connection system to extend the external DC-bus voltage in applications up to 104 A. Can parallel with itself or with another accessory module for up to 208 A with required 2198-KITCON-DCBUSCOND kit that includes flexible bus-bars. |
| 8720MC Regenerative Power Supply | 8720MC-RPSxxx | Sinusoidal PWM converter that can control the increase of DC-bus voltage and perform continuous power generation for one or more servo drives in multi-axis DC common-bus configurations. |
| Shared-bus Connector Kits | 2198-TCON-24VDCIN36 2198-xxxx-P-T 2198-BARCON-xxDCAC100 | 24V input wiring connectors, T-connectors, and bus-bars for most Kinetix 5700 drive modules that use the 24V shared-bus connection system (optional). |
| | 2198T-W25K-P-IN 2198T-W25K-P-T | 24V input wiring connector, T-connector, and bus-bar for the iTRAK motor module and other select Kinetix 5700 drive modules that use the 24V shared-bus connection system (optional). |
| | 2198-BARCON-xxDC200 2198-KITCON-ENDCAP200 | DC-bus links (55, 85, 100, and 220 mm) and end caps for the DC-bus shared-bus connection system (required and included with each respective drive module). DC-bus links (165, 275, and 440 mm) are optional and do not ship with any modules. |
| DSL Feedback Connector Kit | 2198-KITCON-DSL | Replacement DSL motor feedback connector kit with 2-pin connector plug and grounding plate inside the connector housing. Supports 400V-class Kinetix VPL, VPC-Q, VPH, VPF, VPS rotary motors. Included with 2090-CSxM1DE motor cables. Must be purchased separately when used with 2090-CSxM1DG motor cables. |
| Universal Feedback Connector Kit | 2198-K57CK-D15M | Universal feedback connector kit for motor and auxiliary feedback connections with the 15-pin connector plug and grounding plate inside the connector housing. Supports 400V-class Kinetix MPL, MPM, MPF, MPS, Kinetix HPK rotary motors, Kinetix MPAS, MPMA, MPAR, MPAL linear actuators, LDAT-Series linear thrusters, and LDC-Series™ linear motors. |
| Hiperface to DSL Converter Kit | 2198-H2DCK (series B or later) | Provides Hiperface-to-DSL feedback conversion for use with compatible 400V-class motors and actuators. |
| Kinetix 5700 System Mounting Toolkit | 2198-K5700-MOUNTKIT | Use to position the drive modules and identify drill-holes for mounting your Kinetix 5700 servo drive system. |
| Kinetix 5700 Cable Clamp Spacer Kit | 2198-K5700-CLAMPSPACER | Replacement cable clamp spacers for 2198-Dxxx-ERSx dual-axis inverters. |
| Encoder Output Module | 2198-ABQE | The Allen-Bradley® encoder output module is a DIN-rail mounted EtherNet/IP network-based standalone module capable of outputting encoder pulses to a customer-supplied peripheral device (cameras, for example, used in line-scan vision systems). |
| Logix 5000™ Controller Platform | Bulletin 1769 Bulletin 5069 | Integrated Motion on the EtherNet/IP network in CompactLogix 5370, CompactLogix 5380, and CompactLogix 5480 controllers and Integrated Safety in Compact GuardLogix 5370 and Compact GuardLogix 5380 controllers. Linear, device-level ring (DLR), and star topology is supported. |
| | 1756-EN2T module 1756-EN2TR module 1756-EN3TR module | EtherNet/IP network communication modules for use with ControlLogix 5570, ControlLogix 5580, GuardLogix 5570, and GuardLogix 5580 controllers. Linear, device-level ring (DLR), and star topology is supported. |
| Studio 5000® Environment | N/A | Studio 5000 Logix Designer® application, version 26.00 or later, provides support for programming, commissioning, and maintaining the CompactLogix, ControlLogix, and GuardLogix controller families. |

Table 3 - Kinetix 5700 Drive System Overview (continued)

| Drive System Component | Cat. No. | Description |
|----------------------------------|---|--|
| Rotary Servo Motors | Kinetix VP motors | Compatible motors include 400V-class Kinetix VPL, VPC, VPF, VPH, and VPS servo motors. |
| | Kinetix MP motors | Compatible motors include 400V-class Kinetix MPL, MPM, MPF, and MPS servo motors. |
| | Kinetix HPK motors | Compatible motors include 460V and 400V-class Kinetix HPK asynchronous servo motors. |
| Linear Actuators | Kinetix MPAS, VPAR, MPAR, and MPAL actuators LDAT-Series | Compatible actuators include 400V-class Kinetix MPAS/MPMA linear stages, Kinetix VPAR, MPAR, and MPAL electric cylinders, and LDAT-Series linear thrusters. |
| Linear Motors | LDC-Series | Compatible motors include LDC-Series iron-core (400V-class) linear motors. |
| Induction Motors | N/A | Induction motors with open-loop frequency control and closed-loop control are supported. |
| Cables | 2090-CSxM1DE-xxxxxx | Bulletin 2090 single cable for motor power, feedback, and optional 24V DC brake power with Kinetix VPL, VPC-Q, VPH, VPF, VPS motors. Feedback conductors are wired to the 2198-KITCON-DSL feedback connector kit. |
| | 2090-CSxM1DG-xxxxxx | Bulletin 2090 single cable for motor power, feedback, and optional 24V DC brake power with Kinetix VPL, VPC-Q, VPH, VPF, VPS motors. 2090-CSxM1DG cables have flying-lead feedback conductors for connection to a customer-supplied 2198-KITCON-DSL feedback connector kit. |
| | 2090-CFBM7DF-CEAxxx | Bulletin 2090 motor feedback cables for Kinetix MPL, MPM, MPF, and MPS rotary motors and Kinetix MPAS, MPMA, MPAR, MPAL linear actuators with Stegmann Hiperface encoders. |
| | 2090-CPxM7DF-xxAxxx | Bulletin 2090 motor power/brake cables for Kinetix MPL, MPM, MPF, and MPS rotary motors and Kinetix MPAS, MPMA, MPAR, MPAL linear actuators. |
| | 2090-XXNFMF-Sxx 2090-CFBM7DF-CDAFxx | Bulletin 2090 standard and continuous-flex feedback cables that include additional conductors for use with incremental and EnDat encoders. |
| | 2198T-CHBFLS8-12AAxx | Bulletin 2198T power cables for iTRAK power supply to iTRAK motor modules. |
| | 1585J-M8CBJM-x | Ethernet cables are available in standard lengths. Shielded cable is required to meet EMC specifications. |
| AC Line Filters | 2198-DB20-F, 2198-DB42-F, 2198-DB80-F, 2198-DB290-F | Bulletin 2198 three-phase AC line filters are required to meet CE and are available for use with DC-bus power supplies. Use 2198-DBxx-F filters as field replacements in existing installations that use DC-bus power supplies with inverter ground jumpers installed. Select 2198-DBRxx-F filters for all new systems and remove all inverter ground jumpers. |
| | 2198-DBR20-F, 2198-DBR40-F, 2198-DBR90-F, 2198-DBR200-F | Bulletin 2198 three-phase AC line filters are required to meet CE and are available for use with DC-bus power supplies and regenerative bus supplies. Select 2198-DBRxx-F filters for all new systems and remove all inverter ground jumpers. |
| Line Reactors | 1321-3Rxx-x | Bulletin 1321 line reactors help keep equipment running longer by absorbing many of the power line disturbances that can shut down your power supply. For 2198-RPxxx regenerative bus supplies, line reactors can significantly reduce the amount of circulating currents between the integrated LC filter and other devices on the common AC power source. |
| AC Contactor | 100-Cxxxx 100-Dxxxx 100-Exxxx | The AC three-phase contactor control string must be wired in series with the contactor-enable relay at the CED connector to make sure that three-phase power is removed under various fault conditions to protect the power supply. |
| 24V DC Power Supply | 1606-XLxxx | Bulletin 1606 24V DC power supply for control circuitry, digital inputs, safety, and motor brake. |
| External Passive Shunt Resistors | 2198-R014, 2198-R031, 2198-R127, 2198-R004 | Bulletin 2198 external passive-shunt resistors for use when the DC-bus power supply internal shunt capability is exceeded. Not for use with regenerative bus supplies. |
| External Active Shunts | N/A | External active shunts from Rockwell Automation Encompass™ partner, Powerohm Resistors, Inc., are available for connecting to Bulletin 2198 DC-bus power supplies and regenerative bus supplies. See External Active-shunt Connections on page 183 for catalog numbers. |

DC-bus Power Supply Input Power Configurations

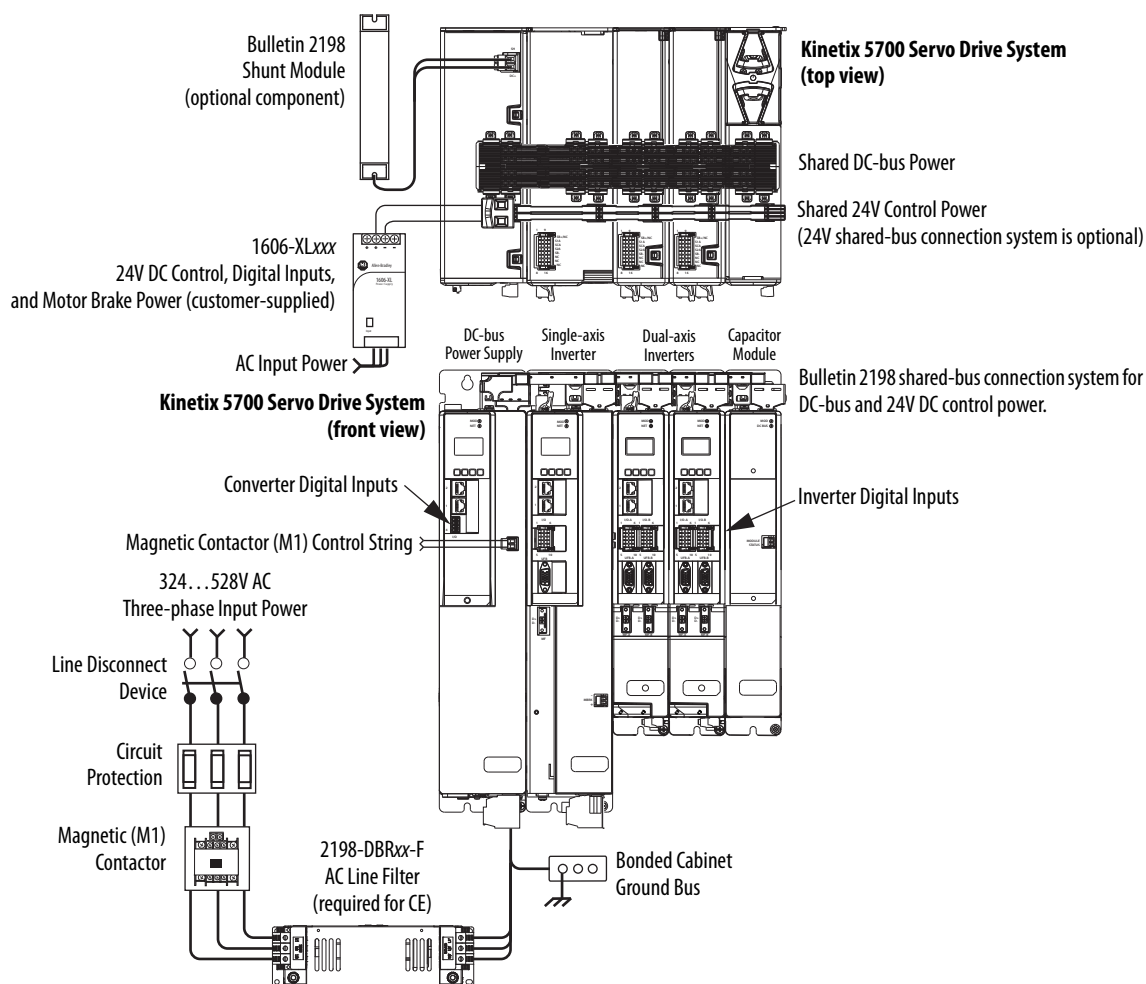
A single 2198-Pxxx DC-bus (converter) power supply can supply the Kinetix 5700 drive system with 458...747V shared DC-bus power (7...46 kW). For additional output power (kW) you can install two or three 2198-P208 DC-bus power supplies. You can also extend the DC-bus to additional inverter clusters via accessory modules.

Typical DC-bus Power Supply Configuration Example

In this multi-axis example, AC input power is fed to the DC-bus (converter) power supply. One single-axis (inverter) module and two dual-axis (inverter) modules support five axes of motion. The DC-bus power supply is mounted on the far left and the inverters are positioned on the right, but the reverse mounting order (right to left) is also possible.

Digital inputs are wired to sensors and the control circuitry at the IOD connectors. The contactor-enable relay protects the DC-bus power supply in the event of shutdown fault conditions.

Figure 1 - Typical DC-bus Power Supply Installation

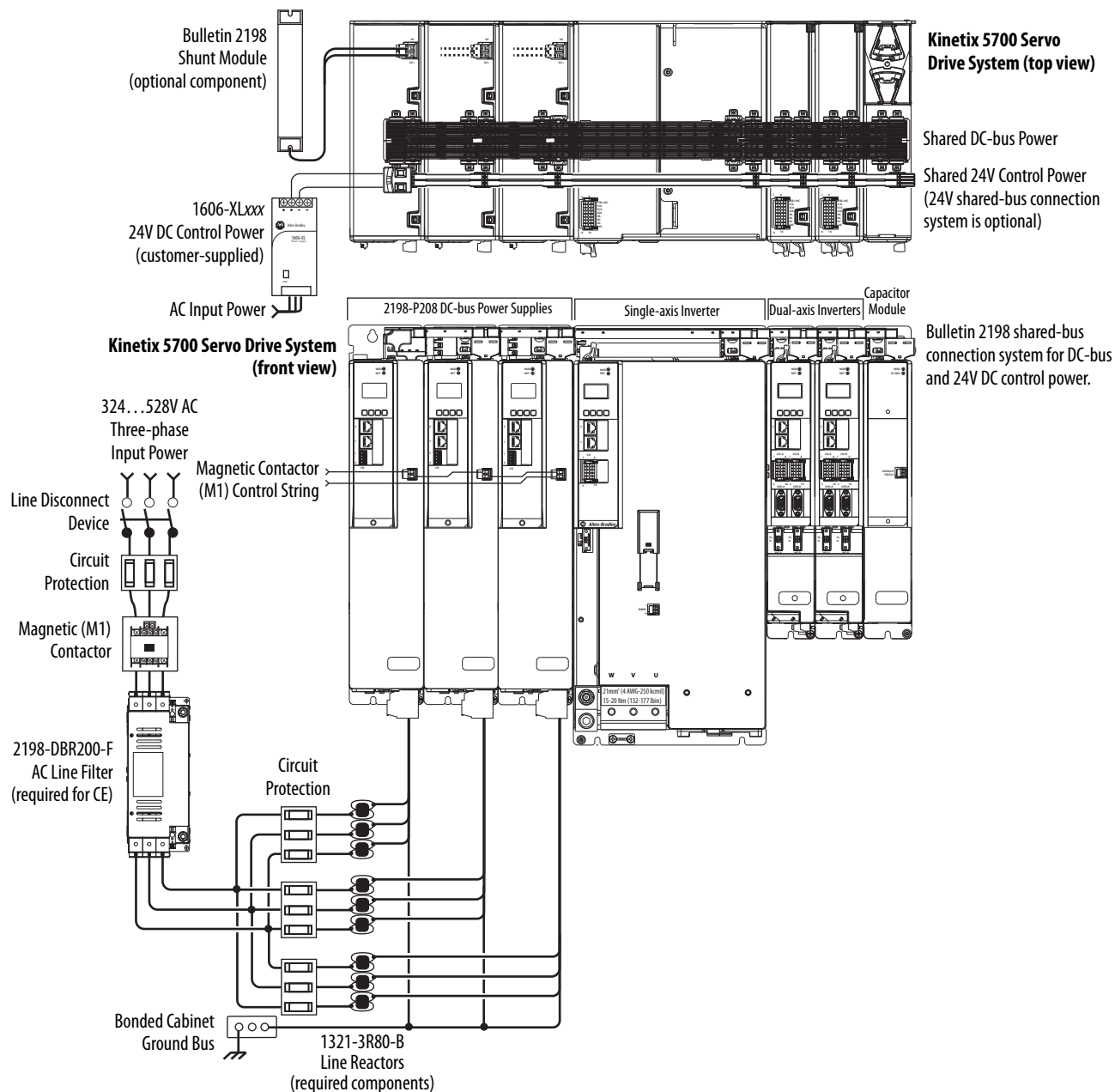


Multiple DC-Bus Power Supply Configuration Example

In this example, three DC-bus (converter) power supplies all receive AC input power and feed the inverter modules for increased output power.

Contactor enable relays from each of the DC-bus power supplies are wired in series to protect the DC-bus power supply in the event of shutdown fault conditions.

Figure 2 - Multiple DC-bus Power Supply Installation

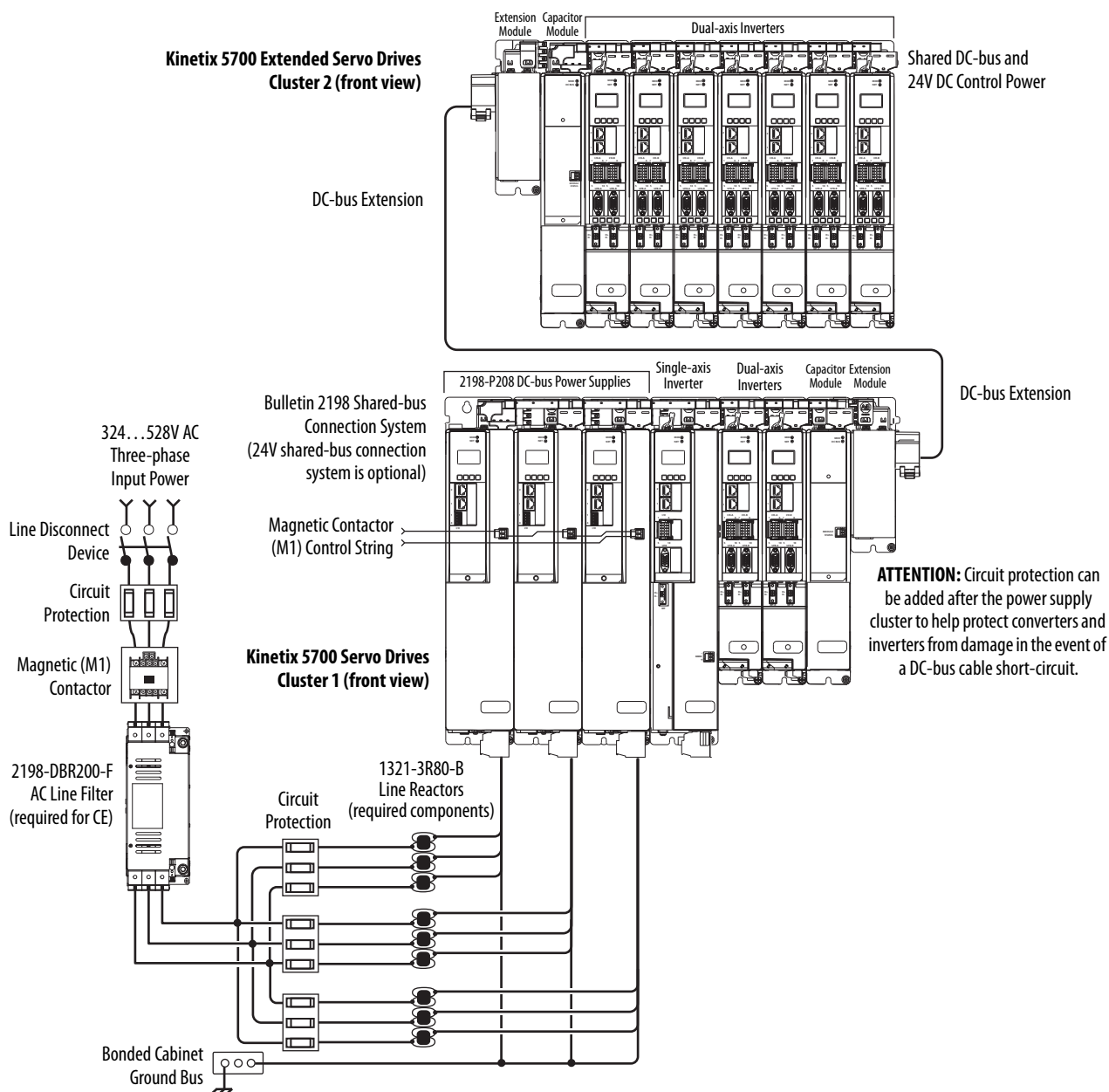


IMPORTANT When two or three DC-bus power supplies are wired together in the same drive cluster, they must all be catalog number 2198-P208.

Extended DC-bus Configuration Example

In this example, two drive clusters in the same cabinet are connected by the same 458...747V DC bus voltage. Kinetix 5700 accessory modules provide connection points for the DC-bus at the end of cluster 1 and the beginning of cluster 2. The Kinetix 5700 servo drive system is capable of up to 208 A DC-bus current. Two accessory modules are needed when the DC-bus system current exceeds 104 A. See [Accessory Module Selection](#) on [page 59](#) for more information on the when accessory modules are required.

Figure 3 - Extended DC-bus Installation



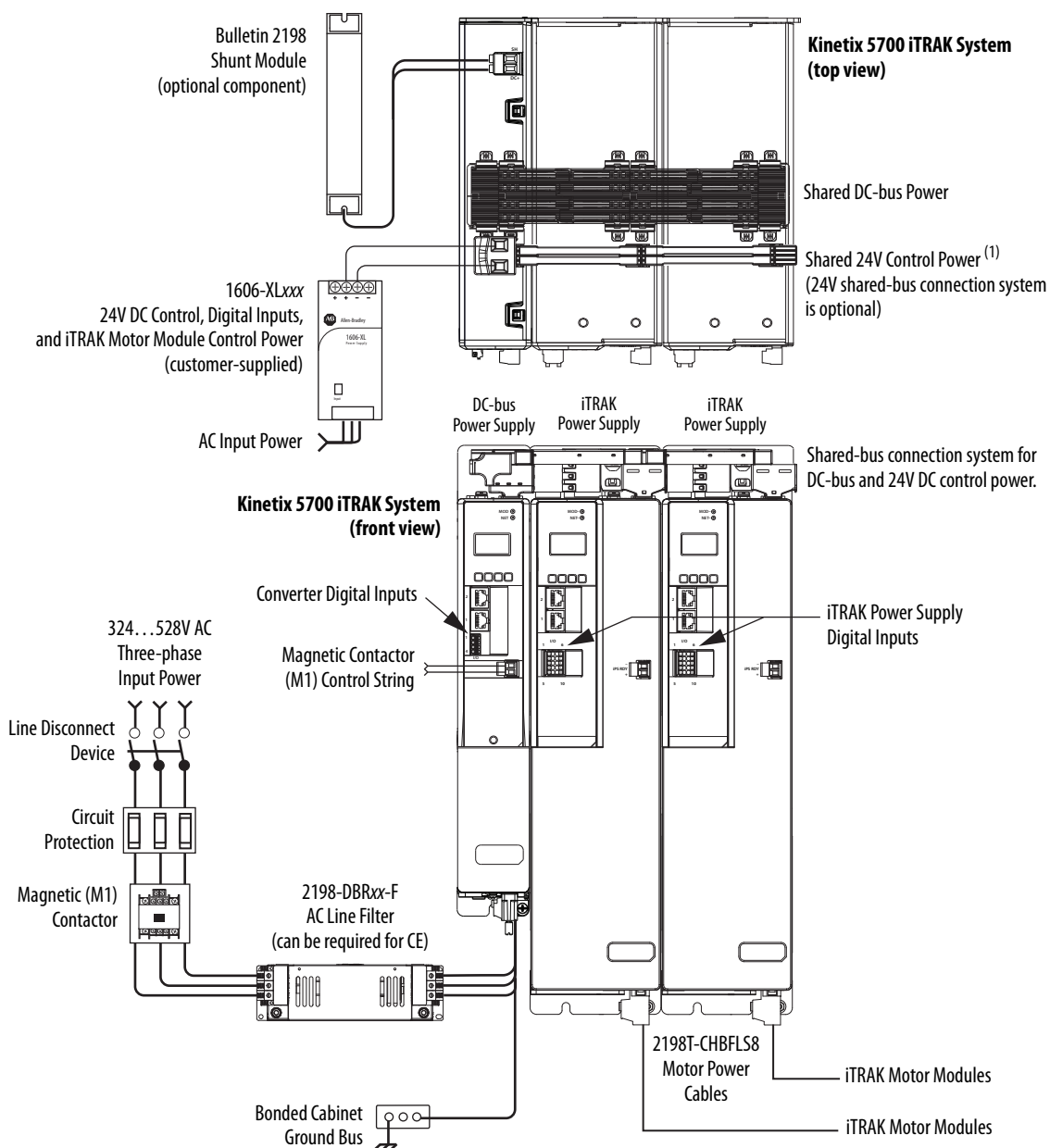
IMPORTANT When two or three DC-bus power supplies are wired together in the same drive cluster, they must all be catalog number 2198-P208.

iTRAK Power Supply Configuration Example

In this example, AC input power is fed to the DC-bus (converter) power supply. Two iTRAK power supplies support up to 40 iTRAK motor modules, depending on cable lengths and iTRAK motor-module power consumption.

Digital inputs are wired to sensors and the control circuitry at the IOD connectors. The contactor-enable relay protects the DC-bus power supply in the event of shutdown fault conditions.

Figure 4 - Typical iTRAK Power Supply Installation



(1) If total control power current exceeds 16 A, a second input connector (catalog number 2198T-W25K-P-IN) can be added to the leftmost iTRAK power supply.

Regenerative Bus Supply Input Power Configurations

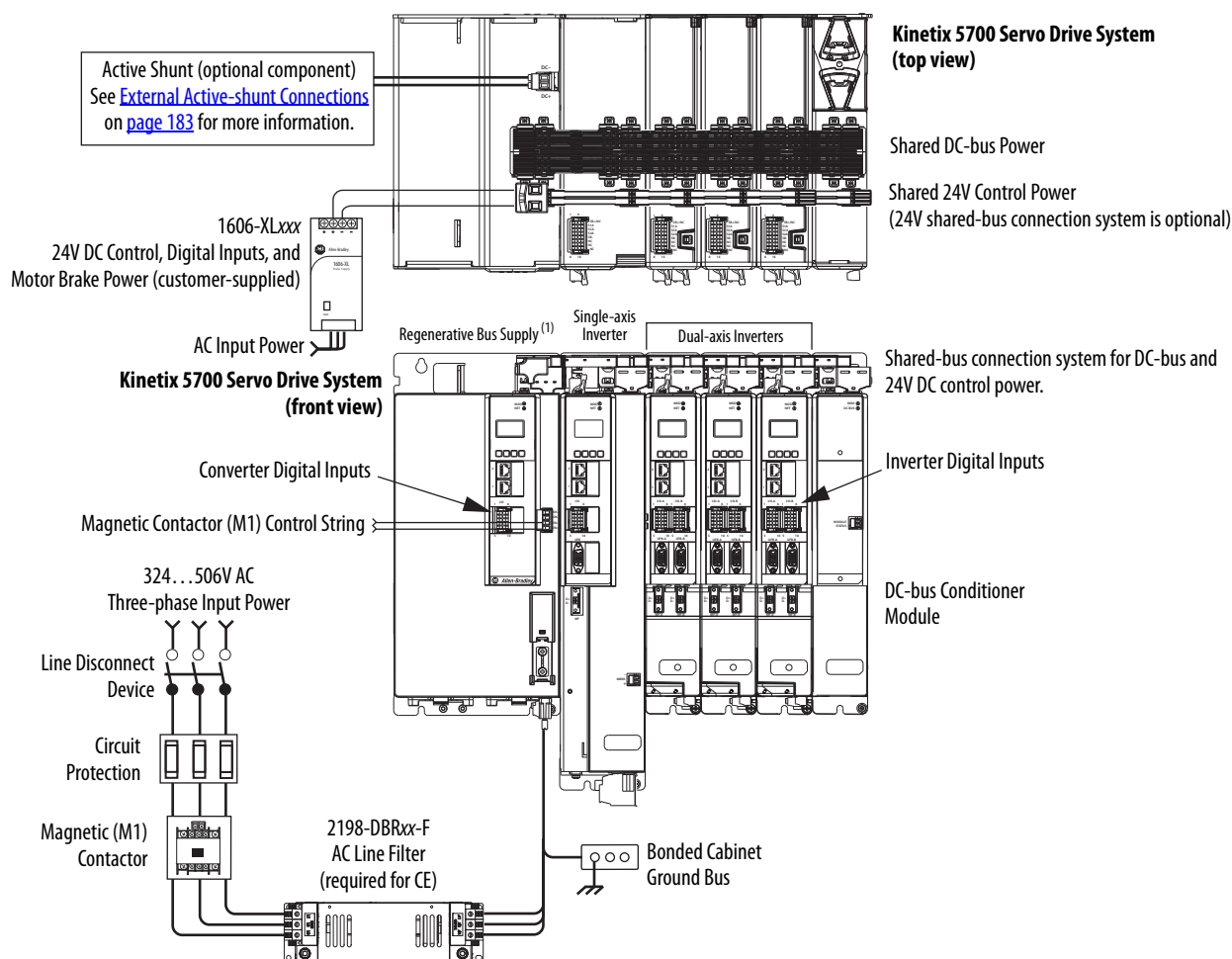
The 2198-RPxxx regenerative bus supply (24...140 kW) provides full-line motoring and regenerative power to and from the Kinetix 5700 drive system. In addition, you can extend the DC-bus voltage to additional inverter clusters via accessory modules.

Typical Regenerative Bus Configuration Examples

In this example, the inverter modules are mounted to the right of the regenerative bus supply. One single-axis (inverter) module and three dual-axis (inverter) modules support seven axes of motion. Other features include:

- Digital inputs are wired to sensors and the control circuitry at the IOD connectors.
- The contactor enable relay protects the regenerative bus supply in the event of shutdown fault conditions.
- The DC-bus conditioner module is required when the combined motor cable length exceeds 400 m (1312 ft). See [Accessory Module Selection](#) on [page 59](#) for more information on accessory module requirements.

Figure 5 - Typical Shared DC-bus Installation (mounted left to right)

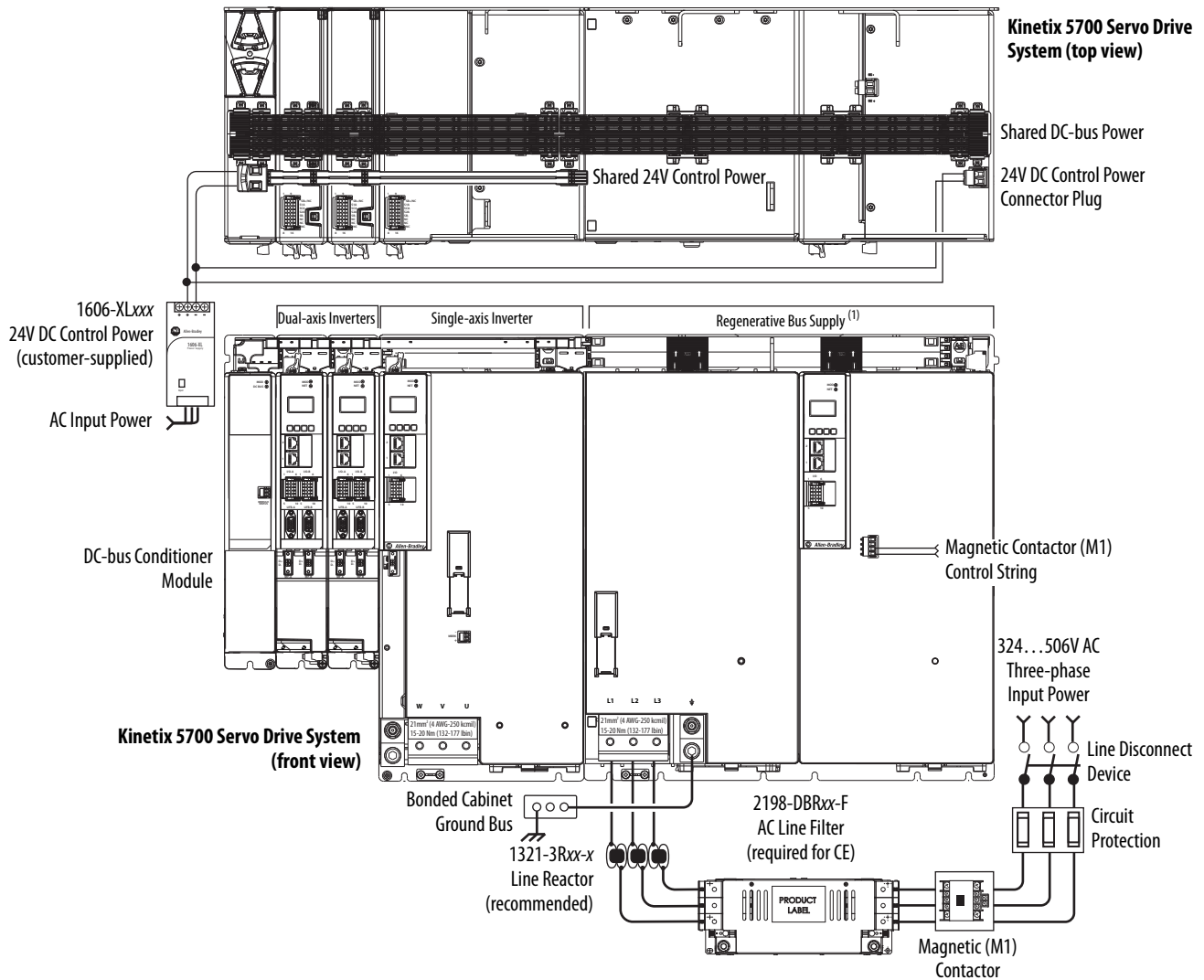


(1) The regenerative bus supply can be left or right of the inverters. Further, we recommend that the highest inverter power ratings are positioned closest to the regenerative bus supply and in decreasing order leading away from the regenerative bus supply.

In this example, the 2198-RP312 regenerative bus supply is mounted on the far right and followed by the 2198-S312-ERSx single-axis inverter, and two 2198-D020-ERSx dual-axis inverters.

- The 2198-BARCON-440DC200 DC-bus link extends the DC-bus from the regenerative bus supply to the single-axis inverter.
- The 2198-BARCON-220DC200 DC-bus link extends the DC-bus from the single-axis inverter to the dual-axis inverter.
- The regenerative bus supply has 24V DC wired to the connector plug
- The 2198-xxxx-P-T bus-bar connector extends 24V control power from the input wire connector to the dual-axis and single-axis inverters.
- The DC-bus conditioner module is required when the combined motor cable length exceeds 400 m (1312 ft). See [Accessory Module Selection](#) on [page 59](#) for more information on accessory module requirements.

Figure 6 - Typical Shared DC-bus Installation (mounted right to left)



(1) The regenerative bus supply can be left or right of the inverters. Further, we recommend that the highest inverter power ratings are positioned closest to the regenerative bus supply and in decreasing order leading away from the regenerative bus supply.

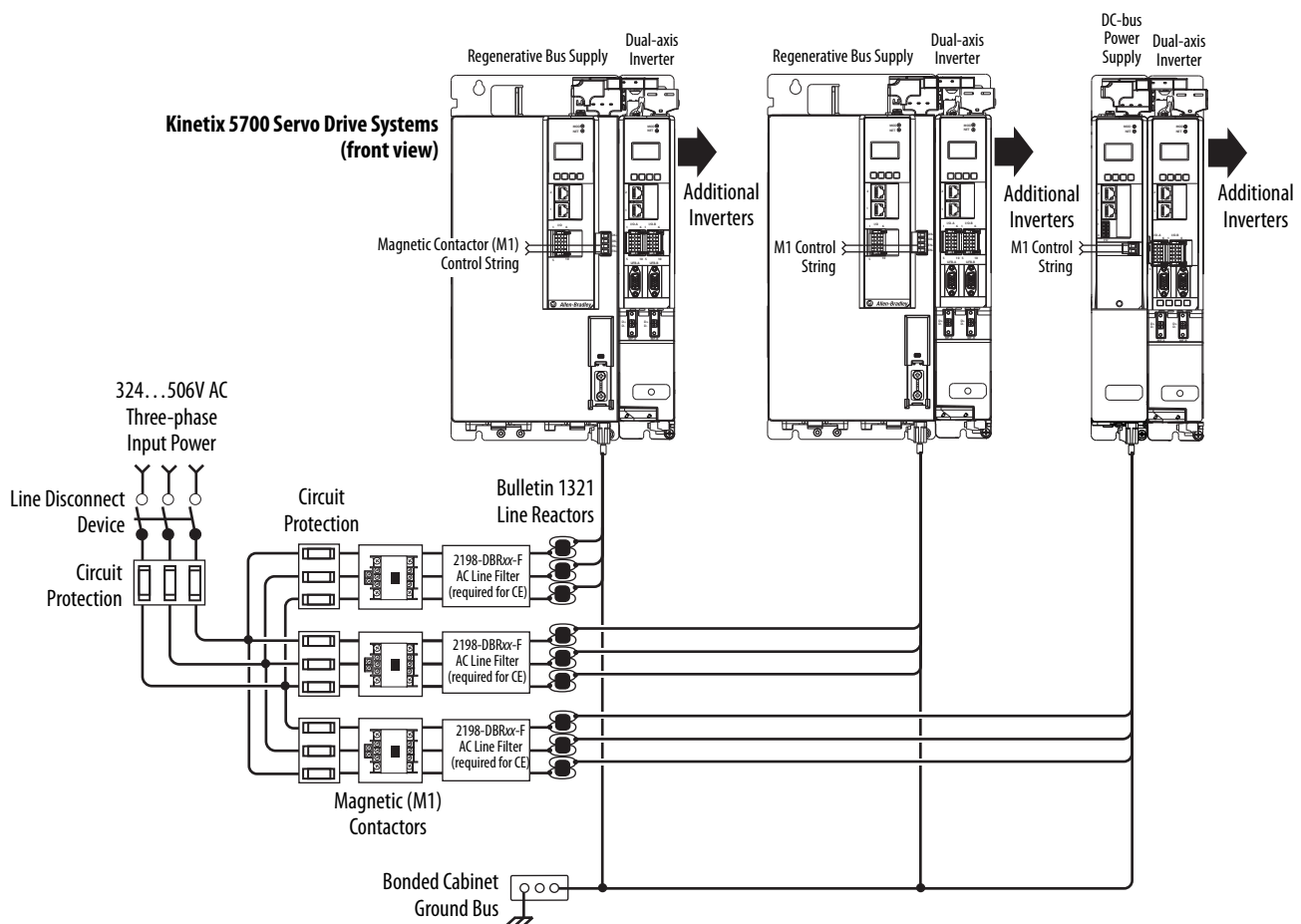
In this example, three-phase input power feeds two 2198-RPxxx regenerative power supplies and one 2198-Pxxx DC-bus power supply.

IMPORTANT We recommend that Bulletin 1321 line reactors be used in any system with multiple regenerative bus supplies sharing the same AC input-power source.

Bulletin 1321 line reactors are used in the regenerative power supply input power circuits to help do the following:

- Reduce circulating currents between different systems
- Prevent all power supplies on the same input power source from nuisance thermal overload faults

Figure 7 - Input Power to Multiple Kinetix 5700 Drive Systems

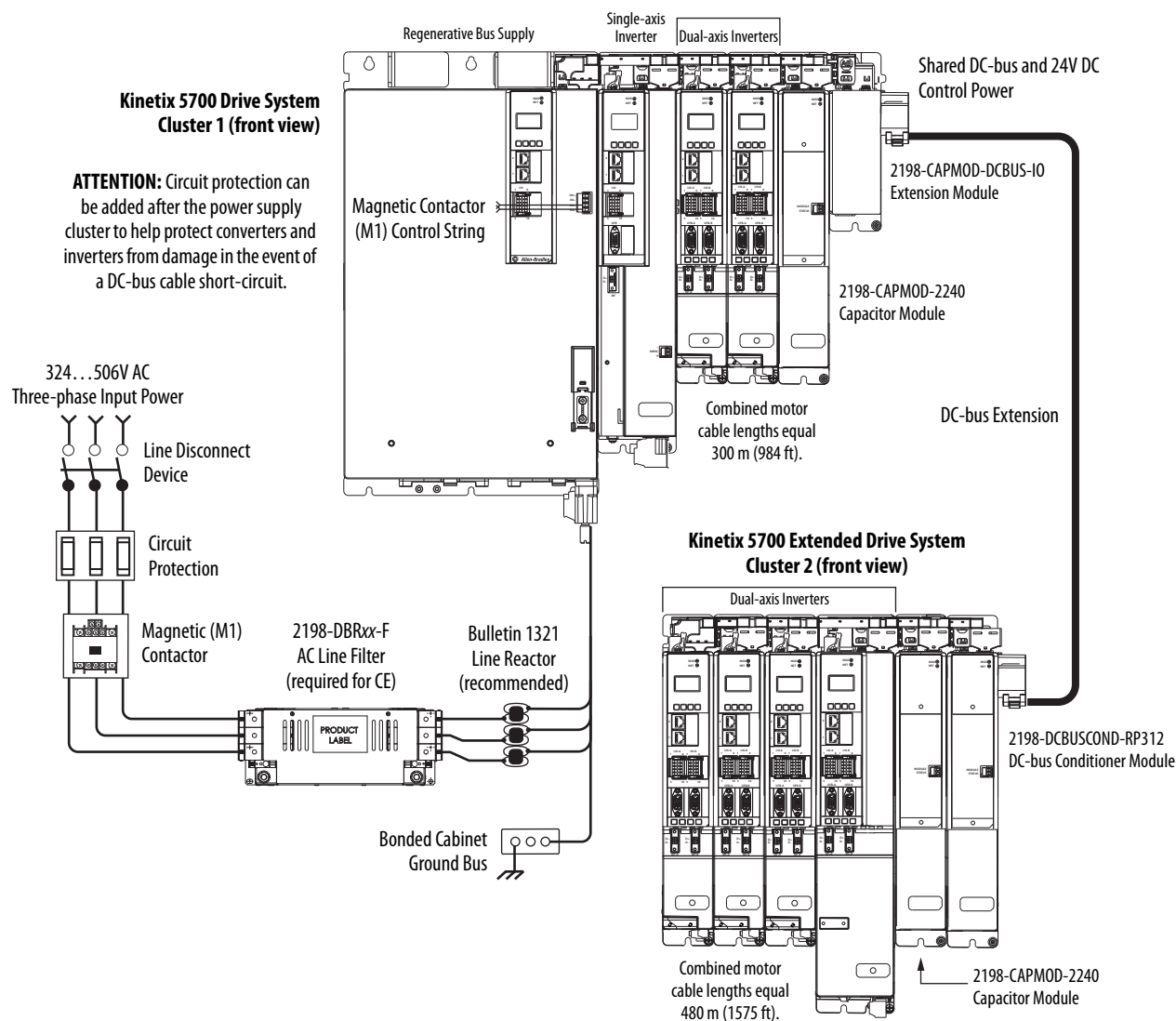


Extended Regenerative Bus Configuration Example

In this example, two drive clusters in the same cabinet are connected by the same 458...747V DC bus voltage.

- Kinetix 5700 accessory modules provide connection points for the DC bus at the end of cluster 1 and the beginning of cluster 2.
- The Kinetix 5700 servo drive system is capable of up to 208 A DC-bus current. Two parallel accessory modules are needed when the DC-bus system current exceeds 104 A.
- The DC-bus conditioner module is required when the combined motor cable length exceeds 400 m (1312 ft). See [Accessory Module Selection](#) on [page 59](#) for more information on accessory module requirements.

Figure 8 - Extended DC-bus Installation

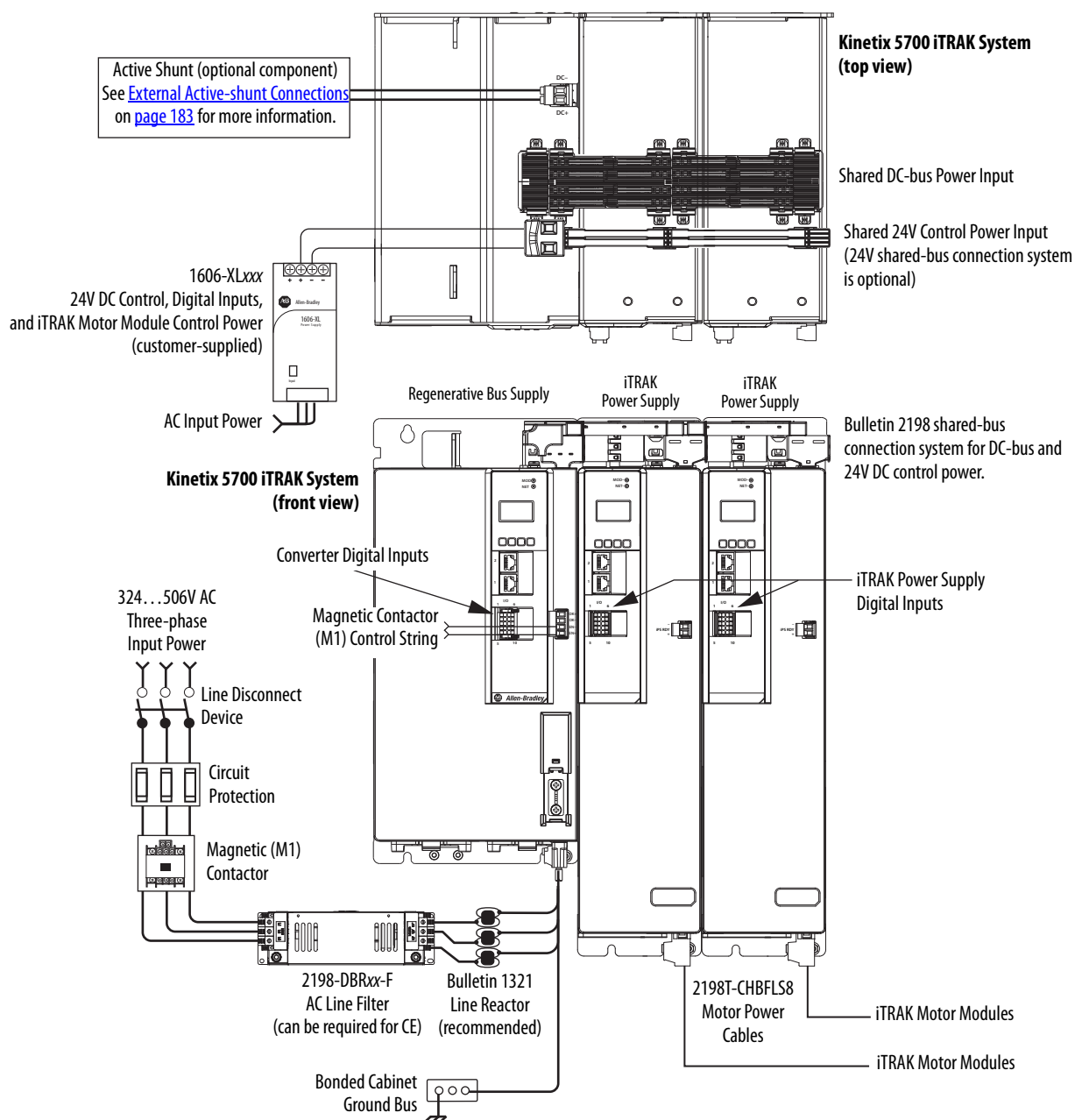


iTRAK Power Supply Configuration Example

In this example, AC input power is fed to the regenerative bus supply. Two iTRAK power supplies support up to 40 iTRAK motor modules, depending on cable lengths and iTRAK motor-module power consumption.

Digital inputs are wired to sensors and the control circuitry at the IOD connectors. The contactor-enable relay protects the regenerative bus supply in the event of shutdown fault conditions.

Figure 9 - Typical iTRAK Power Supply Installation



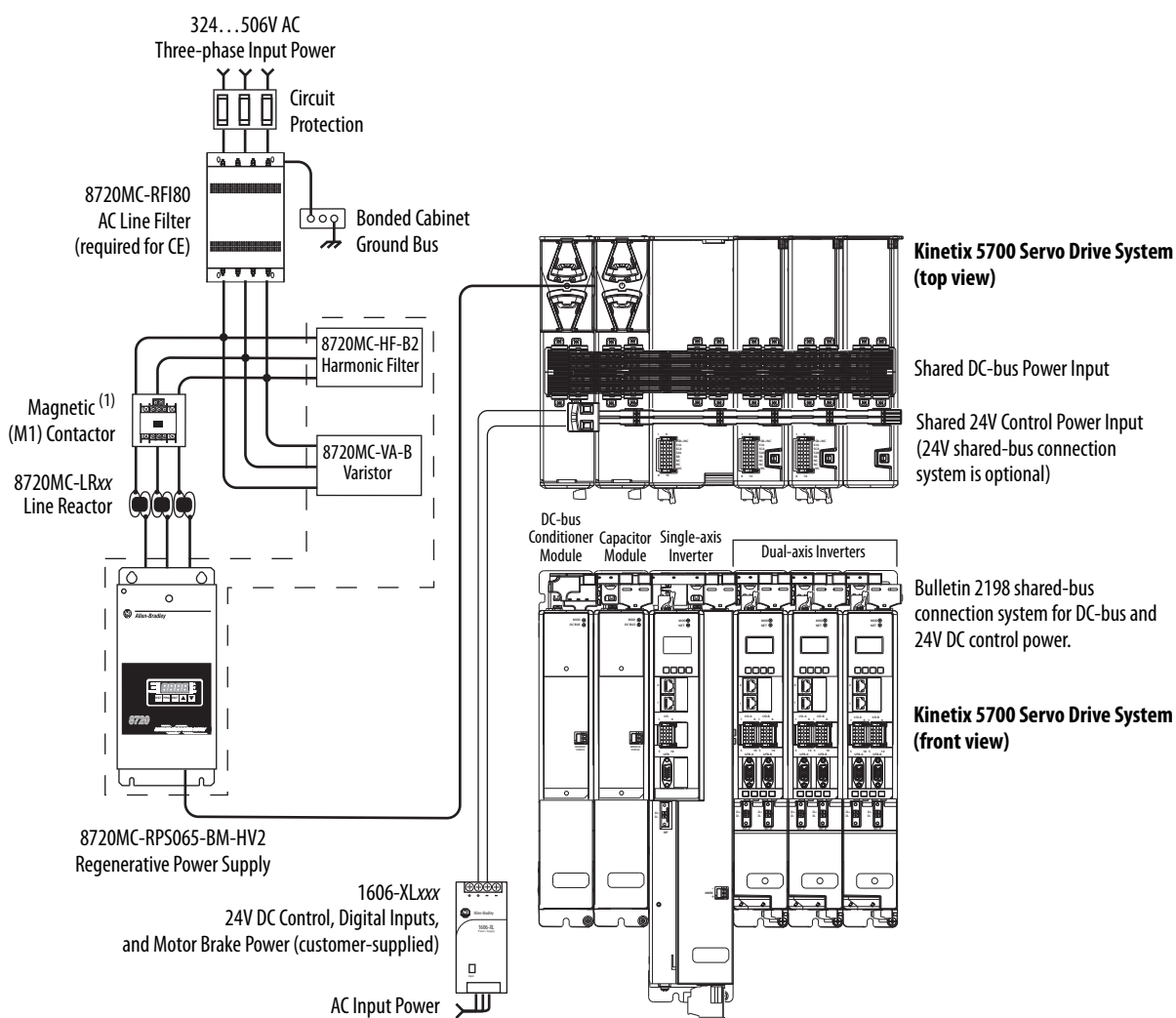
8720MC-RPS Power Supply Input Power Configuration

In this example, three-phase AC input power is fed to the Bulletin 8720MC regenerative power supply. The 8720MC-RPS DC-bus voltage supplies the Kinetix 5700 DC-bus via the capacitor module.

- The 8720MC-RPS065 provides 65 A of DC-bus current. The 2198-CAPMOD-2240 capacitor module and 2198-DCBUSCOND-RP312 DC-bus conditioner are required to reduce voltage stress on the system components.
- If the 8720MC-RPS190 is used, the capacitor module and DC-bus conditioner module provide up to 208 A of DC input current. DC-bus full-regeneration is possible with this configuration.
- The DC-bus conditioner module is required when the combined motor cable length exceeds 400 m (1312 ft). See [Accessory Module Selection](#) on [page 59](#) for more information on accessory module requirements.

IMPORTANT The 8720MC-RPS power supply is not compatible with the iTRAK power supply.

Figure 10 - 8720MC-RPS Power Supply Installations

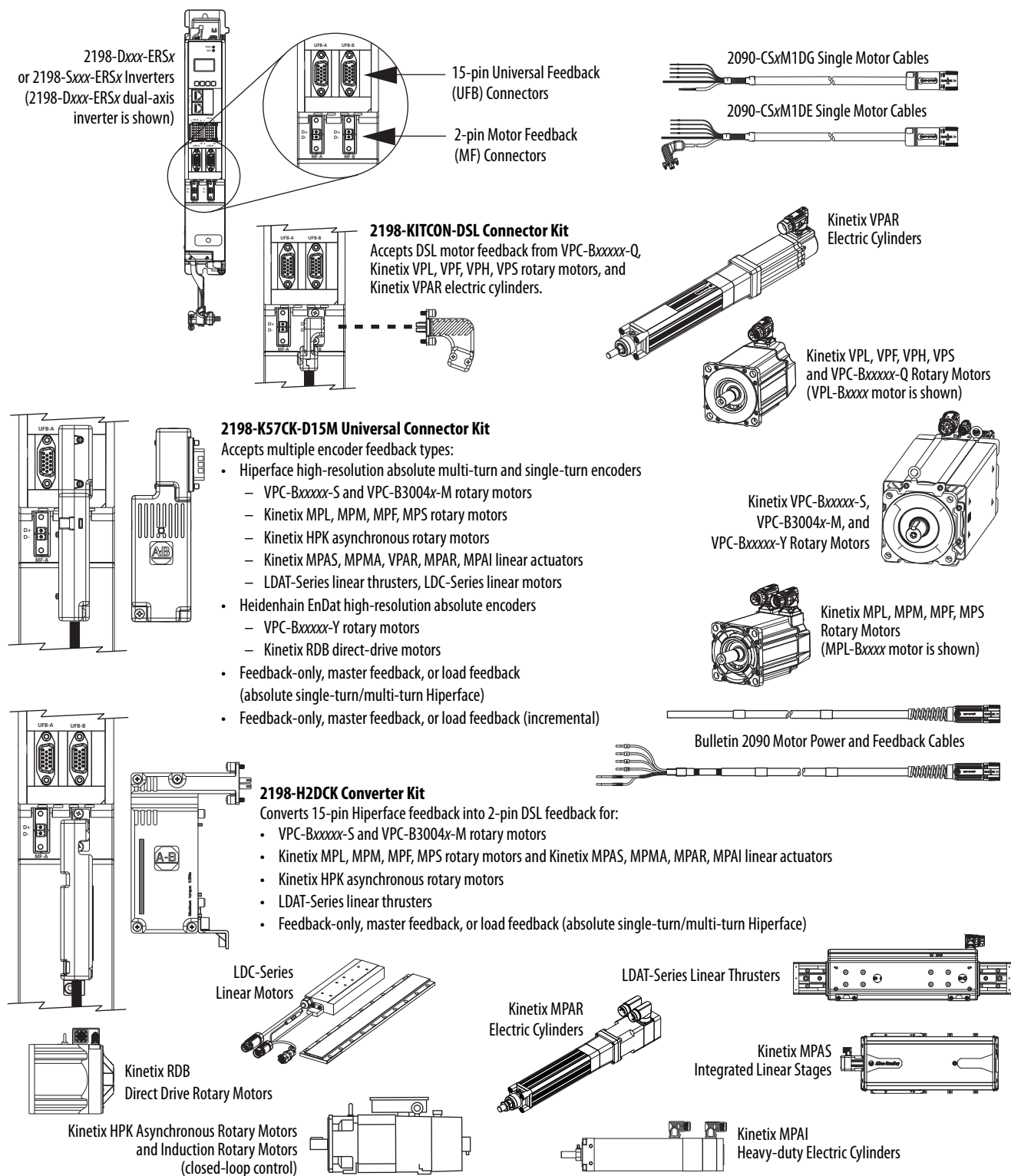


(1) This M1 contactor is controlled by the 8720MC regenerative power supply.

Motor and Auxiliary Feedback Configurations

Feedback connections are made at the 2-pin motor feedback (MF) connector and the 15-pin universal feedback (UFB) connector. These examples illustrate how you can use the Bulletin 2198 connector kits for making these connections. To see motor power and brake connections, refer to [Chapter 5](#) on [page 127](#).

Figure 11 - Feedback Configuration Example



Typical Communication Configurations

The Kinetix 5700 drives support any Ethernet topology including linear, ring, and star by using ControlLogix, GuardLogix, or CompactLogix controllers.

These examples feature the ControlLogix 5570 programmable automation controllers with support for integrated motion and integrated safety over the EtherNet/IP network. Other Allen-Bradley controllers are also compatible with the Kinetix 5700 servo drives.

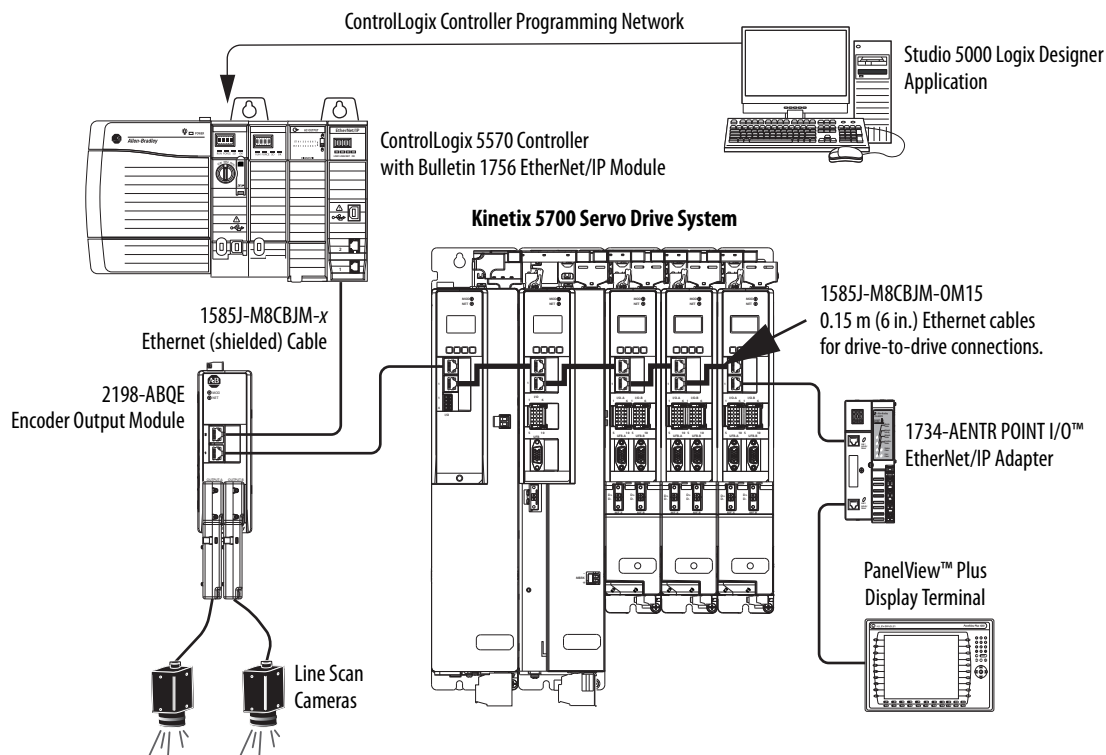
Refer to ControlLogix Communication Module Specifications Technical Data, publication [1756-TD003](#), for more information on ControlLogix 1756-EN2T, 1756-EN2TR, and 1756-EN3TR communication modules.

TIP These example configurations use the 2198-Pxxx DC-bus power supply. However, 2198-RPxxx regenerative bus supply can be used instead.

Linear Topology

In this example, all devices are connected by using linear topology. The Kinetix 5700 drive modules include dual-port connectivity, however, if any device becomes disconnected, all devices downstream of that device lose communication. Devices without dual ports must include the 1783-ETAP module or be connected at the end of the line.

Figure 12 - Kinetix 5700 Linear Communication Installation

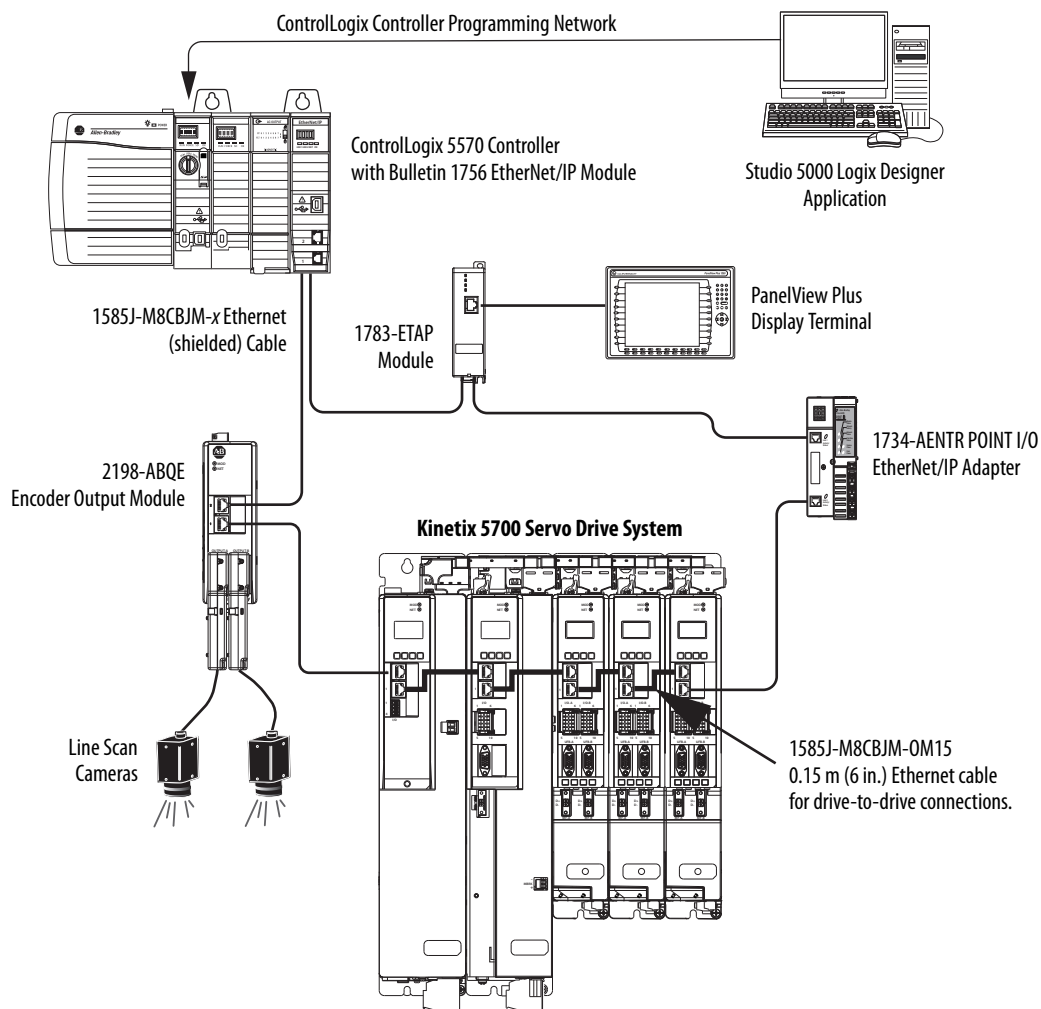


Ring Topology

In this example, the devices are connected by using ring topology. If only one device in the ring is disconnected, the rest of the devices continue to communicate. For ring topology to work correctly, a device level ring (DLR) supervisor is required (for example, the Bulletin 1783 ETAP device). DLR is an ODVA standard. For more information, refer to the EtherNet/IP Embedded Switch Technology Application Guide, publication [ENET-AP005](#).

Devices without dual ports, for example the display terminal, require a 1783-ETAP module to complete the network ring.

Figure 13 - Kinetix 5700 Ring Communication Installation

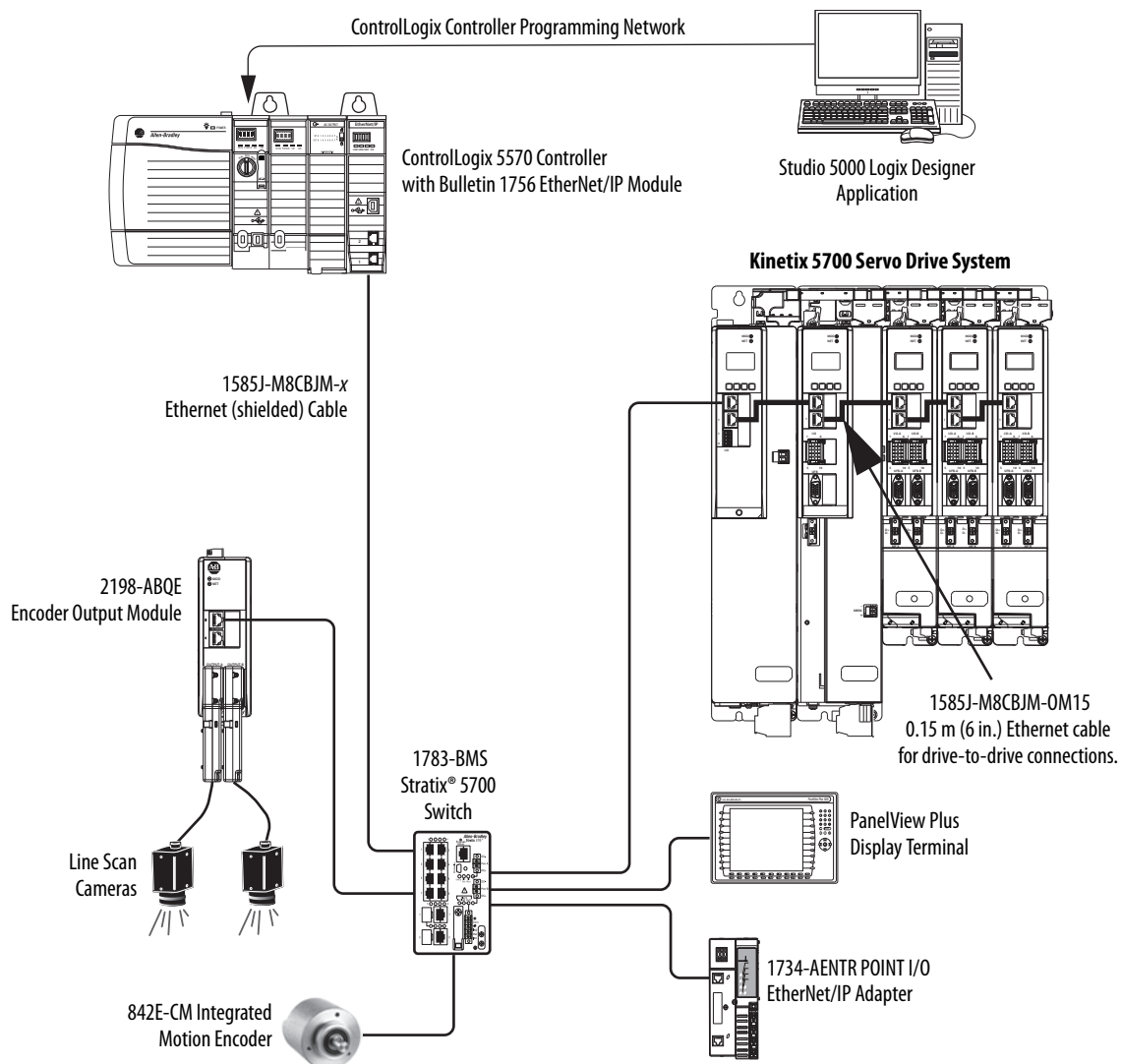


Star Topology

In this example, the devices are connected by using star topology. Each device is connected directly to the switch.

Kinetix 5700 drive modules have dual ports, so linear topology is maintained from one module to another, but the Kinetix 5700 system and other devices operate independently. The loss of one device does not impact the operation of other devices.

Figure 14 - Kinetix 5700 Star Communication Installation



You can use the 842E-CM integrated motion encoder for applications requiring an external encoder for gearing or camming to the Kinetix 5700 drive. By providing auxiliary feedback directly through the EtherNet/IP network, the 842E-CM encoder helps eliminate the need for point-to-point wiring while letting customers use the encoder in a variety of network topologies. For more information, see the 842E-CM Integrated Motion on EtherNet/IP Product Profile, publication [842ECM-PP001](#).

Functional Safety Configurations

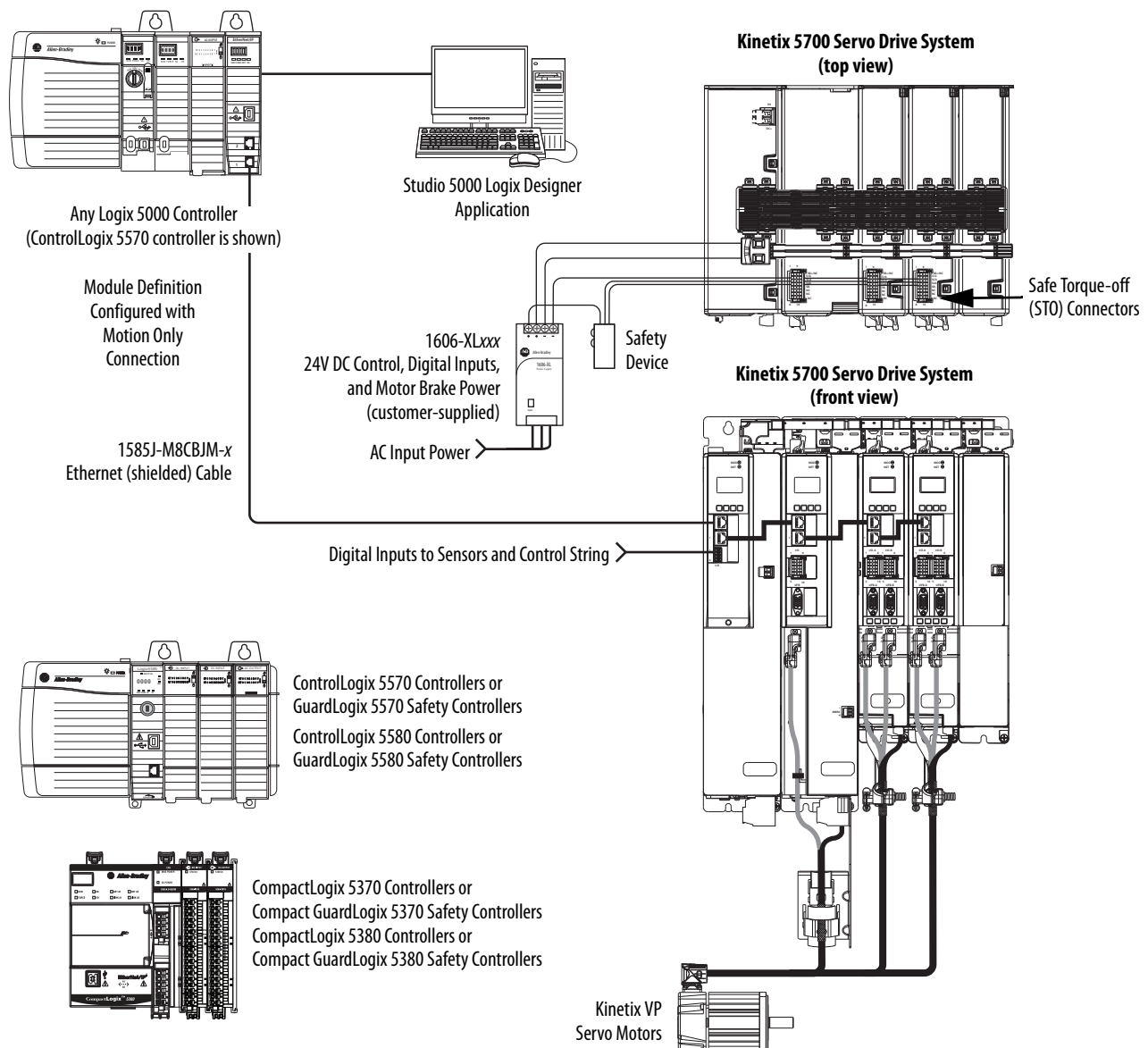
Kinetix 5700 servo drives are capable of safe torque-off (STO) and safe stop 1 (SS1) drive-based safety functions via hardwired connections or integrated over the EtherNet/IP network. In addition, safely limited speed (SLS) and other controller-based safety instructions are also possible. These examples illustrate the functional safety configuration options.

TIP These example configurations use the 2198-Pxxx DC-bus power supply. However, 2198-RPxxx regenerative bus supply can be used instead.

Hardwired Configuration

Kinetix 5700 servo drives use the safe torque-off (STO) connector for wiring external safety-devices and cascading hardwired safety-connections from one drive to another.

Figure 15 - Safe Torque-off (hardwired) Configuration



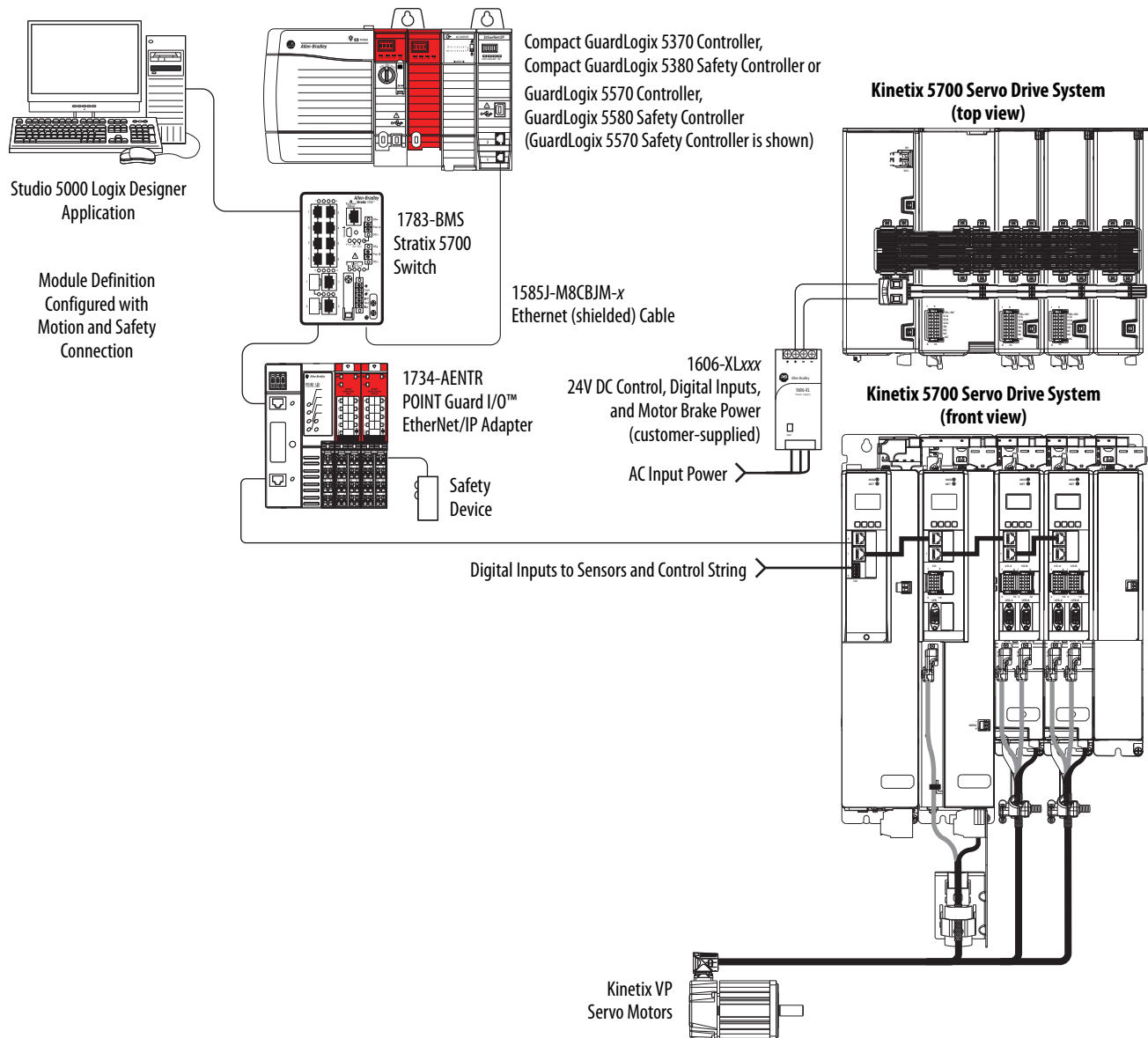
Integrated Safety Configurations

The GuardLogix or Compact GuardLogix safety controller issues the safe torque-off (STO) or safe stop (SS1) command over the EtherNet/IP network and the Kinetix 5700 servo drive executes the command.

In this example, a single GuardLogix safety controller makes the Motion and Safety connections.

IMPORTANT If only one controller is used in an application with Motion and Safety connections, it must be a GuardLogix or Compact GuardLogix safety controller. For more information, see the [Integrated Functional Safety Support](#) table on [page 16](#).

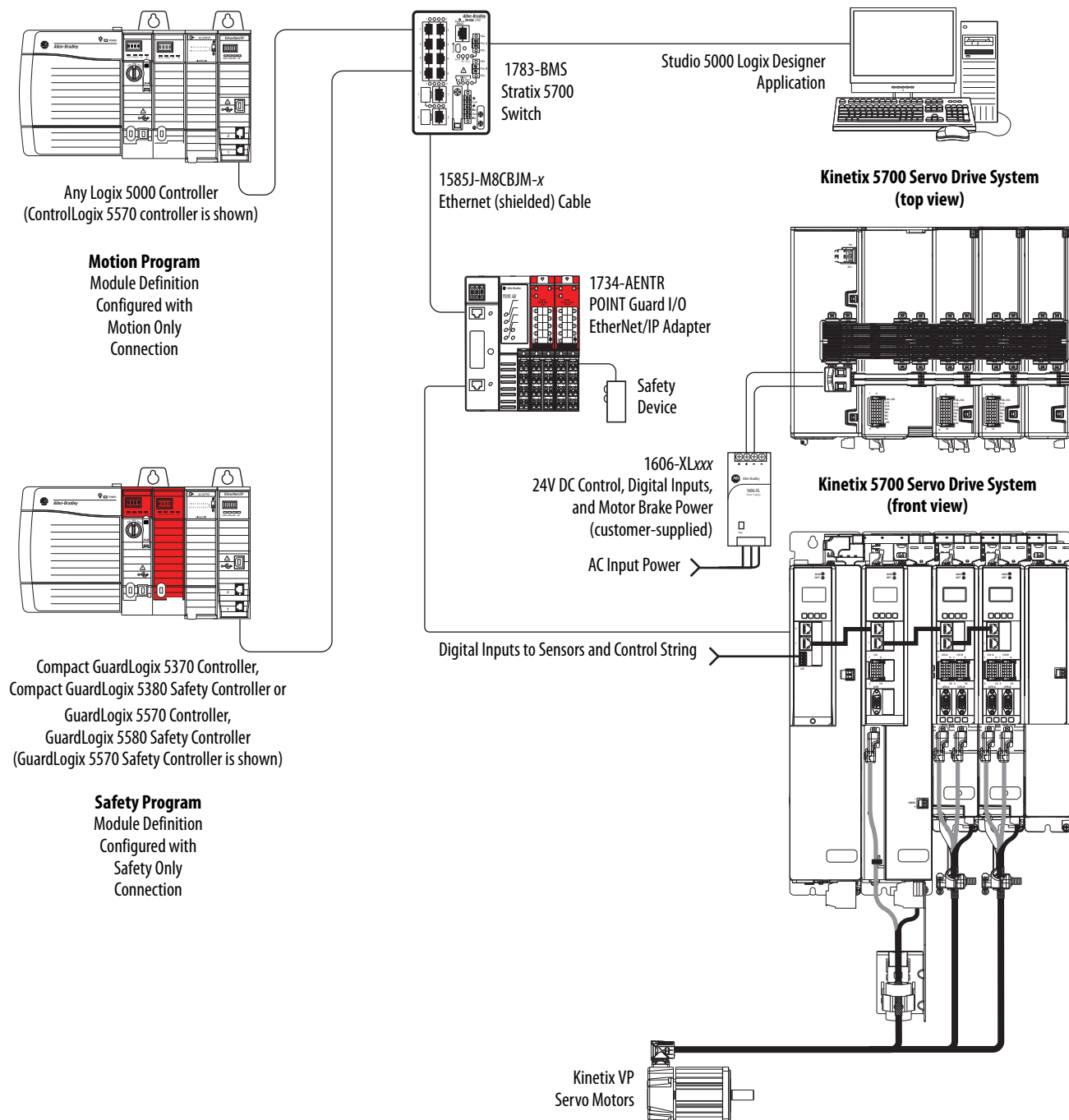
Figure 16 - Motion and Safety Configuration (single controller)



In this example, a non-safety controller makes the Motion-only connection and a separate GuardLogix safety controller makes the Safety-only connection.

IMPORTANT If two controllers are used in an application with Motion Only and Safety Only connections, the Safety Only connection must be a GuardLogix or Compact GuardLogix safety controller and the Motion Only connection must be any Logix 5000 controller. For more information, see the [Integrated Functional Safety Support](#) table on [page 16](#).

Figure 17 - Motion and Safety Configuration (multi-controller)



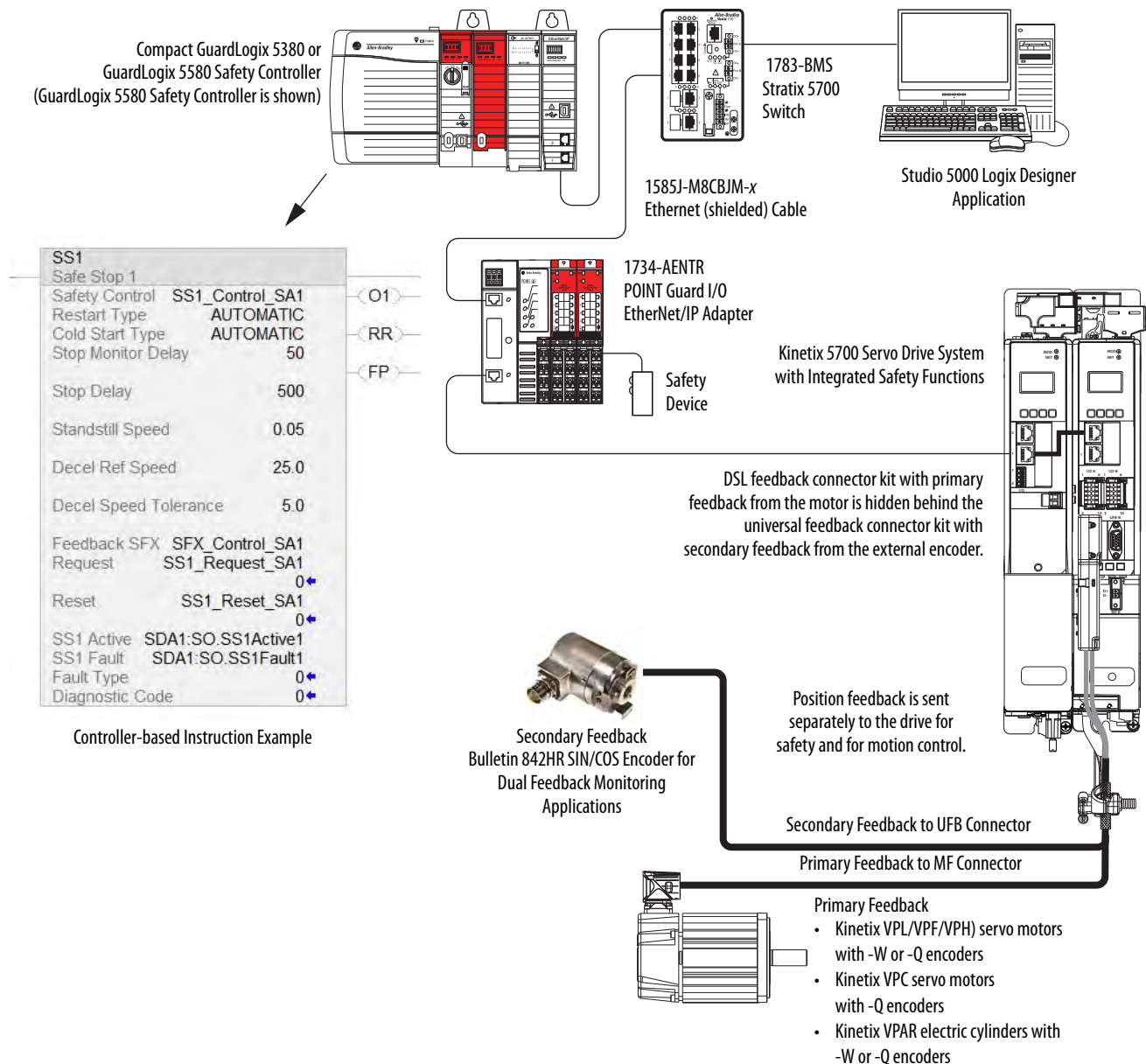
Safe Stop and Safe Monitor Configurations

Kinetix 5700 servo drives are capable of safe stop and safe monitor functions via drive-based and controller-based integrated safety over the EtherNet/IP network.

IMPORTANT For applications with safe stop and safe monitor safety functions, the GuardLogix 5580 or Compact GuardLogix 5380 controllers must be used. For more information, see the [Integrated Functional Safety Support](#) table on [page 16](#).

In this example, the SS1 stopping function is used in a motion and safety controller-based configuration with dual-feedback monitoring.

Figure 18 - Safe Motion-monitoring Configuration



Catalog Number Explanation

Kinetix 5700 drive module catalog numbers and performance descriptions.

Table 4 - Kinetix 5700 Drive Module Catalog Numbers

| Kinetix 5700 Drive Modules | Cat. No. | | Module Width mm | Input Voltage | Continuous Output Power kW | Continuous Output Current to Bus A _{DC} rms | Continuous Output Current A 0-pk |
|----------------------------|--|--|--------------------|--|-------------------------------|---|-------------------------------------|
| DC-bus Power Supply | 2198-P031 2198-P070 | | 55 | 324...528V AC rms, three-phase | 7 17 | 10.5 25.5 | — |
| | 2198-P141 2198-P208 | | 85 | | 31 46 | 46.9 69.2 | |
| Regenerative Power Supply | 2198-RP088 | | 165 | 324...506V AC rms, ⁽¹⁾ three-phase | 24 | 35 | — |
| | 2198-RP200 | | 275 | | 67 | 100 | |
| | 2198-RP263 | | 440 | | 119 | 176 | |
| | 2198-RP312 | | | | 140 | 207 | |
| Single-axis Inverters | 2198-S086-ERS3 2198-S130-ERS3 | 2198-S086-ERS4 2198-S130-ERS4 | 85 | — | 29.7 44.9 | — | 60.8 91.9 |
| | 2198-S160-ERS3 | 2198-S160-ERS4 | 100 | | 60.1 | | 120.2 |
| | 2198-S263-ERS3 2198-S312-ERS3 | 2198-S263-ERS4 2198-S312-ERS4 | 220 | | 90 112 | | 212.1 271.5 |
| Dual-axis Inverters | 2198-D006-ERS3 2198-D012-ERS3 2198-D020-ERS3 2198-D032-ERS3 | 2198-D006-ERS4 2198-D012-ERS4 2198-D020-ERS4 2198-D032-ERS4 | 55 | — | 1.7 3.4 5.5 8.9 | — | 3.5 7.0 11.3 18.3 |
| | 2198-D057-ERS3 | 2198-D057-ERS4 | 85 | | 15.9 | | 32.5 |
| | iTRAK Power Supply | 2198T-W25K-ER | | | 100 | | — |

(1) Applies when DC-bus voltage regulation is enabled. If DC-bus voltage regulation is not enabled, the input voltage range is 324...528V AC. For more information on these two modes of operation, see [DC-bus Voltage Regulation](#) on [page 42](#).

Table 5 - Accessory Module Catalog Numbers

| Accessory Modules ⁽¹⁾ | Cat. No. | Module Width mm | System Current ⁽²⁾ | Rated Voltage | Capacitance |
|----------------------------------|----------------------|--------------------|-------------------------------|--------------------|-------------|
| Capacitor Module | 2198-CAPMOD-2240 | 55 | 104 A | 458...747V DC, nom | 2240 µF |
| Extension Module | 2198-CAPMOD-DCBUS-IO | | | | — |
| DC-bus Conditioner Module | 2198-DCBUSCOND-RP312 | | | | — |

(1) Combination of any two accessory modules increases system current up to 208 A. However, modules must be mounted side-by-side and joined by two flexible bus-bars.

(2) Flexible bus-bars are included with only the 2198-CAPMOD-DCBUS-IO extension module. So, if you have two capacitor modules, two DC-bus conditioner modules, or a capacitor module and DC-bus conditioner module mounted side by side, you must order the 2198-KITCON-CAPMOD2240 or 2198-KITCON-DCBUSCOND connector set separately.

Table 6 - Shared-bus Connector Kit Catalog Numbers

| Shared-bus Connector Kits Cat. No. | Drive Module Cat. No. | Application | Description |
|--|--|-----------------------------------|---|
| 2198-TCON-24VDCIN36 ⁽¹⁾ (2) | 2198-P031, 2198-P070, 2198-P141, 2198-P208 2198-CAPMOD-2240 | 24V DC input power to control bus | 24V DC input wiring connector |
| | 2198-RP088, 2198-RP200, 2198-DCBUSCOND-RP312 | | |
| 2198T-W25K-P-IN ⁽¹⁾ (2) | 2198T-W25K-ER, 2198-RP263, 2198-RP312, 2198-S263-ERSx, 2198-S312-ERSx | | |
| 2198-H040-P-T | 2198-D006-ERSx, 2198-D012-ERSx 2198-D020-ERSx, 2198-D032-ERSx 2198-CAPMOD-2240, 2198-DCBUSCOND-RP312 | Control power sharing | Control power T-connector with bus bars, 55 mm |
| 2198-H070-P-T | 2198-D057-ERSx, 2198-S086-ERSx, 2198-S130-ERSx | Control power sharing | Control power T-connector with bus bars, 85 mm |
| 2198-S160-P-T | 2198-S160-ERSx | Control power sharing | Control power T-connector with bus bars, 100 mm |
| 2198T-W25K-P-T | 2198T-W25K-ER | | |
| 2198-S312-P-T | 2198-S263-ERSx, 2198-S312-ERSx | Control power sharing | Control power T-connector with bus bars, 220 mm |

(1) The input wiring connector can be inserted into any drive module (mid-stream in the drive system) to begin a new 24V control bus when the maximum current value is reached. However, the input connector must always extend the 24V DC-bus from left to right. The 2198T-W25K-P-IN male plug is physically larger than the male plug on 2198-TCON-24VDCIN36.

(2) For drive module amp ratings and connector wire size information, see [Control Power](#) on [page 113](#), and [CP Connector Plug Wiring Specifications](#) table on [page 146](#), respectively.

Agency Compliance

If this product is installed within the European Union and has the CE mark, the following regulations apply.



ATTENTION: Meeting CE requires a grounded system, and the method of grounding the AC line filter and drive module must match. Failure to do this renders the filter ineffective and can cause damage to the filter. For grounding examples, refer to [Grounded Power Configurations](#) on [page 129](#).

For more information on electrical noise reduction, refer to the System Design for Control of Electrical Noise Reference Manual, publication [GMC-RM001](#).

To meet CE requirements, these requirements apply:

- Install an AC line filter (catalog number 2198-DBRxx-F) for input power as close to the 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply as possible.
- Bond DC-bus power supplies, regenerative bus supplies, inverter modules, capacitor modules, and line filter grounding screws by using a braided ground strap as shown in [Figure 91 on page 139](#).
- When using the 2198-P070 DC-bus power supply above 45 °C (113 °F) with stranded input power wiring, conductors must be single-core 6 mm² stranded copper with 90 °C minimum rating.
- When using the 2198-RP088 regenerative power supply above 40 °C (104 °F) with stranded input power wiring, conductors must be single-core 6 mm² stranded copper with 90 °C minimum rating.

- Use Bulletin 2090 single motor cables with Kinetix VP motors and actuators. Use Bulletin 2090 motor power/brake and feedback cables for other compatible Allen-Bradley motors and actuators. Motor cable shield-clamp on the drive must be used.
- Combined motor power cable length for all axes on the same DC bus must not exceed:
 - 1200 m (3937 ft) for 2198-P070, 2198-P141, and 2198-P208, DC-bus power supplies and 2198-RPxxx regenerative bus supplies when paired with 2198-DBRxx-F line filters.
 - 400 m (1312 ft) for 2198-Pxxx DC-bus power supplies when paired with 2198-DBxx-F line filters.
 - 400 m (1312 ft) for 2198-P031 DC-bus power supplies when paired with 2198-DBxx-F or 2198-DBRxx-F line filters.

Drive-to-motor feedback cables must not exceed 90 m (295 ft), depending on system components.

- Motor cable length for the iTRAK power supply to iTRAK motor modules must be at least 3 m (9.8 ft), not to exceed 30 m (98.4 ft).
- Use Bulletin 2198T power cables with iTRAK systems.
- Install the Kinetix 5700 system inside an approved enclosure. Run input power wiring in conduit (grounded to the enclosure) outside of the enclosure. Separate signal and power cables.
- Segregate input power wiring from control wiring and motor cables.

Refer to Appendix A on [page 341](#) for input power wiring and drive/motor interconnect diagrams.

Notes:

Plan the Kinetix 5700 Drive System Installation

This chapter describes system installation guidelines used in preparation for mounting your Kinetix® 5700 drive system components.

| Topic | Page |
|----------------------------|------|
| System Design Guidelines | 41 |
| Accessory Module Selection | 59 |
| Electrical Noise Reduction | 67 |



ATTENTION: Plan the installation of your system so that you can perform all cutting, drilling, tapping, and welding with the system removed from the enclosure. Because the system is of the open type construction, be careful to keep metal debris from falling into it. Metal debris or other foreign matter can become lodged in the circuitry and result in damage to the components.

System Design Guidelines

Use the information in this section when planning to mount your system components on the panel.

For on-line product selection and system configuration tools, including AutoCAD (DXF) drawings of the product, refer to <https://www.rockwellautomation.com/global/support/selection.page>.

System Mounting Requirements

- To comply with UL and CE requirements, the Kinetix 5700 drive system must be mounted in a grounded conductive enclosure offering protection as defined in standard IEC 60529 to IP20 such that they are not accessible to an operator or unskilled person.
To maintain the functional safety rating of the Kinetix 5700 drive system, this enclosure must be appropriate for the environmental conditions of the industrial location and provide a protection class of IP54 or higher.
- The panel you install inside the enclosure for mounting your system components must be on a flat, rigid, vertical surface that won't be subjected to shock, vibration, moisture, oil mist, dust, or corrosive vapors in accordance with pollution degree 2 (EN 61800-5-1) because the product is rated to protection class IP20 (EN 60529).

- Size the system enclosure so as not to exceed the maximum ambient temperature rating. Consider heat dissipation specifications for all system components.
- Use high-frequency (HF) bonding techniques to connect the modules, enclosure, machine frame, and motor housing, and to provide a low-impedance return path for high-frequency (HF) energy and reduce electrical noise.

Bond the Kinetix 5700 system power supply, inverter modules, iTRAK® power supply, accessory modules, and line filter grounding screws by using a braided ground strap as shown in [Figure 91 on page 139](#).

Refer to the System Design for Control of Electrical Noise Reference Manual, publication [GMC-RM001](#), to better understand the concept of electrical noise reduction.

DC-bus Voltage Regulation

The 2198-Pxxx DC-bus power supply does not regulate DC-bus voltage. As a result, the DC-bus power supply always has DC-bus voltage regulation disabled. The 2198-RPxxx regenerative bus supply can be configured to provide active DC-bus voltage regulation or passive AC rectification like the 2198-Pxxx DC-bus (converter) power supply.

IMPORTANT Active or passive DC-bus voltage regulation must be determined during system configuration in the Studio 5000 Logix Designer® application.

IMPORTANT Regeneration back to the AC source is only possible when the DC-bus voltage regulation is enabled.

Converter Startup Method

The Converter Startup Method (Axis Properties>General category) specifies the method to be used to initiate transition of the regenerative converter axis from the STOPPED state to the STARTING state.



ATTENTION: To help prevent permanent inverter damage, make sure that all inverter ground jumpers are removed before enabling DC-bus voltage regulation.

Set the Converter Startup Method to one of these two settings:

- Automatic (default): After applying AC, the converter automatically transitions to the RUNNING state with active DC-bus voltage regulation loops operational
- Enable Request: After applying AC, the converter stays in the STOPPED state and performs passive AC rectification. Once it receives an Enable Request from the controller, the converter transitions to the RUNNING state with active DC-bus voltage control loops operational

In Enable Request mode, you must issue an MSO instruction (after AC is applied and CIP_Axis_State = STOPPED) to enable voltage regulation on the regenerative bus supply and an MSF instruction to disable voltage regulation.

Bus Voltage Loop Parameters

The regenerative bus supply uses an active control loop to maintain the DC bus voltage at a specified level (or reference) and has two settings for the Bus Voltage Reference Source (Axis Properties>Bus Voltage Loop category>Parameters):

- Automatic (default) setting: The converter optimizes the BusVoltageReference for the best converter performance
- Manual setting: You configure the desired BusVoltageSetPoint value for the BusVoltageReference signal

In Manual mode, the BusVoltageSetPoint must be greater than 5% of the peak input AC voltage (or it is clamped automatically) with a maximum of 747V DC.

$$\text{Bus Voltage Set Point (V}_{\text{DC}}) > \text{AC Input Voltage (V}_{\text{RMS}}) \cdot \sqrt{2} \cdot 1.05$$

Boost voltage is the difference between the rectified AC voltage and the BusVoltageSetPoint.

$$\text{Boost Voltage} = \text{Bus Voltage Set Point (V}_{\text{DC}}) - \text{AC Input Voltage (V}_{\text{RMS}}) \cdot \sqrt{2}$$

IMPORTANT Setting a manual fixed DC-bus voltage sets peak motor output power performance regardless of the variance of the input AC rms. Higher boost voltage increases Total Harmonic Distortion (THD), reduces efficiency, and increases acoustic noise, but this is normal and expected. For example, optimal operation is best achieved for 460V AC motors when the input AC rms is also at 460V AC nominal, Automatic mode is selected, and the DC-bus voltage regulates at approximately 683V DC.

Refer to [Configure Regenerative Bus Supply Axis Properties](#) on [page 224](#) for more information.

AC Line Filter Selection

An AC line filter is required to meet CE requirements. Install an AC line filter for input power as close to the 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply as possible.

IMPORTANT AC line filters are only recommended with grounded WYE power configurations. For facility power configuration examples, see [Input Power Configurations for Kinetix 5700 Power Supplies](#) on [page 129](#).

Table 7 - AC Line Filter Selection

| DC-bus Power Supply Cat. No. | AC Line Filter ^{(1) (2) (3)} Cat. No. | Regenerative Bus Supply Cat. No. | AC Line Filter ^{(1) (2) (4)} Cat. No. |
|--|--|-------------------------------------|---|
| 2198-P031 | <ul style="list-style-type: none"> 2198-DBR20-F or 2198-DB20-F | 2198-RP088 | 2198-DBR40-F |
| 2198-P070 | <ul style="list-style-type: none"> 2198-DBR40-F or 2198-DB42-F | 2198-RP200 | 2198-DBR90-F |
| 2198-P141 2198-P208 | <ul style="list-style-type: none"> 2198-DBR90-F or 2198-DB80-F | 2198-RP263 2198-RP312 | 2198-DBR200-F |
| 2198-P208 (2 in parallel) 2198-P208 (3 in parallel) | <ul style="list-style-type: none"> 2198-DBR200-F or 2198-DB290-F | | |

- (1) The use of 2198-DBRxx-F line filters provide a maximum motor-power cable length of up to 1200 m (3937 ft). Maximum motor-power cable length with 2198-DBxx-F line filters is 400 m (1312 ft). Maximum motor-power cable length for 2198-P031 DC-bus power supplies when paired with 2198-DBxx-F or 2198-DBRxx-F line filters is with 400 m (1312 ft).
- (2) See [Chapter 5](#) beginning on [page 127](#), for more information on maximum cable lengths and how the use of 2198-DBRxx-F line filters affect ground screw/jumper settings. See Kinetix Servo Drive Specifications Technical Data, publication [KNX-TD003](#), for AC line filter specifications.
- (3) When using 2198-DBRxx-F line filters with DC-bus power supplies, remove all inverter ground jumpers to reduce overall system leakage current.
- (4) When using 2198-DBRxx-F line filters with regenerative bus supplies, remove all inverter ground jumpers to prevent permanent damage to the inverters.

IMPORTANT Use 2198-DBxx-F line filters only as field replacements in existing installations that use DC-bus power supplies and have inverter ground jumpers installed. Select 2198-DBRxx-F line filters for all new systems and remove inverter ground jumpers. 2198-DBRxx-F line filters can also be used to replace existing 2198-DBxx-F line filters, but you must remove the inverter ground jumpers.

AC Line Impedance Considerations

DC-bus power supplies do not require an isolation transformer for three-phase input power. Regenerative bus supplies also do not require an isolation transformer for three-phase input power unless they are connected to corner-grounded or ungrounded facility power. See [Input Power Configurations for Kinetix 5700 Power Supplies](#) on [page 129](#) for example configurations.

IMPORTANT These recommendations are advisory and do not address all situations. Site-specific conditions must be considered for proper installation.

A transformer can be required to match the voltage requirements of the power supply to the available service. For the AC input voltage requirements, refer to the Kinetix 5700 power specifications in the Kinetix Servo Drives Technical Data, publication [KNX-TD003](#).

IMPORTANT When using an autotransformer, make sure that the phase to neutral/ground voltage does not exceed the input voltage ratings of the power supply.

Use a safety factor of 1.5 for three-phase power (where safety factor is used to compensate for transformer, drive modules, motor losses, and to account for utilization in the intermittent operating area of the torque speed curve).

EXAMPLE Sizing a transformer to the voltage requirements of this power supply:
2198-P141: $31\text{kW} \times 1.5 = 46.5\text{ kVA}$ transformer.

In the following use cases, an additional transformer or line reactor is required due to faults or potential damage associated with AC line disturbances:

- Installation site has switched power-factor correction capacitors.
- Installation site has lightning strikes or voltage spikes in excess of 6000V peak.
- Installation site has power interruptions or voltage dips in excess of 200V AC.
- The transformer kVA is more than 10 times larger than the drive kVA, or the percent source impedance relative to each converter is less than 0.5%.

In the following use cases, a line reactor is required due to faults associated with sharing AC line-input on multiple converters:

- Repetitive AC input line-voltage notching is present. For example, if silicon controlled rectifier drive is connected to the same AC input-power source.
 - In drive systems that include the regenerative bus supply, repetitive AC line voltage notching can cause the integrated AC line filter to overheat and result in FLT S18 converter overtemperature fault.

- Powering multiple (two or more) regenerative bus supplies from the same AC input-power source.
 - Switching ripple from each regenerative bus supply can interfere with other regenerative bus supplies on the same AC input power source.
- Powering 2198-Pxxx DC-bus power supply and 2198-RPxxx regenerative bus supply from the same AC input-power source.
 - Switching ripple from the regenerative bus supply can impact the temperature of DC-bus capacitors in the DC-bus power supply. In this use case, a line reactor is required in the AC input-power string leading to the regenerative bus supply.
 - Line reactor in the AC input-power string is not required for the DC-bus power supply in this use case, but is recommended for the prevention of issues caused by other use cases.
- Powering two or three 2198-P208 DC-bus power supplies from the same AC input-power source that share the same DC-bus.
 - In this use case, a line reactor is required for each 2198-P208 DC-bus power supply to make sure that they share current more evenly.

Use these equations to calculate the impedance of the DC-bus power supply, regenerative bus supply, or transformer to check the percent source-impedance relative to the power supply to make sure it is not less than 0.5%. An additional transformer or line reactor is required in this use case.

DC-bus Power Supply or Regenerative Bus Supply Impedance (in ohms)

$$Z_{\text{drive}} = \frac{V_{\text{line-line}}}{\sqrt{3} \cdot I_{\text{input-rating}}}$$

Transformer Impedance (in ohms)

$$Z_{\text{xfrmr}} = \frac{V_{\text{line-line}}}{\sqrt{3} \cdot I_{\text{xfrmr-rated}}} \cdot \% \text{ Impedance}$$

Or

$$Z_{\text{xfrmr}} = \frac{(V_{\text{line-line}})^2}{\text{VA}} \cdot \% \text{ Impedance}$$

% impedance is the nameplate impedance of the transformer.

Transformer Impedance (in ohms)

$$Z_{\text{xfrmr}} = \frac{V_{\text{line-line}}}{\sqrt{3} \cdot I_{\text{xfrmr-rated}}} \cdot \% \text{ Impedance}$$

% impedance is the nameplate impedance of the transformer.

EXAMPLE The DC-bus power supply or regenerative bus supply is rated 1 Hp, 480V, 2.7 A input.

The supply transformer is rated 50,000 VA (50 kVA), 5% impedance.

$$Z_{\text{drive}} = \frac{V_{\text{line-line}}}{\sqrt{3} \cdot I_{\text{input-rating}}} = \frac{480\text{V}}{\sqrt{3} \cdot 2.7} = 102.6 \text{ Ohms}$$

$$Z_{\text{xfmr}} = \frac{(V_{\text{line-line}})^2}{\text{VA}} \cdot \% \text{ Impedance} = \frac{480^2}{50,000} \cdot 0.05 = 0.2304 \text{ Ohms}$$

The percent (%) impedance has to be in per unit (5% becomes 0.05) for the formula.

$$\frac{Z_{\text{xfmr}}}{Z_{\text{drive}}} = \frac{0.2304}{102.6} = 0.00224 = 0.22\%$$

0.22% is less than 0.5%. Therefore, this transformer is too large for the DC-bus power supply or regenerative bus supply. Consider adding either a line reactor or isolation transformer.

Table 8 - Bulletin 1321 Line Reactor Selection

| Kinetix 5700 Power Supply | Power Supply Cat. No. | Number of Power Supplies in a Bus Group | Bulletin 1321 Line Reactor Cat. No. | Status |
|---------------------------|-----------------------|---|-------------------------------------|-------------|
| DC-bus Power Supply | 2198-P031 | 1 | 1321-3R12-B | Recommended |
| | 2198-P070 | 1 | 1321-3R35-B | Recommended |
| | 2198-P141 | 1 | 1321-3R55-B | Recommended |
| | 2198-P208 | 1 | 1321-3R80-B | Recommended |
| | | 2 | | Required |
| | | 3 | | Required |
| Regenerative Bus Supply | 2198-RP088 | 1 | 1321-3R35-A | Recommended |
| | 2198-RP200 | 1 | 1321-3R100-A | Recommended |
| | 2198-RP263 | 1 | 1321-3R160-B | Recommended |
| | 2198-RP312 | 1 | 1321-3R200-A | Recommended |

See [Power Wiring Examples](#) on [page 343](#) for AC input-power interconnect diagrams. For Bulletin 1321 line reactor specifications, see the 1321 Power Conditioning Products Technical Data, publication [1321-TD001](#).

IMPORTANT You can group multiple 2198-Pxxx DC-bus power supplies on one line reactor if they do not share same DC bus. However, the line reactor percent impedance must be large enough when evaluated for each DC-bus power supply separately, not evaluated for all loads connected at once.

Circuit Breaker/Fuse Selection

The Kinetix 5700 power supplies use internal solid-state motor short-circuit protection and, when protected by suitable branch circuit protection, are rated for use on a circuit capable of delivering up to 200,000 A (fuses) and 65,000 A (circuit breakers).

Refer to [Power Wiring Examples](#), on [page 343](#), for the wiring diagram.



ATTENTION: Do not use circuit protection devices on the output of an AC drive as an isolating disconnect switch or motor overload device. These devices are designed to operate on sine wave voltage and the drive's PWM waveform does not allow it to operate properly. As a result, damage to the device occurs.

Table 9 - DC-bus Power Supply UL/CSA Circuit-protection Specifications

| DC-bus Power Supply Cat. No. | Input Voltage (three-phase) nom | Bussmann Fuses ⁽¹⁾ Cat. No. | Miniature CB ⁽²⁾ Cat. No. | Motor Protection CB, ⁽²⁾ Self Protected CMC Cat. No. | Molded Case CB Cat. No. |
|------------------------------|---------------------------------|--|--------------------------------------|---|-------------------------|
| 2198-P031 | 324...528V AC | LPJ-15SP (15A) | 1489-M3D250 | 140M-D8E-C25 | 140G-G6C3-C25 |
| 2198-P070 | | LPJ-40SP (40A) | N/A | 140M-F8E-C45 | 140G-G6C3-C50 |
| 2198-P141 | | LPJ-70SP (70A) | N/A | N/A | 140G-G6C3-C90 |
| 2198-P208 | | LPJ-100SP (100A) | N/A | N/A | 140G-G6C3-D12 |

- (1) For applications requiring CSA certification, fuses (Bussmann catalog number 170M1760) must be added to the DC link between the two drive clusters when circuit breakers are used for branch circuit protection. The DC bus fuses are not required when AC line fuses are used for branch circuit protection.
- (2) These Bulletin 140M circuit breakers, when used as self-protected (Type E) devices, and Bulletin 1489 circuit breakers can be used on only WYE power systems (480Y/277V).

Table 10 - Regenerative Bus Supply UL/CSA Circuit-protection Specifications

| Regenerative Bus Supply Cat. No. | Input Voltage ⁽¹⁾ (three-phase) nom | Bussmann Fuses ⁽²⁾ Cat. No. | Mersen Fuses Cat. No. | Miniature CB Cat. No. | Molded Case CB Cat. No. |
|----------------------------------|--|--|-----------------------|-----------------------|-------------------------|
| 2198-RP088 | 324...506V AC rms | LPJ-45SP (45A) | AJT45 (45A) | — | 140G-G6C3-C60 |
| 2198-RP200 | | LPJ-125SP (125A) | AJT125 (125A) | — | 140G-J6F3-D15 |
| 2198-RP263 | | LPJ-200SP (200A) | AJT200 (200A) | — | 140G-K6F3-D30 |
| 2198-RP312 | | LPJ-250SP (250A) | AJT250 (250A) | — | 140G-K6F3-D40 |

- (1) Applies when DC-bus voltage regulation is enabled. If DC-bus voltage regulation is not enabled, then the input voltage range is 324...528V AC. For more information on these two modes of operation, see [DC-bus Voltage Regulation](#) on [page 42](#).
- (2) For applications requiring CSA certification, fuses (Bussmann catalog number 170M1760) must be added to the DC link between the two drive clusters when circuit breakers are used for branch circuit protection. The DC bus fuses are not required when AC line fuses are used for branch circuit protection.

Table 11 - DC-bus Power Supply IEC (non-UL/CSA) Circuit-protection Specifications

| DC-bus Power Supply Cat. No. | Drive Voltage (three-phase) nom | DIN gG Fuses Amps, max | Miniature CB Cat. No. | | Motor Protection CB Cat. No. | Molded Case CB Cat. No. |
|------------------------------|---------------------------------|------------------------|-----------------------|---------------|------------------------------|-------------------------|
| 2198-P031 | 324...528V AC | 16 | 1489-M3D250 | N/A | 140M-D8E-C25 | 140G-G6C3-C25 |
| 2198-P070 | | 40 | N/A | 1492-SPM3D400 | 140M-F8E-C45 | 140G-G6C3-C50 |
| 2198-P141 | | 75 | N/A | 1492-SPM3D630 | 140MG-H8E-C60 | 140G-G6C3-C90 |
| 2198-P208 | | 110 | N/A | N/A | 140MG-H8E-D10 | 140G-G6C3-D12 |

Table 12 - Regenerative Bus Supply IEC (non-UL/CSA) Circuit-protection Specifications

| Regenerative Bus Supply Cat. No. | Input Voltage ⁽¹⁾ (three-phase) nom | DIN gG Fuses Amps, max | Miniature CB Cat. No. | | Motor Protection CB Cat. No. | Molded Case CB Cat. No. |
|----------------------------------|--|------------------------|-----------------------|---------------|------------------------------|-------------------------|
| 2198-RP088 | 324...506V AC rms | 50 | 1489-M3C600 | 1492-SPM3C630 | 140MG-H8E-C60 | 140G-G6C3-C60 |
| 2198-RP200 | | 125 | — | — | 140MG-J8E-D15 | 140G-J6F3-D15 |
| 2198-RP263 | | 200 | — | — | — | 140G-K6F3-D30 |
| 2198-RP312 | | 250 | — | — | — | 140G-K6F3-D40 |

(1) Applies when DC-bus voltage regulation is enabled. If DC-bus voltage regulation is not enabled, then the input voltage range is 324...528V AC. For more information on these two modes of operation, see [DC-bus Voltage Regulation](#) on [page 42](#).

Refer to the Kinetix Servo Drives Technical Data, publication [KNX-TD003](#), for additional power specifications for your 2198-Pxxx DC-bus power supply and 2198-RPxxx regenerative bus supply.

24V Control Power Evaluation

The Kinetix 5700 drive system requires 24V DC input for its control circuitry. Due to the 24V shared-bus connection system and the 24V current requirements of the Kinetix 5700 drives, a thorough evaluation of control power is required prior to implementation. Consider the following when sizing such a system:

- Verify that the 24V DC power supply is capable of supplying the 24V current requirements of your Kinetix 5700 drive system. See [Calculate 24V DC Control Power Current Demand](#) on [page 396](#) to determine the 24V current requirements. For systems with a high 24V current demand, consider the following:
 - Install separate 24V power supplies for each cluster or change the cluster configuration to more evenly divide the 24V current demand.
 - Install separate 24V power supplies for each Bulletin 2198 power supply and inverter.
- Verify that the wiring being used is capable of supplying the Kinetix 5700 drive system with a voltage within the 24V input-voltage range; 24V \pm 10% (21.6...26.4V DC). Consider the following:
 - Mount the 24V power supply as close to the Kinetix 5700 drive system as possible to minimize input voltage drop.
 - Install larger gauge wire, up to 4 mm² (12 AWG) and 6 mm² (10 AWG) for 24V control power when using the CP connectors included with the module; or use the 24V shared-bus connection system to lower the DC wire resistance with up to 10 mm² (6 AWG) and result in a lower voltage drop.

IMPORTANT The 24V current demand, wire gauge, and wire length all impact the voltage drop across the wiring being used. For an example, see [24V DC Voltage Drop Calculation Example](#) on [page 397](#).

Contactor Selection

The AC three-phase contactor control string must be wired in series with the contactor-enable relay at the CED connector. The contactor-enable relay (applies to 2198-Pxxx DC-bus power supply and 2198-RPxxx regenerative bus supply) is rated at 24V DC (28V, max) and 1.0 A, max.

IMPORTANT Applying more than 28V DC control voltage or more than 1.0 A control current to the contactor can cause permanent damage to the DC-bus power supply or regenerative bus supply.



ATTENTION: Wiring the contactor-enable relay is required. To avoid personal injury or damage to the system, wire the contactor-enable relay into your control string so that:

- three-phase power is removed and the power supply is protected under various fault conditions.
- three-phase power is never applied to the Kinetix 5700 drive system before control power is applied.

Contactor with auxiliary contacts is strongly recommended when used with 2198-RPxxx regenerative bus supply. Wire auxiliary contact to digital input #2 (default setting) to monitor the three-phase input power. See [Contactor Wiring Examples](#) on [page 358](#) for wiring examples.

Table 13 - DC-bus Power Supply Contactor Specifications

| DC-bus Power Supply Cat. No. | Contactor ^{(1) (2)} Cat. No. | Intermediate Relay ⁽³⁾ Cat. No. |
|---------------------------------|--|---|
| 2198-P031 | 100-C16EJ10 | N/A |
| 2198-P070 | 100-C37EJ10 | |
| 2198-P141 | 100-C72DJ10 | 700-HB32Z24 (relay) 700-HN153 (socket) |
| 2198-P208 | 100-C97DJ10 | |
| 2198-P208 (2 in parallel) | 100-E190KJ11 | |
| 2198-P208 (3 in parallel) | 100-E305KJ11 | |

(1) Auxiliary contact configuration 10 indicates there is 1 N.O. and 0 N.C. contacts. Other configurations are available.

(2) For contactors that are not Bulletin 100-E type, the integrated diode is required with the contactor coil. See Knowledgebase document [19362](#) for more information.

(3) These DC-bus power supplies require an additional intermediate relay used with the contactor.

Table 14 - Regenerative Bus Supply Contactor Specifications

| Regenerative Bus Supply Cat. No. | Contactor ^{(1) (2)} Cat. No. | Intermediate Relay Cat. No. |
|-------------------------------------|--|--------------------------------|
| 2198-RP088 | 100-C43EJ10 | N/A |
| 2198-RP200 | 100-E116KJ11 | |
| 2198-RP263 | 100-E205KJ11 | |
| 2198-RP312 | 100-E265KJ11 | |

(1) Auxiliary contact configuration 10 indicates there is 1 N.O. and 0 N.C. contacts. 11 indicates there is 1 N.O. and 1 N.C. contact. Other configurations are available.

(2) These contactor catalog numbers include a 24V DC coil. For contactors that are not Bulletin 100-E type, see Knowledgebase document [19362](#) for more information.

Passive Shunt Considerations

The 2198-Pxxx DC-bus power supplies all include an internal shunt that is wired to the shunt resistor (RC) connector at the factory. Bulletin 2198-Rxxx external passive shunts are available to provide additional shunt capacity for applications where the internal shunt capacity is exceeded.

IMPORTANT Keep the DC-bus power supply internal shunt wires connected unless you have an external passive shunt to connect.

IMPORTANT 2198-RPxxx regenerative bus supplies do not support passive shunts. The active shunt (RC) connector is used for making active shunt connections.

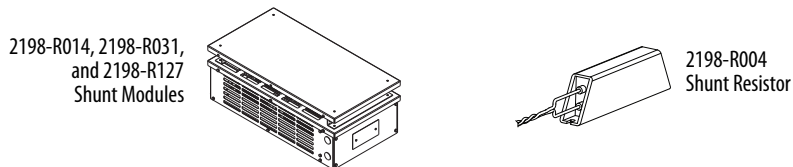
Table 15 - DC-bus Power Supply Passive-shunt Options

| DC-bus Power Supply Cat. No. | Internal Shunt Specifications | | External Shunt Module Compatibility ⁽¹⁾ Cat. No. | | | |
|---------------------------------|-------------------------------|-----|--|-----------|-----------|-----------|
| | Ω | W | 2198-R127 | 2198-R031 | 2198-R014 | 2198-R004 |
| 2198-P031 | 37.5 | 75 | — | — | X | X |
| 2198-P070 | | | — | — | X | X |
| 2198-P141 | 13.5 | 200 | X | X | X | X |
| 2198-P208 | | | X | X | X | X |

(1) Shunt resistor selection is based on the needs of your actual hardware configuration.

Catalog numbers 2198-R014, 2198-R031, and 2198-R127 are composed of resistor coils that are housed inside an enclosure. Catalog number 2198-R004 is a shunt resistor without an enclosure.

Figure 19 - External Passive Shunts



External Shunt Module Specifications

| Shunt Module Cat. No. | Resistance Ω | Continuous Power W | Weight, approx kg (lb) |
|--------------------------|------------------------|-----------------------|---------------------------|
| 2198-R004 | 33 | 400 | 1.8 (4.0) |
| 2198-R014 | 9.4 | 1400 | 9.1 (20) |
| 2198-R031 | 33 | 3100 | 16.8 (37) |
| 2198-R127 ⁽¹⁾ | 13 | 12,700 | 22.2 (49) |

(1) This product presents a lift hazard. To avoid personal injury, use care when lifting the product.

How the Bulletin 2198-Rxxx shunts connect to the 2198-Pxxx DC-bus power supply is explained in [External Passive-shunt Connections](#) on [page 182](#) and illustrated with interconnect diagrams in [Passive Shunt Wiring Examples](#) on [page 359](#).

Active Shunt Considerations

External active shunts are required in the following use cases:

- The 2198-RPxxx regenerative bus supply provides DC-bus power while DC-bus regulation is not enabled.
- One permanent magnet motor runs above its bus overvoltage speed. See [Field Weakening Mode](#) on [page 452](#) for a description of this feature.
- One permanent magnet motor drives a vertical load that could make the motor accelerate above the bus overvoltage speed during a fault condition.
- Any condition where total shared DC-bus regenerative power is greater than the 2198-RPxxx regenerative bus supply capacity. For example, consider a peak-power stopping condition.
- The 2198-RPxxx regenerative bus supply is operating with DC-bus regulation enabled and the regenerative bus supply loses three-phase AC input power, 24V DC input power, or has a fault condition.



ATTENTION: To avoid damage to the Kinetix 5700 drive system, wire the active shunt thermal switch to a digital input on the power supply and configure the Shunt Thermal Switch OK function in the Logix Designer application.



ATTENTION: DC-bus failure can cause damage to all drive modules in the bus group, not just the inverter connected to the motor.

Active shunts are available from the Rockwell Automation Encompass™ partner Powerohm Resistors, Inc. See <http://www.powerohm.com> for more information on Powerohm active shunts.

IMPORTANT Powerohm Bulletin PKBxxx active shunt modules use built-in internal brake resistors. Bulletin PWBxxx active shunt modules require appropriately sized external brake resistors.

Table 16 - Compatible Active Shunt Specifications (internal brake resistor)

| Kinetix 5700 Power Supply | Powerohm Resistors Cat. No. ⁽¹⁾ | Input Voltage, nom | Turn-on Bus Voltage | Continuous Power kW | Resistance (internal) Ω | Resistance (minimum) Ω | Continuous Current Amps | Peak Current Amps |
|--|--|--------------------|---------------------|---------------------|-------------------------|------------------------|-------------------------|-------------------|
| 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply when DC-bus regulation is not enabled. | PKB005 | 480V AC | 750V DC | 1.50 | 108 | — | 2.00 | 6.9 |
| | PKB010 | | | 2.06 | 52.7 | — | 2.75 | 14.2 |
| | PKB050 | | | 7.00 | 10.5 | — | 9.30 | 71.4 |
| 2198-RPxxx regenerative bus supply when DC-bus regulation is enabled. | PKB005-800 | | 800V DC | 1.50 | 108 | — | 1.88 | 7.4 |
| | PKB010-800 | | | 2.06 | 52.7 | — | 2.58 | 15.2 |
| | PKB050-800 | | | 7.00 | 10.5 | — | 8.72 | 76.2 |

(1) How the Powerohm PKBxxx shunts connect to the 2198-Pxxx DC-bus power supply and 2198-RPxxx regenerative bus supply is explained in [External Active-shunt Connections](#) on [page 183](#) and illustrated with interconnect diagrams in [Active Shunt Wiring Examples](#) on [page 360](#).

Table 17 - Compatible Active Shunt Specifications (no internal brake resistor)

| Kinetix 5700 Power Supply | Powerohm Resistors Cat. No. ⁽¹⁾ | Input Voltage, nom | Turn -on Bus Voltage | Continuous Power kW | Resistance (internal) Ω | Resistance (minimum) Ω | Continuous Current Amps | Peak Current Amps |
|--|--|--------------------|----------------------|---------------------|-------------------------|------------------------|-------------------------|-------------------|
| 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply when DC-bus regulation is not enabled. | PWB035 | 480V AC | 750V DC | 26.25 | — | 7.5 | 35 | 100 |
| | PWB110 | | | 82.5 | — | 2.5 | 110 | 300 |
| 2198-RPxxx regenerative bus supply when DC-bus regulation is enabled. | PWB035-800 | | 800V DC | 26.25 | — | 8.0 | 35 | 100 |
| | PWB110-800 | | | 82.5 | — | 2.7 | 110 | 300 |

(1) How the Powerohm PWBxxx shunts connect to the 2198-Pxxx DC-bus power supply and 2198-RPxxx regenerative bus supply is explained in [External Active-shunt Connections](#) on [page 183](#) and illustrated with interconnect diagrams in [Active Shunt Wiring Examples](#) on [page 360](#).



ATTENTION: Do not use Powerohm active-shunt modules at input line voltages that exceed 528V AC. Active-shunt thermal-overload shutdown can occur if input line voltage exceeds 528V AC.

See [External Active-shunt Connections](#) on [page 183](#), when making active shunt connections.

Enclosure Selection

This example is provided to assist you in sizing an enclosure for your Kinetix 5700 drive system. You need heat dissipation data from all components planned for your enclosure to calculate the enclosure size (refer to [Table 18](#)).

With no active method of heat dissipation (such as fans or air conditioning) either of the following approximate equations can be used.

| Metric | Standard English |
|---|--|
| $A = \frac{0.38Q}{1.8T - 1.1}$ | $A = \frac{4.08Q}{T - 1.1}$ |
| Where T is temperature difference between inside air and outside ambient (°C), Q is heat generated in enclosure (Watts), and A is enclosure surface area (m ²). The exterior surface of all six sides of an enclosure is calculated as: | Where T is temperature difference between inside air and outside ambient (°F), Q is heat generated in enclosure (Watts), and A is enclosure surface area (ft ²). The exterior surface of all six sides of an enclosure is calculated as: |
| $A = 2dw + 2dh + 2wh$ | $A = (2dw + 2dh + 2wh) / 144$ |
| Where d (depth), w (width), and h (height) are in meters. | Where d (depth), w (width), and h (height) are in inches. |

If the maximum ambient rating of the Kinetix 5700 drive system is 50 °C (122 °F) and if the maximum environmental temperature is 20 °C (68 °F), then T=30. In this example, the total heat dissipation is 416 W (sum of all components in enclosure). So, in the equation below, T=30 and Q=416.

$$A = \frac{0.38 (416)}{1.8 (30) - 1.1} = 2.99 \text{ m}^2$$

In this example, the enclosure must have an exterior surface of at least 2.99 m². If any portion of the enclosure is not able to transfer heat, do not include that value in the calculation.

Because the minimum cabinet depth to house the Kinetix 5700 system (selected for this example) is 300 mm (11.8 in.), the cabinet needs to be approximately 1500 x 700 x 300 mm (59.0 x 27.6 x 11.8 in.) HxWxD.

$$1.5 \times (0.300 \times 0.70) + 1.5 \times (0.300 \times 2.0) + 1.5 \times (0.70 \times 2.0) = 3.31 \text{ m}^2$$

Because this cabinet size is considerably larger than what is necessary to house the system components, it can be more efficient to provide a means of cooling in a smaller cabinet. Contact your cabinet manufacturer for options available to cool your cabinet.

Table 18 - Power Dissipation Specifications

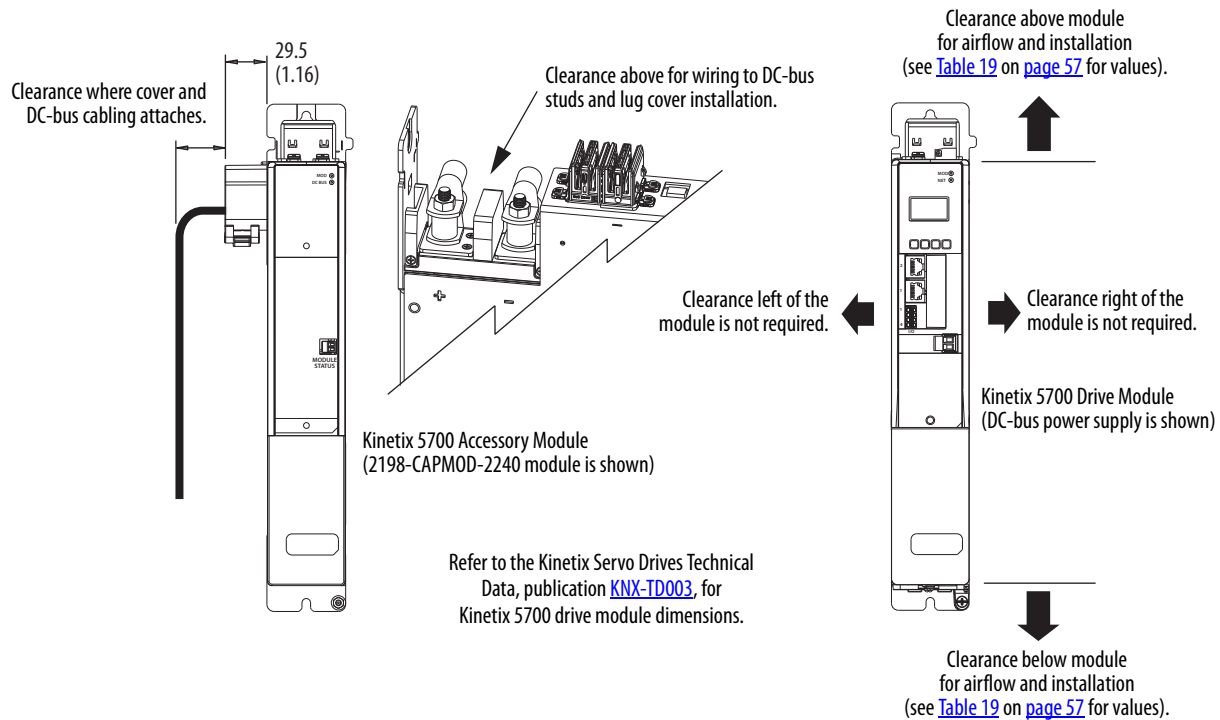
| DC-bus Power Supply Cat. No. | Usage as % of Rated Power Output (watts) | | | | |
|---|---|------|------|------|------|
| | 20% | 40% | 60% | 80% | 100% |
| 2198-P031 | 97 | 101 | 105 | 109 | 113 |
| 2198-P070 | 108 | 119 | 130 | 140 | 151 |
| 2198-P141 | 249 | 267 | 286 | 304 | 323 |
| 2198-P208 | 265 | 294 | 323 | 352 | 380 |
| Regenerative Bus Supply Cat. No. | | | | | |
| 2198-RP088 | 253 | 399 | 544 | 690 | 835 |
| 2198-RP200 | 532 | 832 | 1132 | 1432 | 1732 |
| 2198-RP263 | 850 | 1261 | 1672 | 2083 | 2494 |
| 2198-RP312 | 1037 | 1576 | 2115 | 2654 | 3193 |
| Dual-axis Inverter Cat. No. | | | | | |
| 2198-D006-ERSx | 17 | 29 | 41 | 53 | 65 |
| 2198-D012-ERSx | 34 | 58 | 82 | 106 | 130 |
| 2198-D020-ERSx | 52 | 84 | 116 | 148 | 180 |
| 2198-D032-ERSx | 100 | 155 | 210 | 265 | 320 |
| 2198-D057-ERSx | 252 | 354 | 456 | 558 | 660 |
| Single-axis Inverter Cat. No. | | | | | |
| 2198-S086-ERSx | 190 | 255 | 325 | 400 | 475 |
| 2198-S130-ERSx | 225 | 340 | 460 | 590 | 725 |
| 2198-S160-ERSx | 270 | 420 | 570 | 760 | 950 |
| 2198-S263-ERSx | 556 | 759 | 989 | 1245 | 1529 |
| 2198-S312-ERSx | 610 | 883 | 1200 | 1561 | 1965 |
| iTRAK Power Supply Cat. No. | | | | | |
| 2198T-W25K-ER | 206 | 272 | 338 | 404 | 470 |
| Capacitor Module Cat. No. | | | | | |
| 2198-CAPMOD-2240 | 28 | 34 | 42 | 51 | 62 |
| 2198-CAPMOD-DCBUS-IO | 1.1 | 1.4 | 1.6 | 2.1 | 2.5 |
| DC-bus Conditioner Module Cat. No. | | | | | |
| 2198-DCBUSCOND-RP312 | 1.4 | 2.1 | 3.2 | 4.7 | 6.7 |

Minimum Clearance Requirements

This section provides information to assist you in sizing your cabinet and positioning your Kinetix 5700 drive system:

- Additional clearance is required for cables and wires or the shared-bus connection system connected to the top of the drive modules.
 - Accessory modules require extra clearance above for wiring DC-bus stud connections and installing the cover.
- Additional clearance is required if other devices are installed above and/or below the drive module and have clearance requirements of their own.
 - Accessory modules require extra clearance to route DC-bus wiring into or away from the drive system.
- Additional clearance left and right of the drive module is required when mounted adjacent to noise sensitive equipment or clean wire ways.
- The recommended minimum cabinet depth is 300 mm (11.81 in.).

Figure 20 - Minimum Clearance Requirements



IMPORTANT Mount the drive module in an upright position as shown. Do not mount the module on its side.

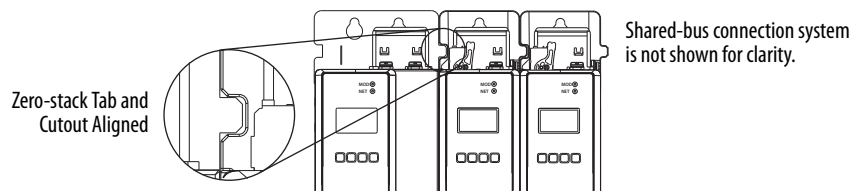
See the [Kinetix 5700 Drive Module Clearance Specifications](#) table on [page 57](#) for clearance specifications.

Table 19 - Kinetix 5700 Drive Module Clearance Specifications

| Kinetix 5700 Drive Modules | Drive Module Cat. No. | Clearance Above, min mm (in.) | Clearance Below, ⁽¹⁾ min mm (in.) |
|----------------------------|--|-------------------------------------|--|
| DC-bus power supply | 2198-P031 2198-P070 2198-P141 2198-P208 | 40 (1.57) | 100 (3.94) |
| Regenerative bus supply | 2198-RP088 2198-RP200 | 40 (1.57) | 100 (3.94) 150 (5.91) |
| | 2198-RP263 2198-RP312 | 80 (3.15) | 200 (7.87) |
| Single-axis inverters | 2198-S086-ERSx 2198-S130-ERSx 2198-S160-ERSx | 40 (1.57) | 185 (7.28) |
| | 2198-S263-ERSx 2198-S312-ERSx | 80 (3.15) | 200 (7.87) |
| Dual-axis inverters | 2198-D006-ERSx 2198-D012-ERSx 2198-D020-ERSx 2198-D032-ERSx 2198-D057-ERSx | 40 (1.57) | 100 (3.94) |
| iTRAK power supply | 2198T-W25K-ER | 40 (1.57) | 100 (3.94) |
| Capacitor module | 2198-CAPMOD-2240 | 115 (4.53) | 100 (3.94) |
| Extension module | 2198-CAPMOD-DCBUS-IO | | |
| DC-bus conditioner module | 2198-DCBUSCOND-RP312 | | |

(1) Additional clearance can be required depending on the actual wiring harness being installed.

In multi-axis shared-bus configurations, drive modules must be spaced by aligning the zero-stack tab and cutout.

Figure 21 - Multi-axis Shared-bus Clearance Requirements

Multi-axis Shared DC-Bus Configurations

The Kinetix 5700 shared DC-bus system can be supplied by the following sources:

- Single 2198-Pxxx DC-bus power supply
- Multiple 2198-P208 DC-bus power supplies (up to three are possible)
- Single 2198-RPxxx regenerative bus supply
- Multiple 8720MC-RPS regenerative power supplies

Table 20 - Shared DC-bus Terminology

| Term | Definition |
|----------------------|--|
| DC-bus group | Drive modules that are all connected to the same DC bus. |
| Cluster | Group of power supply and/or drive modules that are directly connected together via Kinetix 5700 DC bus-bars only. |
| Extended cluster | Group of drive modules that are directly connected together via Kinetix 5700 DC bus-bars and connected to the power supply cluster via customer-supplied DC-bus cable. |
| Power supply cluster | The cluster that contains the AC to DC converter (power supply). |
| Extended DC-bus | When 2 drive clusters are part of the same DC-bus group joined by the DC bus-bars and customer-supplied DC-bus cable. |

The Kinetix 5700 DC-bus power is shared in the following ways:

- Across drive clusters by DC-bus links that are included with the drive module.
- From the power supply cluster to an extended cluster by connection points provided on accessory modules.

System Sizing Considerations

Multi-axis Kinetix 5700 shared-bus drive systems require thorough evaluation to make sure each drive will perform as expected. Consider the following when sizing your system to determine the appropriate configuration:

Consider the following to determine your system configuration:

- Determine motor/drive combinations for full-motor performance
- No more than three 2198-P208 DC-bus power supplies can be used to increase the converter power
- Define the DC-bus groups
- Calculate system and external-bus capacitance
- Calculate the total motor-power cable length
- Calculate the 24V DC control-power current demand
- If using the 24V DC shared-bus connection system to distribute control input power to a cluster of drive modules, current from the 24V power supply must not exceed 40 A
- Calculate the 24VDC voltage drops
- Minimize drive-to-motor cable lengths. Overall system design can significantly limit the drive-to-motor cable lengths. See Appendix D for more information.

See [Appendix C](#) beginning on [page 391](#) for more information and sizing examples.

Accessory Module Selection

The requirements for when to use accessory modules vary depending on whether your system is powered by the 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply.

8720MC-RPS regenerative power supplies follow the same requirements as 2198-RPxxx regenerative bus supplies for accessory modules needed for extended clusters. See 8720MC-RPS wiring examples beginning on [page 352](#).

Table 21 - Introduction to Kinetix 5700 Accessory Modules

| Accessory Module Cat. No. | Accessory Module | Description |
|---------------------------|---------------------------|---|
| 2198-CAPMOD-2240 | Capacitor Module | Use for energy storage and to extend the DC-bus voltage to another inverter cluster. Modules are zero-stacked with servo drives and use the shared-bus connection system to extend the external DC-bus voltage in applications up to 104 A. Can parallel with itself or with another accessory module for up to 208 A. |
| 2198-CAPMOD-DCBUS-IO | Extension Module | The extension module, paired with a capacitor module or DC-bus conditioner module, is used to extend the DC-bus voltage to another inverter cluster in systems with ≥ 104 A current and up to 208 A. |
| 2198-DCBUSCOND-RP312 | DC-bus Conditioner Module | Decreases the voltage stress on insulation components in an inverter system with long cable lengths and used to extend the DC-bus voltage to another inverter cluster. Modules are zero-stacked with servo drives and use the shared-bus connection system to extend the external DC-bus voltage in applications up to 104 A. Can parallel with itself or with another accessory module for applications up to 208 A. |

On the following pages (by power supply) are system configurations showing which accessory modules are required. The examples account for single (power supply) clusters, extended clusters, maximum system current, the input-power ground configuration, and total motor-cable length. Also included are flowcharts to help you determine your accessory module requirements.

DC-bus Power Supply Systems

The following system configurations illustrate the minimum number of accessory modules required.

Figure 22 - DC-bus Power Supply Example/Extended Cluster (104 A, max)

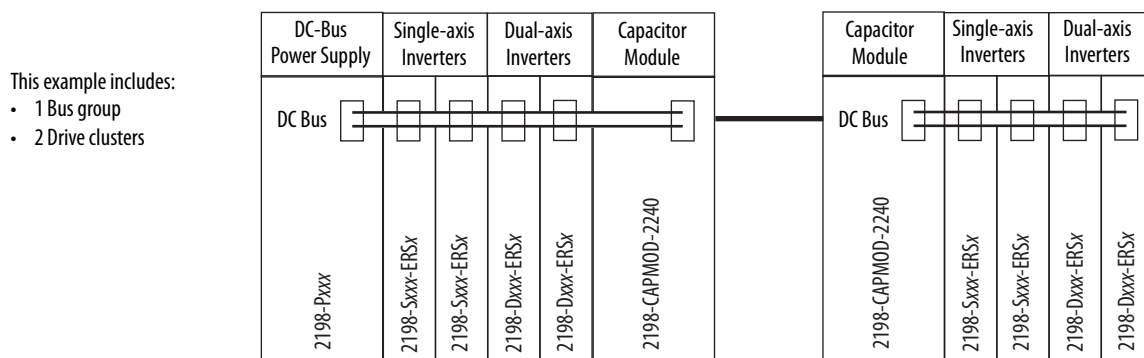
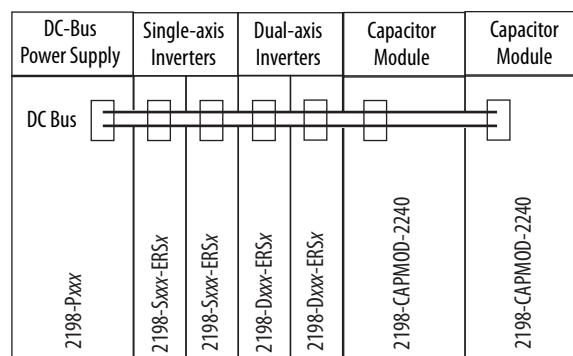


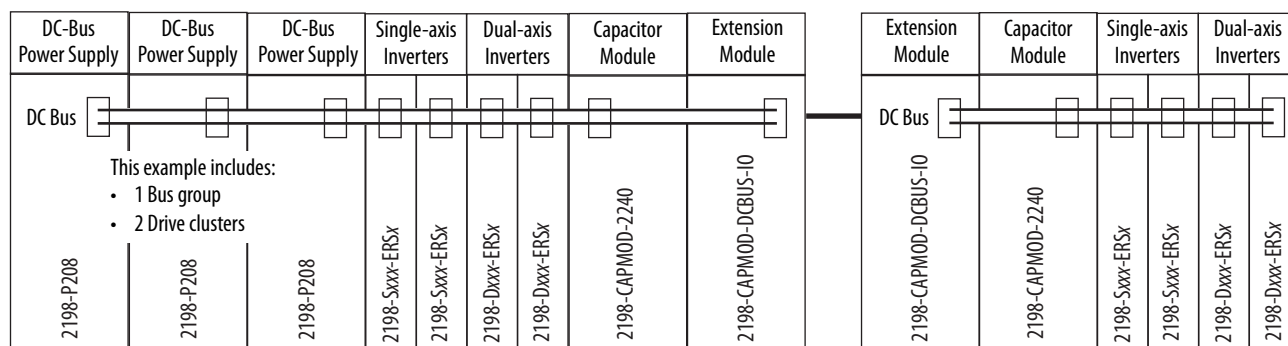
Figure 23 - DC-bus Power Supply Example/Multiple Capacitor Modules

This example includes:

- 1 Bus group
- 1 Drive cluster

**IMPORTANT**

In both of these examples, the Kinetix 5700 drive system includes two accessory modules per cluster. Flexible bus bars are included with only the 2198-CAPMOD-DCBUS-IO extension module. So, if you have two capacitor modules, two DC-bus conditioner modules, or a capacitor module and DC-bus conditioner module mounted side by side, you must order the 2198-KITCON-CAPMOD2240 or 2198-KITCON-DCBUSCOND connector set separately.

Figure 24 - Multiple DC-bus Power Supply Example/Extended Cluster (208 A, max)**IMPORTANT**

The systems that are shown are typical. The maximum number of inverter modules depends on the maximum system capacitance precharge capability of the power supply. With multiple 2198-P208 modules, there is more precharge capability. When there are two or three DC-bus power supplies, they must be catalog number 2198-P208.

Refer to [Appendix C](#) on [page 391](#) for more system sizing information.

Regenerative Bus Supply Systems

Mount the 2198-DCBUSCOND-RP312 DC-bus conditioner module on the far right or far left of any 2198-RPxxx regenerative bus supply system cluster, depending on the input power configuration.

- A DC-bus conditioner module is required on all extended clusters
- A DC-bus conditioner module is required on the power supply cluster if the total motor cable length connected to the power supply cluster is ≥ 400 m (1312 ft)
- A DC-bus conditioner module is required on each cluster of drive systems with impedance-grounded input power
- When a DC-bus conditioner module is installed and there is no use-case for installation, the module does not provide any benefit

The following system configurations illustrate the minimum number of accessory modules required.

Figure 25 - Regenerative Bus Supply Example/Single Cluster

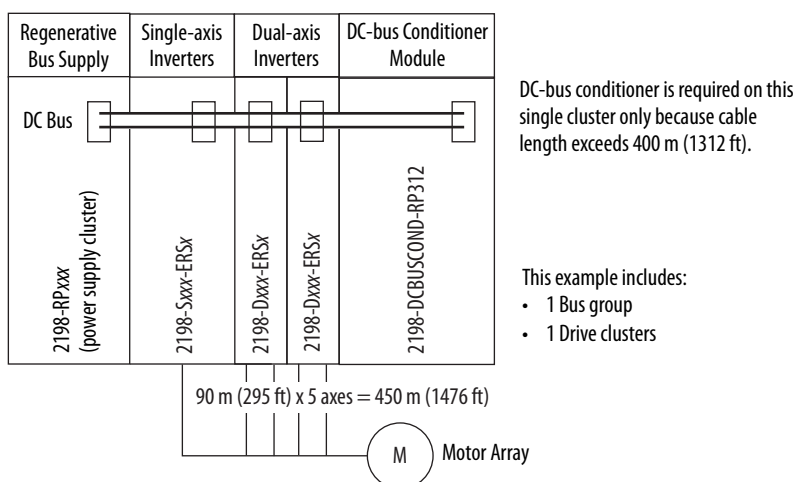


Figure 26 - Regenerative Bus Supply Example/Extended Cluster

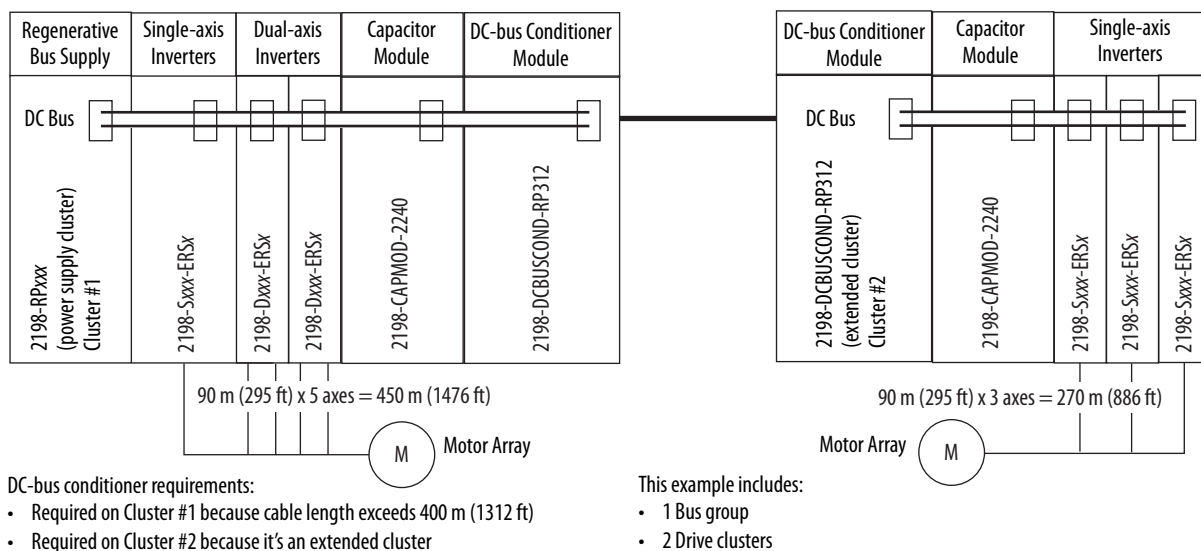
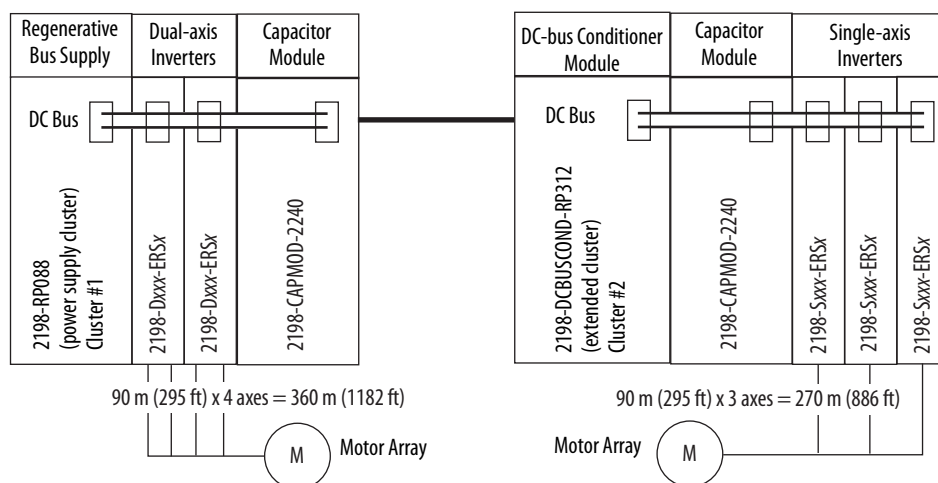


Figure 27 - Regenerative Bus Supply Example/Extended Cluster/104 A System



DC-bus conditioner requirements:

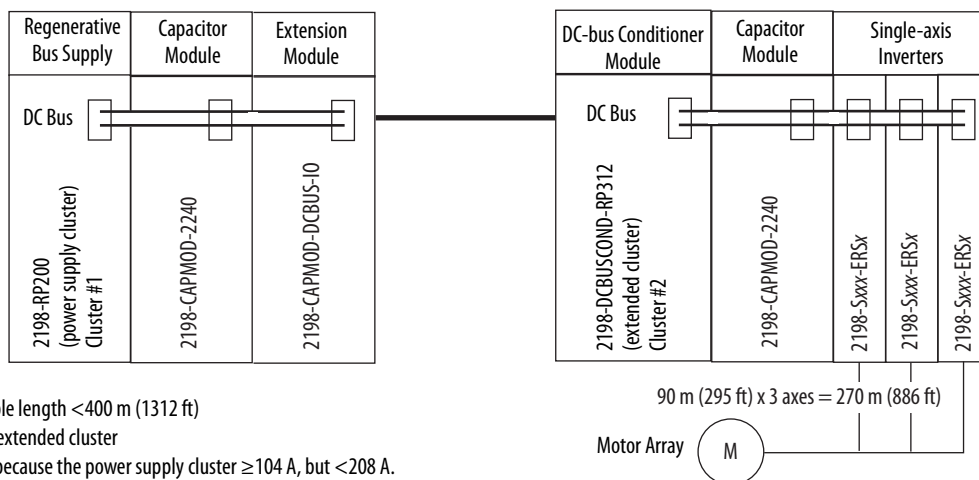
- Not required on Cluster #1 because cable length < 400 m (1312 ft)
- Required on Cluster #2 because it's an extended cluster

Extension module not required because the power supply cluster < 104 A

This example includes:

- 1 Bus group
- 2 Drive clusters

Figure 28 - Regenerative Bus Supply Example/Extended Cluster/208 A System



This example includes:

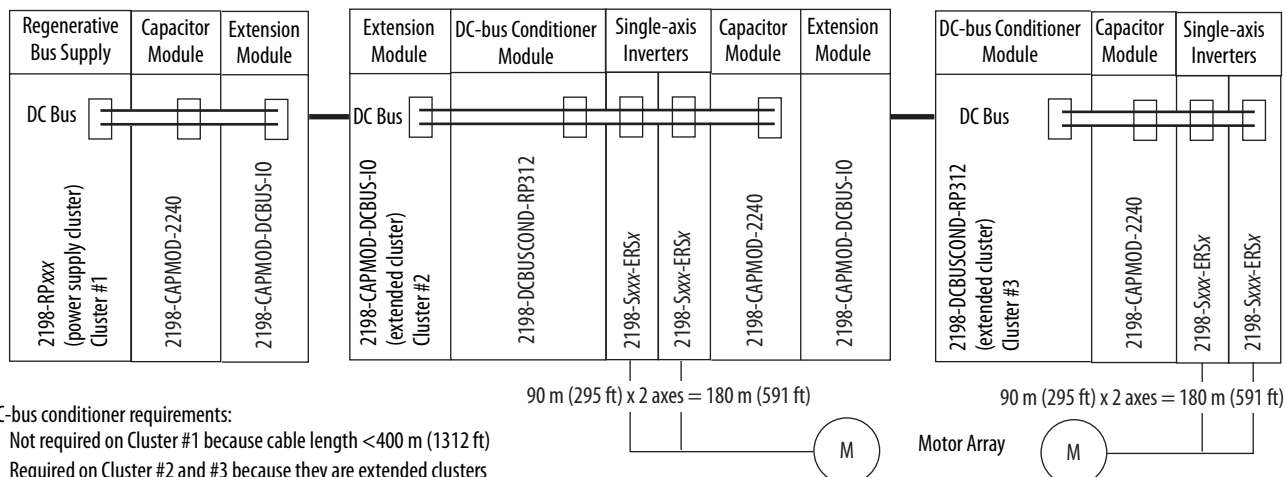
- 1 Bus group
- 2 Drive clusters

DC-bus conditioner requirements:

- Not required on Cluster #1 because cable length < 400 m (1312 ft)
- Required on Cluster #2 because it's an extended cluster

Extension module required on Cluster #1 because the power supply cluster ≥ 104 A, but < 208 A.

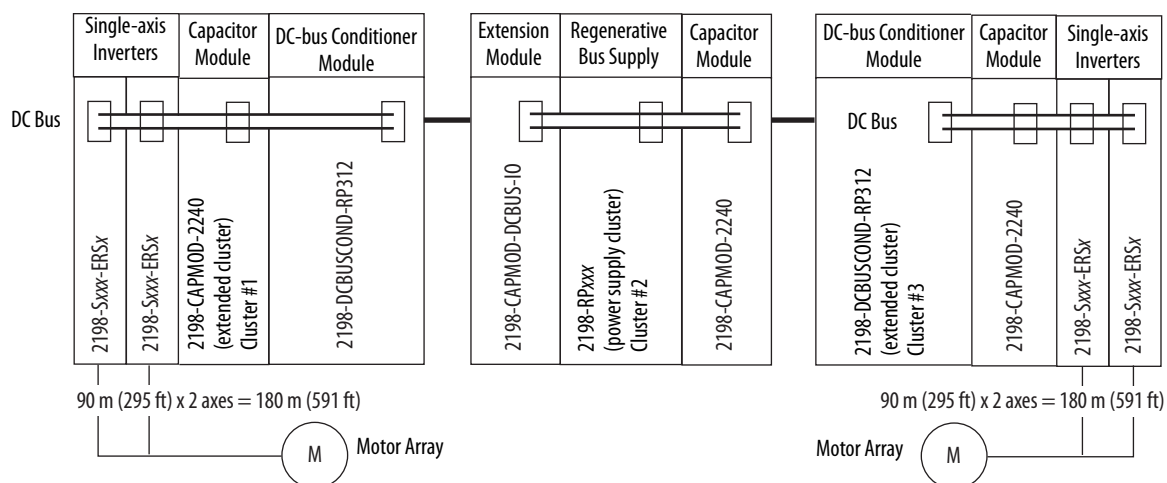
Figure 29 - Regenerative Bus Supply Example/Two Extended Clusters/208 A, max



DC-bus conditioner requirements:

- Not required on Cluster #1 because cable length < 400 m (1312 ft)
- Required on Cluster #2 and #3 because they are extended clusters

Extension module required on Cluster #1 and #2 because the entire extended bus system must have the same current rating (208 A, in this example).

Figure 30 - Regenerative Bus Supply Example/Center Power Supply Cluster/104 A, max

DC-bus conditioner requirements:

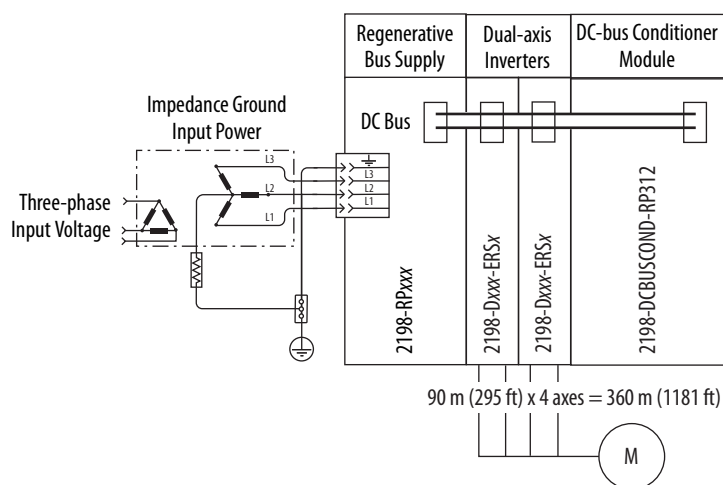
- Not required on Cluster #2 because cable length < 400 m (1312 ft)
- Required on Cluster #1 and #3 because they are extended clusters

Extension module required on Cluster #2 for making DC-bus connections to Cluster #1.

This example includes:

- 1 Bus group
- 3 Drive clusters

IMPORTANT In [Figure 30](#), the Kinetix 5700 drive system includes two accessory modules in each of the clusters. Flexible bus bars are included with only the 2198-CAPMOD-DCBUS-IO extension module. So, if you have two capacitor modules, two DC-bus conditioner modules, or a capacitor module and DC-bus conditioner module mounted side by side, you must order the 2198-KITCON-CAPMOD2240 or 2198-KITCON-DCBUSCOND connector set separately.

Figure 31 - Regenerative Bus Supply Example/Impedance-grounded Input Power

DC-bus conditioner requirements for impedance-grounded systems:

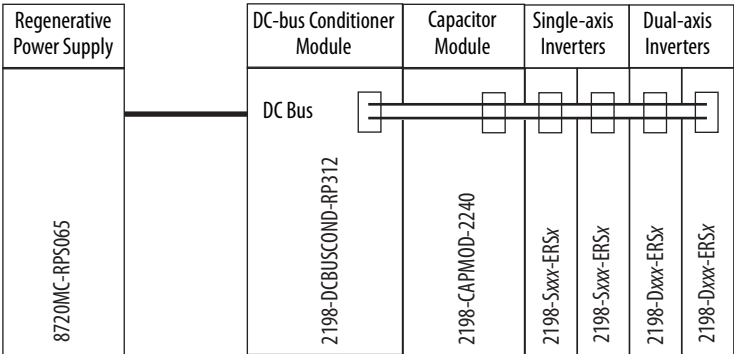
- Required on single cluster system
- Required on each cluster of multi-cluster systems

8720MC-RPS or Other Regenerative Power Supply

The following system configurations illustrate the minimum number of accessory modules required.

Figure 32 - Regenerative Power Supply Example (104 A, max)

- This example includes:
- 1 Bus group
 - 1 Drive cluster

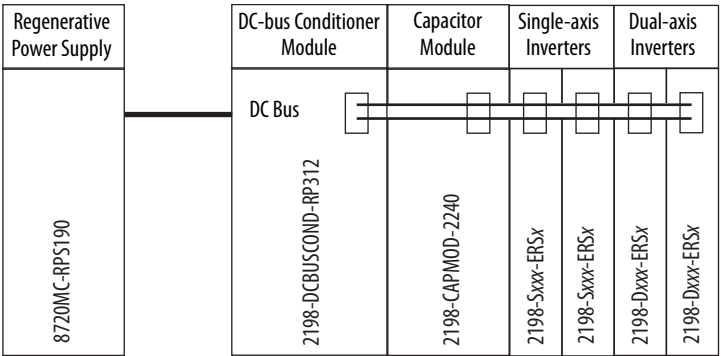


DC-bus conditioner is required only if the total power-cable length exceeds 400 m (1312 ft).

IMPORTANT In both of these examples, the Kinetix 5700 drive system includes two accessory modules. Flexible bus bars are included with only the 2198-CAPMOD-DCBUS-IO extension module. So, if you have two capacitor modules, two DC-bus conditioner modules, or a capacitor module and DC-bus conditioner module mounted side by side, you must order the 2198-KITCON-CAPMOD2240 or 2198-KITCON-DCBUSCOND connector set separately.

Figure 33 - Regenerative Power Supply Example Power (208 A, max)

- This example includes:
- 1 Bus group
 - 1 Drive cluster



DC-bus conditioner is required because this is a 208 A system.
DC-bus conditioner is also required if the total power-cable length exceeds 400 m (1312 ft).

IMPORTANT The 8720MC-RPS power supply is not compatible with the iTRAK power supply.

Accessory Module Flowcharts

The following flowcharts are designed to help you determine the minimum number of accessory modules that are needed for your application.

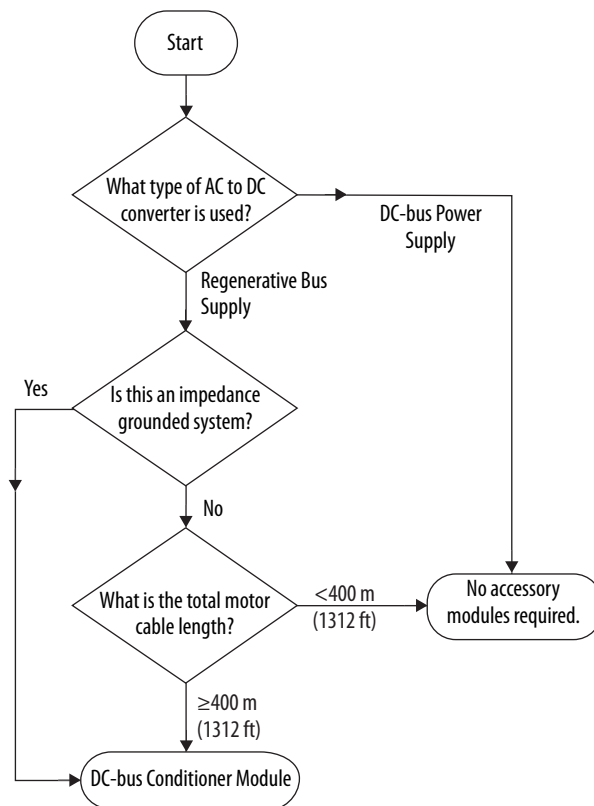
IMPORTANT Specific system demands can justify additional accessory modules based on the previously mentioned benefits.

In this flowchart, a 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply supplies DC-bus power to a single cluster of drives.

System variables that you need to know include the following:

- The type of AC to DC converter used
- The input power ground configuration
- The total motor cable length

Figure 34 - Single-cluster Drive System



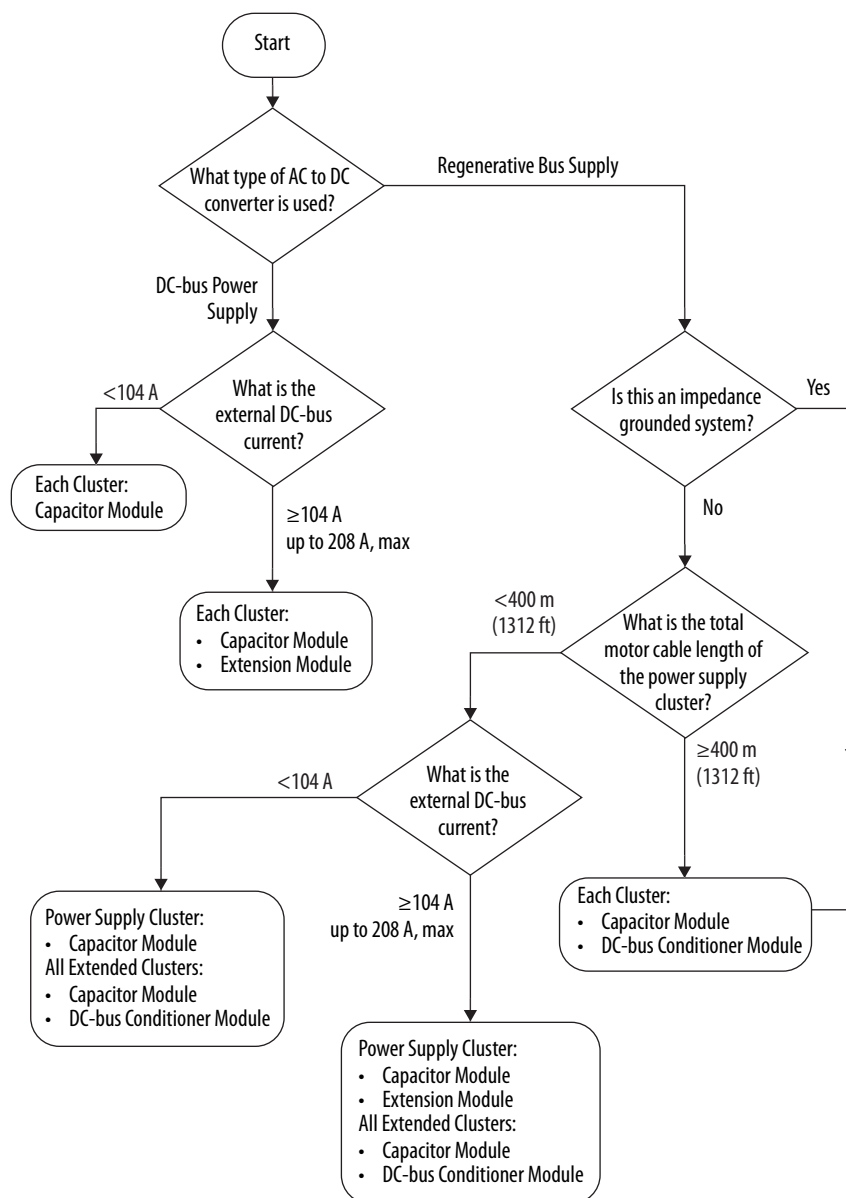
In this flowchart, a 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply supplies DC-bus power to a multi-cluster drive system.

TIP The 'power supply' cluster includes the 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply. Extended clusters are part of the same DC-bus group and connected to the power supply cluster via stud terminals that are available on accessory modules.

System variables that you need to know include the following:

- The type of AC to DC converter used
- The input-power ground configuration
- The external DC-bus current
- The total motor-cable length of the power supply cluster

Figure 35 - Multi-cluster Drive System



Electrical Noise Reduction

This section outlines best practices that minimize the possibility of noise-related failures as they apply specifically to Kinetix 5700 system installations. For more information on the concept of high-frequency (HF) bonding, the ground plane principle, and electrical noise reduction, refer to the System Design for Control of Electrical Noise Reference Manual, publication [GMC-RM001](#).

Bonding Modules

Bonding is the practice of connecting metal chassis, assemblies, frames, shields, and enclosures to reduce the effects of electromagnetic interference (EMI).

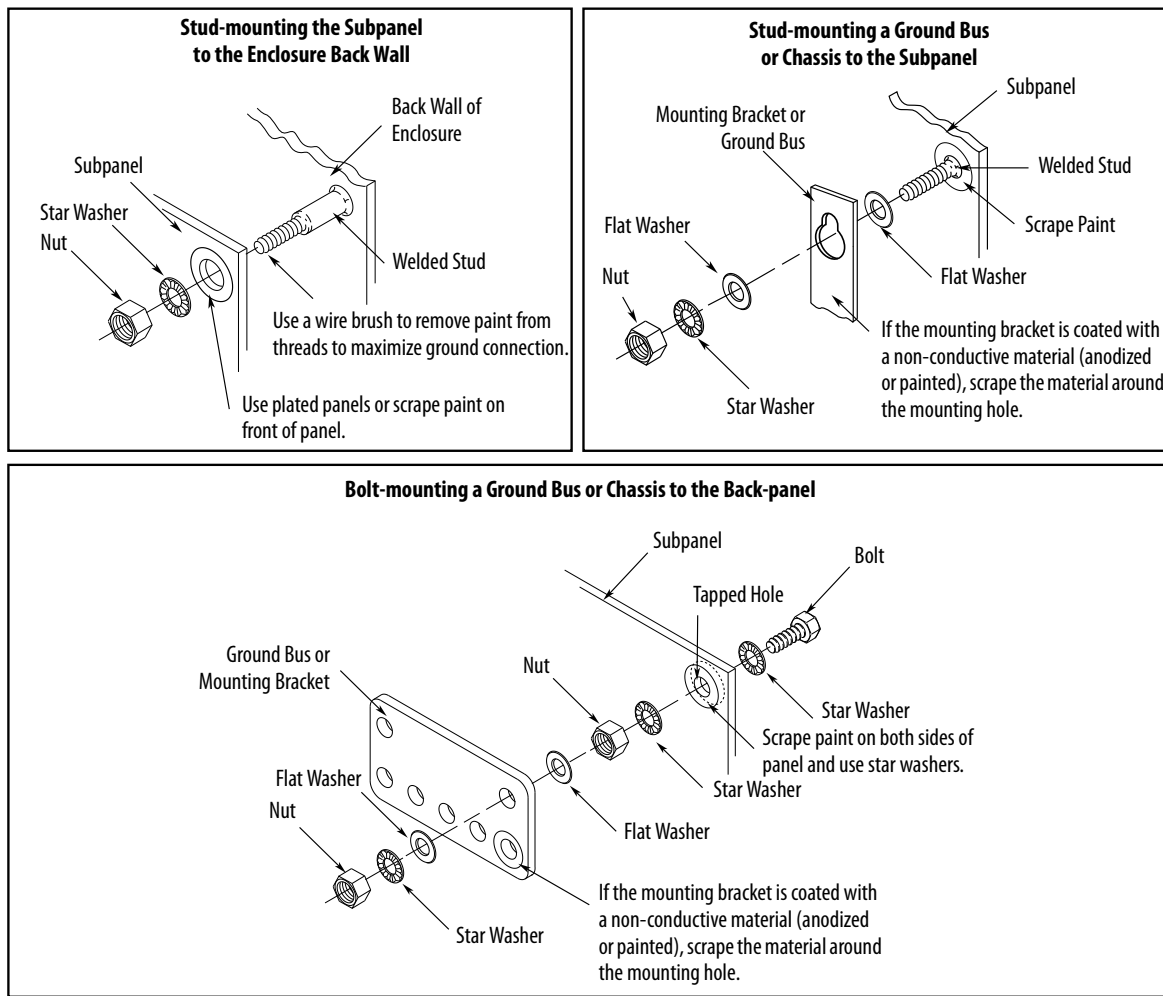
Unless specified, most paints are not conductive and act as insulators. To achieve a good bond between the drive module and subpanel, surfaces need to be paint-free or plated. Bonding metal surfaces creates a low-impedance return path for high-frequency energy.

| | |
|------------------|---|
| IMPORTANT | To improve the bond between the drive module and subpanel, construct your subpanel out of zinc plated (paint-free) steel. |
|------------------|---|

Improper bonding of metal surfaces blocks the direct return path and allows high-frequency energy to travel elsewhere in the cabinet. Excessive high-frequency energy can effect the operation of other microprocessor controlled equipment.

These illustrations show details of recommended bonding practices for painted panels, enclosures, and mounting brackets.

Figure 36 - Recommended Bonding Practices for Painted Panels

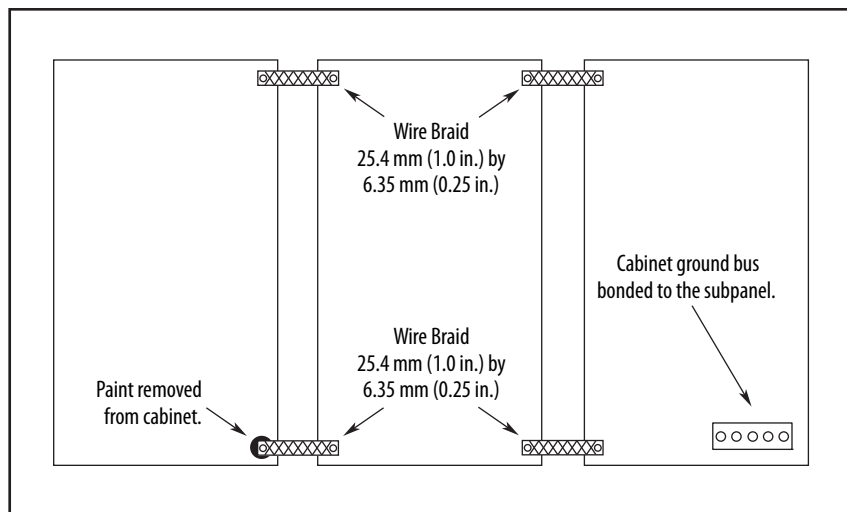


Bonding Multiple Subpanels

Bonding multiple subpanels creates a common low impedance exit path for the high frequency energy inside the cabinet. Subpanels that are not bonded together do not necessarily share a common low impedance path. This difference in impedance can affect networks and other devices that span multiple panels:

- Bond the top and bottom of each subpanel to the cabinet by using 25.4 mm (1.0 in.) by 6.35 mm (0.25 in.) wire braid. As a rule, the wider and shorter the braid is, the better the bond.
- Scrape the paint from around each fastener to maximize metal-to-metal contact.

Figure 37 - Multiple Subpanels and Cabinet Recommendations



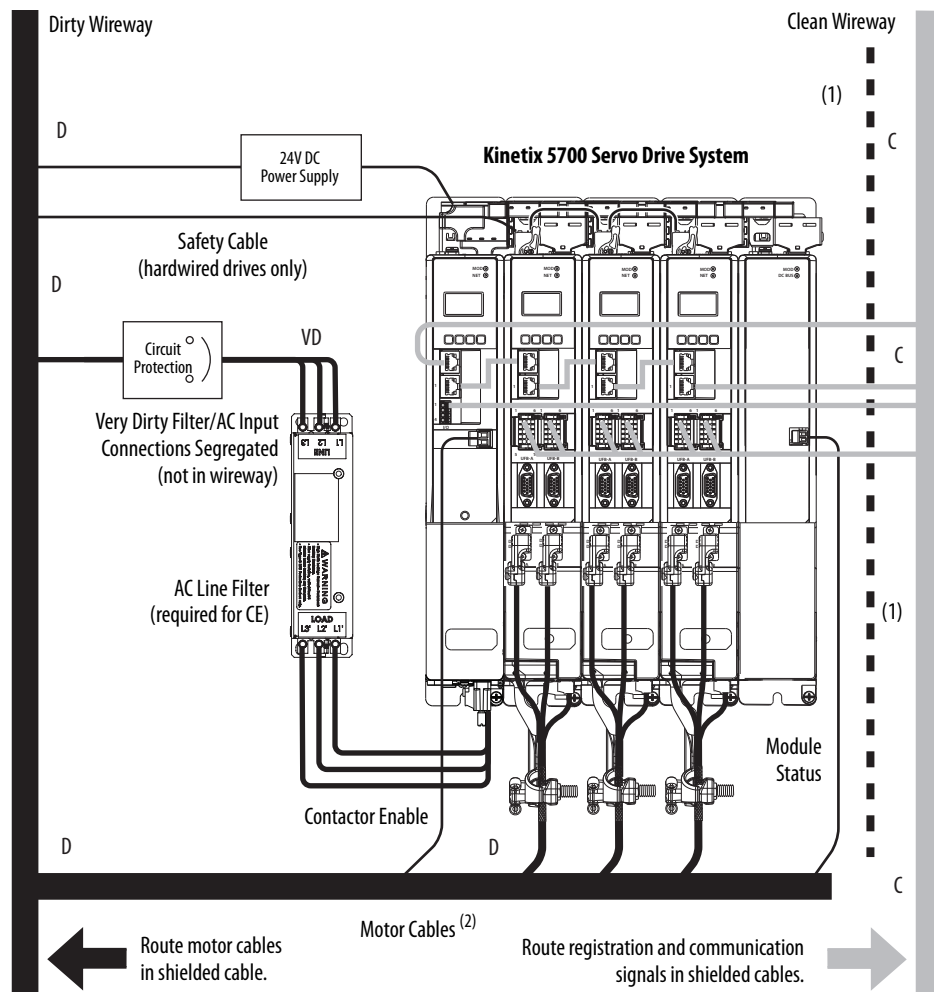
Establishing Noise Zones

The Kinetix 5700 DC-bus system power can be supplied by the 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply.

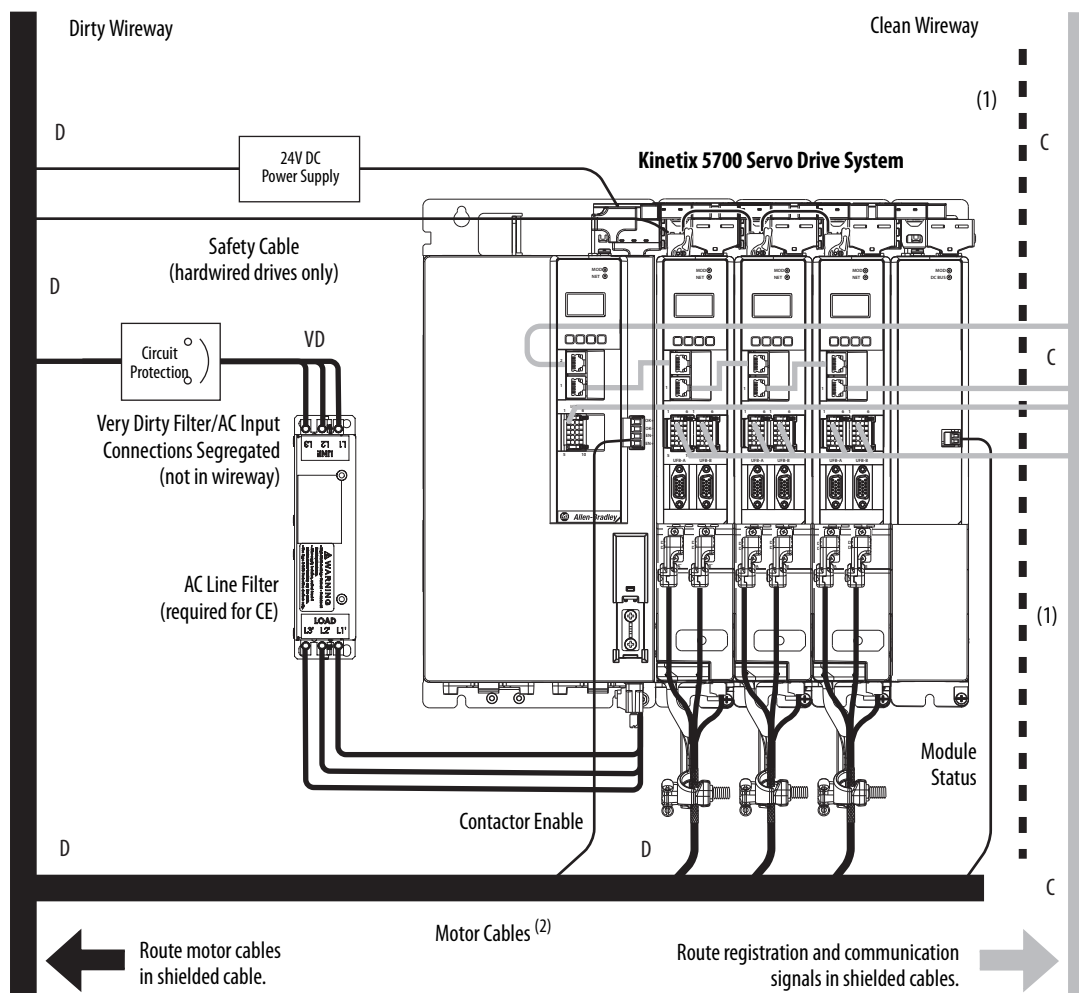
Observe these guidelines when routing cables used in the Kinetix 5700 system:

- The clean zone (C) is right of the drive system and includes the digital inputs wiring and Ethernet cable (gray wireway).
- The dirty zone (D) is left and below the drive system (black wireways) and includes the circuit breakers, 24V DC power supply, safety, and motor cables.
- The very dirty zone (VD) is limited to where the AC (EMC) line filter VAC output jumpers over to the DC-bus power supply. Shielded cable is required only if the very dirty cables enter a wireway.

Figure 38 - Noise Zones (DC-bus power supply)



- (1) When space to the right of the module does not permit 150 mm (6.0 in.) segregation, use a grounded steel shield instead. For examples, refer to the System Design for Control of Electrical Noise Reference Manual, publication [GMC-RM001](#).
- (2) When the 2198-H2DCK feedback converter kit or 2198-K57CK-D15M universal feedback kit is used, feedback cable routes in the clean wireway.

Figure 39 - Noise Zones (regenerative bus supply)

- (1) When space to the right of the module does not permit 150 mm (6.0 in.) segregation, use a grounded steel shield instead. For examples, refer to the System Design for Control of Electrical Noise Reference Manual, publication [GMC-RM001](#).
- (2) When the 2198-H2DCK feedback converter kit or 2198-K57CK-D15M universal feedback kit is used, feedback cable routes in the clean wireway.

Cable Categories for Kinetix 5700 Systems

These tables indicate the best zone for running cables and wires. The tables also show how the use of ferrite sleeves and shielded cable can reduce the noise effects of dirty and very-dirty wires and cables.

Table 22 - DC-bus Power Supply or Regenerative Bus Supply

| Wire/Cable | Power Supply Cat. No. | Connector | Zone | | | Method | |
|--------------------------------------|-------------------------|----------------|------------------------------------|-------|-------|----------------|----------------|
| | | | Very Dirty | Dirty | Clean | Ferrite Sleeve | Shielded Cable |
| L1, L2, L3 (shielded cable) | 2198-Pxxx | IPD | – | X | – | – | X |
| L1, L2, L3 (unshielded cable) | 2198-RPxxx | | X | – | – | – | – |
| DC-/DC+ (DC bus) | 2198-Pxxx 2198-RPxxx | DC | Bus-bar only, no wiring connector. | | | | |
| DC+/SH (passive shunt) | 2198-Pxxx | RC | – | X | – | – | – |
| DC+/DC– (active shunt) | 2198-RPxxx | | – | | – | – | – |
| CONT EN– and CONT EN+ (M1 contactor) | 2198-Pxxx 2198-RPxxx | CED | – | X | – | – | – |
| CONV OK– and CONV OK+ | 2198-RPxxx | | – | | – | – | – |
| 24V DC | 2198-Pxxx 2198-RPxxx | CP | – | X | – | – | – |
| Dedicated digital inputs | 2198-Pxxx 2198-RPxxx | IOD | – | X | – | – | – |
| Ethernet (shielded cable) | 2198-Pxxx 2198-RPxxx | PORT1 PORT2 | – | – | X | – | X |

Table 23 - Dual-axis and Single-axis Inverters

| Wire/Cable | | Connector | Zone | | | Method | |
|---|--|----------------|------------------------------------|-------|-------|----------------|----------------|
| | | | Very Dirty | Dirty | Clean | Ferrite Sleeve | Shielded Cable |
| DC-/DC+ (DC bus) | | DC | Bus-bar only, no wiring connector. | | | | |
| U, V, W (motor power) | Kinetix VPL, VPC-Q VPF, VPH, VPS motors | MP | — | X | — | — | X |
| Motor feedback | | MF | | X | | | X |
| Motor brake | | BC | | X | | | X |
| U, V, W (motor power) | Kinetix VPC-S/Y, MPL, MPM, MPF, MPS motors | MP | — | X | — | — | X |
| Motor feedback | | MF or UFB | | — | X | | X |
| Motor brake | | BC | | X | — | | X |
| 24V DC | | CP | — | X | — | — | — |
| Safety enable for safe torque-off (hardwired) | | STO | — | X | — | — | — |
| Registration input | | IOD | — | — | X | — | X |
| Dedicated digital inputs (other than registration inputs) | | | — | X | — | — | — |
| Ethernet (shielded cable) | | PORT1 PORT2 | — | — | X | — | X |

Table 24 - iTRAK Power Supply

| Wire/Cable | Connector | Zone | | | Method | |
|---|----------------|------------------------------------|-------|-------|----------------|----------------|
| | | Very Dirty | Dirty | Clean | Ferrite Sleeve | Shielded Cable |
| DC-/DC+ (DC bus) | DC | Bus-bar only, no wiring connector. | | | | |
| iTRAK DC-bus output A and B | IDC | – | X | – | – | X |
| 24V DC control input power | CP | – | X | – | – | X |
| iTRAK 24V DC control output power A and B | ICP | | | | | |
| iTRAK digital inputs | IOD | – | – | X | – | – |
| iTRAK ready output | IR | – | – | X | – | – |
| Ethernet (shielded cable) | PORT1 PORT2 | – | – | X | – | X |

Table 25 - Capacitor Module or DC-bus Conditioner Module

| Wire/Cable | Connector | Zone | | | Method | |
|------------------|-----------|------------------------------------|-------|-------|----------------|----------------|
| | | Very Dirty | Dirty | Clean | Ferrite Sleeve | Shielded Cable |
| DC-/DC+ (DC bus) | DC | Bus-bar only, no wiring connector. | | | | |
| DC-/DC+ | M8 Stud | – | X | – | – | – |
| 24V DC | CP | – | X | – | – | – |
| Module status | MS | – | X | – | – | – |

Table 26 - Extension Module

| Wire/Cable | Connector | Zone | | | Method | |
|------------------|-----------|------------------------------------|-------|-------|----------------|----------------|
| | | Very Dirty | Dirty | Clean | Ferrite Sleeve | Shielded Cable |
| DC-/DC+ (DC bus) | DC | Bus-bar only, no wiring connector. | | | | |
| DC-/DC+ | M8 Stud | – | X | – | – | – |

Noise Reduction Guidelines for Drive System Accessories

Refer to this section when mounting an AC (EMC) line filter or external shunt resistor for guidelines designed to reduce system failures caused by excessive electrical noise.

AC Line Filters

Observe these guidelines when mounting your AC (EMC) line filter (refer to the figure on [page 70](#) for an example):

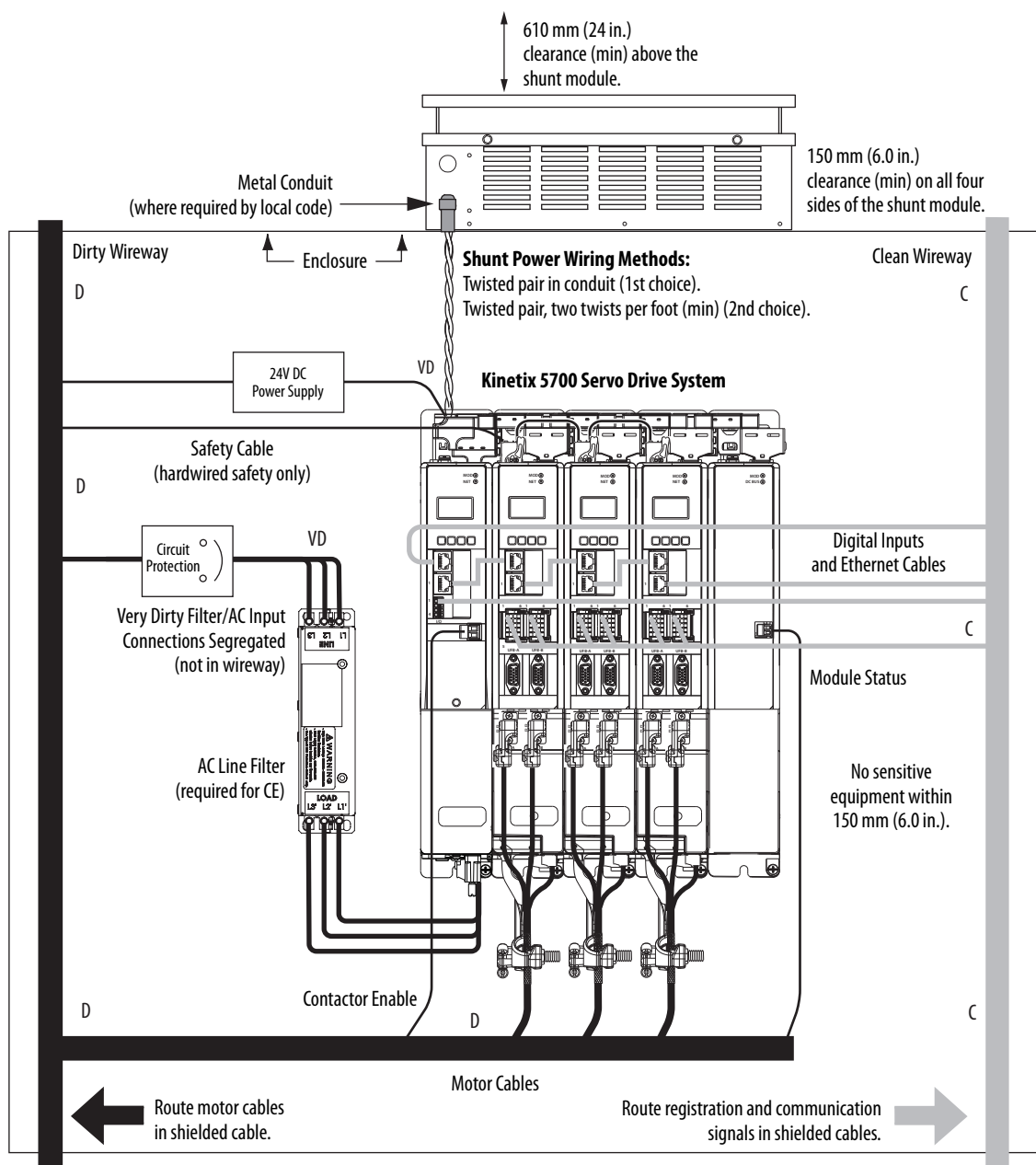
- If your facility has grounded WYE power distribution, as shown in [Figure 80](#) on [page 129](#), mount the AC line filter on the same panel as the Kinetix 5700 power supply and as close to the power supply as possible.
- Good HF bonding to the panel is critical. For painted panels, refer to the examples on [page 68](#).
- Segregate input and output wiring as far apart as possible.

External Passive Shunt Modules

Observe these guidelines when mounting your 2198-R014, 2198-R031, or 2198-R127 external passive shunt modules:

- Mount the shunt module outside of the drive system enclosure.
- Mount the shunt module so that wiring routes in the very dirty zone inside the drive system enclosure.
- Keep unshielded wiring as short as possible, not to exceed 3 m (9.8 ft). Keep shunt wiring as flat to the cabinet as possible.

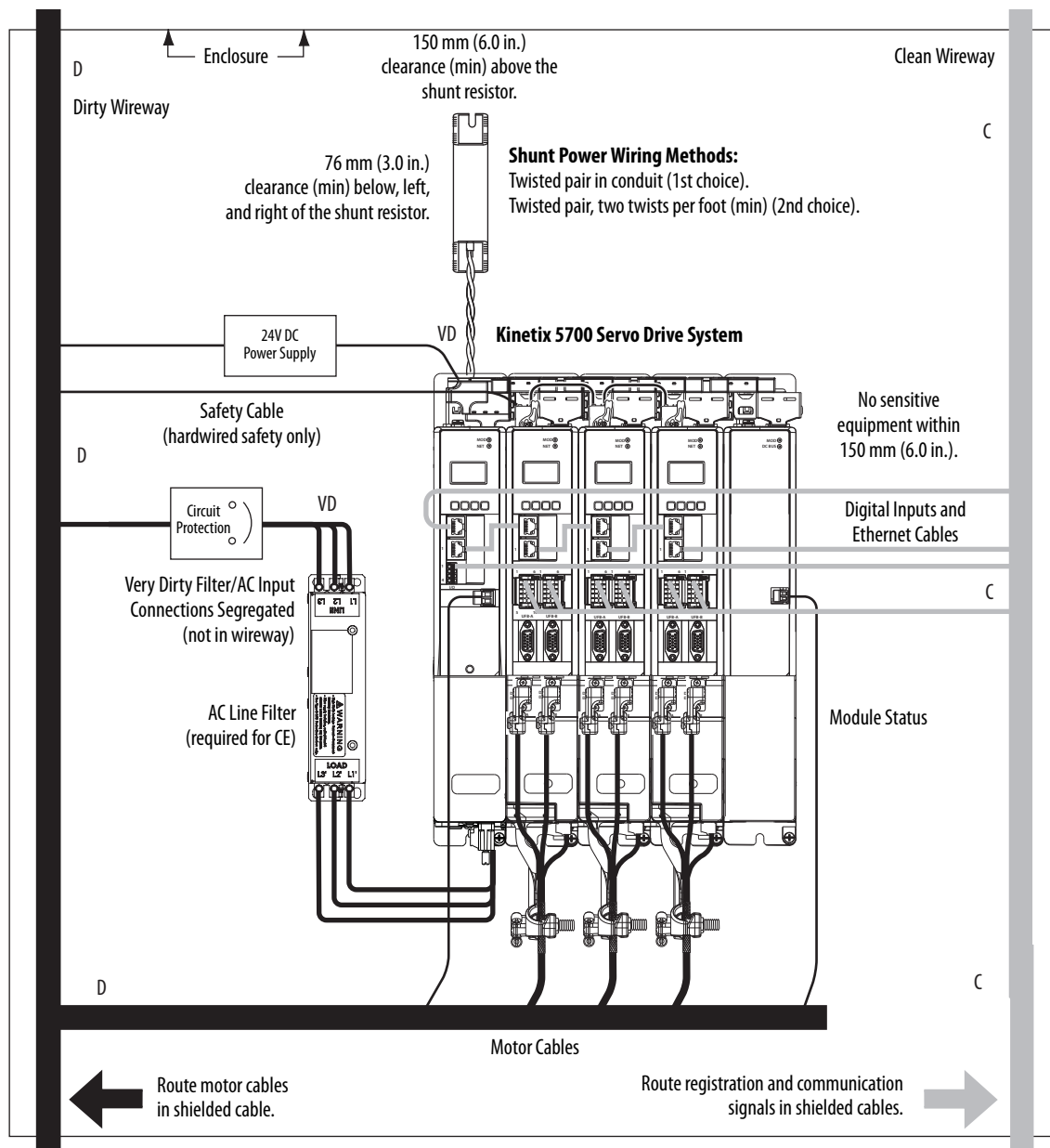
Figure 40 - External Passive Shunt Module Mounted On Top of the Drive System Enclosure



Observe these guidelines when mounting your 2198-R004 external passive shunt resistor:

- Mount the shunt resistors anywhere in the dirty zone, but as close to the Kinetix 5700 power supply as possible.
- Route the shunt power wires with other very dirty wires.
- Keep unshielded wiring as short as possible, not to exceed 457 mm (18 in.). Keep shunt wiring as flat to the cabinet as possible.
- Separate shunt power cables from other sensitive low-voltage signal cables.

Figure 41 - External Shunt Resistor Mounted Inside the Drive System Enclosure

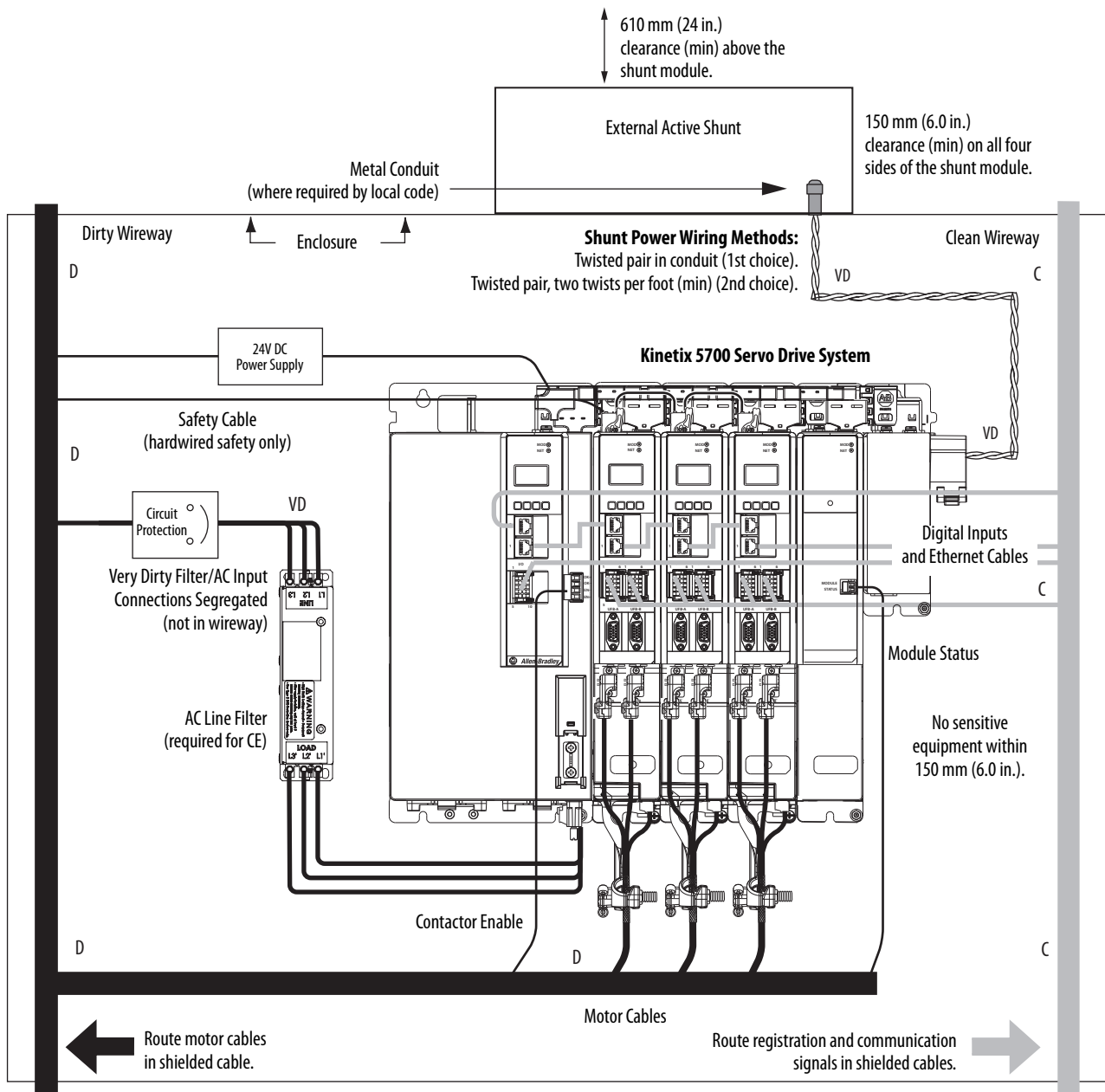


External Active Shunt Modules

Observe these guidelines when mounting external active shunt outside the drive system enclosure:

- Mount the shunt module so that wiring routes in the very dirty zone inside the drive system enclosure.
- Keep unshielded wiring as short as possible, not to exceed 3 m (9.8 ft). Keep shunt wiring as flat to the cabinet as possible.

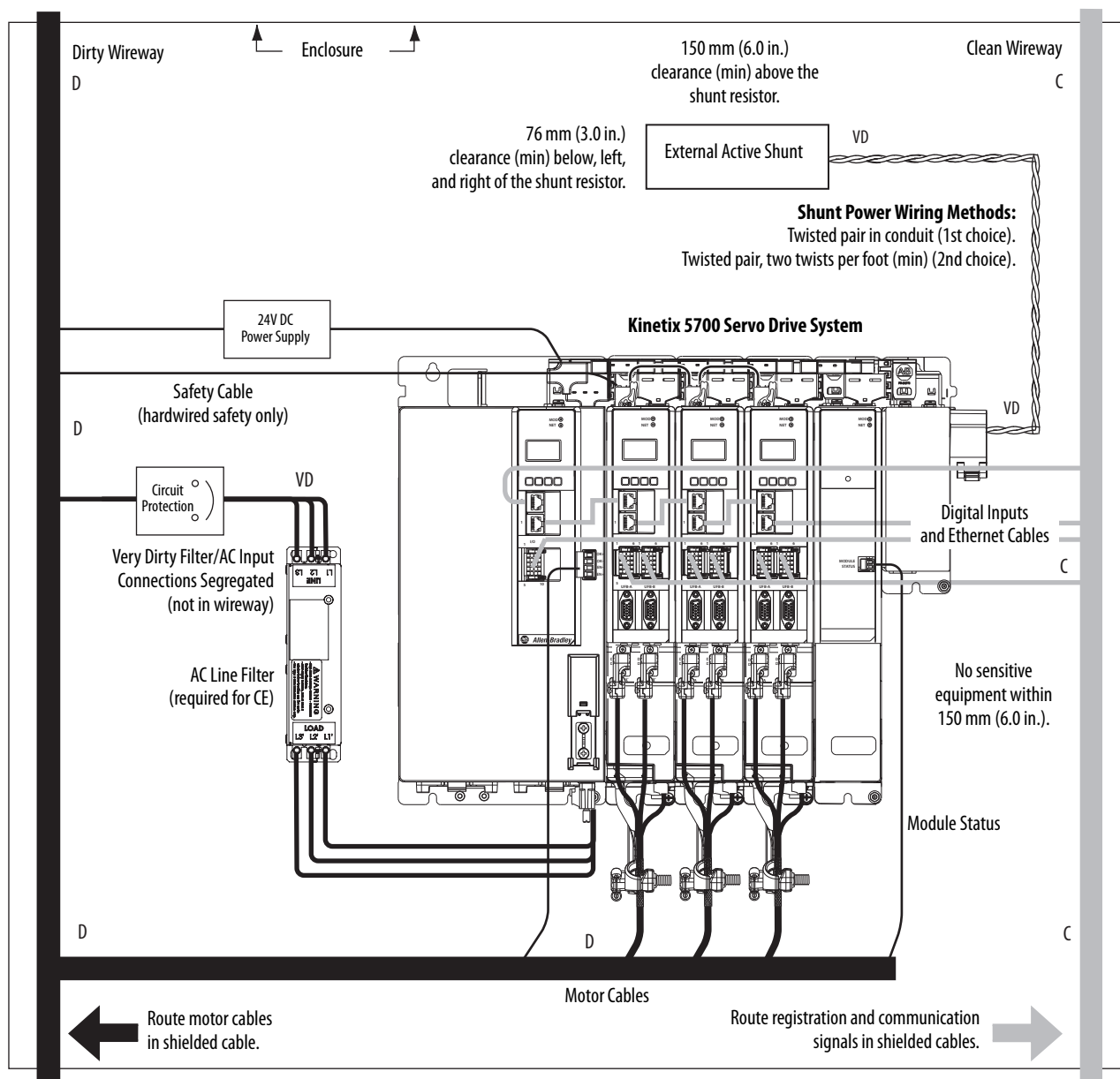
Figure 42 - External Active Shunt Module Mounted On Top of the Drive System Enclosure



Observe these guidelines when mounting your external active shunt inside the drive system enclosure:

- Mount the shunt resistors anywhere in the dirty zone, but as close to the Kinetix 5700 power supply as possible.
- Route the shunt power wires with other very dirty wires.
- Keep unshielded wiring as short as possible, not to exceed 3 m (9.8 ft). Keep shunt wiring as flat to the cabinet as possible.
- Separate shunt power cables from other sensitive low-voltage signal cables.

Figure 43 - External Active Shunt Mounted Inside the Drive System Enclosure



Notes:

Mount the Kinetix 5700 Drive System

This chapter provides installation procedures for mounting your Kinetix® 5700 drive system to the system panel and installing DC-bus links and 24V shared-bus connector kits to the drive modules.

| Topic | Page |
|---------------------------------------|------|
| Determine Mounting Order | 80 |
| Mount Accessory Modules | 83 |
| Zero-stack Tab and Cutout | 84 |
| Install Shared-bus Connection Systems | 84 |
| Drill-hole Patterns | 87 |
| Mount Your Kinetix 5700 Drive Modules | 90 |

This procedure assumes that you have prepared your panel and understand how to bond your system. For installation instructions regarding equipment and accessories not included here, refer to the instructions that came with those products.



SHOCK HAZARD: To avoid the hazard of electrical shock, perform all mounting and wiring of the Kinetix 5700 drive system before applying power. Once power is applied, connector terminals can have voltage present even when not in use.



ATTENTION: Plan the installation of your system so that you can perform all cutting, drilling, tapping, and welding with the system removed from the enclosure. Because the system is of the open type construction, be careful to keep metal debris from falling into it. Metal debris or other foreign matter can become lodged in the circuitry and result in damage to the components.

Determine Mounting Order

Mount the DC-bus power supply or regenerative bus supply on the far right or far left, whichever makes the best use of panel space. Mount inverter modules and iTRAK® power supplies in order from left to right (as shown in [Figure 44](#)) or right to left (as shown in [Figure 46](#)).

IMPORTANT We recommend that you mount inverter modules and iTRAK power supplies according to power rating (highest to lowest) from left to right (or right to left) starting with the highest power rating.

Table 27 - Kinetix 5700 Single-axis Inverter Modules

| Attribute | 2198-S086-ERSx | 2198-S130-ERSx | 2198-S160-ERSx | 2198-S263-ERSx | 2198-S312-ERSx |
|------------------------------|----------------|----------------|----------------|----------------|----------------|
| Continuous Power Output, nom | 29.7 kW | 44.9 kW | 60.1 kW | 90 kW | 112 kW |

Table 28 - Kinetix 5700 Dual-axis Inverter Modules

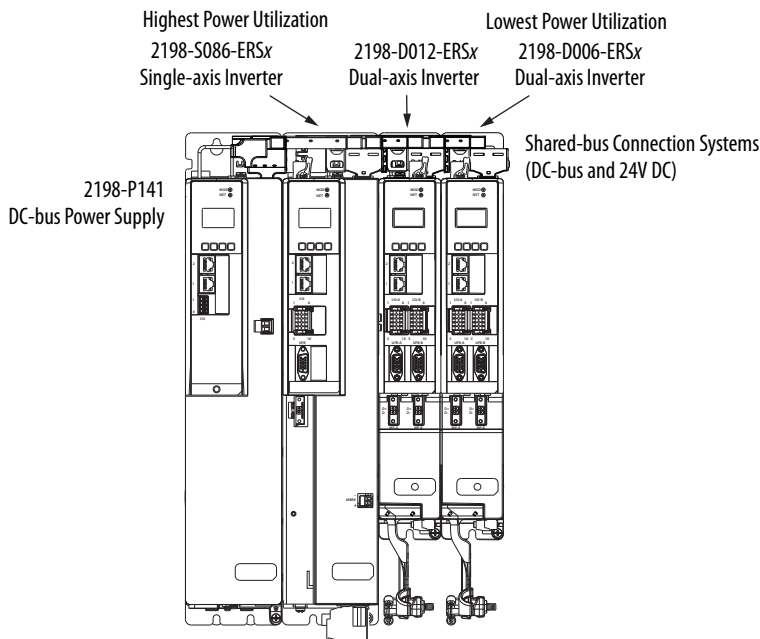
| Attribute | 2198-D006-ERSx | 2198-D012-ERSx | 2198-D020-ERSx | 2198-D032-ERSx | 2198-D057-ERSx |
|------------------------------|----------------|----------------|----------------|----------------|----------------|
| Continuous Power Output, nom | 2 x 1.7 kW | 2 x 3.4 kW | 2 x 5.5 kW | 2 x 8.9 kW | 2 x 15.9 kW |

Table 29 - iTRAK Power Supply

| Attribute | 2198T-W25K-ER |
|------------------------------|---------------|
| Continuous Power Output, nom | 4.1 kW |

The Kinetix 5700 drive system in [Figure 44](#) could be powered by the 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply. This example is powered by the DC-bus power supply (positioned on the left) with inverter modules mounted according to power rating (highest to lowest) from left to right.

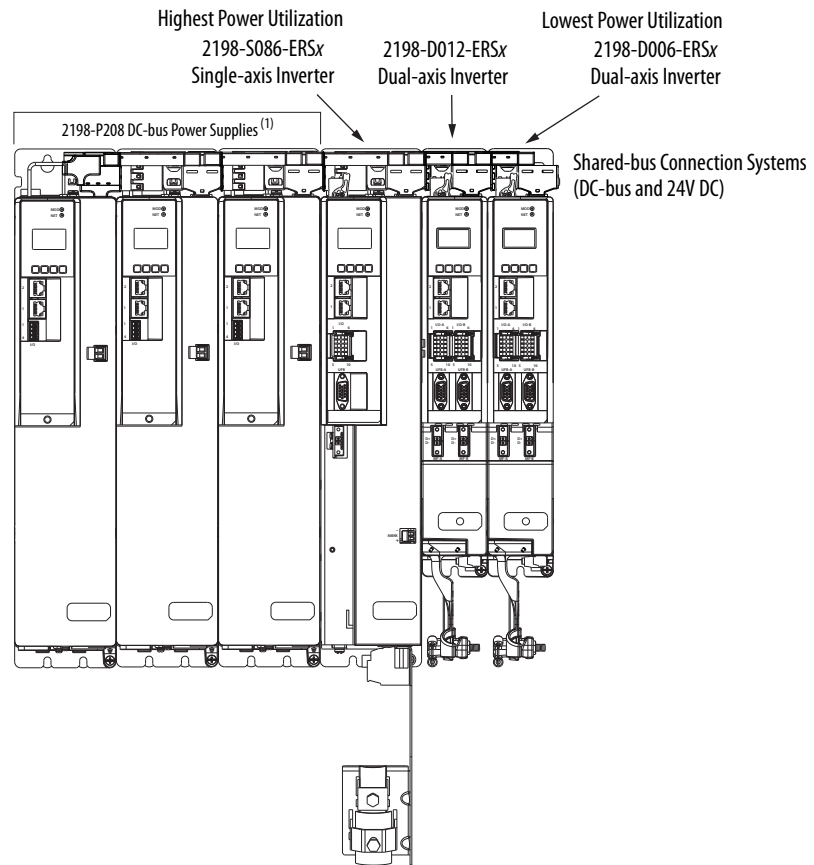
Figure 44 - System Mounting Order Example (single DC-bus power supply)



IMPORTANT The maximum number of inverter modules depends on the maximum system capacitance precharge capability of the power supplies and the total system capacitance. When there are two or three DC-bus power supplies, they must be catalog number 2198-P208.

Refer to Appendix C on [page 391](#) for more system sizing information.

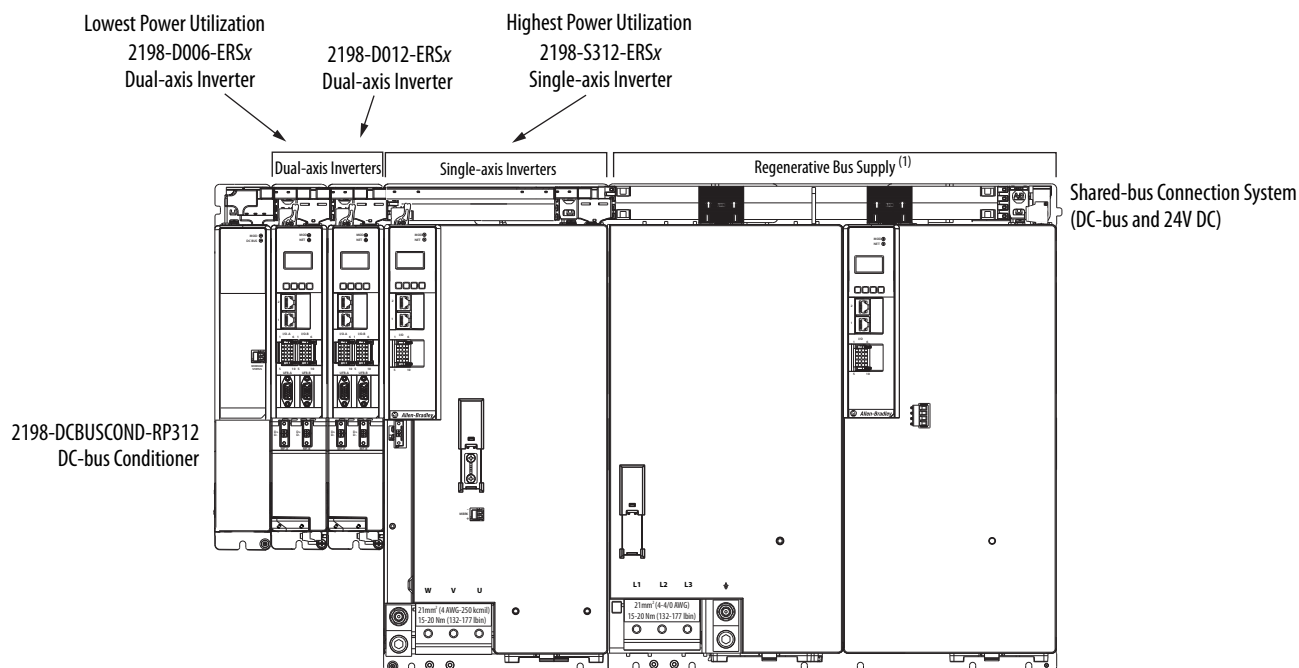
Figure 45 - System Mounting Order Example (multiple DC-bus power supplies)



(1) The DC-bus power supplies can be left or right of the inverters.

This example is powered by the regenerative bus supply (positioned on the right) with inverter modules mounted according to power rating (highest to lowest) from right to left.

Figure 46 - System Mounting Order Example (regenerative bus supply)



(1) The regenerative bus supply can be mounted left or right of the inverters.

IMPORTANT The maximum number of inverter modules depends on the maximum system capacitance precharge capability of the power supply and the total system capacitance.
Refer to Appendix C on [page 391](#) for more system sizing information.

Mount Accessory Modules

Mount the 2198-CAPMOD-2240 capacitor module on the far right or far left of any system cluster, depending on the input power configuration. A capacitor module is required in the following situations:

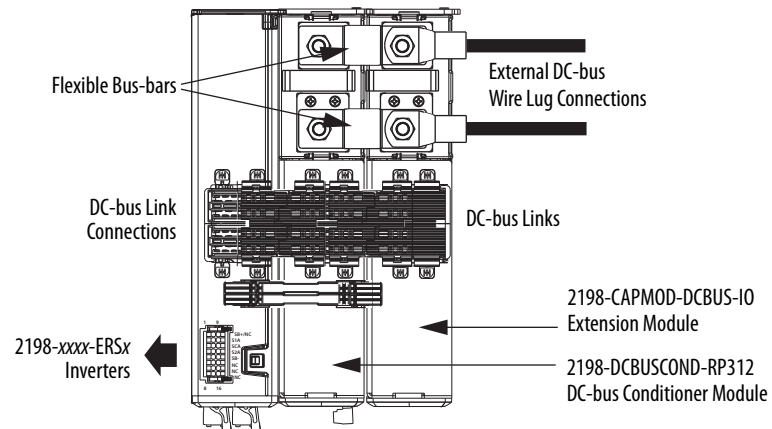
- Required in each cluster of a multi-cluster system
- More than one capacitor module can be used in a cluster, if needed

IMPORTANT Each additional capacitor module adds to the total system capacitance and increased energy storage.

The 2198-CAPMOD-DCBUS-IO extension module is always mounted next to a capacitor module or DC-bus conditioner module and always positioned on the outside of the system cluster (either first or last). The extension module can be paired with another accessory module and flexible bus-bars if external DC-bus current is ≥ 104 A up to a maximum of 208 A.

IMPORTANT When the extension module is mounted next to another accessory module, they must be connected by flexible bus-bars.

Figure 47 - Flexible Bus Bar Example



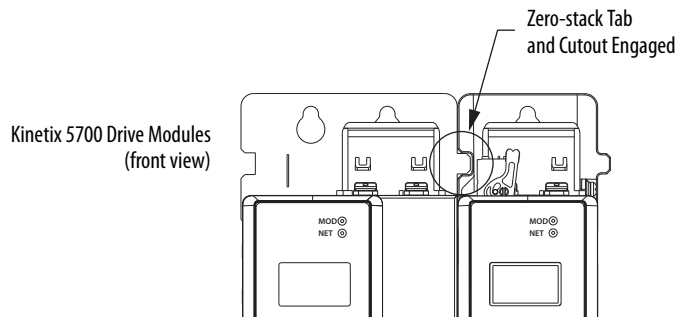
IMPORTANT In a multi-cluster system with a power supply rated ≥ 104 A, two accessory modules connected by flexible bus-bars must be used to create a 208 A extended cluster system. See the [Accessory Module Connector Specifications](#) table on [page 181](#) for DC-bus wiring requirements.

Zero-stack Tab and Cutout

Engaging the zero-stack tab and cutout from one drive module to another makes efficient use of panel space, especially for high axis-count installations.

IMPORTANT Engaging the zero-stack tab and cutout from module-to-module is required for any input power configuration. This is done to make sure that the DC-bus connectors are spaced properly to accept the shared-bus connection system.

Figure 48 - Zero-stack Tab and Cutout Example



For Kinetix 5700 system sizing examples, refer to Appendix C on [page 391](#).

Install Shared-bus Connection Systems

The shared-bus connection system is used to extend the DC-bus power and 24V control power from one drive module to another.

IMPORTANT The zero-stack tab and cutout must be engaged between adjacent drive modules for the shared-bus connection system to fit properly.

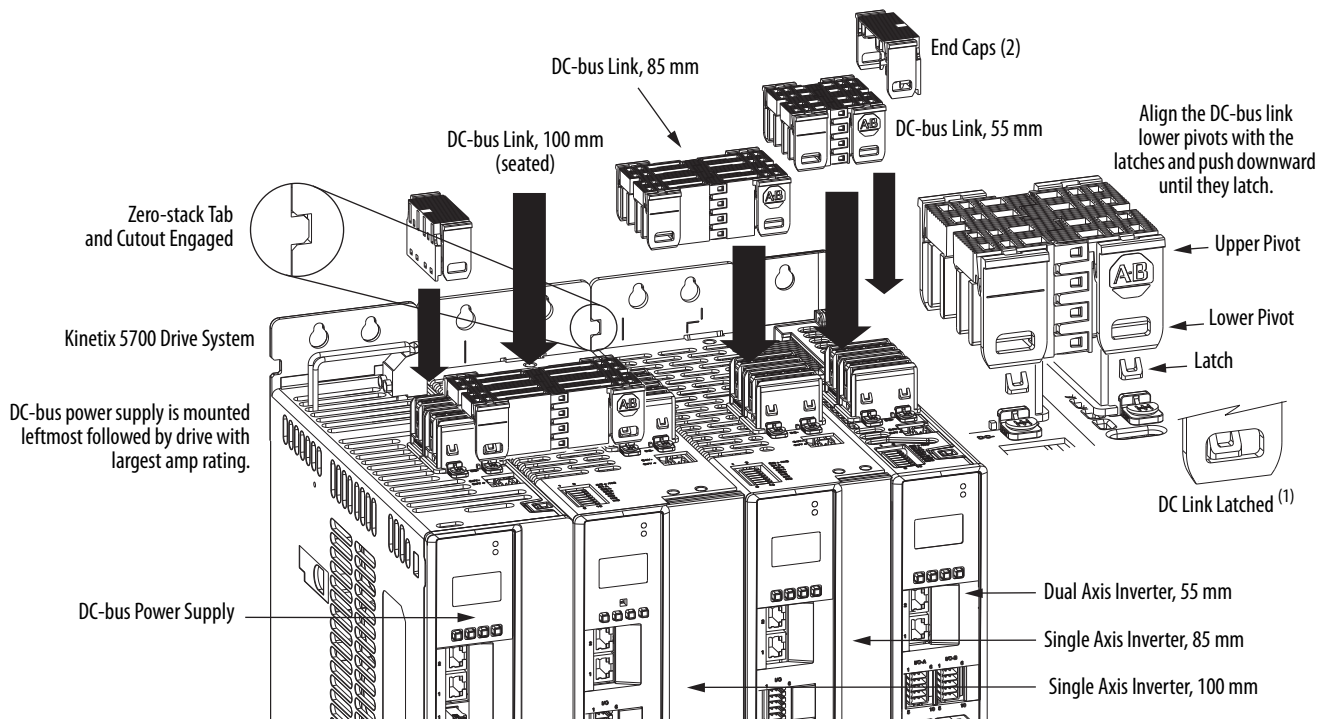
DC-bus Connection System

The DC-bus connection system is required and comprised of these two components:

- DC-bus links that are inserted between drive modules to extend the DC-bus from one drive module to another.

IMPORTANT DC-bus links are included with inverter and accessory modules, so when two or three 2198-P208 DC-bus power supplies are connected in parallel, order extra 2198-BARCON-85DC200 DC-bus links.

- DC-bus end-caps that are inserted into the first and last drive modules to cover the exposed DC-bus connector on both ends of the bus.

Figure 49 - DC-bus Connector Example

(1) DC-bus links latch on both sides when inserted into the DC-bus connectors. To remove the DC-bus link, depress both sets of upper pivots to unlatch the lower pivots and hold the DC-bus link firmly while pulling upward.

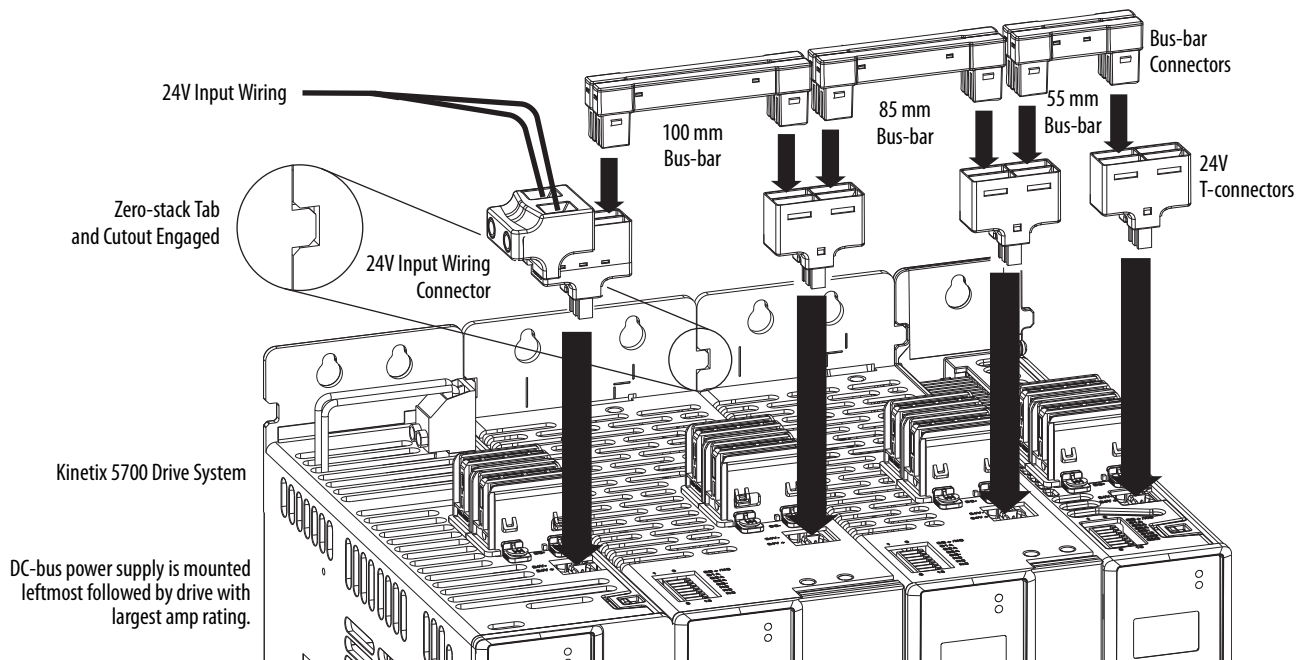
24V Input Power Connection System

The optional 24V input power connection system always feeds 24V DC from left to right and is comprised of three components:

- The 24V input wiring connector that plugs into the DC-bus power supply or first module supplied by the 24V external power receives 24V DC input wiring.
- 24V DC T-connectors that plug into the drive modules downstream from the power supply or first module supplied by the 24V external power where the 24V control power is shared.
- Bus bars that connect between drive modules to extend the 24V control power from one drive module to another.

Multiple 24V shared-bus input wiring connectors can be used in a high axis-count system. If the 40 A shared-bus current rating is exceeded, you can add another connector at any point in the cluster. 2198-S263-ERS x and 2198-S312-ERS x drives and 2198-RP263 and 2198-RP312 bus supplies use the 2198T-W25K-P-IN input wiring connector. All other modules use the 2198-TCON-24VDCIN36 input wiring connector. Both wiring connectors accept up to 10 mm² (6 AWG) wire. The CP connectors that are included with each module accept up to 10 mm² (12 AWG) or 6 mm² (10 AWG), so the shared-bus input wiring connectors can provide the means to use larger gauge conductors for reduced voltage drop on long wire runs.

Figure 50 - 24V Connector Example



The three 24V input power components must assemble from left to right across the drive system.

1. Attach wiring to 24V input wiring connector.
2. Insert input wiring connector and T-connectors into the appropriate drive module connectors.
3. Insert bus-bars to connect between wiring connector and T-connectors.

IMPORTANT The input wiring connector can be inserted into any drive module (mid-stream in the drive system) to begin a new 24V control bus when the maximum current value is reached. However, the input connector must always extend the 24V DC-bus from left to right.

IMPORTANT Mount the 24V power supply as close to the drive system as possible to minimize voltage drop on the 24V input power wiring.

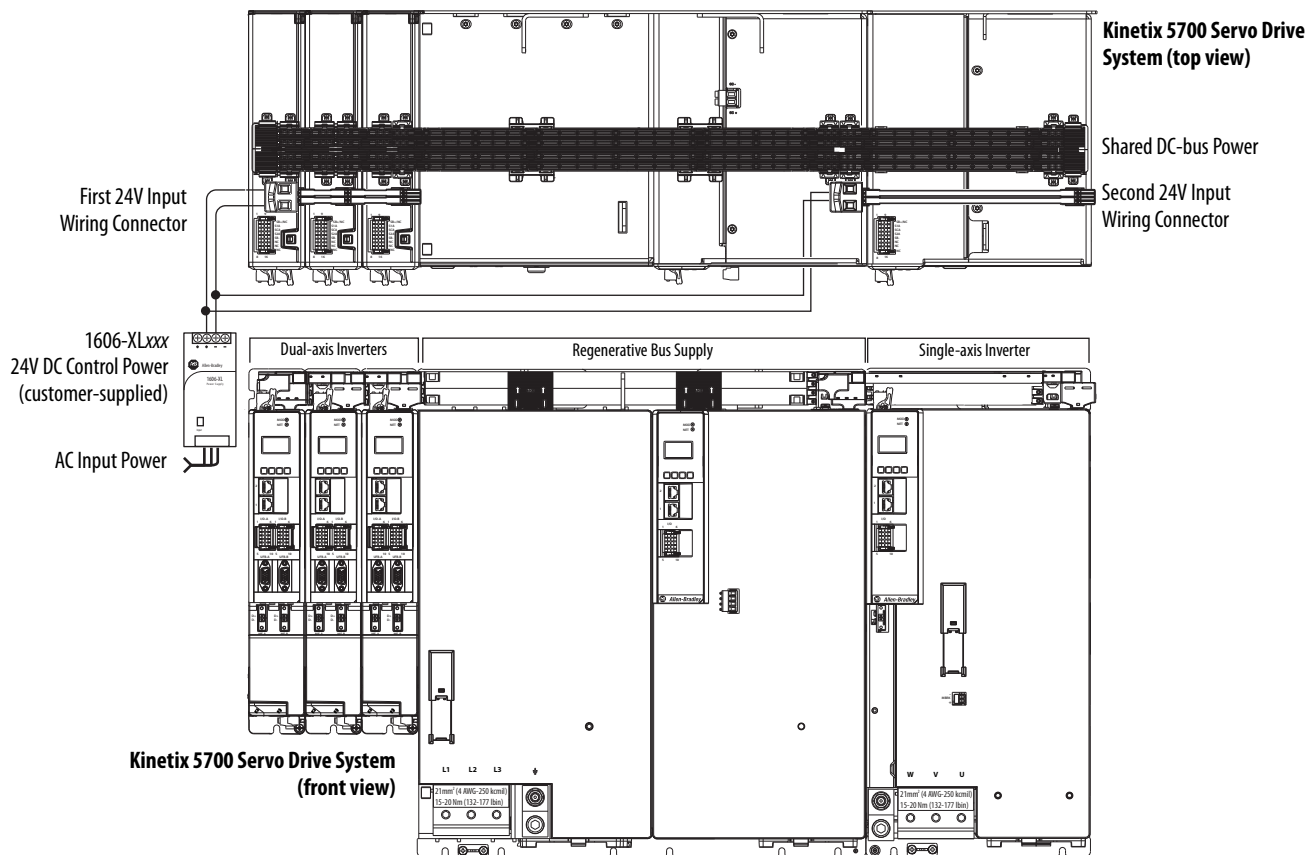
The following configurations require more than one 24V input wiring connector:

- The 40 A maximum current rating is exceeded
- The 2198-RPxxx regenerative bus supply is positioned between the inverters or accessory modules in any single cluster
- The 2198-RPxxx regenerative bus supply is positioned to the right of any other module

In this example, one 24V connection system spans (left to right) across the dual-axis inverters only. In the other 24V input connection system, the 2198-S312-P-T control power T-connector and bus-bar connects the regenerative bus supply and single-axis inverter only.

TIP 24V control power bus-bars that bridge across 2198-RPxxx regenerative bus supplies are not available.

Figure 51 - Multiple 24V Input Wiring Connector Example



Drill-hole Patterns

This section provides drill-hole patterns for Kinetix 5700 drive modules that are mounted in zero-stack (shared-bus) configurations. Properly spaced drill-holes are essential for engaging the zero-stack tab and cutout from module-to-module so that the DC-bus connectors are spaced properly to accept the DC-bus links.

The DC-bus power supply and regenerative bus supply can be mounted on the far right, far left, or anywhere in between. However, the far left position is preferred to accommodate the 24V shared bus.

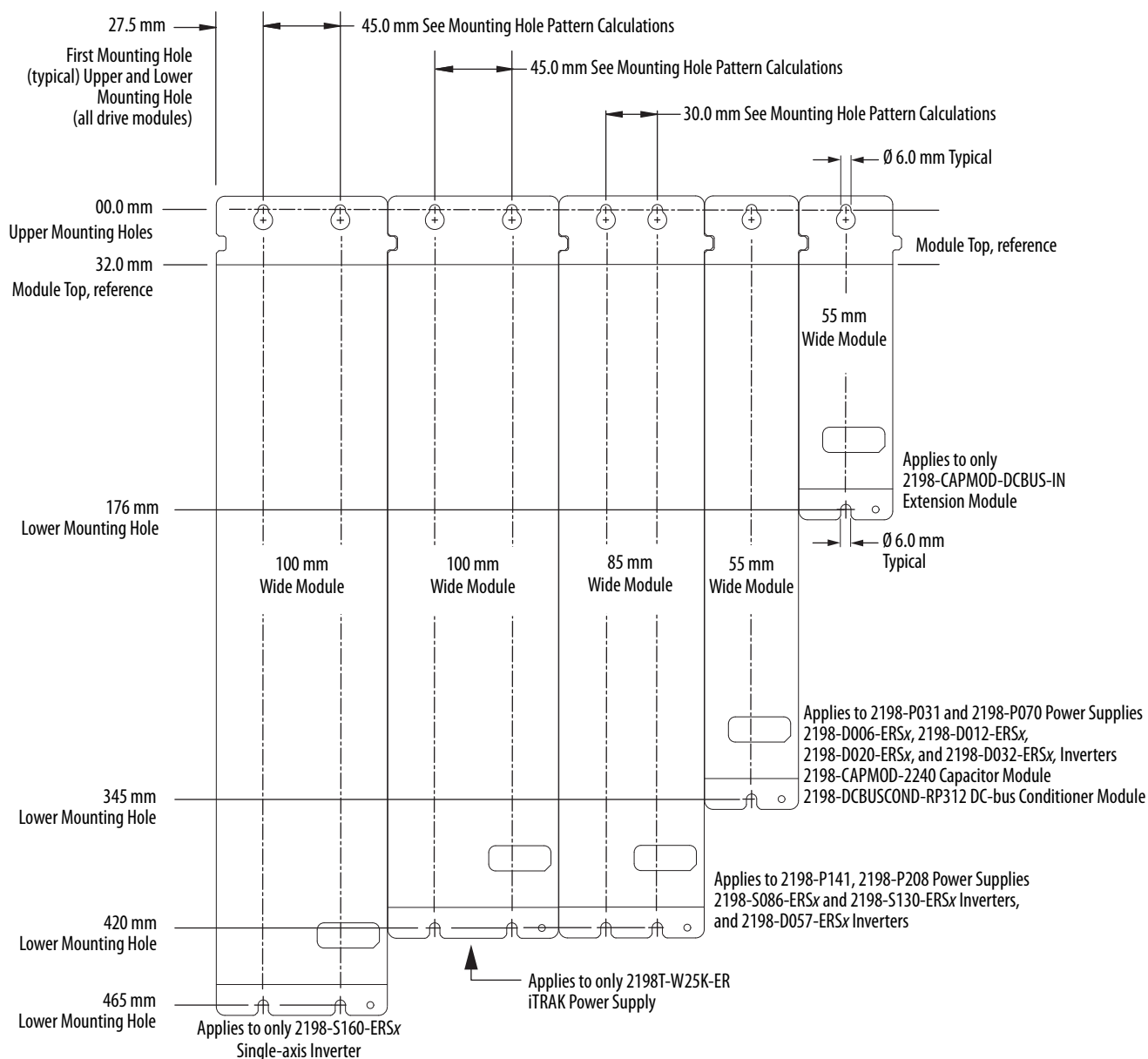
Also available to assist you in mounting Kinetix 5700 drive modules is the 2198-K5700-MOUNTKIT system mounting toolkit.

Drill-hole Pattern Calculations

Use [Figure 52](#) to calculate the left-to-right hole pattern for Kinetix 5700 drive system configurations that include the 2198-Pxxx DC-bus power supply.

1. The first hole location is zero.
2. The second hole location is module width minus 55 mm.
3. The next hole location is 55 mm.
4. Repeat [step 2](#) and [step 3](#) for the remaining holes.

Figure 52 - DC-bus Power Supply Mounting Hole Patterns

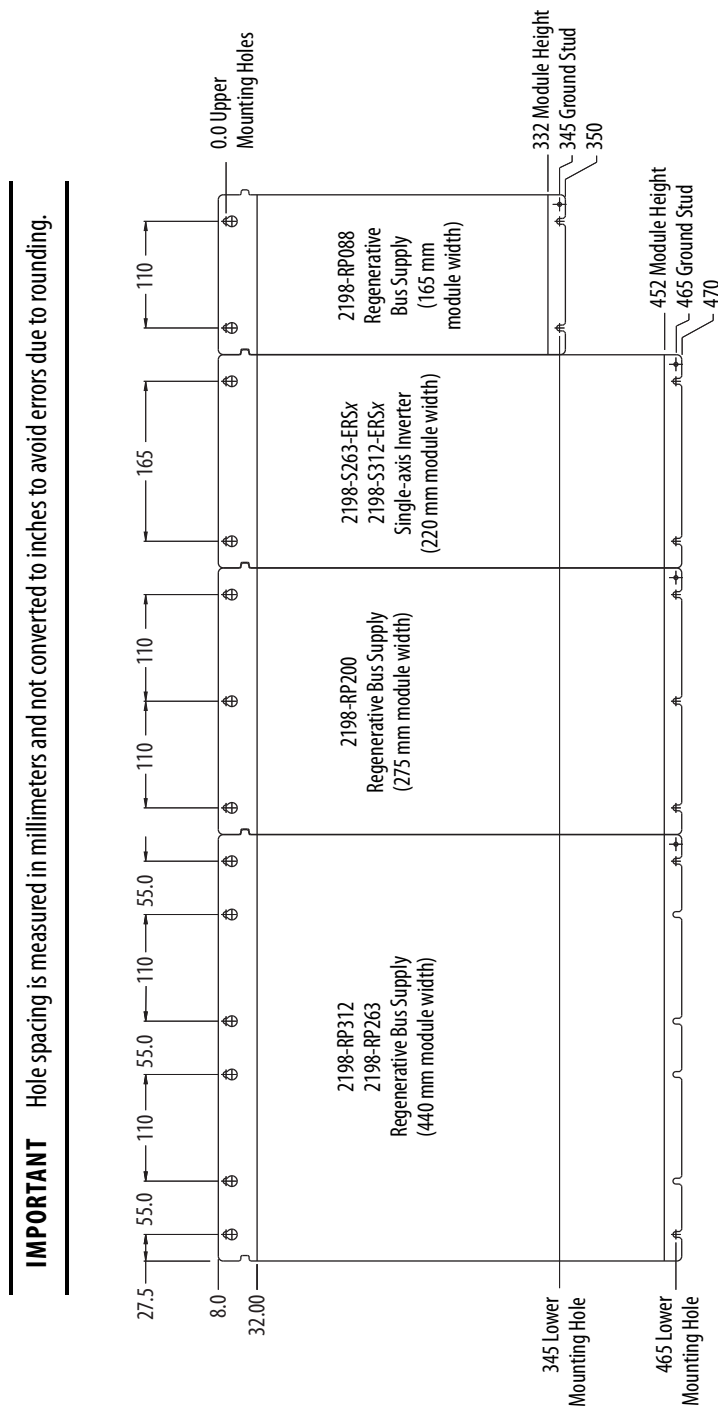


IMPORTANT Hole spacing is measured in millimeters and not converted to inches to avoid errors due to rounding.

Use [Figure 53](#) to calculate the left-to-right hole pattern for Kinetix 5700 drive system configurations that include the 2198-RPxxx regenerative bus supply.

Mounting holes for the Kinetix 5700 regenerative bus supply modules are based on 55 mm spacing, however, only the holes specified for each module are required.

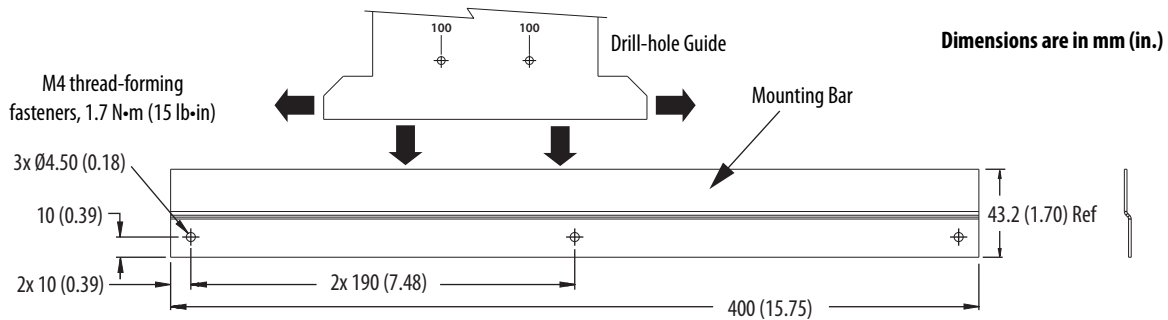
Figure 53 - Regenerative Bus Supply Mounting Hole Patterns



Drill-hole Patterns by Using the System Mounting Toolkit

The mounting bar must be mounted horizontally on the system panel. The drill-hole guide inserts behind the mounting bar and slides left and right. Holes and slots in the drill-hole guide let you establish the location of each Kinetix 5700 drive module.

Figure 54 - Mounting Bar



For step-by-step instructions on how to use the system mounting toolkit, see the Kinetix 5700 System Mounting Toolkit Installation Instructions, publication [2198-IN012](#).

Mount Your Kinetix 5700 Drive Modules

This procedure assumes that you have prepared your panel and understand how to bond your system. For installation instructions regarding other equipment and accessories, refer to the instructions that came with those products.

A hoist, straps, and J-hooks with a lockable clasp capable of supporting the maximum module weight are recommended for catalog numbers 2198-RP200, 2198-RP263, and 2198-RP312. For lifting instructions, see the Kinetix 5700 Regenerative Bus Supply Installation Instructions, publication [2198-IN014](#).

Follow these steps to mount your Kinetix 5700 drive modules to the panel.

1. Lay out the hole pattern for each drive module in the enclosure.

See [Establishing Noise Zones](#) on [page 70](#) for panel layout recommendations.

IMPORTANT To improve the bond between the drive modules and subpanel, construct your subpanel out of zinc plated (paint-free) steel.

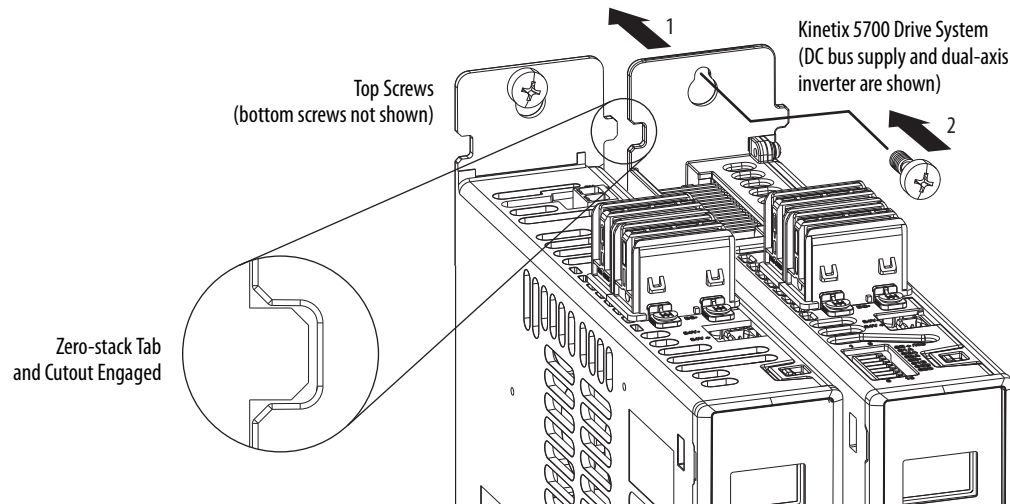
2. Drill holes in the panel for mounting your drive system.

Refer to [Drill-hole Patterns](#) beginning on [page 87](#).

3. Loosely attach the mounting hardware to the panel.

The recommended mounting hardware is M5 (#10-32) steel bolts. Observe bonding techniques as described in [Bonding Modules](#) on [page 67](#).

4. Attach the DC-bus supply (or supplies) or the regenerative bus supply to the cabinet panel.



5. Attach additional drive modules to the right or left of the previous module by using the same method, but also making sure that the zero-stack tabs and cutouts are engaged.

Zero-stack mounting is required for all configurations. See the [Zero-stack Tab and Cutout Example](#) on [page 84](#).

6. Tighten all mounting fasteners.

Apply 4.0 N•m (35.4 lb•in) maximum torque to each fastener.

Notes:

Connector Data and Feature Descriptions

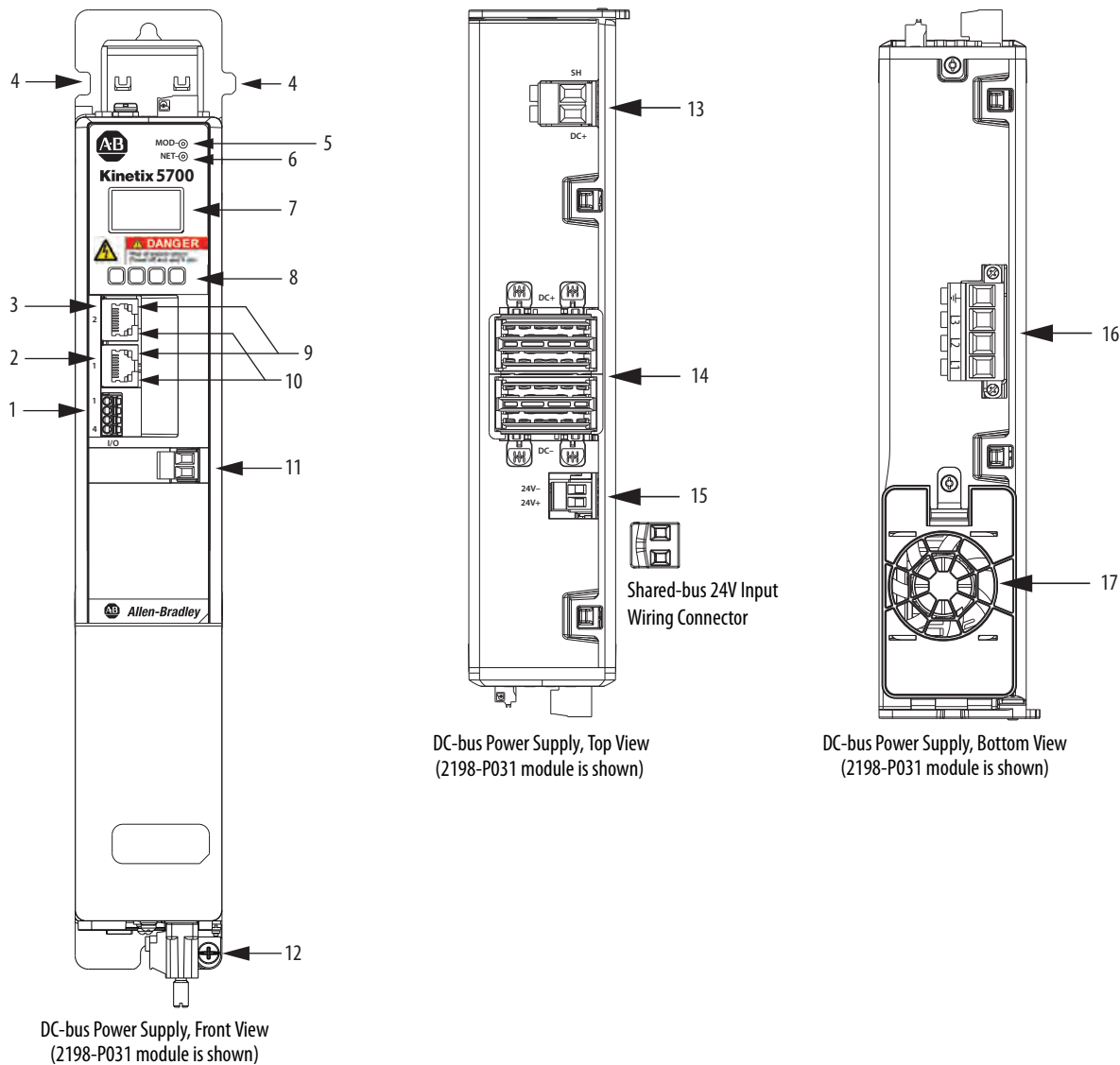
This chapter illustrates connectors and indicators for the Kinetix® 5700 drive system components, including the DC-bus power supply, regenerative bus supply, single-axis inverter, dual-axis inverter, and accessory modules. Also included in this chapter are connector pinouts and descriptions for Kinetix 5700 system components.

| Topic | Page |
|--|-------------|
| Kinetix 5700 Connector Data | 94 |
| Understand Control Signal Specifications | 108 |
| Feedback Specifications | 114 |
| Functional Safety Features | 126 |

Kinetix 5700 Connector Data

Use these illustrations to identify the connectors and indicators for the Kinetix 5700 drive modules.

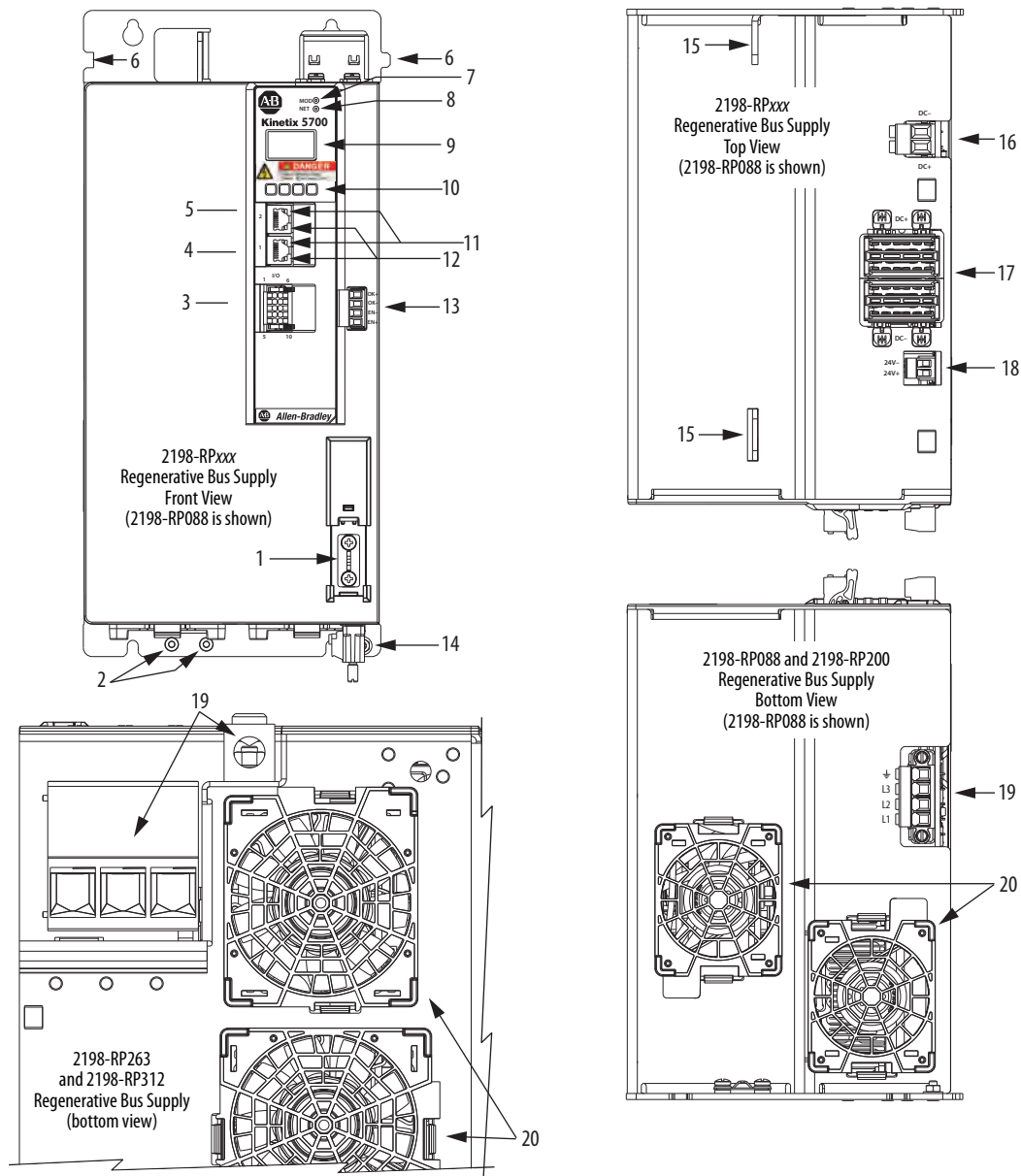
Figure 55 - DC-bus Power Supply Features and Indicators



| Item | Description |
|------|---------------------------------|
| 1 | Digital inputs (IOD) connector |
| 2 | Ethernet (PORT1) RJ45 connector |
| 3 | Ethernet (PORT2) RJ45 connector |
| 4 | Zero-stack mounting tab/cutout |
| 5 | Module status indicator |
| 6 | Network status indicator |

| Item | Description |
|------|----------------------------------|
| 7 | LCD display |
| 8 | Navigation pushbuttons |
| 9 | Link speed status indicators |
| 10 | Link/Activity status indicators |
| 11 | Contactor-enable (CED) connector |
| 12 | Ground terminal |

| Item | Description |
|------|--|
| 13 | Shunt resistor (RC) connector |
| 14 | DC bus (DC) connector |
| 15 | 24V control input power (CP) connector |
| 16 | AC Input power (IPD) connector |
| 17 | Cooling fan |

Figure 56 - Regenerative Bus Supply Features and Indicators

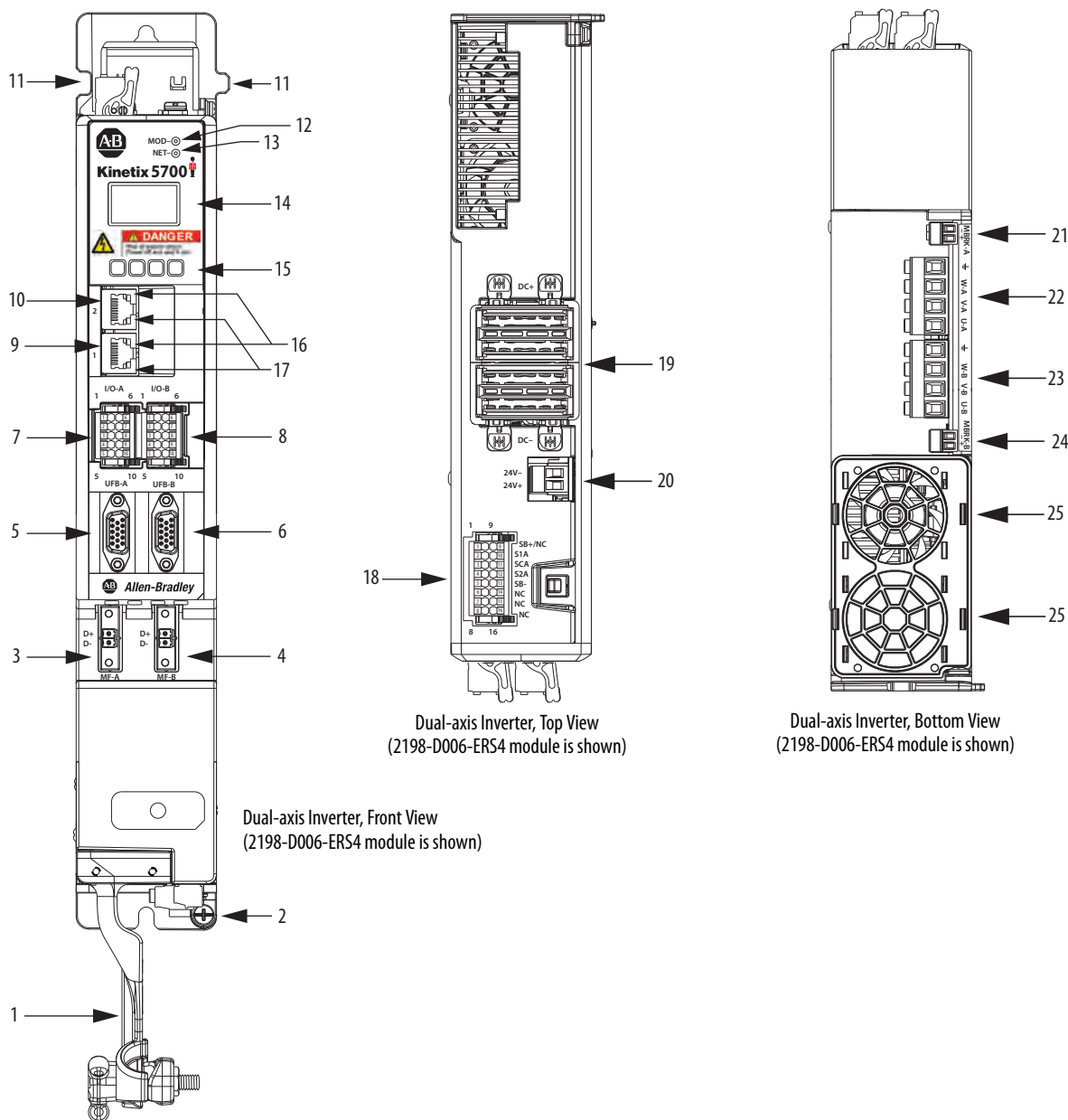
| Item | Description |
|------|---------------------------------|
| 1 | Ground jumper in operation |
| 2 | Ground jumper in storage |
| 3 | Digital inputs (IOD) connector |
| 4 | Ethernet (PORT1) RJ45 connector |
| 5 | Ethernet (PORT2) RJ45 connector |
| 6 | Zero-stack mounting tab/cutout |
| 7 | Module status indicator |

| Item | Description |
|------|---|
| 8 | Network status indicator |
| 9 | LCD display |
| 10 | Navigation push buttons |
| 11 | Link speed status indicators |
| 12 | Link/Activity status indicators |
| 13 | Contactant enable (CED) connector |
| 14 | Ground lug (partially obscured behind input plug) |

| Item | Description |
|------|---|
| 15 | Lifting points |
| 16 | Active shunt (RC) connector |
| 17 | DC bus (DC) connector |
| 18 | 24V control input power (CP) connector |
| 19 | AC Input power (IPD) connector ⁽¹⁾ |
| 20 | Cooling fans |

(1) Connector plug orientation applies to 2198-RP088 and 2198-RP200 modules (2198-RP200 connector size is larger). See adjacent figure for 2198-RP263 and 2198-RP312 connector plug size and orientation.

Figure 57 - Dual-axis Inverter Features and Indicators



| Item | Description |
|------|--|
| 1 | Motor cable clamp with spacers |
| 2 | Ground terminal |
| 3 | Motor feedback (MF) connector - A |
| 4 | Motor feedback (MF) connector - B |
| 5 | Universal feedback (UFB) connector - A |
| 6 | Universal feedback (UFB) connector - B |
| 7 | Digital inputs (IOD) connector - A |
| 8 | Digital inputs (IOD) connector - B |
| 9 | Ethernet (PORT1) RJ45 connector |

| Item | Description |
|------|---------------------------------|
| 10 | Ethernet (PORT2) RJ45 connector |
| 11 | Zero-stack mounting tab/cutout |
| 12 | Module status indicator |
| 13 | Network status indicator |
| 14 | LCD display |
| 15 | Navigation pushbuttons |
| 16 | Link speed status indicators |
| 17 | Link/Activity status indicators |
| 18 | Safe torque-off (STO) connector |

| Item | Description |
|------|--|
| 19 | DC bus (DC) connector |
| 20 | 24V control input power (CP) connector |
| 21 | Motor brake (BC) connector - A |
| 22 | Motor power (MP) connector - A |
| 23 | Motor power (MP) connector - B |
| 24 | Motor brake (BC) connector - B |
| 25 | Cooling fan |

Figure 58 - Single-axis Inverter Features (2198-S086-ERSx, 2198-S130-ERSx, 2198-S160-ERSx)

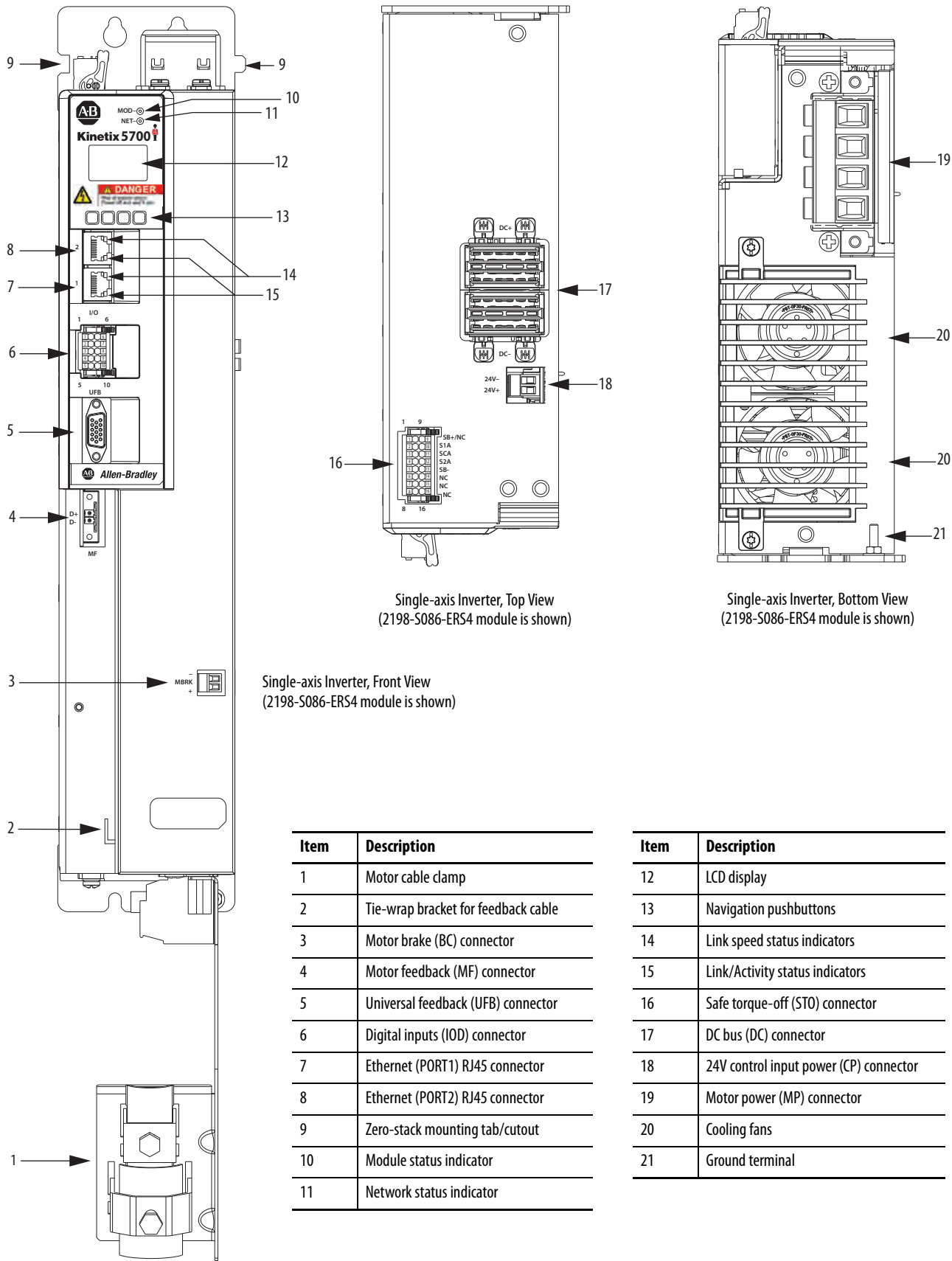
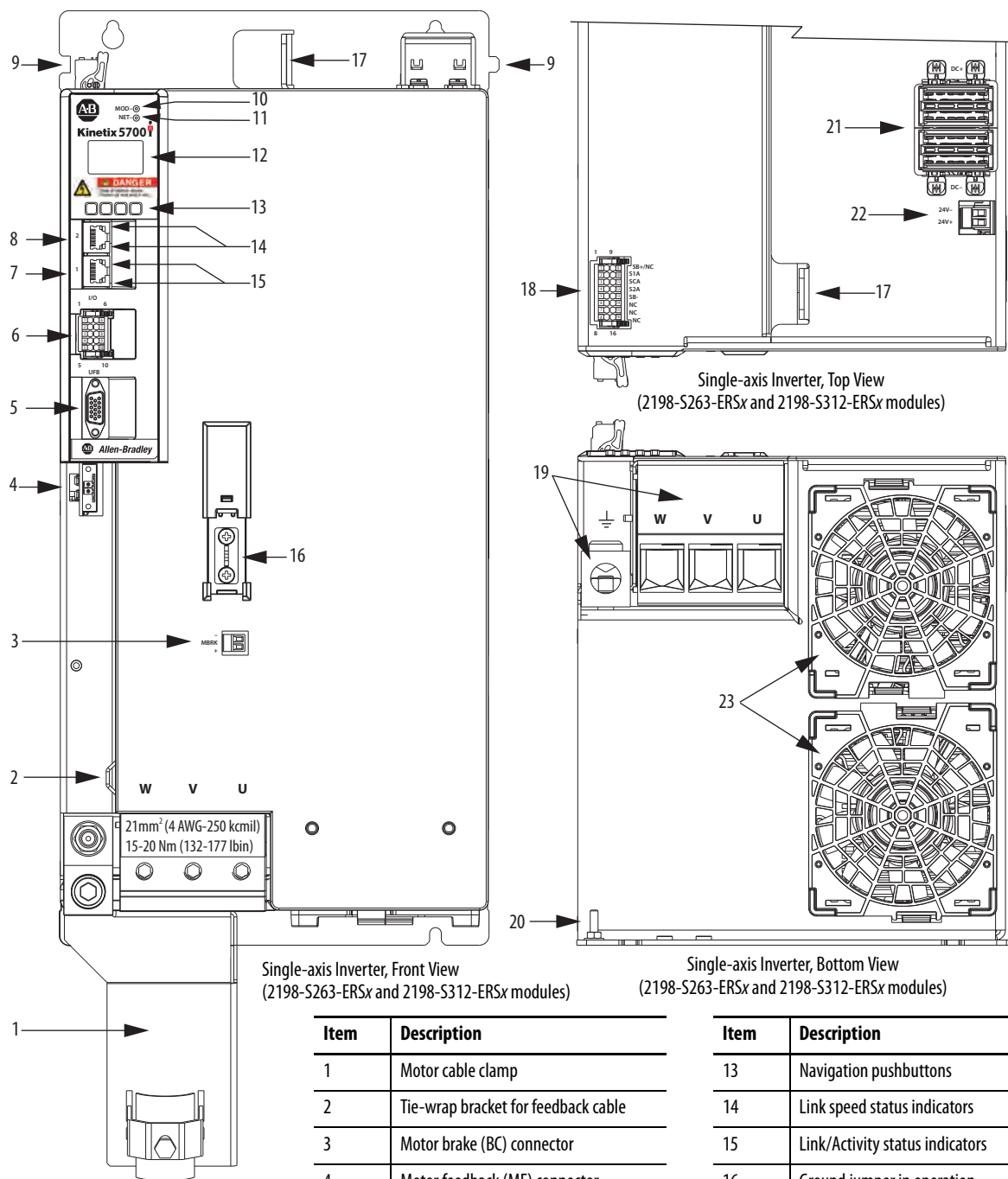
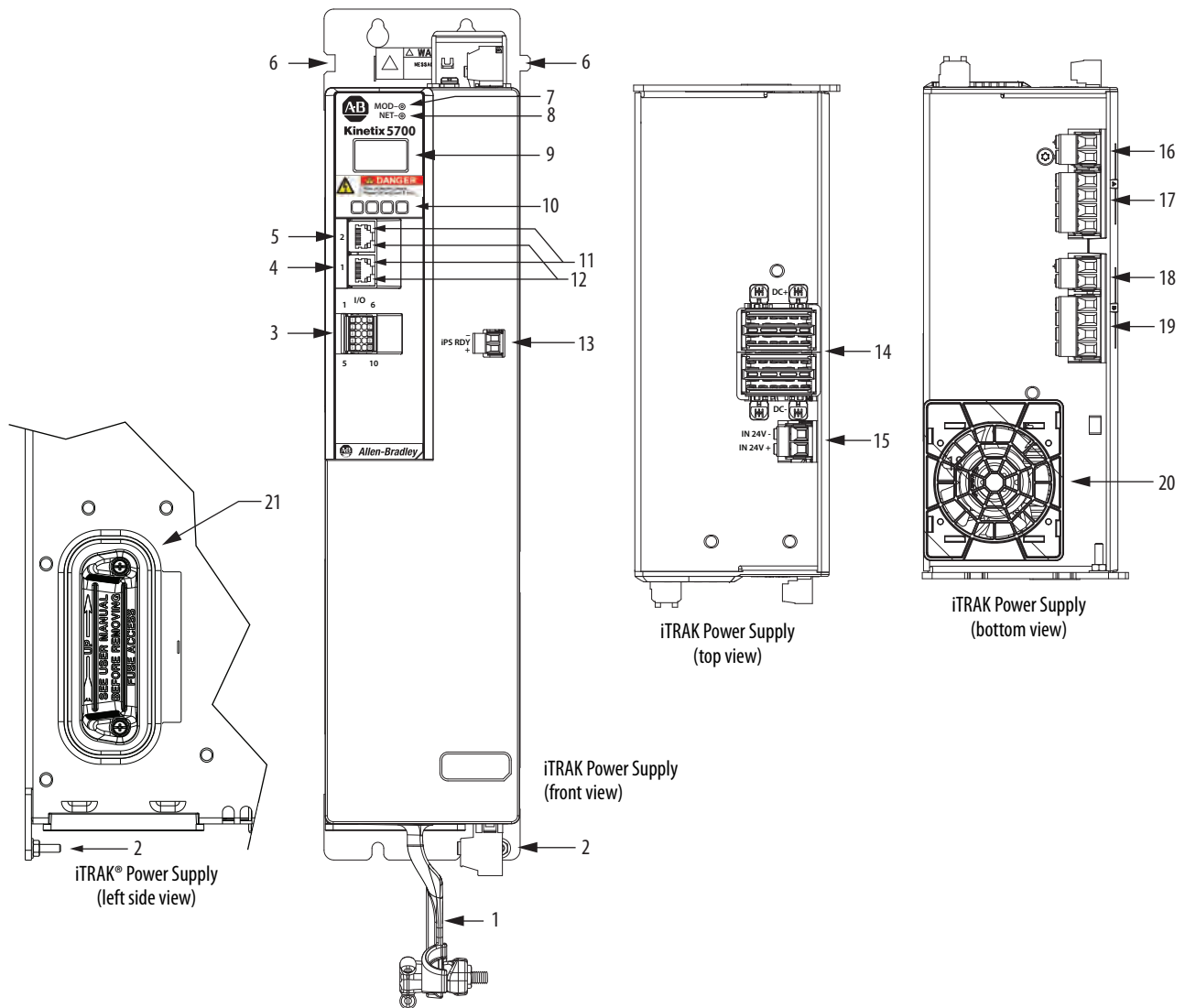


Figure 59 - Single-axis Inverter Features (2198-S263-ERSx, 2198-S312-ERSx)



| Item | Description |
|------|-------------------------------------|
| 1 | Motor cable clamp |
| 2 | Tie-wrap bracket for feedback cable |
| 3 | Motor brake (BC) connector |
| 4 | Motor feedback (MF) connector |
| 5 | Universal feedback (UFB) connector |
| 6 | Digital inputs (IOD) connector |
| 7 | Ethernet (PORT1) RJ45 connector |
| 8 | Ethernet (PORT2) RJ45 connector |
| 9 | Zero-stack mounting tab/cutout |
| 10 | Module status indicator |
| 11 | Network status indicator |
| 12 | LCD display |

| Item | Description |
|------|---|
| 13 | Navigation pushbuttons |
| 14 | Link speed status indicators |
| 15 | Link/Activity status indicators |
| 16 | Ground jumper in operation |
| 17 | Safe torque-off (STO) connector |
| 18 | Lifting points |
| 19 | Motor power (MP) connector |
| 20 | Ground terminal |
| 21 | DC bus (DC) connector |
| 22 | 24V control input power (CP) connector |
| 23 | Cooling fans (replacement kits available) |

Figure 60 - iTRAK Power Supply Features and Indicators

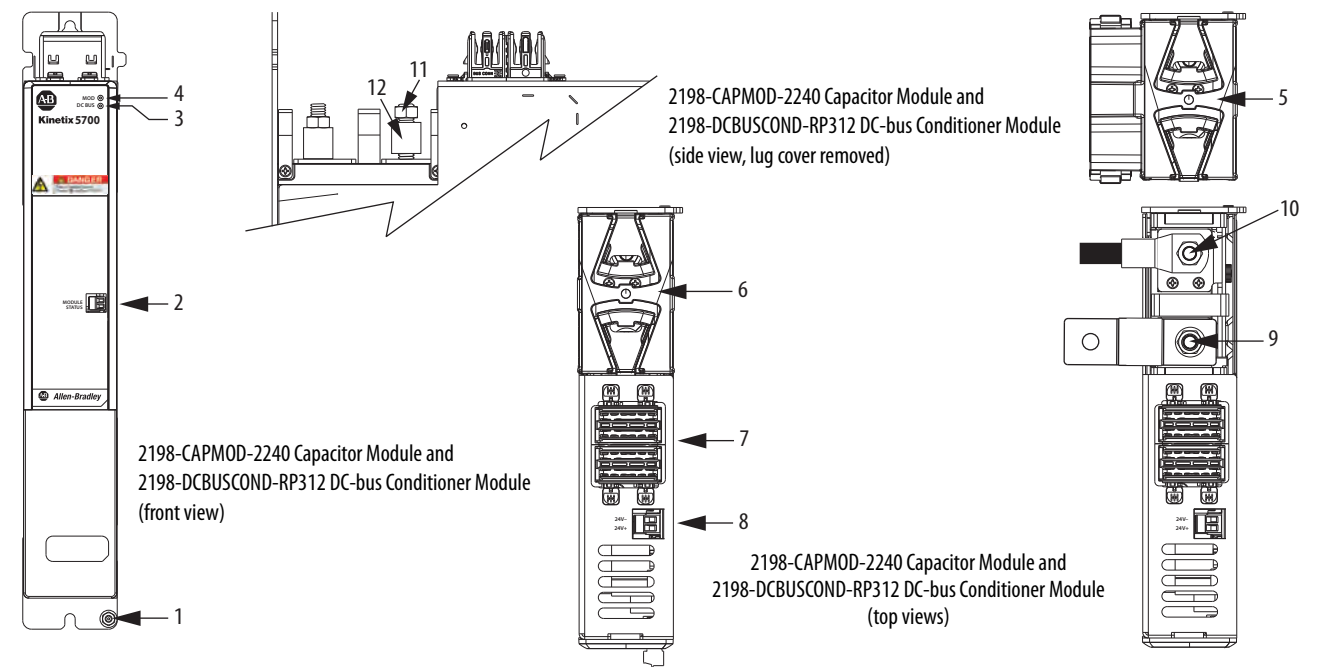
| Item | Description |
|------|---|
| 1 | Power bus cable clamp |
| 2 | Ground lug (partially obscured behind output plugs) |
| 3 | Digital inputs (IOD) connector |
| 4 | Ethernet (PORT1) RJ45 connector |
| 5 | Ethernet (PORT2) RJ45 connector |
| 6 | Zero-stack mounting tab/cutout |
| 7 | Module status indicator |

| Item | Description |
|------|---|
| 8 | Network status indicator |
| 9 | LCD display |
| 10 | Navigation push buttons |
| 11 | Link speed status indicators |
| 12 | Link/Activity status indicators |
| 13 | iTRAK power-supply ready (IR) connector |
| 14 | DC bus input (DC) connector |

| Item | Description |
|------|--|
| 15 | 24V control input power (CP) connector |
| 16 | 24V control output power (ICP) connector - A |
| 17 | DC bus output (IDC) connector - A |
| 18 | 24V control output power (ICP) connector - B |
| 19 | DC bus output (IDC) connector - B |
| 20 | Cooling fan |
| 21 | Power supply internal fuse |

IMPORTANT See the iTRAK System User Manual, publication [2198T-UM001](#), for IOD, IR, IDC, and ICP connector pinouts, and internal fuse information.

Figure 61 - Capacitor Module and DC-bus Conditioner Module Features and Indicators



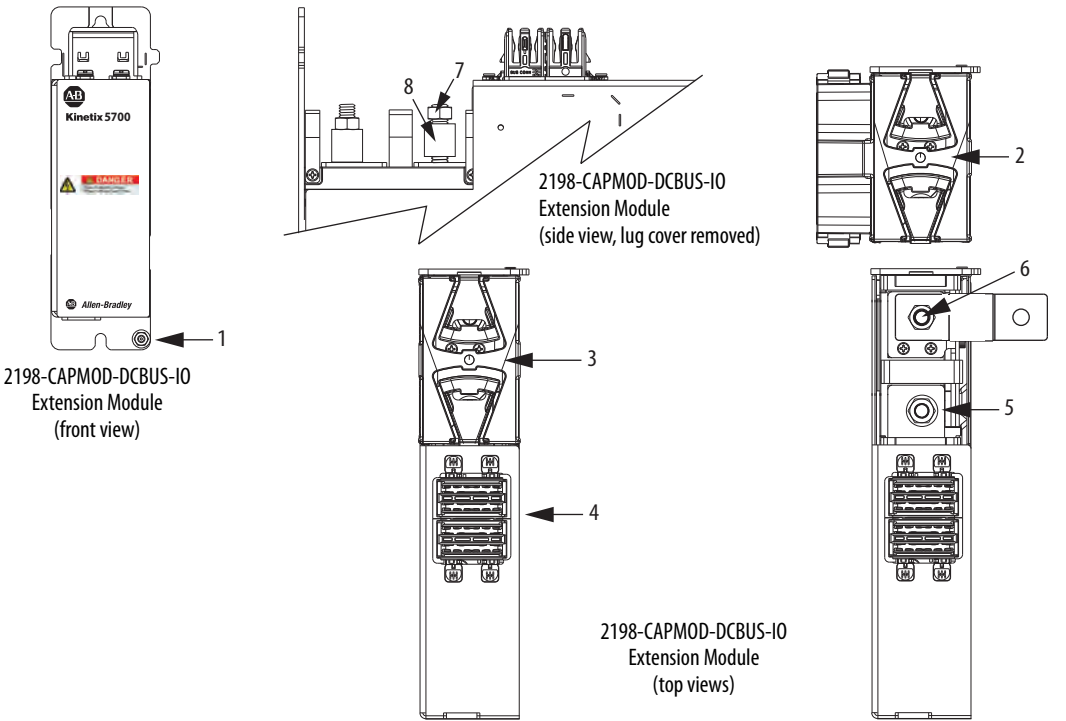
| Item | Description |
|------|------------------------------|
| 1 | Ground stud |
| 2 | Module status (MS) connector |
| 3 | DC-bus status indicator |
| 4 | Module status indicator |

| Item | Description |
|------|--|
| 5 | Stud/lug cover with wires ⁽¹⁾ |
| 6 | Stud cover without wires |
| 7 | DC-bus (DC) connector |
| 8 | 24V control input power (CP) connector |

| Item | Description |
|------|---|
| 9 | DC- M8 stud (external DC-bus), shown with flexible bus-bar ⁽²⁾ |
| 10 | DC+ M8 stud (external DC-bus), shown with wire lug |
| 11 | M8 hex nut |
| 12 | Lug spacer |

- (1) This example shows the lug cover oriented for wires exiting to the left (module is on the far left of the drive configuration). Rotate lug cover 180° when wires exit to the right (module is on the far right of the drive configuration).
- (2) Flexible bus-bars are included with only the 2198-CAPMOD-DCBUS-IO extension module. So, if you have two capacitor modules, two DC-bus conditioner modules, or a capacitor module and DC-bus conditioner module mounted side by side, you must order the 2198-KITCON-CAPMOD2240 or 2198-KITCON-DCBUSCOND connector set separately.

Figure 62 - Extension Module Features and Indicators



| Item | Description |
|------|--|
| 1 | Ground lug |
| 2 | Stud/lug cover with wires ⁽¹⁾ |
| 3 | Stud cover without wires |
| 4 | DC-bus (DC) connector |

| Item | Description |
|------|---|
| 5 | DC- M8 stud (external DC-bus) |
| 6 | DC+ M8 stud (external DC-bus), shown with flexible bus-bar ⁽²⁾ |
| 7 | M8 hex nut |
| 8 | Lug spacer |

(1) This example shows the lug cover oriented for wires exiting to the left (module is on the far left of drive configuration). Rotate lug cover 180° when wires exit to the right (module is on the far right of drive configuration).

(2) Flexible bus-bars are included with only the 2198-CAPMOD-DCBUS-IO extension module.

Safe Torque-off Connector Pinout

The hardwired safe torque-off (STO) connector pinouts apply to single-axis and dual-axis inverters. For feature descriptions and wiring information, refer to [Chapter 9](#) beginning on [page 317](#).

Input Power Connector Pinouts

Input power connectors include the AC input power (IPD) connector, contactor enable (CED) connector, and the 24V input power (CP) connector.

Table 30 - AC Input Power Connector



| IPD Pin | Description | Signal | Module |
|---|-------------------------|---|--|
|  | Chassis ground |  | <ul style="list-style-type: none"> DC-bus power supply Regenerative bus supply |
| L3 | Three-phase input power | L3 | |
| L2 | | L2 | |
| L1 | | L1 | |

Table 31 - 24V Input Power Connector

| CP Pin | Description | Signal | Module |
|--------|-------------------------------------|--------|--|
| 1 | 24V power supply, customer supplied | 24V+ | <ul style="list-style-type: none"> DC-bus power supply Regenerative bus supply Inverters Capacitor module DC-bus conditioner module iTRAK power supply |
| 2 | 24V common | 24V– | |

Table 32 - Contactor Enable Connector

| CED Pin | Description | Signal | Module |
|---------|---|----------|--|
| OK+ | Relay-driven contact that provides a 24V signal to non-Kinetix 5700 inverters indicating that they can draw power from the regenerative power supply. This signal is intended for use with Kinetix 6000, Kinetix 7000, or PowerFlex® drive migration. | CONV OK+ | Regenerative bus supply |
| OK– | | CONV OK– | |
| EN– | Relay-driven contact that is used in the control string for a three-phase power contactor. | CONT EN– | <ul style="list-style-type: none"> DC-bus power supply Regenerative bus supply |
| EN+ | | CONT EN+ | |

DC Bus and Shunt Resistor Connector Pinouts

The 2198-Pxxx DC-bus power supply RC connector wires to an external passive shunt when the internal shunt capacity is exceeded. The 2198-RPxxx regenerative bus supply has no internal shunt and the RC connector wires to an external active shunt.

Table 33 - DC Bus Power Connector

| DC Pin | Description | Signal | Module |
|---------|--------------------|--------|--|
| Bus bar | DC bus connections | DC– | <ul style="list-style-type: none"> DC-bus power supply Regenerative bus supply Inverters Accessory modules iTRAK power supply |
| | | DC+ | |

Table 34 - Shunt Connector

| RC Pin | Description | Signal | Module |
|--------|---------------------------|--------|-------------------------|
| 1 | Passive shunt connections | SH | DC-bus power supply |
| 2 | | DC+ | |
| 1 | Active shunt connections | DC– | Regenerative bus supply |
| 2 | | DC+ | |

Digital Inputs Connector Pinouts

The DC-bus power supply has two configurable digital inputs and four configurable functions to choose from in the Logix Designer application.

Table 35 - DC-bus Power Supply Digital Input Pinouts

| IOD Pin | Description | Signal | Module |
|---------|---|--------|---------------------|
| 1 | 24V current sinking fast input #1 | IN1 | DC-bus power supply |
| 2 | I/O common for customer-supplied 24V supply | COM | |
| 3 | 24V current sinking fast input #2 | IN2 | |
| 4 | I/O cable shield termination | SHLD | |

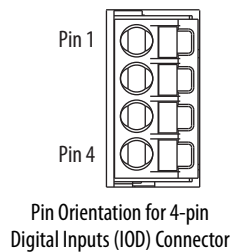
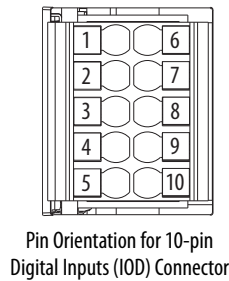


Table 36 - DC-bus Power Supply Configurable Functions

| Default Configuration | Description |
|--|-------------------------|
| Digital input1 = Enable Digital input2 = Unassigned | Unassigned |
| | Enable |
| | Bus Capacitor OK |
| | Shunt Thermal Switch OK |
| | Bus Conditioner OK |

Single-axis inverters, dual-axis inverters, and the regenerative bus supply have four configurable digital inputs with fast response times and ten configurable functions to choose from in the Logix Designer application.

Table 37 - Inverter and Regenerative Bus Supply Digital Input Pinouts



| IOD Pin | Description | Signal | Module |
|---------|---|--------|--|
| 1 | 24V current sinking fast input #1 | IN1 | <ul style="list-style-type: none"> Inverters Regenerative bus supply |
| 2 | I/O common for customer-supplied 24V supply | COM | |
| 3 | 24V current sinking fast input #2 | IN2 | |
| 4 | I/O common for customer-supplied 24V supply | COM | |
| 5 | Chassis ground | SHLD | |
| 6 | 24V current sinking fast input #3 | IN3 | |
| 7 | I/O common for customer-supplied 24V supply | COM | |
| 8 | 24V current sinking fast input #4 | IN4 | |
| 9 | I/O common for customer-supplied 24V supply | COM | |
| 10 | Chassis ground | SHLD | |

Table 38 - Inverter Configurable Functions

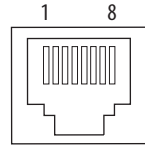
| Default Configuration | Description |
|--|-------------------------|
| Digital input1 = Enable Digital input2 = Home Digital input3 = Registration 1 Digital input4 = Registration 2 | Unassigned |
| | Enable |
| | Home |
| | Registration 1 |
| | Registration 2 |
| | Positive overtravel |
| | Negative overtravel |
| | Regeneration OK |
| | Bus Capacitor OK |
| | Shunt Thermal Switch OK |
| | Bus Conditioner OK |

Table 39 - Regenerative Bus Supply Configurable Functions

| Default Configuration | Description |
|--|-------------------------|
| Digital input1 = Enable Digital input2 = AC Line Contactor OK Digital input3 = Unassigned Digital input4 = Unassigned | Unassigned |
| | Enable |
| | Bus Capacitor OK |
| | Shunt Thermal Switch OK |
| | AC Line Contactor OK |
| | Bus Conditioner OK |

Ethernet Communication Connector Pinout



| Pin | Description | Signal | Module |
|-----|-------------|--------|---|
| 1 | Transmit+ | TD+ | <ul style="list-style-type: none"> • DC-bus power supply • Regenerative bus supply • Inverters • iTRAK power supply |
| 2 | Transmit– | TD– | |
| 3 | Receive+ | RD+ | |
| 4 | Reserved | – | |
| 5 | Reserved | – | |
| 6 | Receive– | RD– | |
| 7 | Reserved | – | |
| 8 | Reserved | – | |



Motor Power, Brake, and Feedback Connector Pinouts

These connector pinouts apply to the single-axis and dual-axis inverter.

Table 40 - Motor Power Connector

| MP Pin | Description | Signal | Color |
|---|-------------------------|---|-------|
| U | Three-phase motor power | U | Brown |
| V | | V | Black |
| W | | W | Blue |
|  | Chassis ground |  | Green |



ATTENTION: To avoid damage to the Kinetix 5700 system power supply and inverter, make sure the motor power signals are wired correctly. Refer to [Figure 100](#) and [Figure 101](#) beginning on [page 153](#) for connector wiring examples.

IMPORTANT Drive-to-motor power cables must not exceed 90 m (295 ft), depending on feedback type and overall system design. See [Appendix D](#), beginning on [page 401](#), for more information.

System performance was tested at this cable length. These limitations also apply when meeting CE requirements.

Table 41 - Motor Brake Connector

| BC Pin | Description | Signal |
|--------|-------------------------|--------|
| 1 | Motor brake connections | MBRK+ |
| 2 | | MBRK– |

Motor Feedback Connector Pinouts

These connector pinouts apply to the single-axis and dual-axis inverter.

Table 42 - DSL Feedback Connector

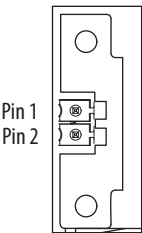
| MF Pin | Description | Signal |
|--------|---|--------|
| 1 | Bidirectional data and power for digital encoder interface | D+ |
| 2 | | D- |
| SHIELD | Cable shield and grounding plate (internal to 2198-KITCON-DSL connector kit) termination point. | SHIELD |
| | Cable shield and shield clamp (internal to 2198-H2DCK converter kit) termination point | |

IMPORTANT

Drive-to-motor power cables must not exceed 90 m (295 ft), depending on feedback type and overall system design. See [Appendix D](#), beginning on [page 401](#), for more information.

System performance was tested at these cable length specifications. These limitations also apply when meeting CE requirements.

Figure 63 - Pin Orientation for 2-pin DSL Feedback (MF) Connector



Universal Feedback Connector Pinouts

These connector pinouts apply to the single-axis and dual-axis inverter.

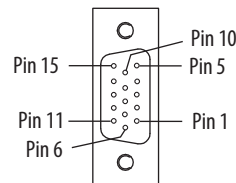
Table 43 - Stegmann Hiperface and TTL Sine/Cosine Universal Feedback Connector

| UFB Pin | Description | Signal | UFB Pin | Description | Signal |
|---------|--|---------------------------|---------|--|---------------------------|
| 1 | Sine differential input + A differential input + | MTR_SIN+ MTR_AM+ | 9 | Clock output + | MTR_CLK+ |
| 2 | Sine differential input– A differential input– | MTR_SIN– MTR_AM– | 10 | Data differential input/output – Index differential input – | MTR_DATA- MTR_IM– |
| 3 | Cosine differential input + B differential input + | MTR_COS+ MTR_BM+ | 11 | Motor thermostat (normally closed) ⁽²⁾ | MTR_TS |
| 4 | Cosine differential input – B differential input – | MTR_COS– MTR_BM– | 12 | Hall commutation S1 input | MTR_S1 |
| 5 | Data differential input/output + Index differential input + | MTR_DATA+ MTR_IM+ | 13 | Hall commutation S2 input | MTR_S2 |
| 6 | Encoder common | MTR_ECOM | 14 | Encoder 5V power output | MTR_EPWR5V ⁽¹⁾ |
| 7 | Encoder 9V power output | MTR_EPWR9V ⁽¹⁾ | 15 | Clock output – | MTR_CLK– |
| 8 | Hall commutation S3 input | MTR_S3 | | | |

(1) Determine which power supply your encoder requires and connect to only the specified supply. Do not make connections to both supplies.

(2) Not applicable unless motor has integrated thermal protection.

Figure 64 - Pin Orientation for 15-pin Universal Feedback (UFB) Connector



Accessory Module Pinouts

The module status (MS) connector applies to capacitor modules and DC-bus conditioner modules.

Table 44 - Module Status Connector

| MS Pin | Description | Signal |
|--------|----------------------|--------|
| 1 | Module status output | MS |
| 2 | | MS |

Understand Control Signal Specifications

This section provides a description of the Kinetix 5700 digital inputs, Ethernet communication, power and relay specifications, encoder feedback specifications, and safe torque-off features.

Digital Inputs

Digital inputs are available for the machine interface on the IOD connector. Two for the DC-bus power supply, four for the single-axis inverter, four per axis for the dual-axis inverters, and four for the regenerative bus supply. Digital inputs require a 24V DC @ 15 mA supply. These are sinking inputs that require a sourcing device. A common connection is provided on the IOD connector for each of the digital inputs.

IMPORTANT To improve registration input EMC performance, refer to the System Design for Control of Electrical Noise Reference Manual, publication [GMC-RM001](#).

Table 45 - Understand Digital Input Functions

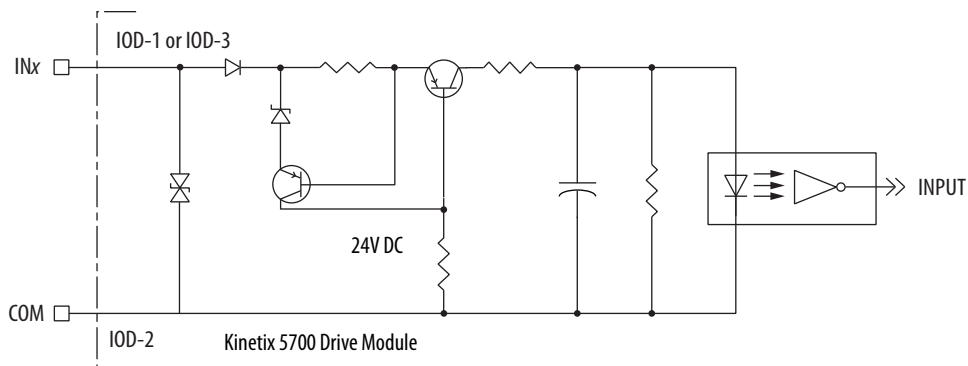
| Functions | Description ⁽²⁾ | 2198-Pxxx | 2198-xxx-ERSx | 2198-RPxxx |
|--|--|-----------|---------------|------------|
| Enable | A 24V DC input is applied to this terminal as a condition to enable each module. | X | X | X |
| Home | An active state indicates to a homing sequence that the referencing sensor has been seen. Typically, a transition of this signal is used to establish a reference position for the machine axis. | – | X | – |
| Registration 1 | An inactive-to-active transition (also known as a positive transition) or active-to-inactive transition (also known as a negative transition) is used to latch position values for use in registration moves. | – | X | – |
| Registration 2 | | – | X | – |
| Positive Overtravel Negative Overtravel | The positive/negative limit switch (normally closed contact) inputs for each axis require 24V DC (nominal). | – | X | – |
| Regeneration OK ⁽¹⁾ | In the active state the inverters can be enabled. An inactive state indicates that the Bulletin 8720MC-RPS unit is not ready to supply DC-bus power. The inverters cannot be enabled. When a bus group is supplied by an 8720MC-RPS unit, one inverter in the bus group must be configured in the Logix Designer application as Shared-DC Non-CIP Motion™ Converter and assigned to Regeneration OK. This signal is wired from RDY on the 8720MC-RPS unit and indicates to the Kinetix 5700 drive system that the 8720MC-RPS unit is ready to supply power. Enabled inverters enumerate a Bus Power Sharing fault if the Regeneration OK input goes inactive. | – | X | – |
| Shunt Thermal Switch OK | When the 2198-R014, 2198-R031, or 2198-R127 external shunt resistor is wired to the DC-bus power supply, this input must be configured in the Logix Designer application to monitor the status of the external shunt module thermal switch and assigned to Shunt thermal switch OK. This function does not apply to the 2198-R004 shunt resistor. You can also use this input to monitor the status of an active shunt module in DC-bus power supply systems that are connected via the capacitor module or extension module, or in regenerative bus supply systems that are connected via the RC connector or an accessory module. | X | X | X |
| Bus Capacitor OK | You can configure this input in the Logix Designer application and wire the module status (MS) output from the 2198-CAPMOD-2240 capacitor module to indicate to the DC-bus power supply, regenerative bus supply, or inverters that a major fault is present on the capacitor module. | X | X | X |
| Bus Conditioner OK | You can configure this input in the Logix Designer application and wire the module status (MS) output from the 2198-DCBUSCOND-RP312 DC-bus conditioner module to indicate to the DC-bus power supply, regenerative bus supply, or inverters that a major fault is present on the DC-bus conditioner module. | X | X | X |
| AC Line Contactor OK | You can configure this input in the Logix Designer application to tell the 2198-RPxxx regenerative bus supply that the main AC line contactor has closed and is sending L1...L3 AC line voltage. This is accomplished by wiring an auxiliary Normally Open contact off the main M1 contactor into one of the regenerative bus supply digital inputs. | – | – | X |

(1) For more information on configuring a Shared-bus Non-CIP Motion Converter, refer to [step 1](#) on [page 217](#). For more information on wiring the 8720MC-RPS unit, refer to [Figure 177](#) on [page 356](#).

(2) The function is always inactive unless assigned to a digital input in the Logix Designer application. To configure your DC-bus power supply digital input for Shunt Thermal Switch OK or Bus capacitor OK, refer to [step 11](#) on [page 205](#). To configure your regenerative bus supply digital input for Bus Conditioner OK or AC Line Contactor OK, refer to [step 11](#) on [page 209](#).

Table 46 - Digital Input Specifications

| Attribute | Value | Drive Module | | |
|--|--|--------------|---------------|------------|
| | | 2198-Pxxx | 2198-xxx-ERSx | 2198-RPxxx |
| Digital input type | Optically isolated, active high, single-ended, current sinking (EN 61131-2 Type 1) | X | X | X |
| Input current (with 24V applied) | 12 mA, typical | X | X | X |
| On-state input voltage | 15...30V @ 15 mA, max | X | X | X |
| Off-state input voltage | -1.0...5.0V | X | X | X |
| Pulse reject filtering (applies to registration function only) | 12.0 μ s | — | X | — |
| Pulse reject filtering (debounce filter) Applies to all other input functions, Home, for example. | 20 ms, nom | X | X | X |
| Propagation delay (registration functions, inverters only) | 0 (delay compensated) | — | X | — |
| Registration accuracy (inverters only) | ± 3 μ s | — | X | — |
| Registration repeatability (inverters only) | 700 ns | — | X | — |
| Windowed registration invalid-to-valid event delay (inverters only) | 125 μ s, min | — | X | — |

Figure 65 - Digital Input Circuitry

Ethernet Communication Specifications

The PORT1 and PORT2 (RJ45) Ethernet connectors provide communication with the Logix 5000™ controller.

| Attribute | Value |
|--|---|
| Communication | The drive auto-negotiates speed and duplex modes. These modes can be forced through the Logix Designer application. 100BASE-TX, full duplex is recommended for maximum performance. |
| Cyclic update period ⁽¹⁾ | 1.0 ms, min |
| Embedded switch features | Three-port, cut-through, time correction on IEEE-1588 packets, limited filtering, quality of service with four priority levels |
| Auto MDI/MDIX crossover detection/correction | Yes |
| Port-to-port time synchronization variation | 100 ns, max |
| Cabling | CAT5e shielded, 100 m (328 ft) max |

(1) With CIP Security™ enabled on the 2198-Pxxx DC-bus power supply, the cyclic update period cannot be faster than 4.0 ms.

Contactor Enable Relay

The contactor-enable circuitry includes a relay-driven contact within the 2198-Pxxx DC-bus power supply and 2198-RPxxx regenerative bus supply. The relay protects the Kinetix 5700 drive system in the event of overloads or other fault conditions.

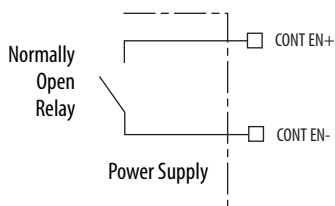
An AC three-phase mains contactor must be wired in series between the branch circuit protection and the power supply. In addition, the AC three-phase contactor control string must be wired in series with the contactor-enable relay at the contactor-enable (CED) connector. Refer to [Power Wiring Examples](#) on [page 343](#) for wiring examples.



ATTENTION: Wiring the contactor-enable relay is required. To avoid personal injury or damage to the drive, wire the contactor-enable relay into your control string so that:

- three-phase power is removed and the power supply is protected under various fault conditions.
- three-phase power is never applied to the Kinetix 5700 drive system before control power is applied.

Figure 66 - Contactor-enable Relay Circuit



Surge suppression (diode, varistor module, RC module, or DC electronic interface) is required across the auxiliary and main contactor coils.

Table 47 - Regenerative Bus Supply (CED) Relay Output Specifications

| Attribute | Value | Nominal | Maximum |
|---------------------|---|--------------|---------|
| On-state current | Current flow when the relay is closed. | — | 1 A |
| On-state resistance | Contact resistance when the relay is closed. | 0.1 Ω | — |
| Off-state voltage | Voltage across the contacts when the relay is open. | 24V DC | 28V DC |

Table 48 - DC-bus Power Supply (CED) Relay Output Specifications

| Attribute | Value | Nominal | Maximum |
|---------------------|---|--------------|---------|
| On-state current | Current flow when the relay is closed. | — | 1 A |
| On-state resistance | Contact resistance when the relay is closed. | 1.0 Ω | — |
| Off-state voltage | Voltage across the contacts when the relay is open. | 24V DC | 28V DC |

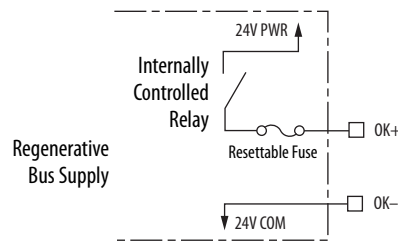
Converter OK Relay

The converter OK circuitry includes a relay-driven contact within the 2198-RPxxx regenerative bus supply. The relay provides a 24V signal to non-Kinetix 5700 inverters indicating that they can draw power from the regenerative power supply and that the power supply is not faulted.

TIP This signal is intended for use with Kinetix 6000, Kinetix 6200, Kinetix 6500 Kinetix 7000, or PowerFlex drives when migrating from the 8720MC-RPS to the 2198-RPxxx regenerative bus supply.

Refer to [Power Wiring Examples](#) on [page 343](#) for wiring examples.

Figure 67 - Converter OK Relay Circuit



Current limited output with auto-resettable fuse.

Table 49 - Converter OK Relay Output Specifications

| Attribute | Value | Min | Max |
|-------------------|---|-----|--------|
| On-state current | Current flow when the relay is closed. | — | 0.8 A |
| Off-state voltage | Voltage across the contacts when the relay is open or closed. | — | 0V DC |
| On-state voltage | | — | 24V DC |

Motor Brake Circuit

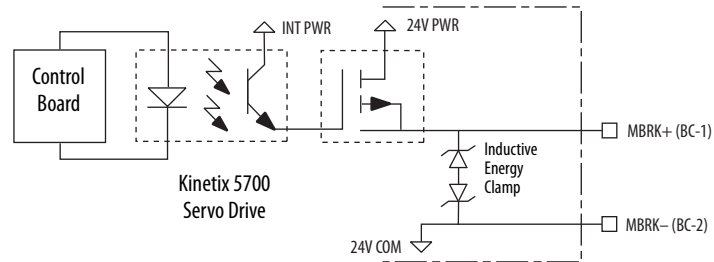
The brake option is a spring-set holding brake that releases when voltage is applied to the brake coil in the motor. The customer-supplied 24V power supply drives the brake output through a solid-state relay. The dual-axis inverters have separate brake circuits for each axis. The solid-state brake driver circuit provides the following:

- Brake current-overload protection
- Brake over-voltage protection

For a detailed information on vertical loads and how the servo motor holding-brake option can be used to help keep a load from falling, see the Vertical Load and Holding Brake Management Application Technique, publication [MOTION-AT003](#).

Two connections (BC-1 and BC-2) are required for the motor brake output (refer to [Figure 68](#)). Connections are rated for 2.0 A @ +24V (dual-axis inverters) and 5.0 A @ +24V (single-axis inverters).

Figure 68 - Motor Brake Circuit



IMPORTANT Motor holding-brake switching frequency must not exceed 10 cycles/min.

Control of the solid-state relay to release the motor brake is configurable in the Logix Designer application (refer to [Configure SPM Motor Closed-loop Control Axis Properties](#) on [page 245](#)). An active signal releases the motor brake. Turn-on and turn-off delays are specified by the MechanicalBrakeEngageDelay and MechanicalBrakeReleaseDelay settings.

IMPORTANT Holding brakes that are available on Allen-Bradley® rotary motors are designed to hold a motor shaft at 0 rpm for up to the rated brake-holding torque, not to stop the rotation of the motor shaft, or be used as a safety device.

You must command the servo drive to 0 rpm and engage the brake only after verifying that the motor shaft is at 0 rpm.

These steps provide one method you can use to control a brake.

1. Wire the mechanical brake according to the appropriate interconnect diagram in [Appendix A](#) beginning on [page 362](#).
2. Enter the MechanicalBrakeEngageDelay and MechanicalBrakeReleaseDelay times in the Logix Designer application.
Refer to Axis Properties>Parameter List. The delay times must be from the appropriate motor family brake specifications table in the Kinetix Rotary Motion Specifications Technical Data, publication [KNX-TD001](#).
3. Use the drive stop-action default setting (Current Decel & Disable).
Refer to Axis Properties>Actions>Stop Action in the Logix Designer application.
4. Use the motion instruction Motion Axis Stop (MAS) to decelerate the servo motor to 0 rpm.
5. Use the motion instruction Motion Servo Off (MSF) to engage the brake and disable drive.

Control Power

The Kinetix 5700 drive modules require 24V DC (21.6...26.4V) input power for control circuitry.

IMPORTANT SELV or PELV rated power supplies must be used to energize external safety devices connected to the Kinetix 5700 safety inputs.

The National Electrical Code and local electrical codes take precedence over the values and methods provided. Implementation of these codes is the responsibility of the machine builder.

Table 50 - Control Power Current Specifications

| Drive Module | Drive Module Cat. No. | 24V Current Per Module (non-brake motor) A _{DC} | 24V Current, max (with maximum brake current) A _{DC} | 24V Inrush Current ⁽⁵⁾ A |
|-----------------------------------|----------------------------|--|---|--|
| DC-bus Power Supplies | 2198-P031 | 0.8 | — | 4.0 |
| | 2198-P070 | | | |
| | 2198-P141 | 1.9 | | |
| | 2198-P208 | | | |
| Regenerative Bus Supplies | 2198-RP088 | 4.3 | — | 4.0 |
| | 2198-RP200 | 5.4 | | |
| | 2198-RP263 | 9.1 | | |
| | 2198-RP312 | | | |
| Dual-axis Inverters | 2198-D006-ERS _x | 1.4 ⁽²⁾ | 5.5 ⁽³⁾ | 4.0 |
| | 2198-D012-ERS _x | | | |
| | 2198-D020-ERS _x | 1.7 ⁽²⁾ | 7.7 ⁽³⁾ | |
| | 2198-D032-ERS _x | | 8.3 ⁽³⁾ | |
| | 2198-D057-ERS _x | | | |
| Single-axis Inverters | 2198-S086-ERS _x | 4.6 | 9.6 ⁽⁴⁾ | 4.0 |
| | 2198-S130-ERS _x | | | |
| | 2198-S160-ERS _x | | | |
| | 2198-S263-ERS _x | | | |
| | 2198-S312-ERS _x | | | |
| iTRAK Power Supply ⁽¹⁾ | 2198T-W25K-ER | 1.3 | — | 2.2 |
| Capacitor Module | 2198-CAPMOD-2240 | 0.1 | — | 7.0 |
| Extension Module | 2198-CAPMOD-DCBUS-IO | — | | — |
| DC-bus Conditioner Module | 2198-DCBUSCOND-RP312 | 0.1 | | 7.0 |

(1) These values represent only the iTRAK power supply. They do not include the iTRAK motor modules that are connected to the iTRAK power supply and also draw current from this 24V control power input. For more information regarding 24V control power requirements, see the iTRAK System User Manual, publication [2198T-UM001](#).

(2) Values are base current per module.

(3) Values assume two brake motors, each drawing the maximum rating of 2 A, are attached to each module.

(4) Values assume the maximum rated brake current of 5 A.

(5) Inrush current duration is less than 30 ms.

Feedback Specifications

The Kinetix 5700 drives accept motor feedback signals from Stegmann Hiperface digital-servo-link (DSL) encoders on the motor feedback (MF) connector and Hiperface, incremental, and EnDat encoders on the universal feedback (UFB) connector.

IMPORTANT Auto-configuration in the Logix Designer application of intelligent absolute, high-resolution encoders, incremental, and EnDat encoders is possible with only Allen-Bradley motors.

The MF and UFB connectors can be used in the following applications:

- Motor feedback
- Auxiliary feedback-only axis
- Dual-loop control applications

Encoder Feedback Supported on the DSL Feedback Connector

The Kinetix 5700 drives support Kinetix VPL, VPC-Q, VPF, VPH, and VPS servo motors with Stegmann Hiperface digital-servo-link (DSL) encoders by using the 2-pin (MF) feedback connector.

Other Allen-Bradley motors and actuators with Stegmann Hiperface single-turn or multi-turn high-resolution absolute encoders are also accepted. However, to connect these devices to the MF connector, you must also use the 2198-H2DCK Hiperface-to-DSL (series B or later) converter kit for Hiperface-to-DSL feedback conversion. Alternatively, you can use the universal (UFB) feedback connector for those motors and actuators.

Encoder Feedback Supported on the UFB Feedback Connector

The Kinetix 5700 drives also support multiple types of feedback devices by using the 15-pin (UFB) universal feedback connector and sharing connector pins in many cases. Use the 2198-K57CK-D15M universal feedback connector kit for terminating the feedback conductors.

Table 51 - Universal Feedback General Specifications

| Attribute | Motor Feedback | Auxiliary Feedback |
|--|--|--|
| Feedback device support | <ul style="list-style-type: none"> • Stegmann Hiperface • Generic TTL Incremental • Generic Sine/Cosine Incremental • Heidenhain EnDat Sin/Cos ⁽¹⁾ • Heidenhain EnDat Digital ⁽²⁾ | <ul style="list-style-type: none"> • Stegmann Hiperface • Generic TTL Incremental • Generic Sine/Cosine Incremental • Heidenhain EnDat Sin/Cos ⁽¹⁾ • Heidenhain EnDat Digital ⁽²⁾ |
| Power supply voltage (MTR_EPWR5V) Power supply current (MTR_EPWR5V) | 5.27...5.50V 300 mA, max | |
| Power supply voltage (MTR_EPWR9V) Power supply current (MTR_EPWR9V) | 8.30...9.90V 150 mA, max | |
| Thermostat | Single-ended, under 500 Ω = no fault, over 10 k Ω = fault | Single-ended, under 500 Ω = no fault, over 10 k Ω = fault |

(1) EnDat sine/cosine encoders support only Kinetix RDB direct-drive motors.

(2) EnDat digital encoders support VPC-Bxxxxx-Y motors and applicable third-party motors as described in [Table 57](#) on [page 121](#).

Table 52 - Universal Feedback Signals by Device Type

| UFB Pin | Stegmann HiPerface | Generic TTL Incremental | Generic Sine/Cosine Incremental | Heidenhain EnDat Sine/Cosine | Heidenhain EnDat Digital |
|---------|---------------------------|----------------------------|------------------------------------|---------------------------------|-----------------------------|
| 1 | MTR_SIN+ | MTR_AM+ | MTR_SIN+ | ENDAT_B+ | — |
| 2 | MTR_SIN— | MTR_AM— | MTR_SIN— | ENDAT_B— | — |
| 3 | MTR_COS+ | MTR_BM+ | MTR_COS+ | ENDAT_A+ | — |
| 4 | MTR_COS— | MTR_BM— | MTR_COS— | ENDAT_A— | — |
| 5 | MTR_DATA+ | MTR_IM+ | MTR_IM+ | MTR_DATA+ | MTR_DATA+ |
| 6 | MTR_ECOM | MTR_ECOM | MTR_ECOM | MTR_ECOM | MTR_ECOM |
| 7 | MTR_EPWR9V ⁽¹⁾ | — | — | MTR_EPWR9V ⁽¹⁾ | MTR_EPWR9V ⁽¹⁾ |
| 8 | — | MTR_S3 | MTR_S3 | — | — |
| 9 | — | — | — | MTR_CLK+ | MTR_CLK+ |
| 10 | MTR_DATA— | MTR_IM— | MTR_IM— | MTR_DATA— | MTR_DATA— |
| 11 | MTR_TS | MTR_TS | MTR_TS | MTR_TS | MTR_TS |
| 12 | — | MTR_S1 | MTR_S1 | — | — |
| 13 | — | MTR_S2 | MTR_S2 | — | — |
| 14 | MTR_EPWR5V ⁽¹⁾ | MTR_EPWR5V | MTR_EPWR5V | MTR_EPWR5V ⁽¹⁾ | MTR_EPWR5V ⁽¹⁾ |
| 15 | — | — | — | MTR_CLK— | MTR_CLK— |

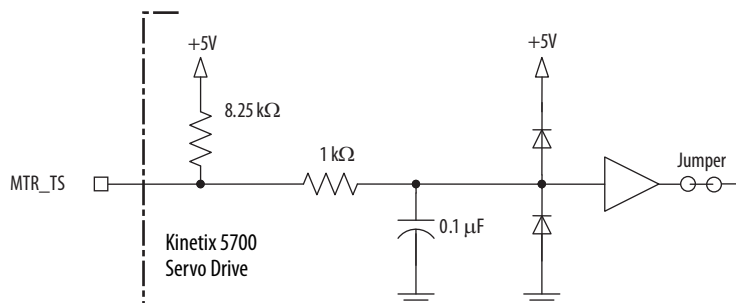
(1) Determine which power supply your encoder requires and connect to only the specified supply. Do not make connections to both supplies.



ATTENTION: To avoid damage to components, determine which power supply your encoder requires and connect to either the 5V or 9V supply, but not both.

This is the motor thermostat interface schematic. Although the thermostat signal is shown for all feedback types, some motors may not support this feature because it is not part of the feedback device.

Figure 69 - Motor Thermostat Interface



Stegmann Hiperface Feedback

Figure 70 - Stegmann Hiperface Interface, MTR_SIN and MTR_COS Signals

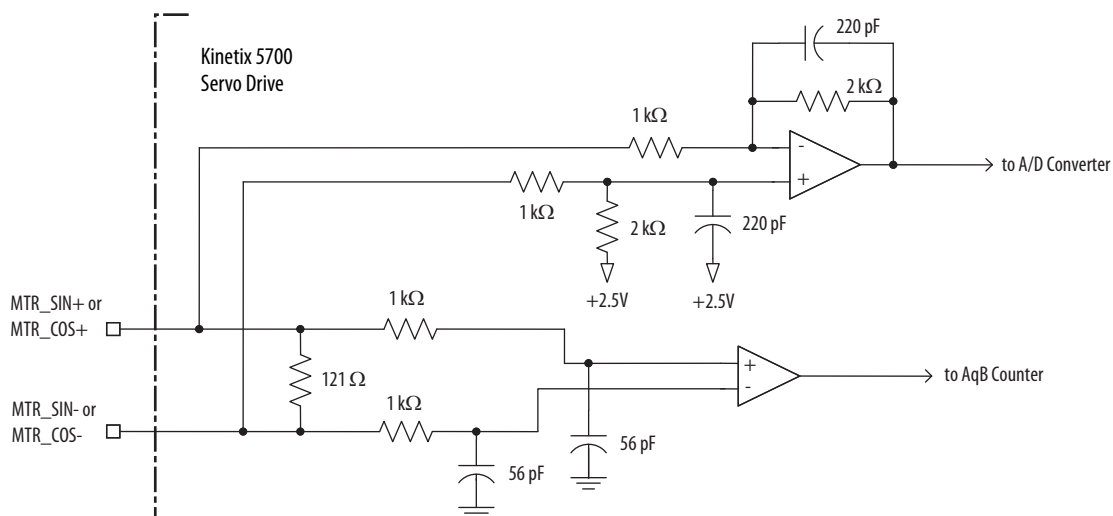
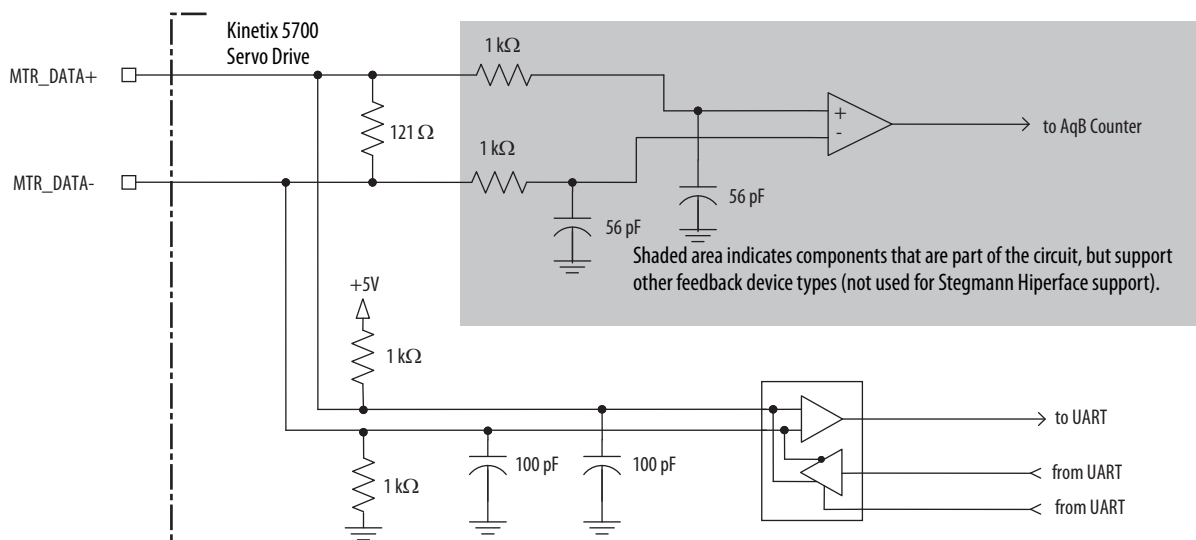


Figure 71 - Stegmann Hiperface Interface, MTR_DATA Signals



*Generic TTL Feedback***Table 53 - Generic TTL Incremental Specifications**

| Attribute | Value |
|---|---|
| TTL incremental encoder support | 5V, differential A quad B |
| Quadrature interpolation | 4 counts / square wave period |
| Differential input voltage (MTR_AM, MTR_BM, and MTR_IM) | 5V DC, differential line driver (DLD) output compatible |
| DC current draw (MTR_AM, MTR_BM, and MTR_IM) | 30 mA, max |
| Input signal frequency (MTR_AM, MTR_BM, and MTR_IM) | 5.0 MHz, max |
| Edge separation (MTR_AM and MTR_BM) | 42 ns min, between any two edges |
| Commutation verification | Commutation angle verification performed at the first Hall signal transition and periodically verifies thereafter |
| Hall inputs (MTR_S1, MTR_S2, and MTR_S3) | Single-ended, TTL, open collector, or none |

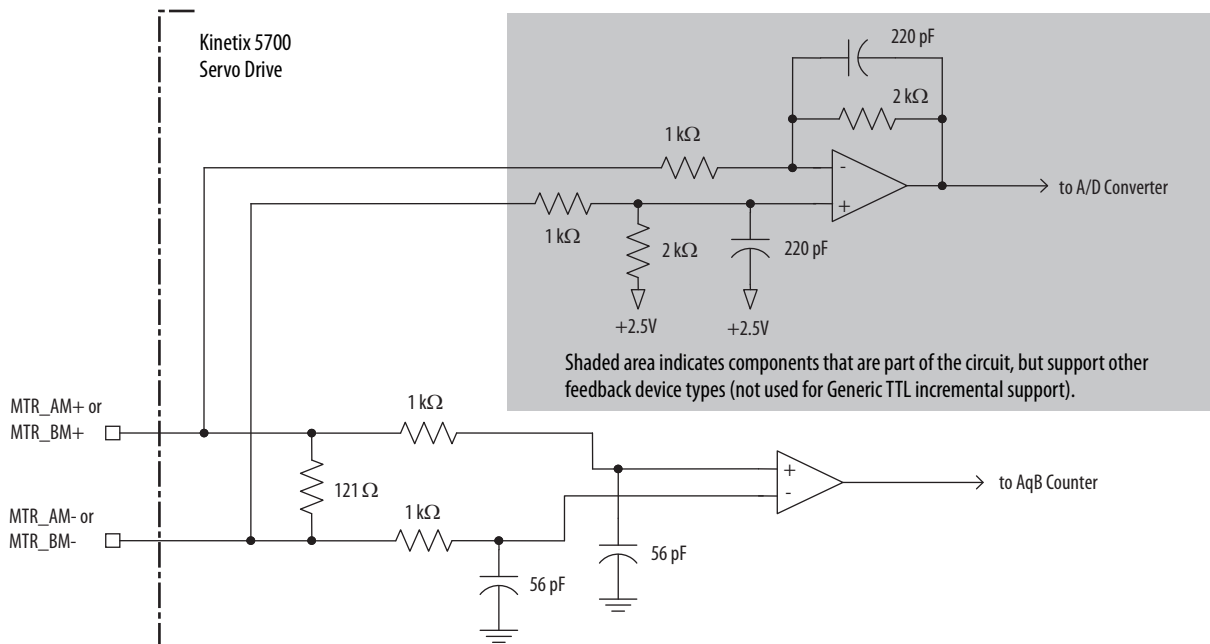
Figure 72 - Generic TTL Incremental, MTR_AM and MTR_BM Signals

Figure 73 - Generic TTL Interface, MTR_IM Signals

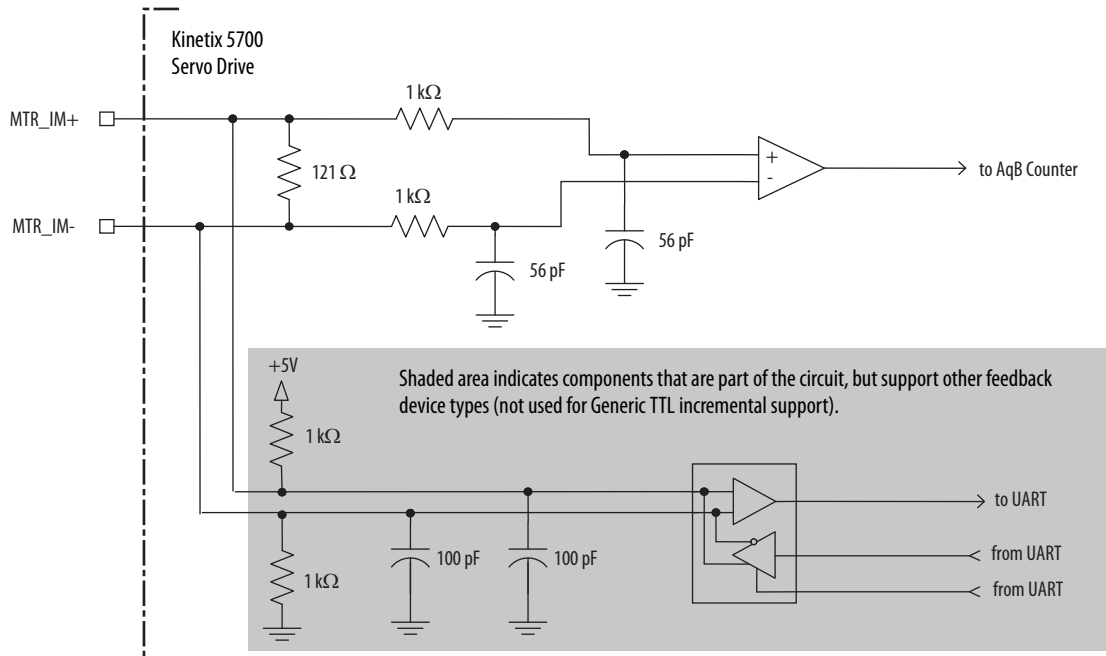
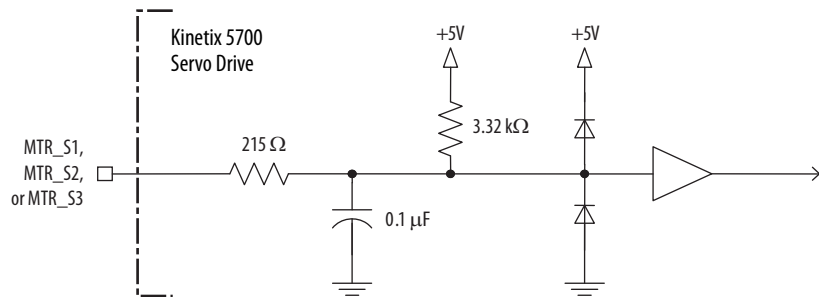


Figure 74 - Generic TTL Interface, MTR_S1, MTR_S2, or MTR_S3 Signals



*Generic Sine/Cosine Feedback***Table 54 - Generic Sine/Cosine Incremental Specifications**

| Attribute | Value |
|---|---|
| Sine/Cosine interpolation | 2048 counts/sine wave period |
| Input frequency (MTR_SIN and MTR_COS) | 250 kHz, max |
| Differential input voltage (MTR_SIN and MTR_COS) | 0.6...1.2V, p-p |
| Commutation verification | Commutation angle verification performed at the first Hall signal transition and periodically verifies thereafter |
| Hall inputs (MTR_S1, MTR_S2, and MTR_S3) | Single-ended, TTL, open collector, or none |

Refer to [page 117](#) for the generic sine/cosine interface schematic. It is identical to the Stegmann Hiperface (MTR_AM and MTR_BM) signal schematic.

Refer to [page 118](#) for the Hall (MTR_S1, MTR_S2, and MTR_S3) signal schematic.

Refer to [Encoder Phasing Definitions](#) on [page 123](#) for encoder phasing alignment diagrams.

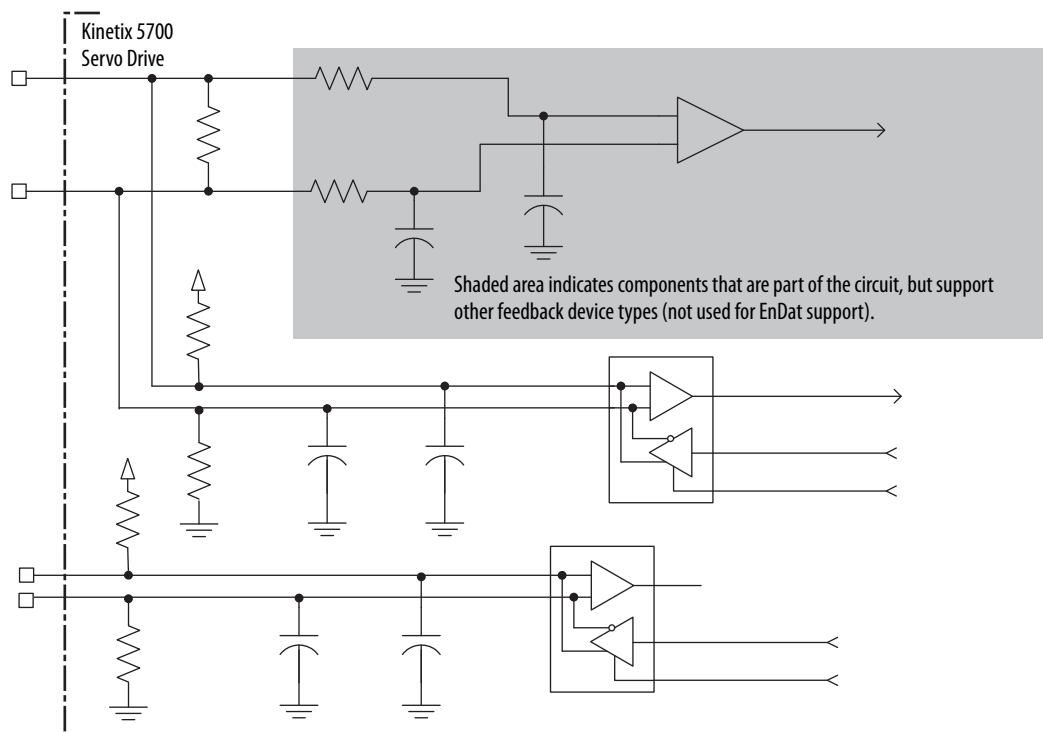
EnDat Sine/Cosine Feedback

Table 55 - EnDat Sine/Cosine Interface Specifications

| Attribute | Value |
|--|---|
| Protocol | EnDat Sine/Cosine |
| EnDat Sine/Cosine data communication | 2 Mbps, synchronous |
| Sine/Cosine interpolation | 2048 counts/sine wave period |
| Input frequency (MTR_SIN and MTR_COS) | 250 kHz, max |
| Differential input voltage (MTR_SIN and MTR_COS) | 0.6...1.2V, p-p |
| Incremental position verification | Position compare between incremental accumulator and serial data performed every 50 ms or less. |

Refer to [page 116](#) for the EnDat sine/cosine interface schematic. It is identical to the Stegmann Hipurface (MTR_SIN and MTR_COS) schematic.

Figure 75 - EnDat Sin/Cos and EnDat Digital Interface Schematic for Serial Communication



*EnDat Digital Feedback***Table 56 - EnDat Digital Interface Specifications**

| Attribute | Value |
|----------------------------------|---------------------|
| EnDat Digital data communication | 4 Mbps, synchronous |

Table 57 - Support Requirements for EnDat Encoders

| Requirement | EnDat Sine/Cosine | EnDat Digital |
|-------------------------|--|---|
| Supported models | LC 483 ECI 119 ⁽¹⁾ ECN 113 ECN 1313/EQN 1325 ECN 413/EQN 425 ROQ 425 | LIC 4000 ECI 119 ⁽¹⁾ ROQ 437 ECN 1123/ EQN 1135 ECN 1325 / EQN 1337 ECI 1319/EQI 1331 ECI 1118/EQI 1130 ECN 125 |
| Position initialization | Digital | |
| Position tracking | Uses sine/cosine signals | Digital |
| Data frequency | 100 kHz | 4.125 MHz |
| Sine/cosine frequency | 0...250 kHz | — |

(1) ECI119 can be procured from Heidenhain as either EnDat Sin/Cos or EnDat Digital.

IMPORTANT To properly support system EnDat feedback, the keying configuration in drive Module Properties of the Logix Designer application must be selected to use Kinetix 5700 drive firmware revision 5.0 or later.

IMPORTANT Unprogrammed Smart feedback devices (Hiperface Sin/Cos, Hiperface DSL, EnDat Sin/Cos, and EnDat Digital) are not supported. Unprogrammed as load or feedback-only feedback types are supported. Contact your local distributor or Rockwell Automation representative for support options.

Auxiliary Feedback Specifications

The Kinetix 5700 inverters support multiple types of feedback devices by using the 15-pin (UFB) connector and sharing connector pins in many cases. Refer to [Configure Feedback-only Axis Properties](#) on [page 230](#) to use these in your application.

Table 58 - Auxiliary Feedback Signals by Device Type

| UFB Pin | Stegmann Hiperface | Generic TTL Incremental | Generic Sine/Cosine Incremental | Heidenhain EnDat Sin/Cos | Heidenhain EnDat Digital |
|---------|---------------------------|-------------------------|---------------------------------|---------------------------|---------------------------|
| 1 | AUX_SIN+ | AUX_AM+ | AUX_SIN+ | ENDAT_B+ | — |
| 2 | AUX_SIN- | AUX_AM- | AUX_SIN- | ENDAT_B- | — |
| 3 | AUX_COS+ | AUX_BM+ | AUX_COS+ | ENDAT_A+ | — |
| 4 | AUX_COS- | AUX_BM- | AUX_COS- | ENDAT_A- | — |
| 5 | AUX_DATA+ | AUX_IM+ | AUX_IM+ | AUX_DATA+ | AUX_DATA+ |
| 6 | AUX_ECOM | AUX_ECOM | AUX_ECOM | AUX_ECOM | AUX_ECOM |
| 7 | AUX_EPWR9V ⁽¹⁾ | — | — | AUX_EPWR9V ⁽¹⁾ | AUX_EPWR9V ⁽¹⁾ |
| 9 | — | — | — | AUX_CLK+ | AUX_CLK+ |
| 10 | AUX_DATA- | AUX_IM- | AUX_IM- | AUX_DATA- | AUX_DATA- |
| 14 | AUX_EPWR5V ⁽¹⁾ | AUX_EPWR5V | AUX_EPWR5V | AUX_EPWR5V ⁽¹⁾ | AUX_EPWR5V ⁽¹⁾ |
| 15 | — | — | — | AUX_CLK- | AUX_CLK- |

(1) Determine which power supply your encoder requires and connect to only the specified supply. Do not make connections to both supplies.



ATTENTION: To avoid damage to components, determine which power supply your encoder requires and connect to either the 5V or 9V supply, but not both.

Specifications for the auxiliary feedback channel are identical to the motor feedback channel, except for specifications related to commutation and BLOB programming.

The 9.0V and 5.0V power supplies for auxiliary feedback devices are shared with the motor feedback channel, and the total current capability is outlined in the table on [page 114](#).

Allen-Bradley Bulletin 842HR, 844D, 847H, and 847T encoders are the preferred encoders for auxiliary feedback connections.

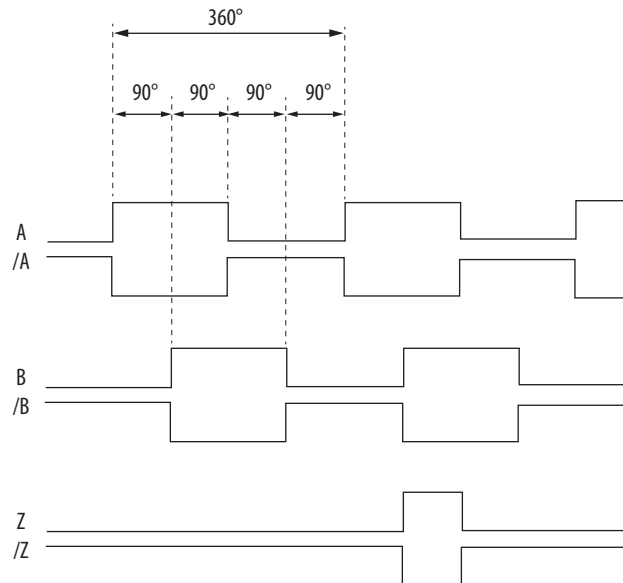
Table 59 - Allen-Bradley Auxiliary Feedback Encoders

| Cat. No. | Description |
|---|---|
| 842HR-MJDZ115FWYD (multi-turn) 842HR-SJDZ115FWYD (single-turn) | Size 25, sine/cosine (serial), square flange, 3/8 in. solid shaft with flat, 5...12V DC, digital RS-485 interface, M23, 17-pin connector |
| 844D-B5CC1FW 844D-B5CC1CS 844D-B5CC1DR | HS35, hollow-shaft incremental encoders, rear (through-shaft), 5/8 inch, tether, 3/8 in. bolt on a 2.5...4.0 in. diameter, 10-pin connector, 5V DC in, 5V DC DLD out |
| 847H-DN1A-RH01024 847H-DN1A-RH02048 847H-DN1A-RH05000 | Size 25, incremental encoder, standard square flange, 3/8 inch diameter shaft with flat, 4.5...5.5V line driver, TTL (B-Leads-A, CW, Z gated with BN), MS connector, 10-pin |
| 847T-DN1A-RH01024 847T-DN1A-RH02048 | Size 20, incremental encoder, standard square flange, 3/8 inch diameter shaft with flat, 4.5...5.5V line driver, TTL (B-Leads-A, CW, Z gated with BN), MS connector, 10-pin |

Refer to the Kinetix Motion Accessories Technical Data, publication [KNX-TD004](#), for more information on these Allen-Bradley encoders.

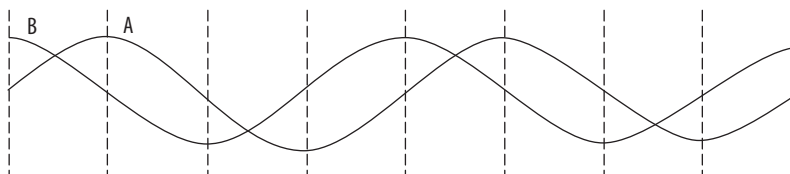
Encoder Phasing Definitions

For TTL encoders, the drive position increases when A leads B. Clockwise motor rotation is assumed, when looking at the shaft.

Figure 76 - TTL Encoder Phasing

For Sin/Cos encoders (Stegmann Hiperface and Heidenhain EnDat), the drive position increases when Cosine (B) leads Sine (A). Clockwise motor rotation is assumed, when looking at the shaft.

Figure 77 - Sine/Cosine Encoder Phasing



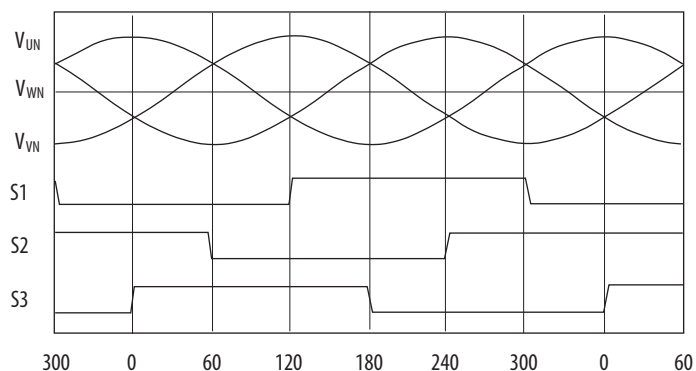
IMPORTANT The Sine/Cosine encoder signal phasing is different than the TTL encoder signal phasing.

IMPORTANT When using an incremental Sine/Cosine feedback device, the drive cannot synthesize a marker signal, so a physical marker signal is required for the home-to-marker sequence (and the marker hookup test) to complete.

When using absolute feedback devices (for example, Stegmann Hiperface) the drive synthesizes a marker signal because these devices don't have a marker signal required for the home-to-marker sequence (and the marker hookup test) to complete.

The drive UFB feedback connector uses Hall signals to initialize the commutation angle for permanent magnet motor commutation.

Figure 78 - Hall Encoder Phasing



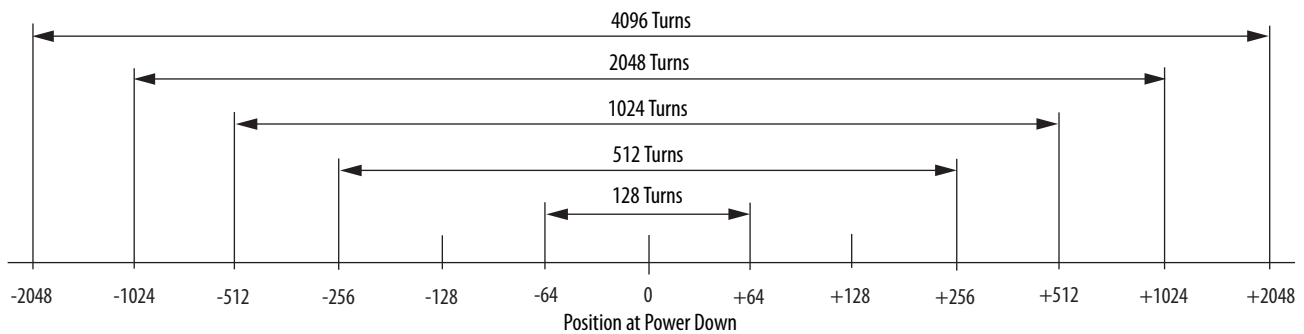
Absolute Position Feature

The absolute position feature tracks the position of the motor, within the multi-turn retention limits, while the drive is powered off. The absolute position feature is available with only multi-turn encoders.

Table 60 - Absolute Position Retention Limits

| Encoder Type | Cat. No. Designator | Motor Cat. No. | Actuator Cat. No. | Retention Limits | |
|-------------------------------------|---------------------|--|--|---------------------|-------------|
| | | | | Turns (rotary) | mm (linear) |
| Stegmann Hiperface (DSL) | -P | VPL-A/Bxxxxx-P VPF-A/Bxxxxx-P VPS-Bxxxxx-P | VPAR-A/Bxxxxx-P | 4096 (± 2048) | — |
| | -W | VPL-A/Bxxxxx-W, VPF-A/Bxxxxx-W VPH-A/Bxxxxx-W | VPAR-Bxxxxx-W | 4096 (± 2048) | — |
| | -Q | VPL-A/Bxxxxx-Q VPC-Bxxxxx-Q VPF-A/Bxxxxx-Q VPH-A/Bxxxxx-Q | VPAR-Bxxxxx-Q | 512 (± 256) | — |
| Stegmann Hiperface | -M | VPC-B3004x-M MPL-A/Bxxxxx-M MPM-A/Bxxxxx-M MPF-A/Bxxxxx-M MPS-A/Bxxxxx-M | MPAR-A/B3xxxx-M MPAI-A/BxxxxxM | 2048 (± 1024) | — |
| | -V | MPL-A/Bxxxxx-V | MPAS-A/Bxxxx1-V05, MPAS-A/Bxxxx2-V20 MPAR-A/B1xxxx-V, MPAR-A/B2xxxx-V MPAI-A/BxxxxxV | 4096 (± 2048) | — |
| Stegmann Hiperface (magnetic scale) | -xDx | — | LDAT-Sxxxxxx-xDx | — | 960 (37.8) |
| Heidenhain EnDat | -7 | RDB-Bxxxxxx-7 | — | 1024 (± 512) | — |
| | -Y | VPC-Bxxxxx-Y | — | 128 (± 64) | — |

Figure 79 - Absolute Position Limits (measured in turns)



Functional Safety Features

Kinetix 5700 servo drives have safe torque-off (STO) capability and can safely turn off the inverter power transistors in response to the removal of the STO digital inputs, resulting in Stop Category 0 behavior. Hardwired and integrated safety options are available on all Kinetix 5700 servo drives.

Hardwired STO Mode

Hardwired safe torque-off (STO) mode supports parallel input terminals for cascading to adjacent drives over duplex wiring. For applications that do not require the safety function you must install jumper wires to bypass the safe torque-off feature. This applies to 2198-xxxx-ERS3 and 2198-xxxx-ERS4 inverters.

Refer to [Hardwired Safe Torque-off](#) on [page 314](#) for the STO connector pinout, installation, and wiring information.

Integrated Mode

For 2198-xxxx-ERS3 inverters in integrated STO mode, when any GuardLogix® or Compact GuardLogix safety controller issues the safe torque-off (STO) command over the EtherNet/IP™ network and the Kinetix 5700 drives execute the STO commands.

Refer to [Integrated Safe Torque-off](#) on [page 323](#) for integrated safety drive specifications, configuring motion and safety connections, direct motion commands, and the STO bypass feature.

For 2189-xxxx-ERS4 inverters in integrated mode, the GuardLogix 5580 or Compact GuardLogix 5380 safety controller activates the Monitored SS1 stopping function or any of the Drive Safety instructions providing controller-based safety functions over the EtherNet/IP network.

For 2189-xxxx-ERS4 and 2189-xxxx-ERS3 (series B) drives, Timed SS1 and STO are drive-based safety functions that are activated by the GuardLogix 5580 or Compact GuardLogix 5380 controller over the EtherNet/IP network.

Refer to the Kinetix 5700 Safe Monitor Functions Safety Reference Manual, publication [2198-RM001](#), for a description and configuration examples of the integrated stopping functions in the Studio 5000 Logix Designer® application.

Connect the Kinetix 5700 Drive System

This chapter provides procedures for wiring your Kinetix® 5700 system components and making cable connections.

| Topic | Page |
|--|-------------|
| Basic Wiring Requirements | 128 |
| Input Power Configurations for Kinetix 5700 Power Supplies | 129 |
| Ground Screw/Jumper Settings | 135 |
| Remove/Install the Ground Screw/Jumper | 137 |
| Ground the Drive System | 139 |
| Wiring Requirements | 141 |
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| Wire the Power Connectors | 145 |
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| Wiring Single Cables | 159 |
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| Customer-supplied Motor Power Cables | 178 |
| Accessory Module Connections | 181 |
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| Ethernet Cable Connections | 186 |

Basic Wiring Requirements

This section contains basic wiring information for the Kinetix 5700 drive system power supplies, servo drives, the iTRAK® power supply, and accessories.



ATTENTION: Plan the installation of your system so that you can perform all cutting, drilling, tapping, and welding with the system removed from the enclosure. Because the system is of the open type construction, be careful to keep metal debris from falling into it. Metal debris or other foreign matter can become lodged in the circuitry and result in damage to components.



SHOCK HAZARD: To avoid hazard of electrical shock, perform all mounting and wiring of the Bulletin 2198 drive modules prior to applying power. Once power is applied, connector terminals can have voltage present even when not in use.

IMPORTANT This section contains common PWM servo system wiring configurations, size, and practices that can be used in a majority of applications. National Electrical Code, local electrical codes, special operating temperatures, duty cycles, or system configurations take precedence over the values and methods provided.

Routing the Power and Signal Cables

Be aware that when you route power and signal wiring on a machine or system, radiated noise from nearby relays, transformers, and other electronic devices can be induced into I/O communication, or other sensitive low voltage signals. This can cause system faults and communication anomalies.

The Bulletin 2090 single motor cable contains the power, brake, and feedback wires, but is properly shielded to protect the noise-sensitive feedback signals.

Refer to [Electrical Noise Reduction](#) on [page 67](#) for examples of routing high and low voltage cables in wireways. Refer to the System Design for Control of Electrical Noise Reference Manual, publication [GMC-RM001](#), for more information.

Input Power Configurations for Kinetix 5700 Power Supplies

The Kinetix 5700 drive system power supply can be either the 2198-Pxxx DC-bus power supply or the 2198-RPxxx regenerative bus supply. The input power components and wiring depend on which power supply is used.

DC-bus Power Supply

Before wiring input power to your 2198-Pxxx DC-bus power supply, you must determine the type of input power within your facility. The drive modules are designed to operate in both grounded and ungrounded environments.

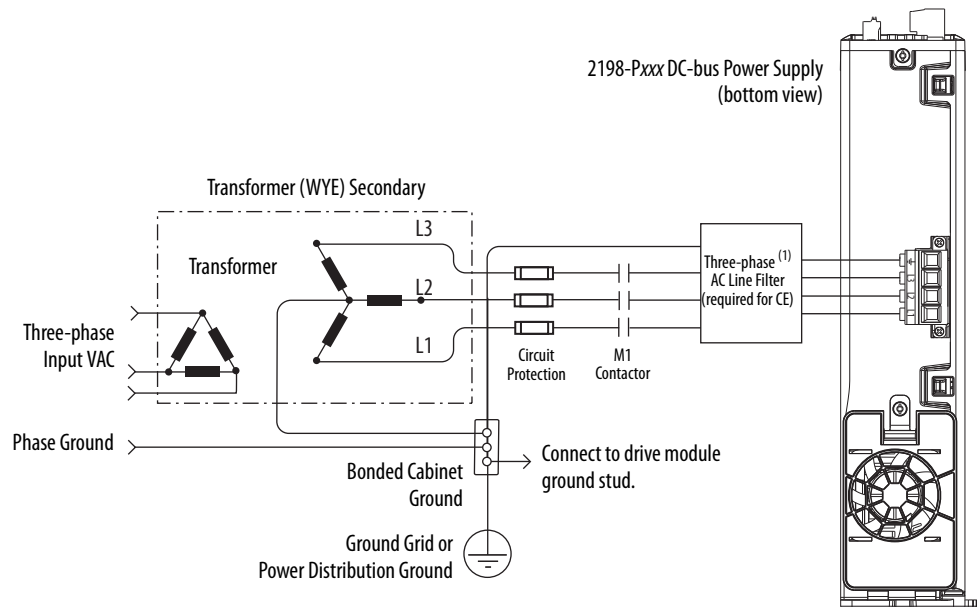
IMPORTANT For IEC 61800-3 category C3 compliance, use the appropriate 2198-DBRxx-F line filter with a grounded WYE configuration. The use of a line filter in an ungrounded, corner-grounded, or impedance-grounded configuration can affect the line filter components and result in equipment damage.

2198-DBRxx-F line filters also provide compliance, but are not the preferred solution because they require inverter ground jumpers installed manually.

Grounded Power Configurations

The grounded (WYE) power configuration grounds your three-phase power at a neutral point. This type of grounded power configuration is preferred.

Figure 80 - Grounded Power Configuration (WYE Secondary)

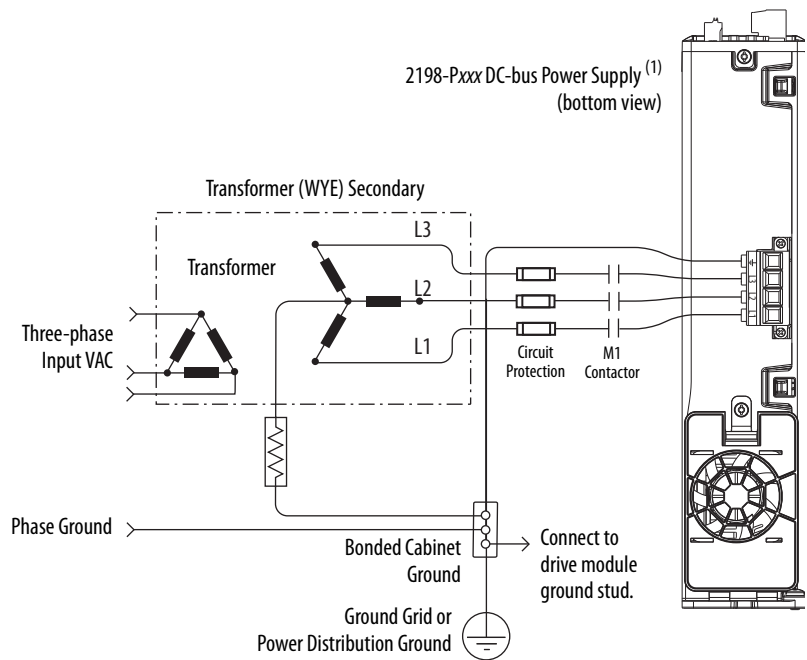


- (1) When using 2198-DBRxx-F line filter, 2198-Pxxx power supply has the ground jumper installed and 2198-xxxx-ERSx inverters have the ground jumpers installed.
When using 2198-DBRxx-F line filter, 2198-Pxxx power supply has the ground jumper installed, 2198-xxxx-ERSx inverters have the ground jumpers removed.



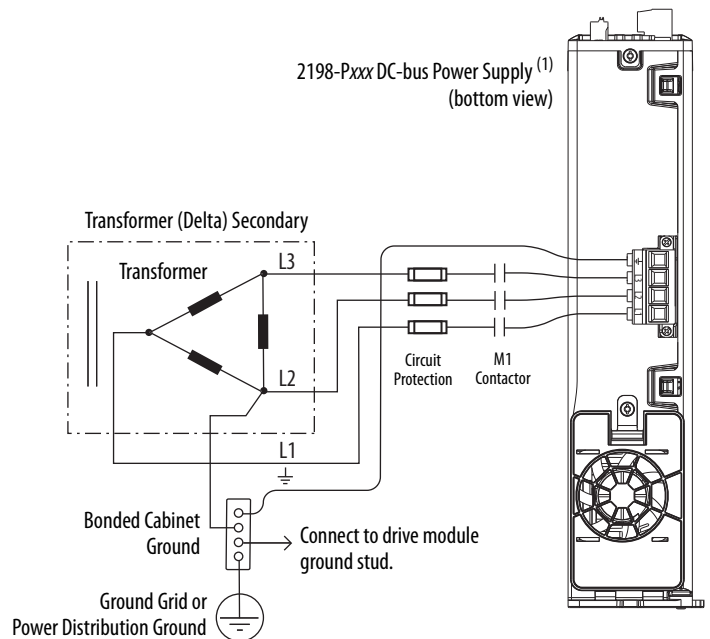
ATTENTION: The 2198T-W25K-ER (iTRAK) power supply must receive DC-bus voltage from a grounded-wye power configuration.

Figure 81 - Impedance-grounded Power Configuration (WYE secondary)



(1) 2198-Pxxx power supply has the ground jumper removed. 2198-xxxx-ERSx inverters have the ground jumpers removed.

Figure 82 - Corner-grounded Power Configuration (Delta secondary)



(1) 2198-Pxxx power supply has the ground jumper removed. 2198-xxxx-ERSx inverters have the ground jumpers removed.

Refer to [Power Wiring Examples](#) beginning on [page 343](#) for input power interconnect diagrams.

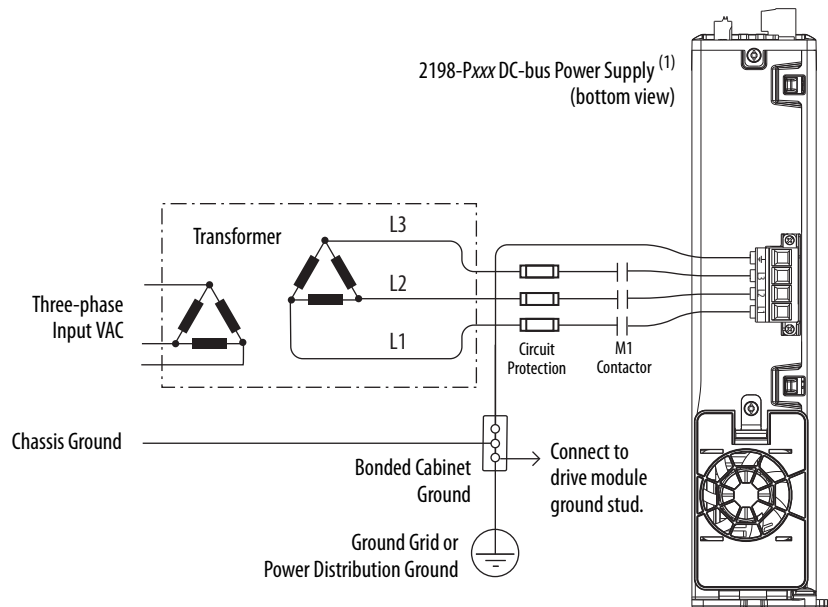
Ungrounded Power Configurations

The ungrounded power configuration ([Figure 83](#)), corner-grounded ([Figure 82](#)), and impedance-grounded ([Figure 81](#)) power configurations do not provide a neutral ground point.

IMPORTANT If you determine that you have ungrounded, corner-grounded, or impedance-grounded power distribution in your facility, you must remove the ground screw in each of your DC-bus power supplies, iTRAK power supplies, and dual-axis inverters, and the ground jumper in each of your single-axis inverters.

Refer to [Ground Screw/Jumper Settings](#) on [page 135](#) for more information.

Figure 83 - Ungrounded Power Configuration



(1) 2198-Pxxx power supply has the ground jumper removed. 2198-xxxx-ERSx inverters have the ground jumpers removed.



ATTENTION: Ungrounded and corner-grounded systems do not reference each phase potential to a power distribution ground. This can result in an unknown potential to earth ground. Drive-to-motor cable lengths are limited with these AC power source types. See Appendix D, beginning on [page 401](#), for more information.

Refer to [Power Wiring Examples](#) beginning on [page 343](#) for input power interconnect diagrams.

Regenerative Bus Supply

Before wiring input power to your 2198-RPxxx regenerative bus supply, you must determine the type of input power within your facility. The regenerative bus supply is designed to operate in grounded-wye and impedance grounded environments. Corner-grounded and ungrounded power can be used, but you must add an isolation transformer to the input power circuit to provide grounded-wye power.

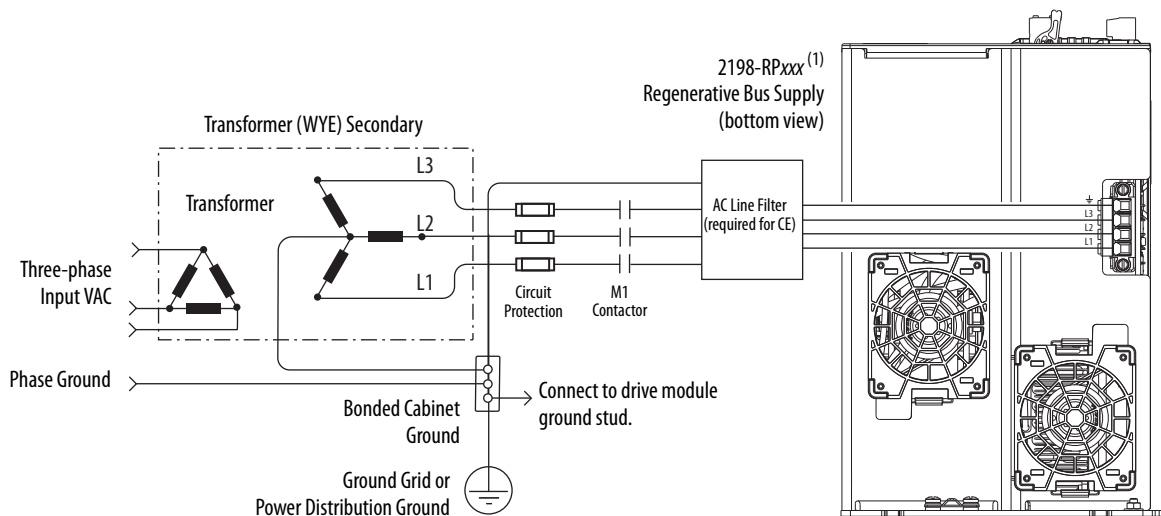


ATTENTION: For IEC 61800-3 category C3 compliance, use the appropriate 2198-DBRxx-F AC line filter with a grounded WYE configuration. Use of the AC line filter in an ungrounded or corner-grounded configuration (without an isolation transformer) or in an impedance-grounded configuration can affect the line filter components and result in equipment damage. 2198-DBxx-F line filters are not compatible with regenerative bus supplies.

Grounded Power Configurations

This grounded (WYE) power configuration ([Figure 84](#)) grounds the three-phase input power at a neutral point. This is the preferred grounded power configuration.

Figure 84 - Grounded Power Configuration (WYE secondary)



(1) 2198-RPxxx power supply has the ground jumper installed. 2198-xxxx-ERSx inverters have the ground jumpers removed.



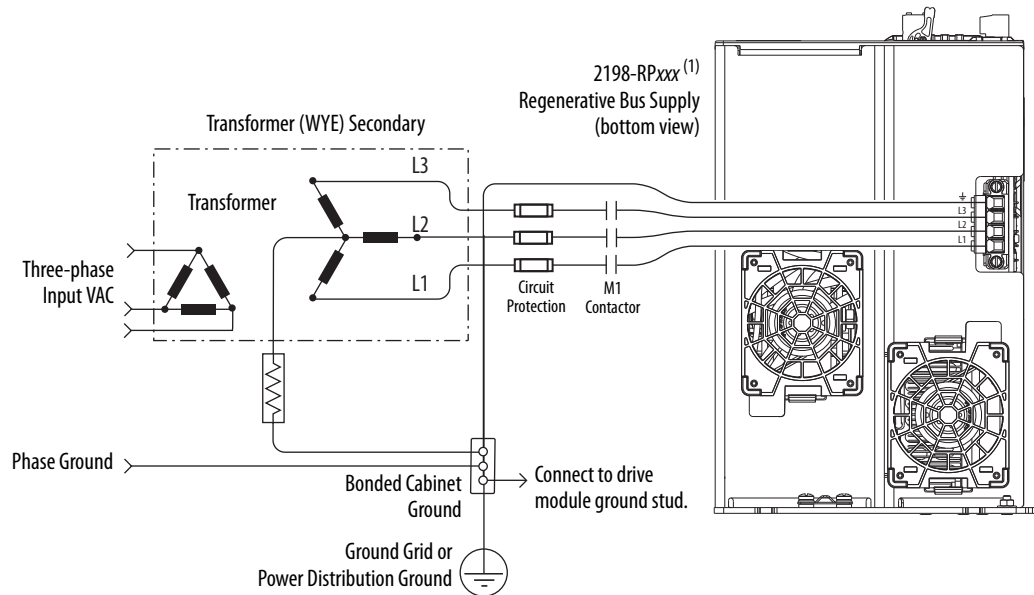
ATTENTION: The 2198T-W25K-ER (iTRAK) power supply must receive DC-bus voltage from a grounded-wye power configuration.

This impedance-grounded power configuration ([Figure 85](#)) does not provide a neutral ground point.



ATTENTION: Ungrounded systems do not reference each phase potential to a power distribution ground. This can result in an unknown potential to earth ground.

Figure 85 - Impedance-grounded Power Configuration (WYE secondary)



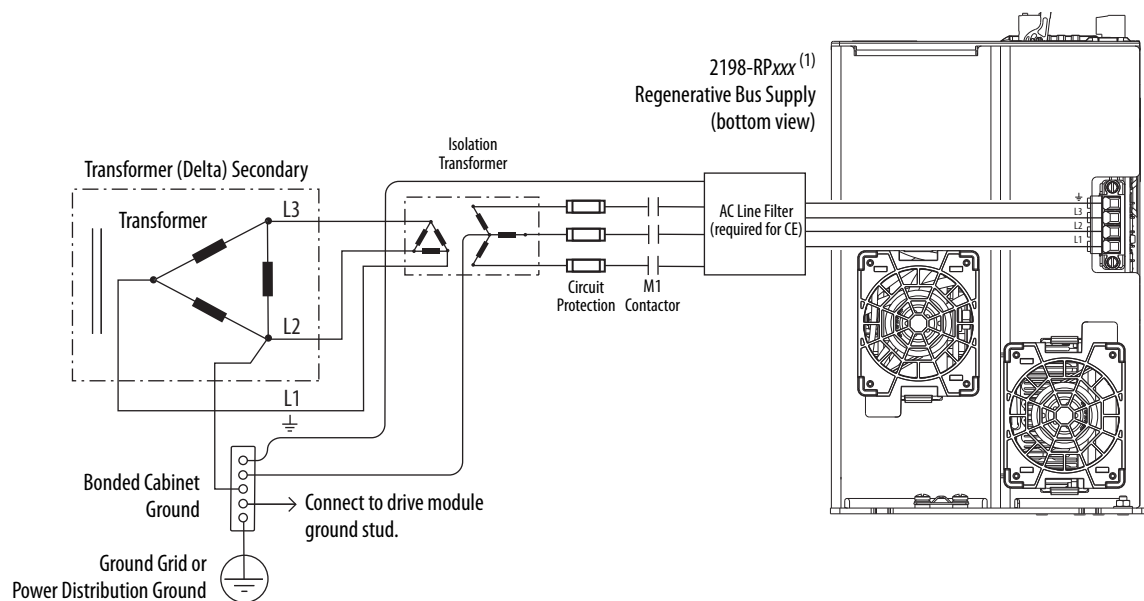
(1) 2198-RPxxx power supply has the ground jumper removed. 2198-xxxx-ERSx inverters have the ground jumpers removed.

IMPORTANT If you determine that you have impedance-grounded power distribution in your facility, you must remove the ground screw in your regenerative power supply, iTRAK power supplies, and dual-axis inverters, and the ground jumper in each of your single-axis inverters.

Refer to [Ground Screw/Jumper Settings](#) on [page 135](#) for more information.

This corner-grounded power configuration ([Figure 86](#)) includes an isolation transformer that results in grounded-wye power distribution.

Figure 86 - Corner-grounded Power Configuration (with isolation transformer)



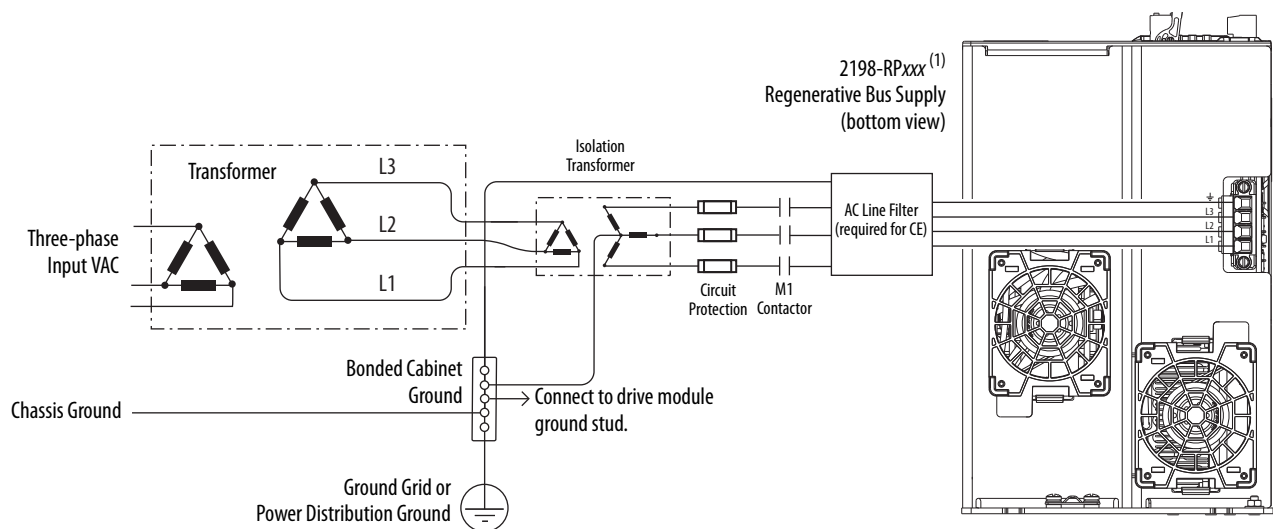
(1) 2198-RPxxx power supply has the ground jumper installed. 2198-xxxx-ERSx inverters have the ground jumpers removed.

Refer to [Power Wiring Examples](#) beginning on [page 343](#) for input power interconnect diagrams.

Ungrounded Power Configurations

This ungrounded power configuration ([Figure 87](#)) includes an isolation transformer that results in grounded-wye power distribution.

Figure 87 - Ungrounded Power Configuration (with isolation transformer)



(1) 2198-RPxxx power supply has the ground jumper installed. 2198-xxxx-ERSx inverters have the ground jumpers removed.

Ground Screw/Jumper Settings

Determine the ground screw/jumper setting for your Kinetix 5700 drive system power supply, iTRAK power supply, and Kinetix 5700 inverters.

Kinetix 5700 Drive System Power Supply

The Kinetix 5700 drive system power supply can be either 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply.

DC-bus Power Supply

The 2198-Pxxx DC-bus power supply has a factory-installed ground screw for grounded-wye power distribution. [Table 61](#) summarizes the ground screw/jumper settings for the 2198-Pxxx DC-bus power supply.

Table 61 - Ground Screw Setting for the DC-bus Power Supply

| Ground Configuration | Example Diagram | 2198-Pxxx DC-bus Power Supply |
|--|---|---|
| Grounded (wye) | Figure 80 on page 129 | Ground screw installed (default setting) ⁽¹⁾ |
| <ul style="list-style-type: none"> • Impedance grounded • Corner grounded • AC-fed ungrounded | Figure 81 on page 130 Figure 82 on page 130 Figure 83 on page 131 | Remove ground screw/jumper |

(1) Ground screw is factory installed.

IMPORTANT If you have grounded-wye power distribution in your facility, do not remove the ground screw from the DC-bus power supply. Remove the ground screw when using ungrounded, corner-grounded, or impedance-grounded power.

Regenerative Bus Supply

The 2198-RPxxx regenerative bus supply includes a factory-installed ground jumper for grounded-wye power distribution. [Table 62](#) summarizes the ground jumper settings for the 2198-RPxxx regenerative bus supply.

Table 62 - Ground Jumper Setting for the Regenerative Bus Supply

| Ground Configuration | Example Diagram | 2198-RPxxx Regenerative Bus Supply |
|---|---|--|
| <ul style="list-style-type: none"> • Grounded (wye) • Corner-grounded with isolation transformer • Ungrounded with isolation transformer | Figure 84 on page 132 Figure 86 on page 134 Figure 87 on page 134 | Ground jumper is factory installed (default setting) |
| Impedance grounded | Figure 85 on page 133 | Remove ground jumper ⁽¹⁾ |

(1) When the regenerative bus supply ground jumper is removed, it can be permanently stored in threaded holes at the bottom of the chassis.

IMPORTANT If you have grounded-wye power distribution in your facility, or corner-grounded or ungrounded power with an isolation transformer, do not remove the ground jumper from the regenerative bus supply. Remove the ground jumper when using impedance-grounded power.

Kinetix 5700 Inverters

The 2198-Dxxx-ERSx dual-axis and 2198-Sxxx-ERSx single-axis inverters also have a ground screw/jumper setting that depends on the input-power ground configuration.

The 2198-Dxxx-ERSx dual-axis and 2198-Sxxx-ERSx single-axis inverters also have a ground screw/jumper setting that depends on the input-power ground configuration and whether a 2198-DBxx-F or 2198-DBRxx-F filter is used.

[Table 63](#) summarizes the ground screw/jumper default settings for the 2198-xxxx-ERSx inverters.

Table 63 - Ground Screw/Jumper Setting for 2198-xxxx-ERSx Inverters

| 2198-xxxx-ERS3 (series A) | 2198-xxxx-ERS3 (series B) | 2198-xxxx-ERS4 |
|--|--|----------------|
| Ground screw is factory installed (default setting) | Ground screw/jumper is not installed ⁽¹⁾ (default setting) | |

(1) Ground screw/jumper is included with the drive, but not installed.

[Table 64](#) summarizes the ground screw/jumper settings required for the 2198-xxxx-ERSx inverters depending on the Kinetix 5700 power supply in use.

Table 64 - Ground Screw/Jumper Setting for 2198-xxxx-ERSx Inverters

| AC Power Source Type | Inverter Ground Jumper Setting Based on Selected Power Supply | |
|--|---|--|
| | 2198-Pxxx ⁽¹⁾ DC-bus Power Supply | <ul style="list-style-type: none"> 2198-Pxxx DC-bus Power Supply ⁽²⁾ 2198-RPxxx Regenerative Bus Supply 8720MC-RPS Regenerative Power Supply Any Other Active Converter |
| Grounded (wye) | Inverter ground screw/ jumper installed. | Inverter ground screw/jumper not installed ⁽³⁾ . |
| <ul style="list-style-type: none"> AC-fed ungrounded Corner grounded Impedance grounded | Inverter ground screw/ jumper not installed. | |

(1) 2198-Pxxx DC-bus power supply when 2198-DB20-F, 2198-DB42-F, 2198-DB80-F, or 2198-DB290-F AC line filter is used.

(2) 2198-Pxxx DC-bus power supply when 2198-DBR20-F, 2198-DBR40-F, 2198-DBR90-F, or 2198-DBR200-F AC line filter is used.

(3) When the 2198-S263-ERSx or 2198-S312-ERSx inverter ground jumper is removed, it can be permanently stored in threaded holes at the bottom of the chassis.

IMPORTANT If you have grounded-wye power distribution and the 2198-Pxxx DC-bus power supply with:

- 2198-DB20-F, 2198-DB42-F, 2198-DB80-F, or 2198-DB290-F AC line filters, install the ground jumper in the inverters. EMC performance can be affected if the ground jumper is not installed.
- 2198-DBR20-F, 2198-DBR40-F, 2198-DBR90-F, or 2198-DBR200-F AC line filters, remove the ground jumper in the inverters. Ground jumper removed is preferred when using the 2198-DBRxx-F AC line filters. EMC performance is achieved with or without the ground jumper installed.

IMPORTANT If you are using the 2198-RPxxx regenerative bus supply, always remove the ground jumper in the inverters.

Kinetix 5700 iTRAK Power Supply

The 2198T-W25K-ER iTRAK power supply has a factory-installed ground screw for grounded-wye power distribution. When the 2198-Pxxx DC-bus power supply is used, keep the ground screw installed. When the 2198-RPxxx regenerative bus supply is used, remove the ground screw.



ATTENTION: The 2198T-W25K-ER (iTRAK) power supply must receive DC-bus voltage from a grounded-wye power configuration.



ATTENTION: The iTRAK power supply can cause damage to equipment when used with the 2198-RPxxx regenerative bus supply, if the ground screw is not removed.

Remove/Install the Ground Screw/Jumper

We recommend that you remove or install the ground screw/jumper when the drive module is removed from the panel and placed on its side on a solid work surface (does not apply to catalog numbers 2198-RPxxx, 2198-S263-ERSx, or 2198-S312-ERSx).

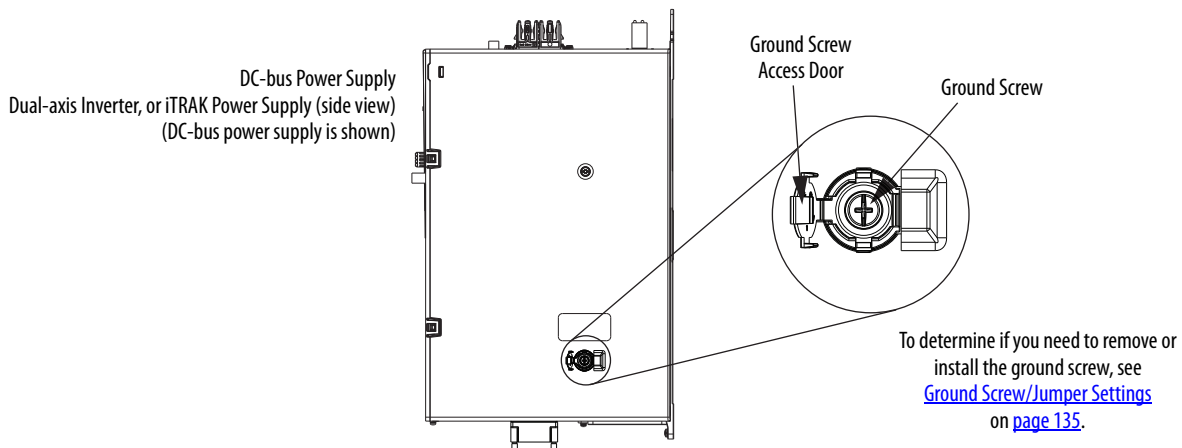
IMPORTANT To determine if you need to remove or install the ground screw/jumper, see [Ground Screw/Jumper Settings](#) on [page 135](#).



ATTENTION: When the ground screw/jumper is not installed on DC-bus power supplies, the risk of equipment damage exists because the unit no longer maintains line-to-neutral or line-to-line voltage protection.

To access or remove/install the ground screw on DC-bus power supplies, dual-axis inverters, and the iTRAK power supply, open the small plastic door on the right side of the module.

Figure 88 - Remove/Install the Ground Screw

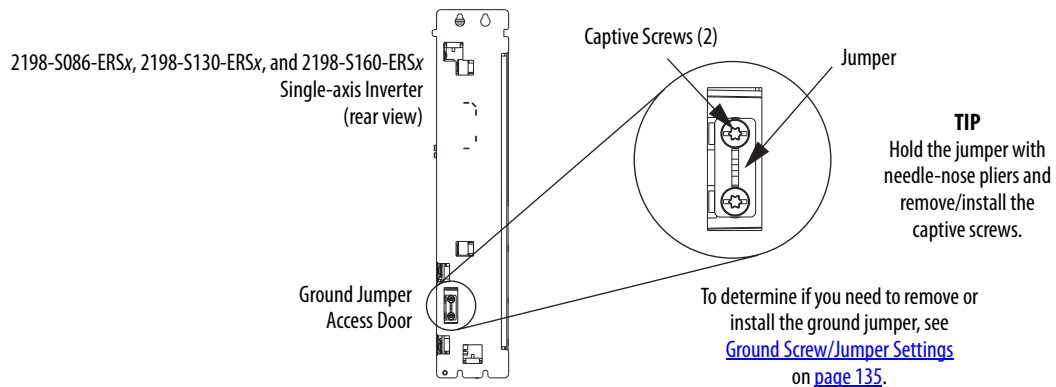




ATTENTION: To avoid personal injury, the ground screw/jumper access door must be kept closed when power is applied. If power was present and then removed, wait at least 5 minutes for the DC-bus voltage to dissipate and verify that no DC-bus voltage exists before accessing the ground screw/jumper. This applies to the DC-bus power supply, regenerative bus supply, dual-axis inverters, and single-axis inverters.

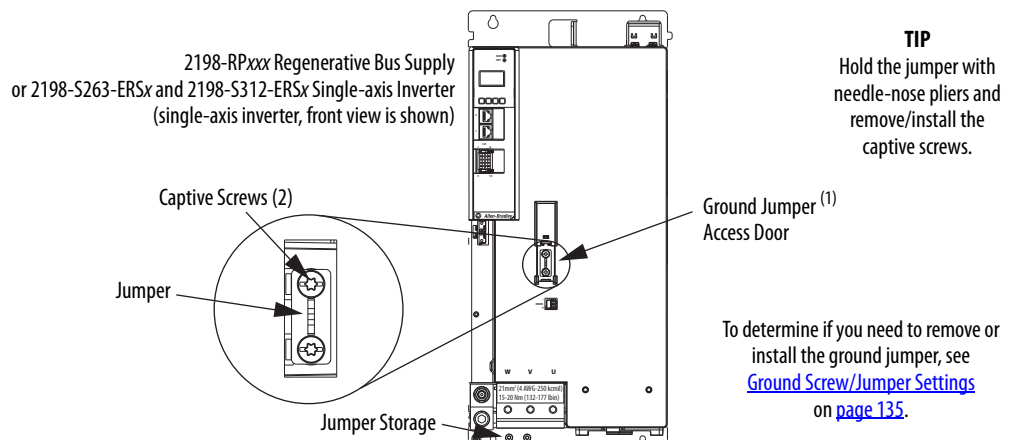
Single-axis inverters (catalog numbers 2198-S086-ERSx, 2198-S130-ERSx, and 2198-S160-ERSx) have a ground-jumper access door on the back of the unit. Two captive screws secure the jumper.

Figure 89 - Remove/Install the Single-axis Inverter Ground Jumper



Regenerative bus supplies (catalog numbers 2198-RPxxx) and single-axis inverters (catalog numbers 2198-S263-ERSx and 2198-S312-ERSx) have a ground-jumper access door on the front of the unit. Two captive screws secure the jumper.

Figure 90 - Remove/Install the Ground Jumper



(1) When the regenerative bus supply or 2198-S263-ERSx or 2198-S312-ERSx inverter ground jumper is removed, it can be permanently stored in threaded holes at the bottom of the chassis.



ATTENTION: Risk of equipment damage exists. The module ground configuration must be accurately determined. See [Ground Screw/Jumper Settings](#) on [page 135](#).

Ground the Drive System

All equipment and components of a machine or process system must have a common earth-ground point that is connected to chassis. A grounded system provides a ground path for protection against electrical shock. Grounding your drive modules and panels minimize the shock hazard to personnel and damage to equipment caused by short circuits, transient overvoltages, and accidental connection of energized conductors to the equipment chassis.

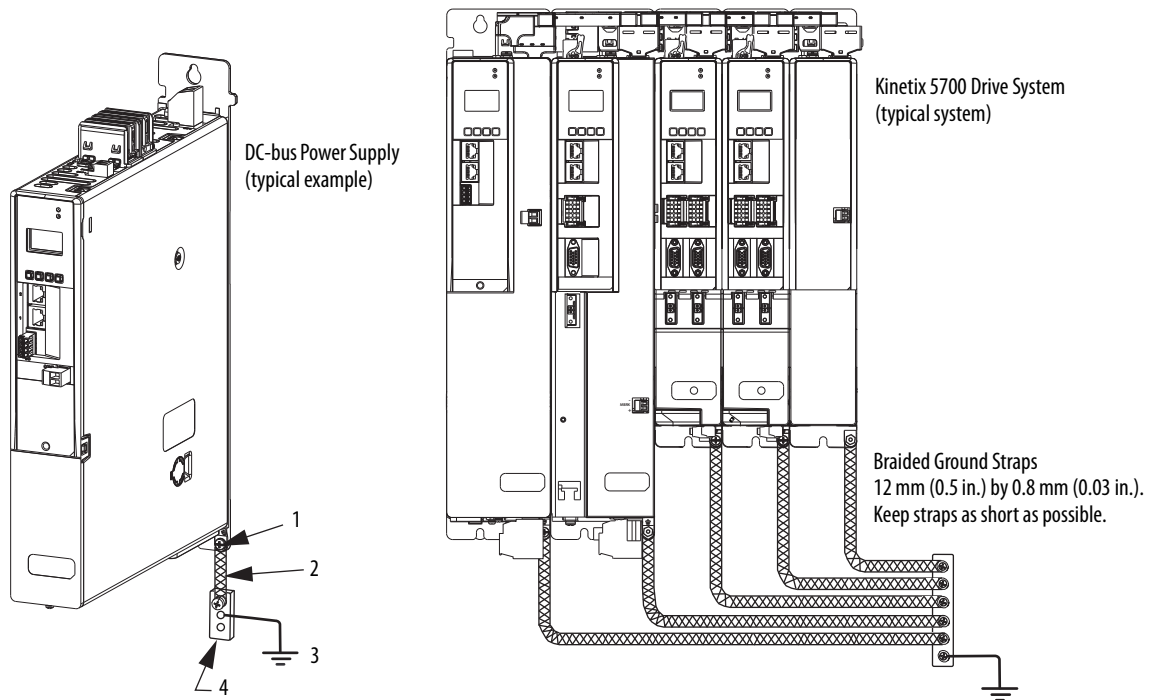


ATTENTION: The National Electrical Code contains grounding requirements, conventions, and definitions. Follow all applicable local codes and regulations to safely ground your system.
For CE grounding requirements, refer to [Agency Compliance](#) on [page 38](#).

Ground the System Subpanel

Ground Kinetix 5700 power supplies, inverters, and accessory modules to a bonded cabinet ground bus with a braided ground strap. Keep the braided ground strap as short as possible for optimum bonding.

Figure 91 - Connect the Ground Terminal



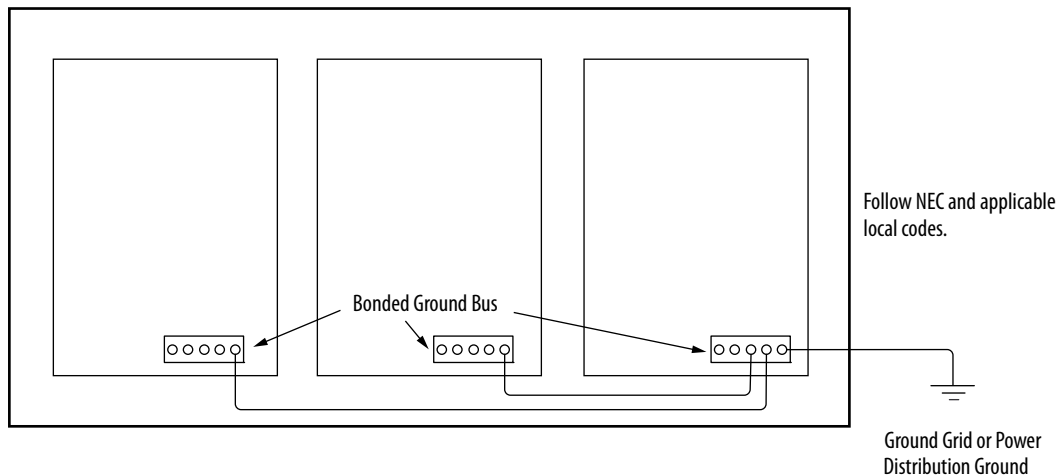
| Item | Description |
|------|--|
| 1 | Ground screw (green) 2.0 N•m (17.7 lb-in), max |
| 2 | Braided ground strap (customer supplied) |
| 3 | Ground grid or power distribution ground |
| 4 | Bonded cabinet ground bus (customer supplied) |

Refer to the System Design for Control of Electrical Noise Reference Manual, publication [GMC-RM001](#), for more information.

Ground Multiple Subpanels

In this figure, the chassis ground is extended to multiple subpanels.

Figure 92 - Subpanels Connected to a Single Ground Point



High-frequency (HF) bonding is not illustrated. For HF bonding information, refer to [Bonding Multiple Subpanels](#) on [page 69](#).



Wiring Requirements

Wires must be copper with 75 °C (167 °F) minimum rating. Phasing of main AC power is arbitrary and earth ground connection is required for safe and proper operation.

Refer to [Power Wiring Examples](#) on [page 343](#) for interconnect diagrams.

IMPORTANT The National Electrical Code and local electrical codes take precedence over the values and methods provided.

Table 65 - DC-bus Power Supply Wiring Requirements

| DC-bus Power Supply Cat. No. | Description | Connects to Terminals | | Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N•m (lb•in) |
|------------------------------|--------------------------------------|---|---|-----------------------------------|-----------------------|----------------------------|
| | | Pin | Signal | | | |
| 2198-P031 | Mains input power |  L3 L2 L1 |  L3 L2 L1 | 6...10 ⁽¹⁾ (10...8) | 10.0 (0.39) | 0.5...0.8 (4.4...7.1) |
| 2198-P070 | | | | 6...10 ⁽²⁾ (10...8) | | |
| 2198-P141 2198-P208 | | | | 10...35 (8...2) | 20.0 (0.79) | 2.5...4.5 (22...40) |
| 2198-Pxxx | PELV/SELV 24V power (connector plug) | CP-1 CP-2 | 24V+ 24V– | 0.5...4 (20...12) | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) |
| | DC Bus power | Bus bar | DC– DC+ | N/A ⁽³⁾ | N/A ⁽³⁾ | N/A ⁽³⁾ |
| | Contactor enable | EN– EN+ | CONT EN– CONT EN+ | 0.14...2.5 (26...12) | 7.0 (0.28) | 0.4...0.5 (3.5...4.4) |
| | Shunt resistor | RC-1 RC-2 | SH DC+ | 1.5...6 (16...10) | 12.0 (0.47) | 0.5...0.6 (4.5...5.3) |
| | Digital inputs | IOD-1 IOD-2 IOD-3 IOD-4 | IN1 COM IN2 SHLD | 0.14...1.5 (26...16) | 10.0 (0.39) | N/A ⁽⁴⁾ |



(1) Applies to solid wire. If using stranded wire, the maximum wire size is 6 mm² (10 AWG).

(2) Applies to solid wire. If using stranded wire, the maximum wire size is 6 mm² (10 AWG). To meet CE requirements above 45 °C (113 °F) for 6 mm² stranded wires, single-core copper conductors must be used with 90 °C minimum rating.

(3) Shared DC-bus power connections are always made from one drive module to another over the bus-bar connection system. These terminals do not receive discrete wires.

(4) This connector uses spring tension to hold wires in place.

Table 66 - Regenerative Bus Supply Wiring Requirements

| Regen Bus Supply Cat. No. | Description | Connects to Terminals | | Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|------------------------------|--|---|---|------------------------------------|--------------------------|-----------------------------|
| | | Pin | Signal | | | |
| 2198-RP088 | Mains input power |  L3 L2 L1 |  L3 L2 L1 | 6...10 ⁽¹⁾ (10...8) | 10.0 (0.39) | 0.5...0.8 (4.4...7.1) |
| 2198-RP200 | | | | 10...35 (8...2) | 20.0 (0.79) | 2.5...4.5 (22...40) |
| 2198-RP263 2198-RP312 | | | | 21.1...120 (4...250 kcmil) | 27.0 (1.06) | 15...20 (132...177) |
| 2198-RP088 2198-RP200 | PELV/SELV 24V power (connector plug) | CP-1 CP-2 | 24V+ 24V– | 0.5...4 (20...12) | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) |
| 2198-RP263 2198-RP312 | | | | 1.5...4 (16...12) | 10.0 (0.39) | 0.5...0.6 (4.4...5.3) |
| | | | | 6 (10) | | 0.7...0.8 (6.1...7.0) |
| 2198-RPxxx | DC Bus power | Bus bar | DC– DC+ | N/A ⁽²⁾ | N/A ⁽³⁾ | N/A ⁽³⁾ |
| | Contactor enable | OK+ OK– EN– EN+ | CONV OK+ CONV OK– CONT EN– CONT EN+ | 0.14...2.5 (26...12) | 7.0 (0.28) | 0.4...0.5 (3.5...4.4) |
| | Active shunt | RC-2 RC-1 | DC+ DC– | 1.5...6 (16...10) | 12.0 (0.47) | 0.5...0.6 (4.5...5.3) |
| | Digital inputs | IOD-1 IOD-2 IOD-3 IOD-4 IOD-5 IOD-6 IOD-7 IOD-8 IOD-9 IOD-10 | IN1 COM IN2 COM SHLD IN3 COM IN4 COM SHLD | 0.14...1.5 (26...16) | 10.0 (0.39) | N/A ⁽³⁾ |

(1) Applies to solid wire. If using stranded wire, the maximum wire size is 6 mm² (10 AWG). To meet CE requirements above 40 °C (104 °F) for 6 mm² stranded wires, single-core copper conductors must be used with 90 °C minimum rating.

(2) Shared DC-bus power connections are always made from drive to drive over the bus-bar connection system. These terminals do not receive discrete wires.

(3) This connector uses spring tension to hold wires in place.

Table 67 - iTRAK Power Supply Wiring Requirements

| iTRAK Power Supply Cat. No. | Description | Connects to Terminals | | Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|-----------------------------|--|-----------------------|--------------|-------------------------------------|-----------------------|---|
| | | Pin | Signal | | | |
| 2198T-W25K-ER | DC-bus input power | Bus bar | DC– DC+ | N/A ⁽¹⁾ | N/A ⁽¹⁾ | N/A ⁽¹⁾ |
| | SELV/PELV rated 24V power (connector plug) | CP-1 CP-2 | 24V+ 24V– | 1.5...4 ⁽²⁾ (16...12) | 10.0 (0.39) | 0.5...0.6 (4.4...5.3) |
| | | | | 6 (10) ⁽²⁾ | | 0.7...0.8 ⁽³⁾ (6.1...7.0) |



(1) Shared DC-bus power connections are always made from power supply to power supply over the bus-bar connection system. These terminals do not receive discrete wires.

(2) Use sufficient wire size to support the complete control power load, including the Kinetix 5700 drive modules and pass-through current for the attached motor modules.

(3) Depending on 24V current demand, 6 mm² (10 AWG) wire can be required. When 6 mm² (10 AWG) wire is used, these torque specifications apply.

TIP For iTRAK power supply wiring requirements not shown here, see the iTRAK System User Manual, publication [2198T-UM001](#).

Table 68 - Single-axis Inverter Wiring Requirements

| Single-axis Inverter Cat. No. | Description | Connects to Terminals | | Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) | |
|----------------------------------|--|---|---|--|-------------------------------|-----------------------------|--------------------------|
| | | Pin | Signal | | | | |
| 2198-S086-ERSx 2198-S130-ERSx | Motor power | U V W | U V W | Motor power cable depends on motor/ drive combination. 6...25 ⁽¹⁾ (10...4) | 20.0 (0.79) | 2.5...4.5 (22...40) | |
| 2198-S160-ERSx | |  |  | 10...35 ⁽¹⁾ (8...2) | | | |
| 2198-S263-ERSx 2198-S312-ERSx | | | | | 21.1...120 (4...250 kcmil) | 27.0 (1.06) | 15...20 (132...177) |
| 2198-S086-ERSx 2198-S130-ERSx | PELV/SELV 24V power (connector plug) | CP-1 CP-2 | 24V+ 24V- | 0.5...4 (20...12) | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) | |
| 2198-S263-ERSx 2198-S312-ERSx | | | | 1.5...4 (16...12) | 10.0 (0.39) | 0.5...0.6 (4.4...5.3) | |
| | | | | 6 (10) | | | 0.7...0.8 (6.1...7.0) |
| 2198-Sxxx-ERSx | Brake power | BC-1 BC-2 | MBRK+ MBRK- | N/A ⁽²⁾ | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) | |
| | DC Bus power | Bus bar | DC- DC+ | N/A ⁽³⁾ | N/A ⁽³⁾ | N/A ⁽³⁾ | |
| | Safety | STO-1 STO-2 STO-3 STO-4 STO-5 STO-6 STO-7 STO-8 | STO-9 STO-10 STO-11 STO-12 STO-13 STO-14 STO-15 STO-16 | SB+/NC S1A SCA S2A SB- NC NC NC | 0.14...1.5 (26...16) | 10.0 (0.39) | N/A ⁽⁴⁾ |
| | Digital inputs | IOD-1 IOD-2 IOD-3 IOD-4 IOD-5 IOD-6 IOD-7 IOD-8 IOD-9 IOD-10 | IN1 COM IN2 COM SHLD IN3 COM IN4 COM SHLD | 0.14...1.5 (26...16) | 10.0 (0.39) | N/A ⁽⁴⁾ | |
| | | | | | | | |



(1) Building your own single cables or using third-party single cables for Kinetix VP motors and actuators is not an option. Use 2090-CSxM1DE/DG single motor cables. Refer to the Kinetix Motion Accessories Specifications Technical Data, publication [KNX-TD004](#), for cable specifications.

(2) Motor brake wires are included in the Bulletin 2090 motor cable.

(3) Shared DC-bus power connections are always made from one drive module to another over the bus-bar connection system. These terminals do not receive discrete wires.

(4) This connector uses spring tension to hold wires in place.

Table 69 - Dual-axis Inverter Wiring Requirements

| Dual-axis Inverter Cat. No. | Description | Connects to Terminals | | Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|--|--|--|---|--|--------------------------|-----------------------------|
| | | Pin | Signal | | | |
| 2198-D006-ERSx 2198-D012-ERSx 2198-D020-ERSx 2198-D032-ERSx | Motor power (axis A and B) | U V W  | U V W  | Motor power cable depends on motor/ drive combination. 0.75...2.5 ⁽¹⁾ (18...14) | 10.0 (0.39) | 0.5...0.6 (4.4...5.3) |
| 2198-D057-ERSx | | | | 2.5...6 ⁽¹⁾ (14...10) | 10.0 (0.39) | 0.5...0.8 (4.4...7.1) |
| 2198-Dxxx-ERSx | PELV/SELV 24V power (connector plug) | CP-1 CP-2 | 24V+ 24V- | 0.5...4 (20...12) | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) |
| | Brake power (axis A and B) | BC-1 BC-2 | MBRK+ MBRK- | N/A ⁽²⁾ | | |
| | DC Bus power | Bus bar | DC- DC+ | N/A ⁽³⁾ | N/A ⁽³⁾ | N/A ⁽³⁾ |
| | Safety | ST0-1 ST0-2 ST0-3 ST0-4 ST0-5 ST0-6 ST0-7 ST0-8 | ST0-9 ST0-10 ST0-11 ST0-12 ST0-13 ST0-14 ST0-15 ST0-16 SB+ /NC S1A SCA S2A SB- S1B SCB S2B | 0.14...1.5 (26...16) | 10.0 (0.39) | N/A ⁽⁴⁾ |
| | Digital inputs | IOD-1 IOD-2 IOD-3 IOD-4 IOD-5 IOD-6 IOD-7 IOD-8 IOD-9 IOD-10 | IN1 COM IN2 COM SHLD IN3 COM IN4 COM SHLD | 0.14...1.5 (26...16) | 10.0 (0.39) | N/A ⁽⁴⁾ |

(1) Building your own single cables or using third-party single cables for Kinetix VP motors and actuators is not an option. Use 2090-CSxM1DE/DG single motor cables. Refer to the Kinetix Motion Accessories Specifications Technical Data, publication [KNX-TD004](#), for cable specifications.

(2) Motor brake wires are included in the Bulletin 2090 motor cable.

(3) Shared DC-bus power connections are always made from one drive module to another over the bus-bar connection system. These terminals do not receive discrete wires.

(4) This connector uses spring tension to hold wires in place.



ATTENTION: To avoid personal injury and/or equipment damage, observe the following:

- Make sure installation complies with specifications regarding wire types, conductor sizes, branch circuit protection, and disconnect devices. The National Electrical Code (NEC) and local codes outline provisions for safely installing electrical equipment.
- Use motor power connectors for connection purposes only. Do not use them to turn the motor on and off.
- Ground shielded power cables to prevent potentially high voltages on the shield.

Wiring Guidelines

Use these guidelines as a reference when wiring the power connectors on your Kinetix 5700 drive modules.

IMPORTANT For connector locations of the Kinetix 5700 drive modules, refer to [Kinetix 5700 Connector Data](#) on [page 94](#).
When removing insulation from wires and tightening screws to secure the wires, refer to the table on [page 141](#) for strip lengths and torque values.

IMPORTANT To improve system performance, run wires and cables in the wireways as established in [Establishing Noise Zones](#) on [page 70](#).

Follow these steps when wiring the connectors for your Kinetix 5700 drive modules.

1. Prepare the wires for attachment to each connector plug by removing insulation equal to the recommended strip length.

Some cables come prepared with wires appropriately stripped.

IMPORTANT Use caution not to nick, cut, or otherwise damage strands as you remove the insulation.

2. Route the cable/wires to your Kinetix 5700 drive module connector.
3. Insert wires into connector plugs.

Refer to the connector pinout tables in [Chapter 4](#) or the interconnect diagrams in [Appendix A](#).

4. Tighten the connector screws.
5. Gently pull on each wire to make sure it does not come out of its terminal; reinsert and tighten any loose wires.
6. Insert the connector plug into the drive module connector.

Wire the Power Connectors

This section provides examples and guidelines to assist you in making connections to the input power connectors.

Refer to [Power Wiring Examples](#) on [page 343](#) for interconnect diagrams.

Wire the 24V Control Power Input Connector

The 24V power (CP) connector requires 24V DC input for the control circuitry. The connector plug ships with the drive module and shared-bus connector kits are purchased separately.

IMPORTANT Mount the 24V power supply as close to the drive system as possible to minimize voltage drop on the 24V input power wiring.

Figure 93 - CP Connector Wiring - Connector Plug

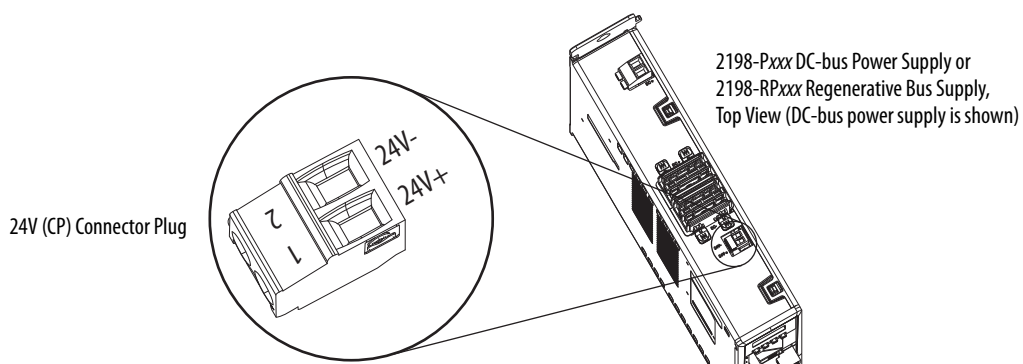


Table 70 - CP Connector Plug Wiring Specifications

| Drive Module Cat. No. | CP Pin | Signal | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|--|--------------|--------------|---|--------------------------|-----------------------------|
| 2198-Pxxx, 2198-RP088, 2198-RP200, 2198-Dxxx-ERSx, 2198-S086-ERSx, 2198-S130-ERSx, 2198-S160-ERSx, 2198-CAPMOD-2240 and 2198-DCBUSCOND-RP312 | CP-1 CP-2 | 24V+ 24V- | 0.5...4 ⁽¹⁾ (20...12) | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) |
| 2198-RP263, 2198-RP312, 2198-S263-ERSx, 2198-S312-ERSx, 2198T-W25K-ER | CP-1 CP-2 | 24V+ 24V- | 1.5...4 ⁽¹⁾ (16...12) | 10.0 (0.39) | 0.5...0.6 (4.4...5.3) |
| | | | 6 (10) | | 0.7...0.8 (6.1...7.0) |

(1) Use sufficient wire size to support the complete control power load, including the Kinetix 5700 drive modules and pass-through current for the attached motor modules. See [24V Control Power Evaluation](#) on [page 49](#) for more information.

Figure 94 - CP Connector Wiring - Shared Bus

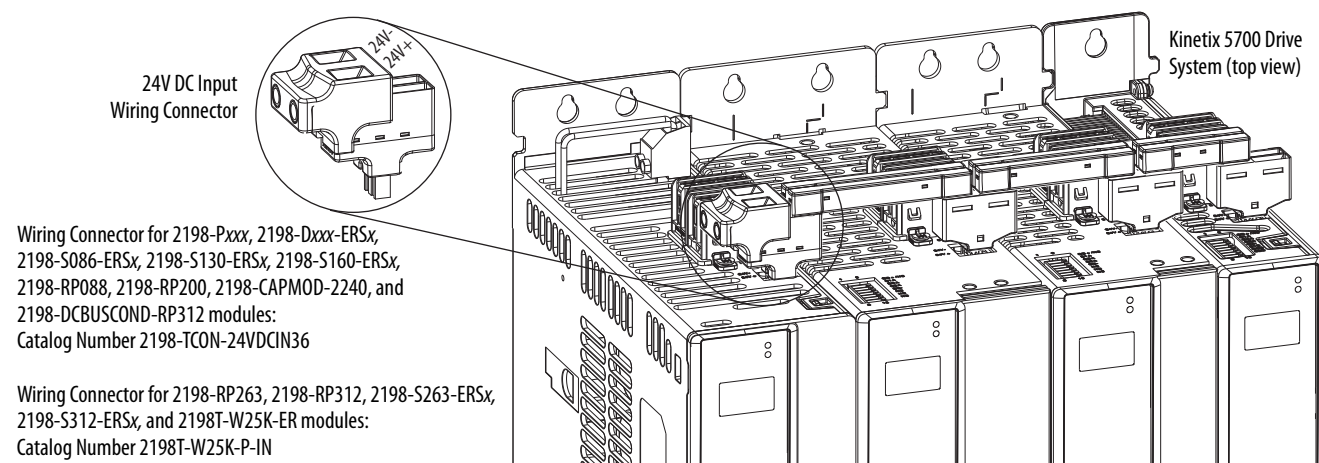


Table 71 - CP Shared-bus Wiring Specifications


| Drive Module ^{(1) (2)} Cat. No. | CP Pin | Signal | Input Current, max A rms | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|---|--------------|--------------|-----------------------------|---|--------------------------|-----------------------------|
| 2198-RPxxx and 2198-Pxxx 2198-Dxxx-ERSx, 2198-Sxxx-ERSx, 2198-CAPMOD-2240, 2198-DCBUSCOND-RP312, 2198T-W25K-ER | CP-1 CP-2 | 24V+ 24V- | 40 | 10 (6) | 11.0 (0.43) | 1.7...1.8 (15.0...15.9) |

(1) Catalog numbers 2198T-W25K-ER, 2198-RP263, 2198-RP312, 2198-S263-ERSx, and 2198-S312-ERSx, use a slightly larger input wiring connector than the other Kinetix 5700 drive modules.

(2) Bus-bars and T-connectors can be added only to the right of the 24V DC input wiring connector.

Wire the Input Power Connector

The input power (IPD) connector applies to the 2198-Pxxx DC-bus power supply and 2198-RPxxx regenerative bus supply.



ATTENTION: Make sure the input power connections are correct when wiring the IPD connector plug. Insert the plug into the module connector and tighten screws to the specified torque value. Incorrect wiring/polarity or loose wiring can cause damage to equipment.

Figure 95 - IPD Connector Wiring

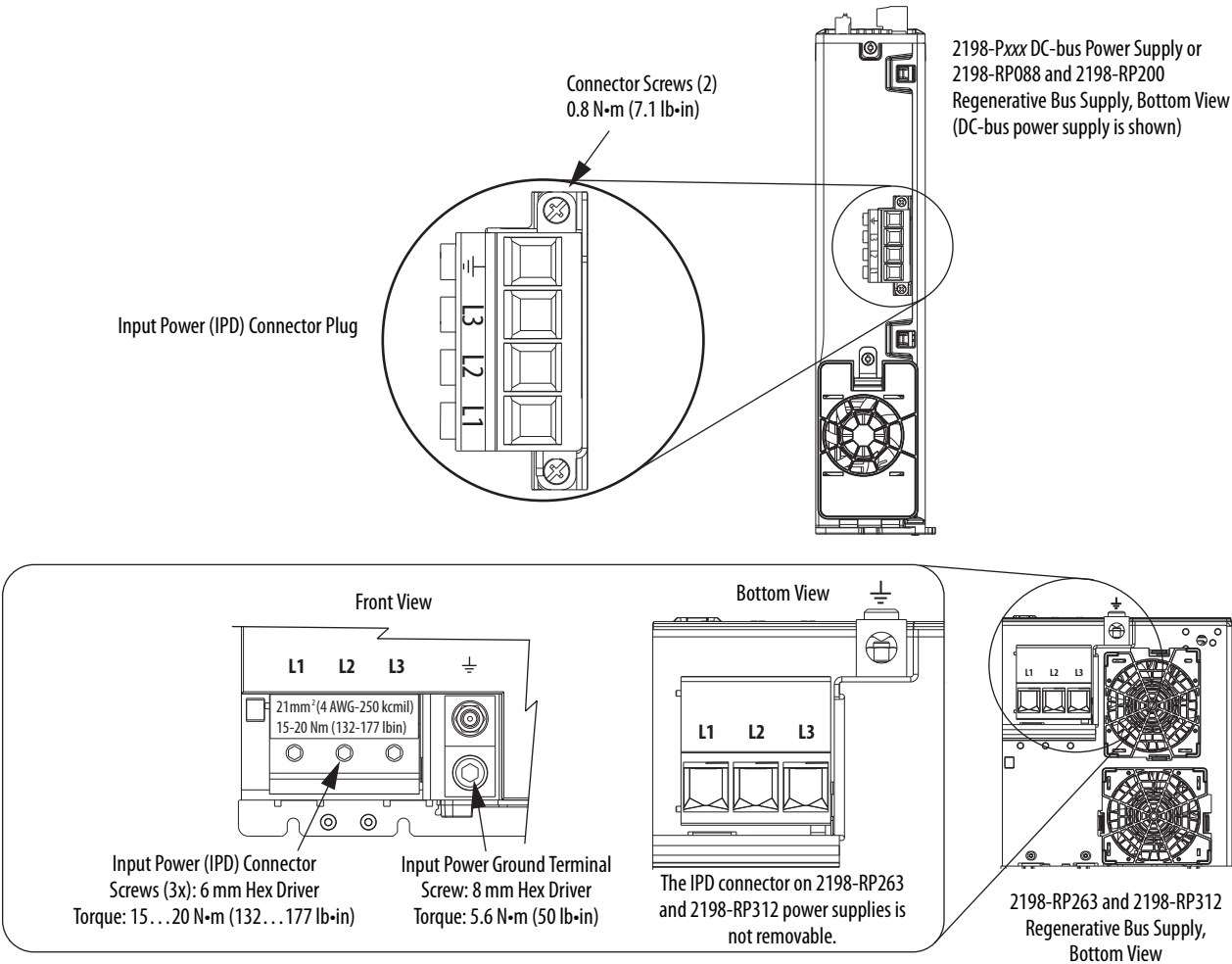




Table 72 - Input Power (IPD) Connector Specifications

| Regenerative Bus Supply Cat. No. | DC-bus Power Supply Cat. No. | Pin | Signal | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|-------------------------------------|---------------------------------|---|---|---|--------------------------|-----------------------------|
| 2198-RP088 | 2198-P031 2198-P070 |  L3 L2 L1 |  L3 L2 L1 | 6...10 (10...8) | 10.0 (0.39) | 0.8 (7.1) |
| 2198-RP200 | 2198-P141 2198-P208 | | | 10...35 (8...2) | 20.0 (0.79) | |
| 2198-RP263 2198-RP312 | — | | | 21.1...120 (4...250 kcmil) | 27.0 (1.06) | 15...20 (132...177) |

Wire the Contactor Enable Connector

The contactor enable (2-pin CED) connector applies to the DC-bus power supply. The regenerative bus supply has a 4-pin CED connector and includes wiring to the Converter OK relay.



ATTENTION: Wiring the contactor enable relay is required. To avoid personal injury or damage to the Kinetix 5700 drive system, wire the contactor enable relay into your control string so that:

- three-phase power is removed and the DC-bus power supply or regenerative bus supply is protected under various fault conditions.
- three-phase power is never applied to the Kinetix 5700 drive system before control power is applied.

Figure 96 - CED Connector Wiring - Connector Plug

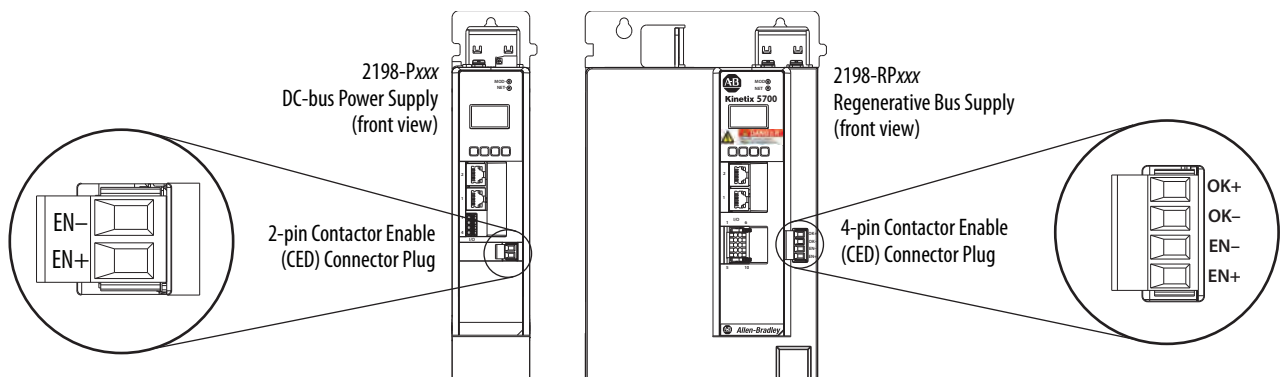


Table 73 - CED Connector Plug Specifications

| Regenerative Bus Supply Cat. No. | DC-bus Power Supply Cat. No. | Pin | Signal | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|--|--|------------|----------------------|---|--------------------------|-----------------------------|
| 2198-RP088 2198-RP200 2198-RP263 2198-RP312 | 2198-P031 2198-P070 2198-P141 2198-P208 | EN- EN+ | CONT EN- CONT EN+ | 0.14...2.5 (26...12) | 7.0 (0.28) | 0.4...0.5 (3.5...4.4) |
| | — | OK+ OK- | CONV OK+ CONV OK- | | | |

Wire the Digital Input Connectors

This section provides guidelines to assist you in making digital input connections. The digital inputs (IOD) and safety (STO) connector plugs for all 2198-xxxx-ERS3 and 2198-xxxx-ERS4 drives require special attention to help keep the plugs seated properly during normal operation.

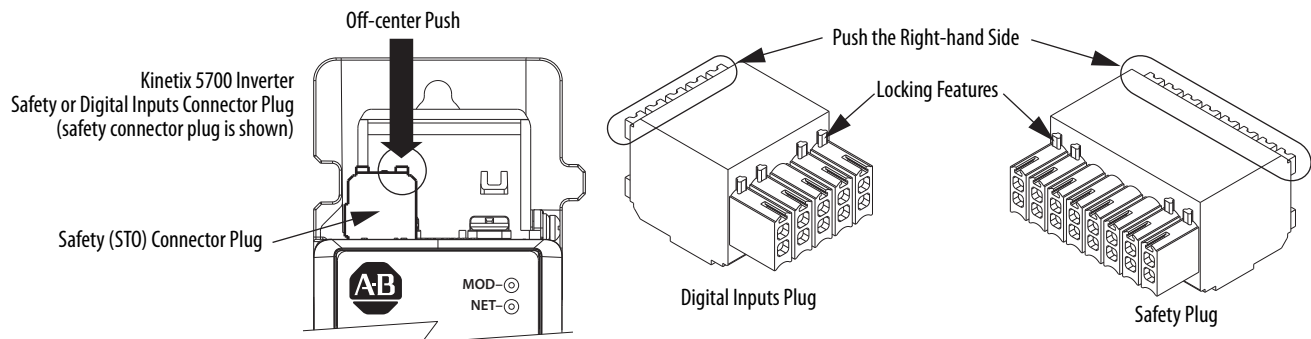
IMPORTANT When replacing 2198-xxxx-ERS3 (series A) single-axis and dual-axis inverters with 2198-xxxx-ERSx (series B) inverters, you must use the series B (safety and digital input) connector plugs that are included with your series B inverter.

2198-xxxx-ERS3 (series A) Connector Plugs

The right side of the safety and digital-input connector plugs require an off-center push when inserting them into their respective connectors. This applies to 2198-xxxx-ERS3 (series A) single-axis and dual-axis inverters.

IMPORTANT An off-center push is required to engage the locking features on the bottom of the safety and digital-input connector plugs and seat properly with the drive (STO and IOD) connectors. Failure to do this can result in the connector plugs pulling out of the drive connector during normal operation.

Figure 97 - 2198-xxxx-ERS3 (series A) Connector Plugs

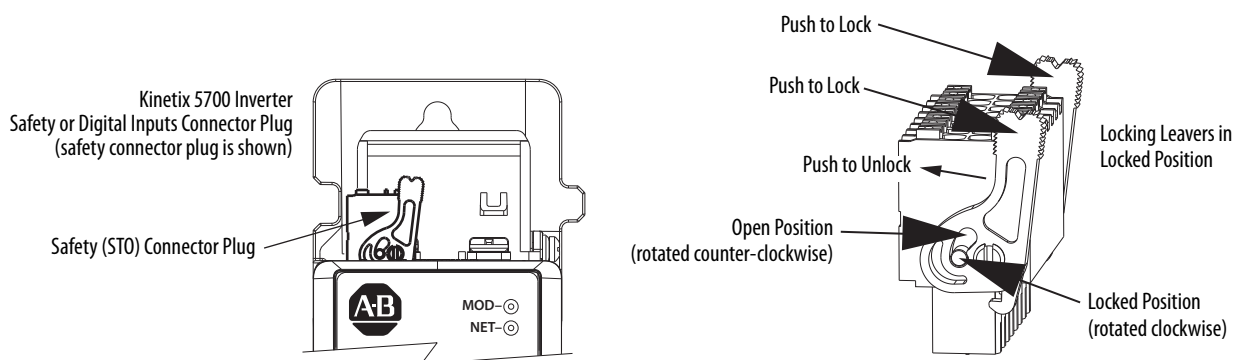


2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) Connector Plugs

The safety and digital-input connector plugs have two locking levers that you push in a clockwise direction as you insert the plugs into the drive connector. This is the locked position. Rotate the levers counter-clockwise (open position) to release the connector plugs. This applies to 2198-RPxxx regenerative bus supply and 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) single-axis and dual-axis inverters.

IMPORTANT Push the locking levers clockwise into the locked position as you insert the (STO and IOD) connector plugs. Failure to do this can result in the connector plugs pulling out of the drive connector during normal operation.

Figure 98 - 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) Connector Plugs



Wire the Safe Torque-off Connector

For the hardwired safe torque-off (STO) connector pinouts, feature descriptions, and wiring information, refer to Chapter 9 beginning on [page 305](#).

Wire the Digital Inputs Connector

The digital inputs (IOD) connector applies to the DC-bus power supply, 2198-RPxxx regenerative bus supply, single-axis inverter, and dual-axis inverters and use spring tension to hold wires in place.

Figure 99 - IOD Connector Wiring

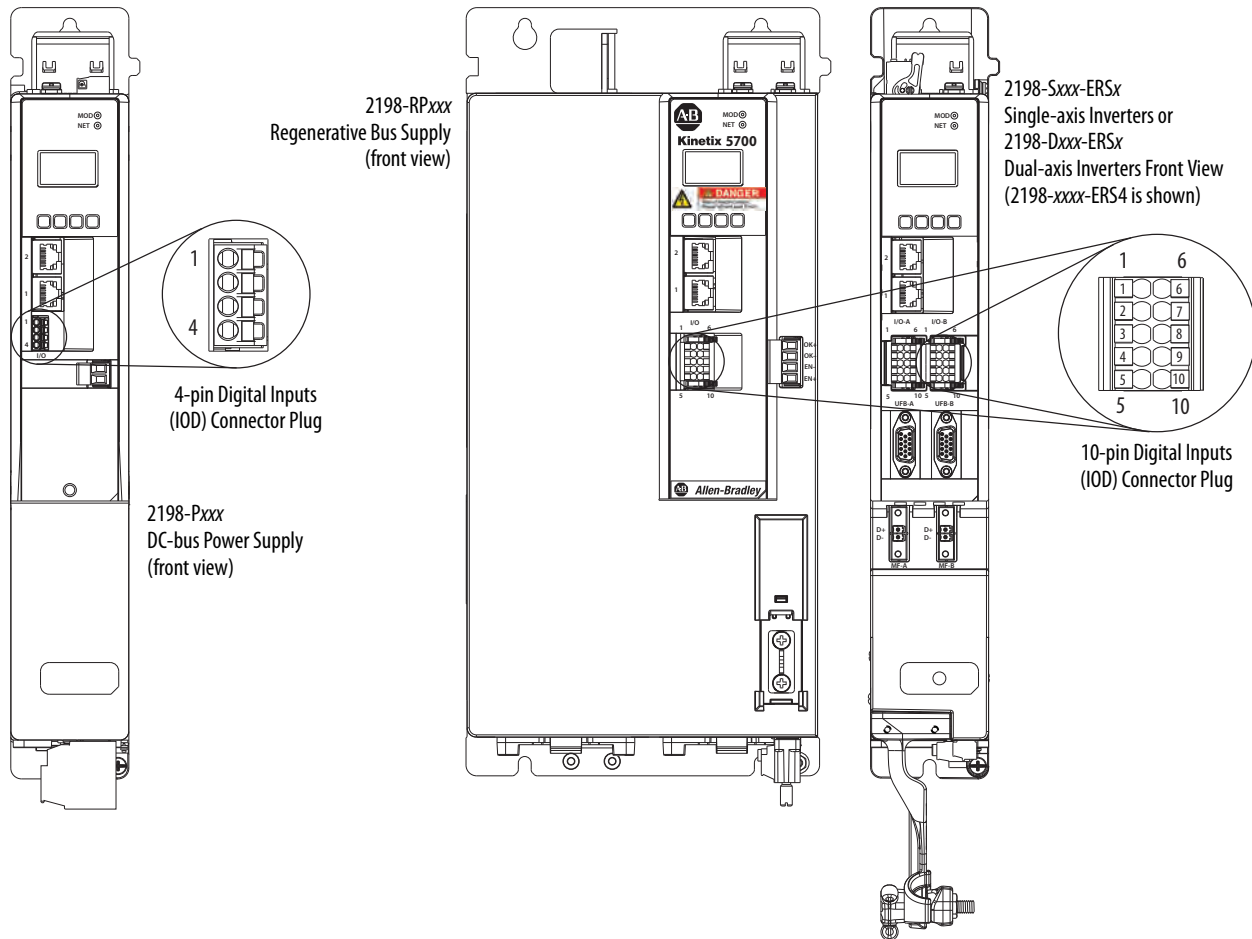


Table 74 - Digital Inputs (IOD) Connector Specifications

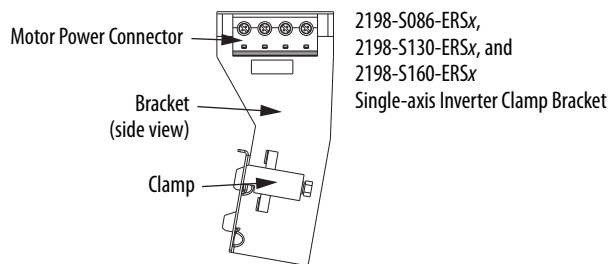
| Drive Module Cat. No. | IOD Pin | Signal | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|--|---|--|---|--------------------------|-----------------------------|
| 2198-Pxxx | IOD-1 IOD-2 IOD-3 IOD-4 | IN1 COM IN2 SHLD | 0.14...1.5 (26...16) | 10.0 (0.39) | N/A ⁽¹⁾ |
| 2198-RPxxx 2198-Dxxx-ERSx 2198-Sxxx-ERSx | IOD-1 IOD-2 IOD-3 IOD-4 IOD-5 IOD-6 IOD-7 IOD-8 IOD-9 IOD-10 | IN1 COM IN2 COM SHLD IN3 COM IN4 COM SHLD | 0.14...1.5 (26...16) | 10.0 (0.39) | N/A ⁽¹⁾ |

(1) This connector uses spring tension to hold wires in place.

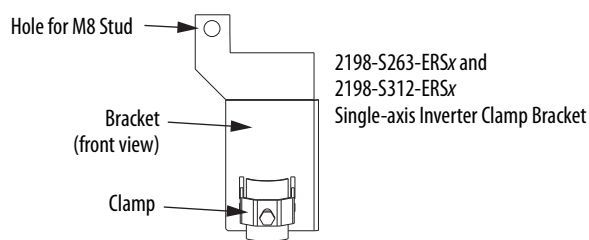
Wire Motor Power and Brake Connectors

Motor power connections are made at the MP connector on the bottom of the dual-axis and single-axis inverters. Motor brake connections are made at the BC connector. On dual-axis inverters, the BC connectors are on either side of the MP connectors on the bottom of the drive. On single-axis inverters, the BC connector is on the front of the drive.

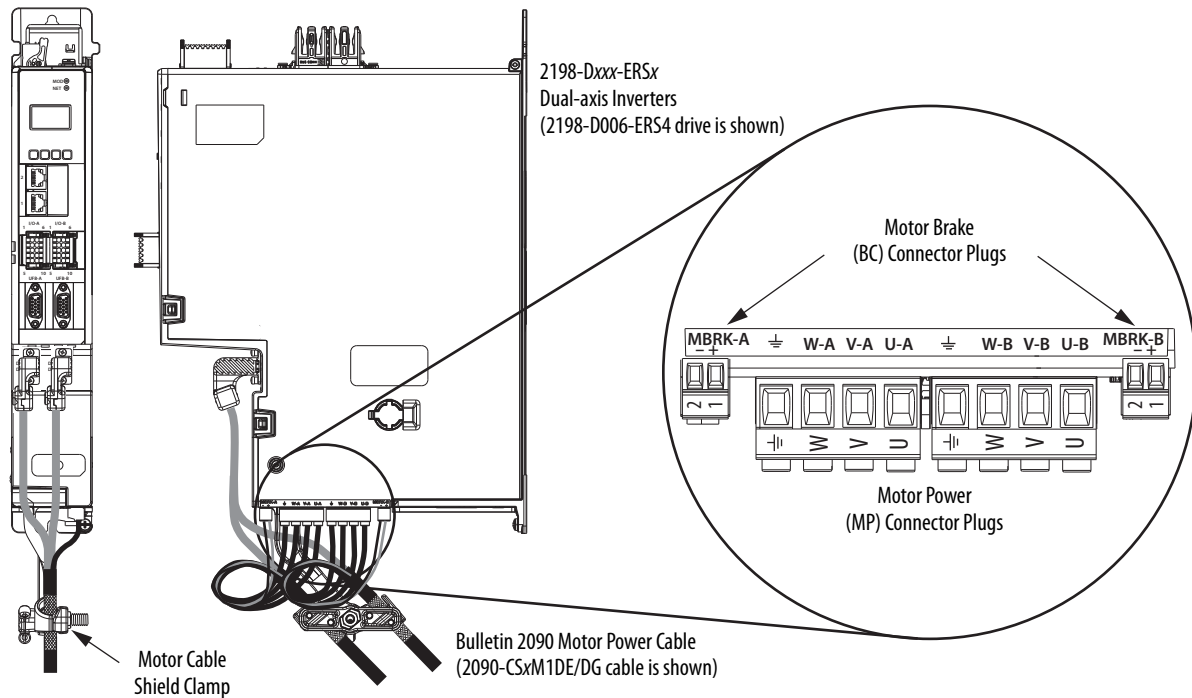
- On 2198-S086-ERSx, 2198-S130-ERSx, and 2198-S160-ERSx single-axis inverters, the motor power connector and shield clamp are mounted to a separate bracket that plugs into the bottom of the drive and has mounting screws to hold it secure.



- On 2198-S263-ERSx and 2198-S312-ERSx single-axis inverters, the motor power connector is part of the drive. The clamp bracket is included with the drive, but requires some assembly.



IMPORTANT The clamp included with 2198-S263-ERSx and 2198-S312-ERSx inverters is compatible with Bulletin 2090 (4 and 2 AWG) motor power cable. Do not use the clamp for smaller or larger cables.

Figure 100 - MP and BC Connector Wiring (dual-axis inverters)

ATTENTION: Make sure the motor power connections are correct when wiring the MP connector plug and that the plug is fully engaged in the module connector. Incorrect wiring/polarity or loose wiring can cause damage to equipment.

Table 75 - Motor Power (MP) Connector Specifications (dual-axis inverters)

| Dual-axis Inverter Cat. No. | Pin | Signal/Wire Color | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|--|------------------|--|--|--------------------------|-----------------------------|
| 2198-D006-ERSx 2198-D012-ERSx 2198-D020-ERSx 2198-D032-ERSx | U V W ⏏ | U Brown V Black W Blue ⏏ Green/Yellow | Motor power cable depends on motor/ drive combination. 0.75...2.5 ⁽¹⁾ (18...14) | 10.0 (0.39) | 0.5...0.6 (4.4...5.3) |
| 2198-D057-ERSx | | | 2.5...6 ⁽¹⁾ (14...10) | 10.0 (0.39) | 0.5...0.8 (4.4...7.1) |

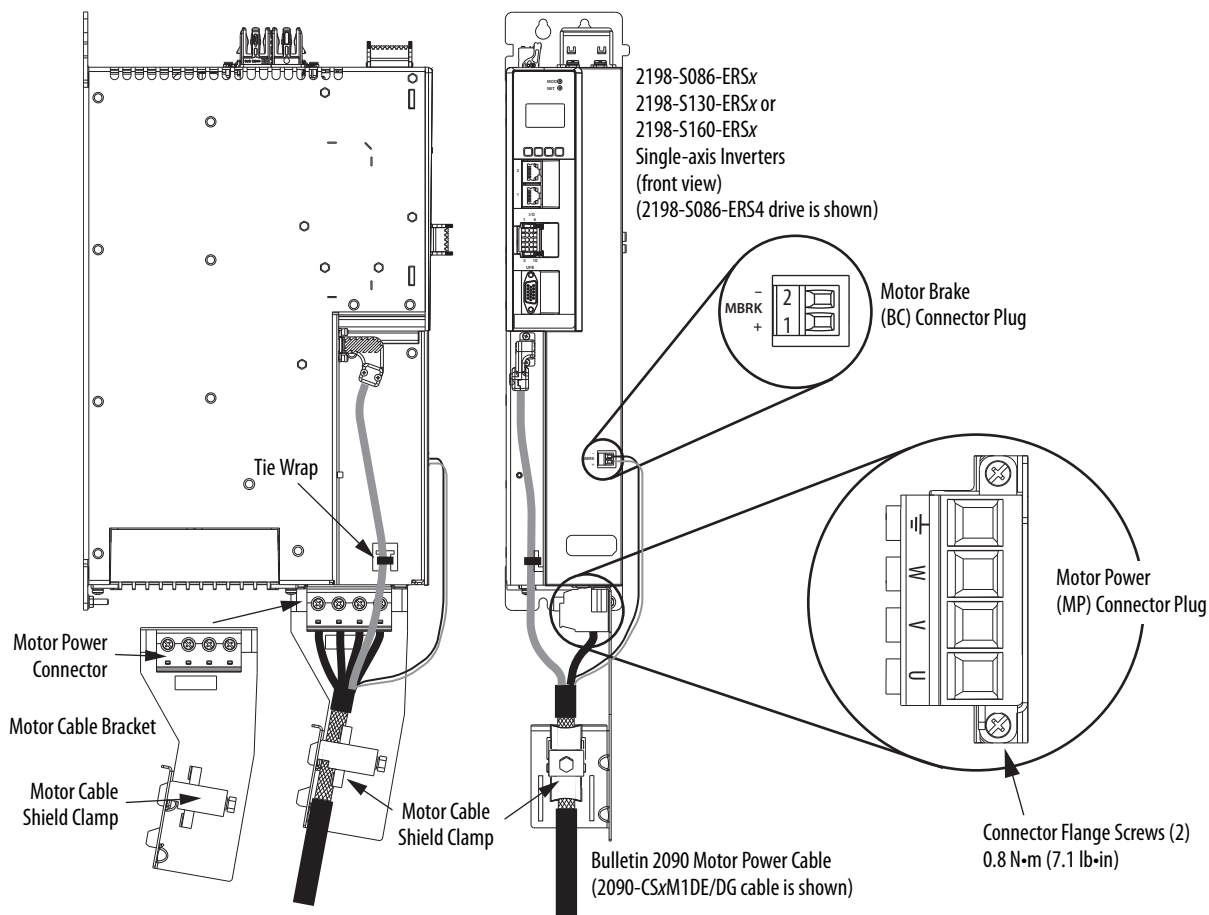
(1) Building your own single cables or using third-party single cables with Kinetix VP motors and actuators is not an option. Use 2090-CSxM1DE/DG single motor cables. Refer to the Kinetix Motion Accessories Specifications Technical Data, publication [KNX-TD004](#), for cable specifications.

Table 76 - Motor Brake (BC) Connector Specifications

| Drive Module Cat. No. | Pin | Signal/ Wire Color | Recommended Wire Size (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|----------------------------------|------|-----------------------|-----------------------------------|--------------------------|-----------------------------|
| 2198-Dxxx-ERSx 2198-Sxxx-ERSx | BC-1 | MBRK+/Black | N/A ⁽¹⁾ | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) |
| | BC-2 | MBRK-/White | | | |

(1) Motor brake wires are part of the Bulletin 2090 motor power cable.

Figure 101 - MP and BC Connector Wiring (single-axis inverters)



Attach the motor power wires to the motor power connector, plug in the motor feedback and brake connectors, and then connect the bracket to the drive.

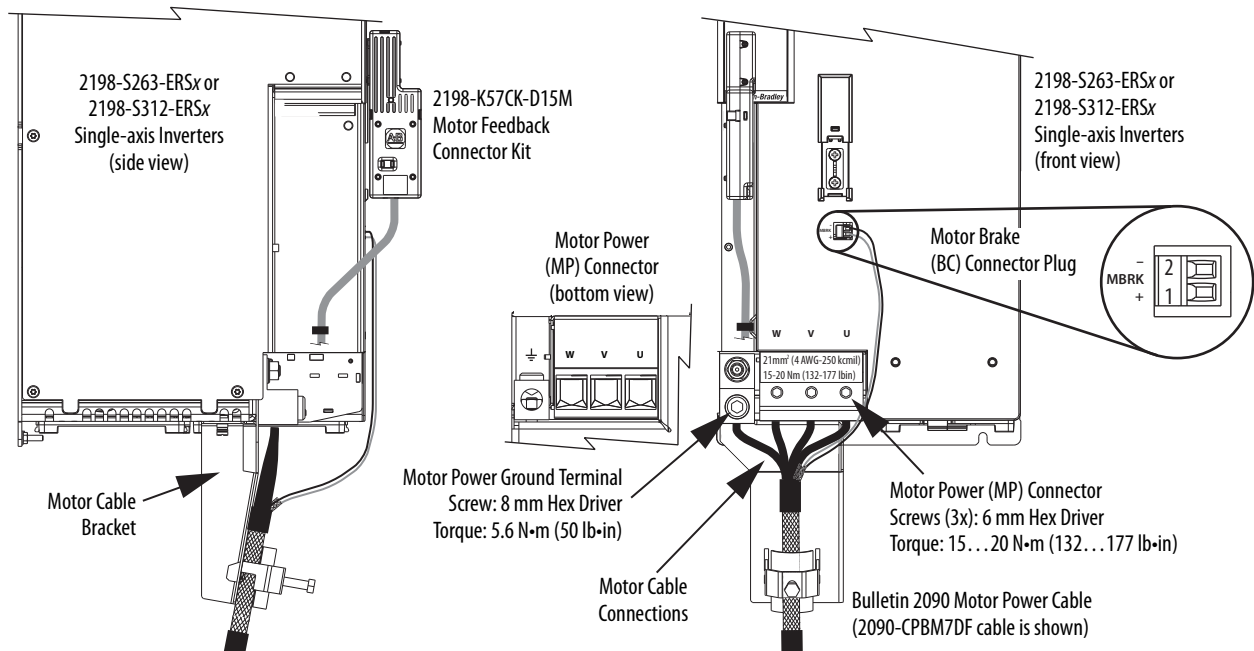


ATTENTION: Make sure the motor power connections are correct when wiring the MP connector plug. Insert the plug into the module connector and tighten flange screws to 0.8 N•m (7.1 lb•in). Incorrect wiring/polarity or loose wiring can cause damage to equipment.

Table 77 - Motor Power (MP) Connector Specifications (single-axis inverters)

| Drive Module Cat. No. | Pin | Signal/Wire Color | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Terminal Torque Value N•m (lb•in) | Flange Torque Value, max N•m (lb•in) |
|----------------------------------|-----------------|---|---|--------------------------|---|--|
| 2198-S086-ERSx 2198-S130-ERSx | U V W | U Brown V Black W Blue Green/Yellow | Motor power cable depends on motor/ drive combination. 6...16 ⁽¹⁾ (10...6) | 20.0 (0.79) | 2.5...4.5 (22...40) | 0.8 (7.1) |
| 2198-S160-ERSx | | | 10...35 (8...2) | | | |

(1) Building your own single cables or using third-party single cables for Kinetix VP motors and actuators is not an option. Use 2090-CSxM1DE/DG single motor cables. Refer to the Kinetix Motion Accessories Specifications Technical Data, publication [KNX-TD004](#), for cable specifications.

Figure 102 - MP and BC Connector Wiring (single-axis inverters)

Install the motor cable bracket (see [page 170](#)), then attach motor power and ground wires to the motor power connector and ground terminal. Plug in motor feedback and brake connectors.

Table 78 - Motor Power and Brake Connector Specifications (single-axis inverters)

| Drive Module Cat. No. | Pin | Signal/Wire Color | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Terminal Torque Value N·m (lb·in) |
|----------------------------------|------------------|--|---|-----------------------|-----------------------------------|
| 2198-S263-ERSx 2198-S312-ERSx | U V W ⏏ | U Brown V Black W Blue ⏏ Green/Yellow | 21.1...120 (4...250 kcmil) | 27.0 (1.06) | 15...20 (132...177) |

Maximum Cable Lengths

There are maximum cable length limitations that apply to the DC-bus cables (cluster to cluster) and motor power/brake and feedback cables (drive to motor).

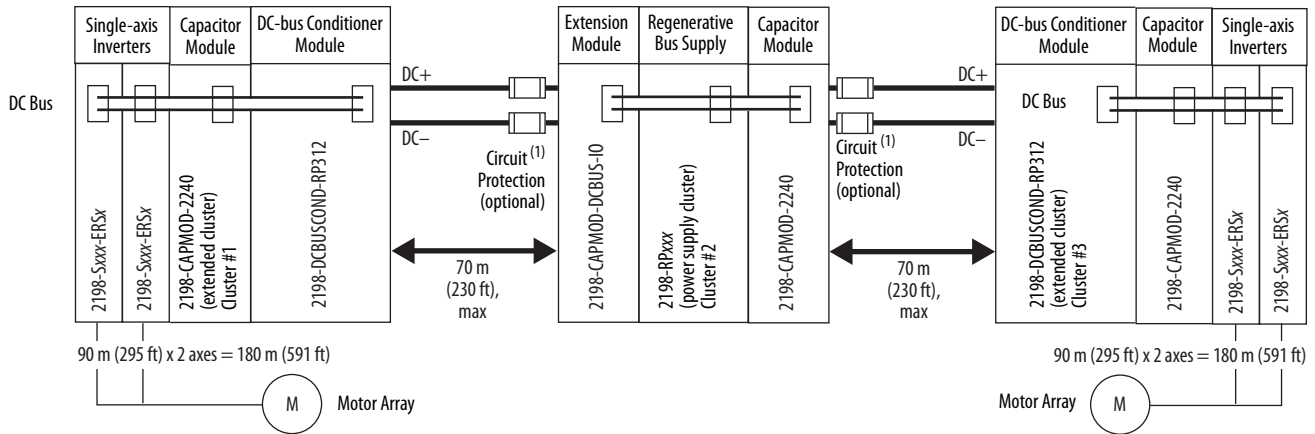
DC Bus Cluster-to-Cluster Cable Lengths

In this example, the power supply (center) feeds two extended clusters. The following DC-bus cable length limitations apply:

- The maximum DC-bus cable length (power supply cluster to extended cluster) is 70 m (230 ft)
- The maximum total DC-bus cable length is 140 m (459 ft)

IMPORTANT These examples feature the 2198-RPxxx regenerative bus supply, however, they also apply to the 2198-Pxxx DC-bus power supply.

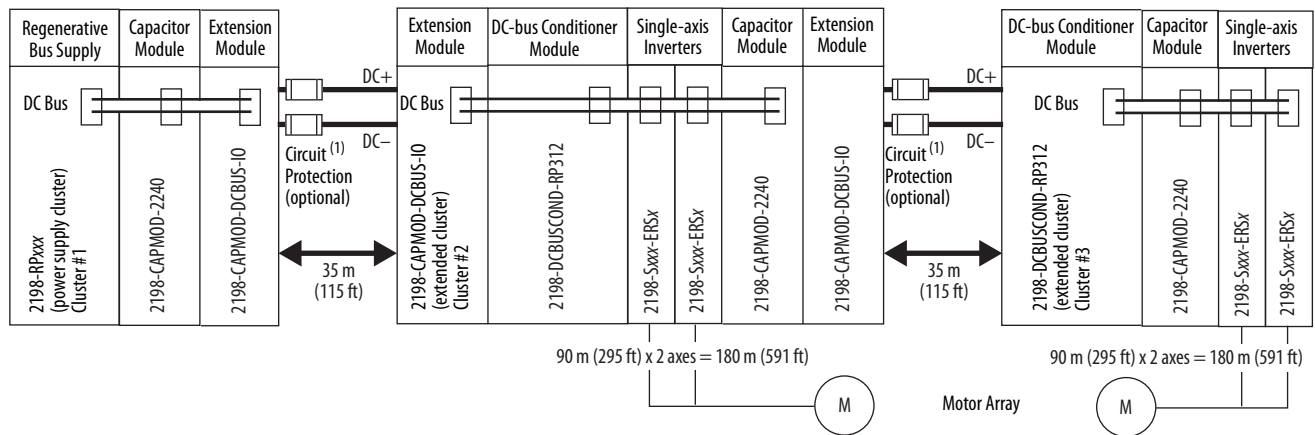
Figure 103 - Regenerative Bus Supply Example/Center Power Supply Cluster/104 A, max



(1) The National Electrical Code and local electrical codes take precedence over the values and methods provided.

When the power supply is positioned right or left of the extended clusters, the maximum total DC-bus cable length is 70 m (230 ft).

Figure 104 - Regenerative Bus Supply Example/Two Extended Clusters/208 A, max



(1) The National Electrical Code and local electrical codes take precedence over the values and methods provided.

IMPORTANT It is important to use low-inductance DC cable routing to help reduce the risk of voltage oscillations between clusters.

Low-inductance DC cable routing can be achieved by means of positive and negative cables routed in parallel and as close to one another as possible, less than 0.3 m (1.0 ft).

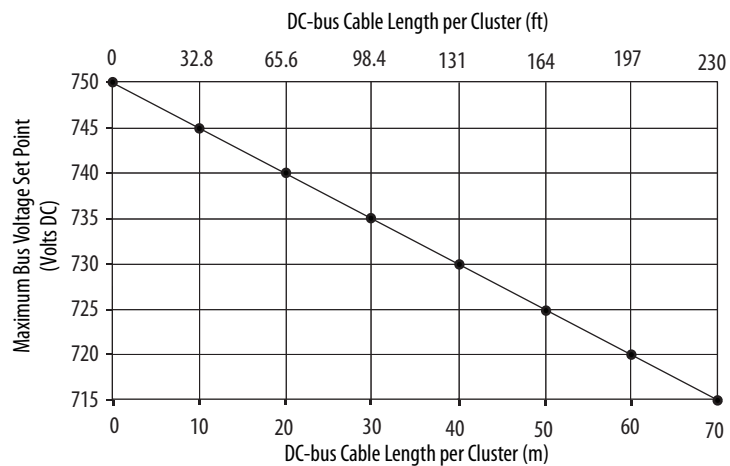
Size the DC cable in accordance with UL or applicable agency guidelines. The voltage drop across the DC cable can be further reduced by using a bigger cable size because voltage drop is directly proportional to cable resistance (see [Recommended DC-bus Cable Gauge](#) on page 157).

Table 79 - Recommended DC-bus Cable Gauge

| Regenerative Bus Supply Cat. No. | Recommended DC-bus Cable Gauge mm² (AWG/MCM) |
|---|--|
| 2198-RP088 | 53.5 (1/0) |
| 2198-RP200 | |
| 2198-RP263 | 152 (300 MCM) |
| 2198-RP312 | |
| DC-bus Power Supply Cat. No. | Recommended DC-bus Cable Gauge mm² (AWG/MCM) |
| 2198-P031 | 53.5 (1/0) |
| 2198-P070 | |
| 2198-P141 | |
| 2198-P208 | |
| 2198-P208 x 2 | 152 (300 MCM) |
| 2198-P208 x 3 | |

Observe the following guidelines when installing DC-bus cable:

- Use only unshielded cable for DC-bus voltage
- Use 1000V rated insulation cable in this application
- Make the DC+ and DC- cable distance as short as possible to help reduce cable inductance
- Twisting the DC-bus cable together is not required, but we recommend twisting to make sure the DC cables are routed close to each other
- The maximum Bus Voltage Set Point reduces linearly from 750V DC to 715V DC as the DC-bus cable length per cluster increases from 0 to 70 m (230 ft) respectively
- To prevent nuisance bus-overvoltage faults, the maximum Bus Voltage Set Point reduces linearly from 750V DC to 715V DC as the DC-bus cable length per cluster increases from 0 to 70 m (230 ft) respectively.



Drive to Motor Cable Lengths

Combined motor-power cable length for all axes on the same DC bus depends on the Kinetix 5700 system power supply in use.

- For applications that include the 2198-Pxxx DC-bus power supply and 2198-DBxx-F AC line filter, the maximum length is up to 400 m (1312 ft)
 - When 2198-P070, 2198-P141, and 2198-P208 DC-bus power supplies are used with 2198-DBRxx-F AC line filters, the maximum length is up to 1200 m (3937 ft)
 - When 2198-P031 DC-bus power supplies are used with 2198-DBxx-F or 2198-DBRxx-F line filters, the maximum length is up to 400 m (1312 ft)
- For applications that include the 2198-RPxxx regenerative bus supply and 2198-DBRxx-F AC line filter, the maximum length is up to 1200 m (3937 ft)

The maximum drive-to-motor cable length for Kinetix 5700 drives and motor/actuator combinations with 2090-CSxM1Dx cables is up to 90 m (295 ft), depending on the feedback type and overall system design. See Appendix D, beginning on [page 401](#), for more information.

Table 80 - Drive-to-Motor Feedback Cable Length

| Feedback Type | Cable Length, max ⁽¹⁾ m (ft) |
|------------------------------------|--|
| Single-turn or multi-turn absolute | up to 90 (295) |
| Incremental | up to 30 (98) |
| Heidenhain EnDat | up to 90 (295) |

(1) See Appendix D on [page 401](#) for the maximum motor-to-drive cable length for specific motor and actuator families.

IMPORTANT For more information on maximum motor cable lengths, see Appendix D beginning on [page 401](#).

This cable length example is based on the Kinetix 5700 system in [Figure 103](#) on [page 156](#).

Table 81 - Combined Cable Length Example

| Cluster | Total Motor Power Cable Length m (ft) | Total DC-bus Cable Length m (ft) |
|-------------------------|---|--|
| Extended Cluster #1 | 180 (591) | 70 (230) |
| Power Supply Cluster #2 | — | — |
| Extended Cluster #3 | 180 (591) | 70 (230) |
| Total | 360 (1182) | 140 (460) |

Wiring Single Cables

Kinetix 5700 inverters and Kinetix VPL, VPC-Q, VPF, VPH, VPS servo motors and Kinetix VPAR electric cylinder combinations use single motor-cable technology with motor power, feedback, and brake wires (when specified) housed in a single cable. Feedback wires are shielded separately and provide a shield braid for grounding in the connector kit.

IMPORTANT Due to the unique characteristics of single cable technology, designed for and tested with Kinetix 5700 inverters and Kinetix VP motors and actuators, you cannot build your own single cables or use third-party single cables.

Refer to the Kinetix Motion Accessories Specifications Technical Data, publication [KNX-TD004](#), for cable specifications.

Table 82 - Single Cable Catalog Numbers

| Motor /Actuator Cat. No. | Feedback Kit Cat. No. | Motor Cable Cat. No. (with brake wires) | Motor Cable Cat. No. (without brake wires) | Feedback Connections |
|---|-----------------------|---|--|--|
| VPL-Bxxxx VPF-Bxxxx VPH-Bxxxx VPS-Bxxxx VPC-Bxxxx-Q VPAR-Bxxxx | 2198-KITCON-DSL | 2090-CSBM1DE-xxxAxx (standard) cables 2090-CSBM1DE-xxxFxx (continuous-flex) cables | 2090-CSWM1DE-xxxAxx (standard) cables | 2198-KITCON-DSL kit is pre-wired to feedback conductors |
| | | 2090-CSBM1DG-xxxAxx (standard) cables 2090-CSBM1DG-xxxFxx (continuous-flex) cables | 2090-CSWM1DG-xxxAxx (standard) cables | Flying-lead feedback conductors. 2198-KITCON-DSL connector kit is purchased separately |

Table 83 - Kinetix VPL, VPF, VPH, VPS, VPC-Q, and VPAR Motor/Actuator Compatibility

| Drive Module ⁽¹⁾ Cat. No. | Kinetix VPL | Kinetix VPF | Kinetix VPH | Kinetix VPS | VPC-Bxxxx-Q ⁽²⁾ | Kinetix VPAR |
|---|-------------|-------------|-------------|-------------|----------------------------|--------------|
| 2198-Dxxx-ERSx | X | X | X | X | X | X |
| 2198-Sxxx-ERSx | — | — | — | — | | — |

(1) For wiring to compatible motors with 2198-S160-ERSx drives, see [Single-axis Inverter Power/Brake Cable Installation](#) on [page 168](#).

For wiring to compatible motors with 2198-S263-ERSx, 2198-S312-ERSx drives, see [Customer-supplied Motor Power Cables](#) on [page 178](#).

(2) Due to the motor power conductor size, VPC-B3004 motors do not support single cable technology. See the [Motor Power Cable Compatibility](#) table on [page 163](#) for VPC-Bxxxx-S, VPC-B3004x-M, and VPC-Bxxxx-Y motor cables intended for use with Kinetix 5700 drives.

Motor Feedback Connections



ATTENTION: When routing 2090-CSxM1DE cables through tight spaces, we recommend removing the 2198-KITCON-DSL feedback connector kit to avoid causing damage to the kit.

Single motor-cable feedback connections are made by using the 2198-KITCON-DSL feedback connector kit.

- 2090-CSxM1DE cables include the connector kit pre-wired to the feedback conductors.
- 2090-CSxM1DG cables have flying-lead feedback conductors. The 2198-KITCON-DSL feedback connector kit must be purchased separately and installed.

Figure 105 - MF Connector Wiring Example

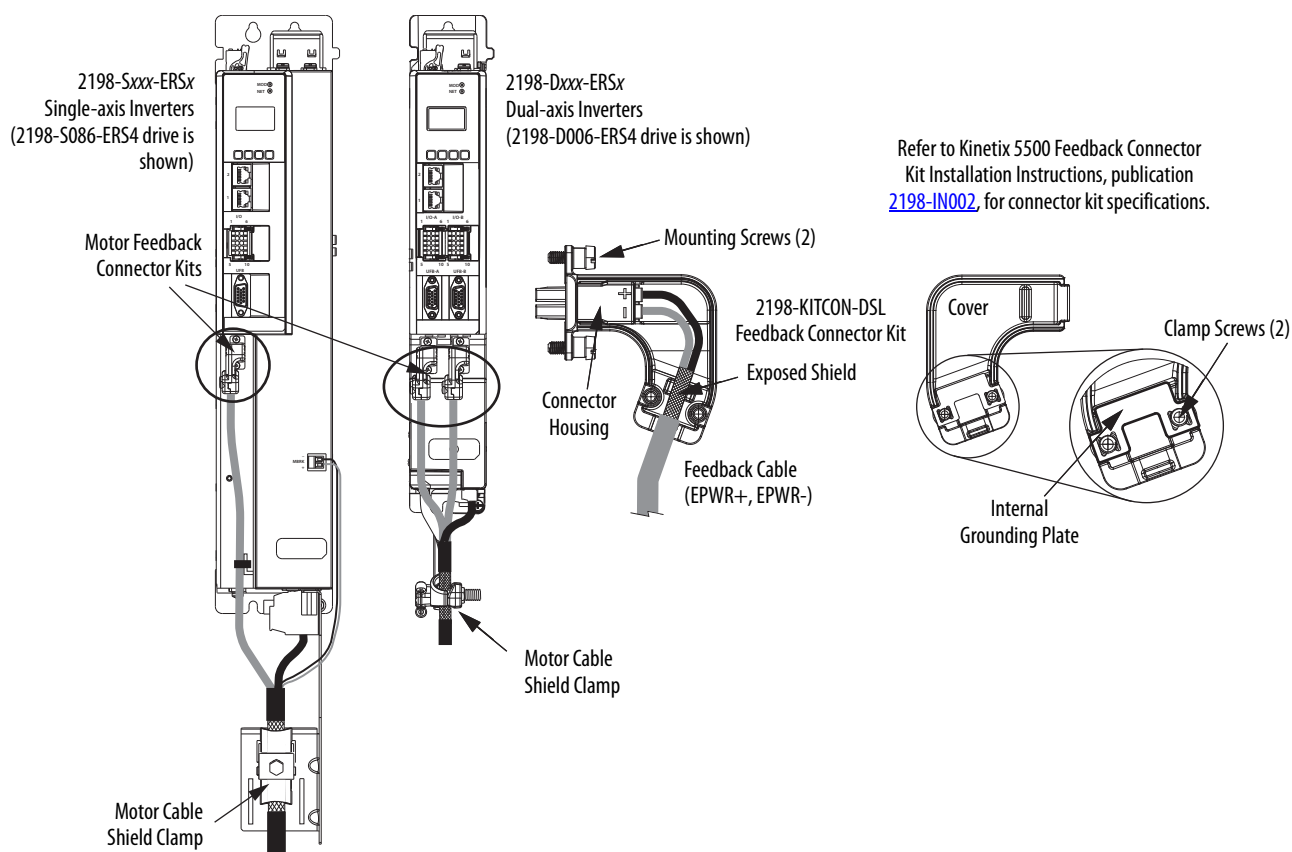


Table 84 - Motor Feedback (MF) Connector Specifications

| Drive Module Cat. No. | Pin | Signal/ Wire Color | Wire Size AWG | Strip Length mm (in.) | Torque Value N•m (lb•in) |
|----------------------------------|------|-----------------------|------------------|--------------------------|-----------------------------|
| 2198-Dxxx-ERSx 2198-Sxxx-ERSx | MF-1 | D+/Blue | 22 | 10.0 (0.39) | 0.4 (3.5) |
| | MF-2 | D-/White/Blue | | | |

Apply the Single Motor Cable Shield Clamp

Factory-supplied 2090-Series single motor cables are shielded, and the braided cable shield must terminate at the drive during installation. A small portion of the cable jacket has been removed to expose the shield braid. The exposed area must be clamped (with the clamp provided) at the bottom front of the drive.



SHOCK HAZARD: To avoid hazard of electrical shock, make sure shielded power cables are grounded according to recommendations.

These procedures assume you have completed wiring your motor power, brake, and feedback connectors and are ready to apply the cable shield clamp.

Dual-axis Inverter Shield Clamp Installation

Follow these steps to apply the dual-axis inverter cable shield clamp.

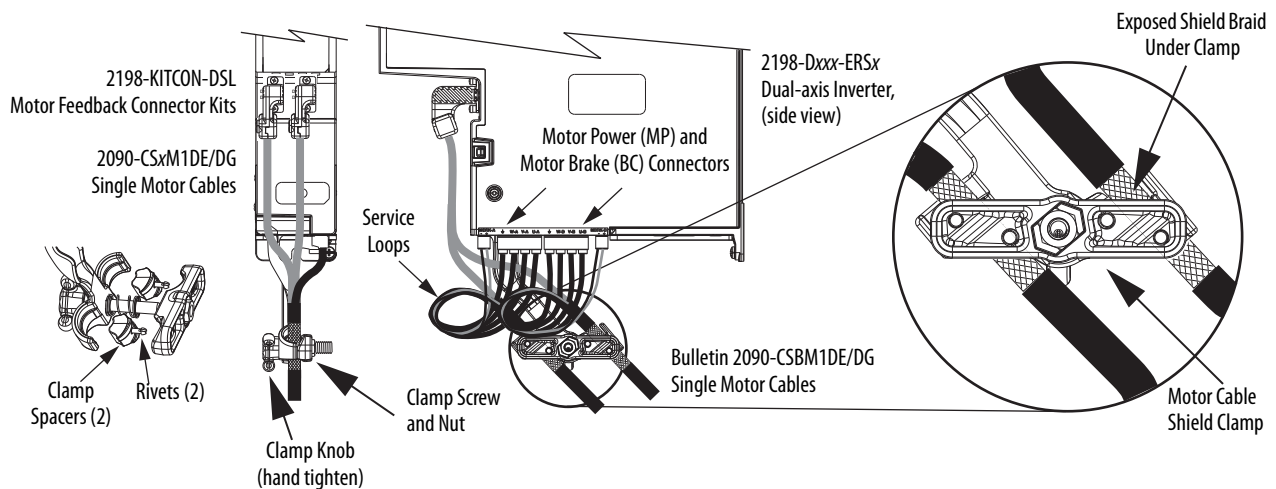
1. Loosen the clamp knob and determine if you need the clamp spacers.

Clamp spacers are included with the dual-axis inverters for cable diameters that are too small for a tight fit within the drive clamp alone.

The spacers are held captive by nylon rivets. Remove the rivets and spacers when your cable shield is of sufficient diameter for the clamp to hold the cable secure.

IMPORTANT Use clamp spaces (supplied with drive) when the cable shield diameter is too small for a tight fit within the shield clamp. Remove the clamp spacers when not needed.

Figure 106 - Dual-axis Inverter Shield Clamp Installation



2. Position the exposed portion of each cable braid directly in line with the clamp.
3. Hand tighten the clamp knob.

Make sure the cable clamp tightens around the cable shield and provides a good bond between the cable shield and the drive chassis.

Only finger-tight torque on the clamp knob is required. The cable should not move within the clamp under its own weight or when slight pressure is applied by hand.

IMPORTANT If the power/brake cable shield on the dual-axis inverter has a loose fit inside the shield clamp, use a clamp spacer to reduce the clamp diameter. When the clamp knob is tightened, the result must be a high-frequency bond between the cable shield and the drive chassis.

Make sure the clamp is aligned with the shield braid and not heat shrink.

4. Repeat [step 1](#) through [step 3](#) for each dual-axis inverter.

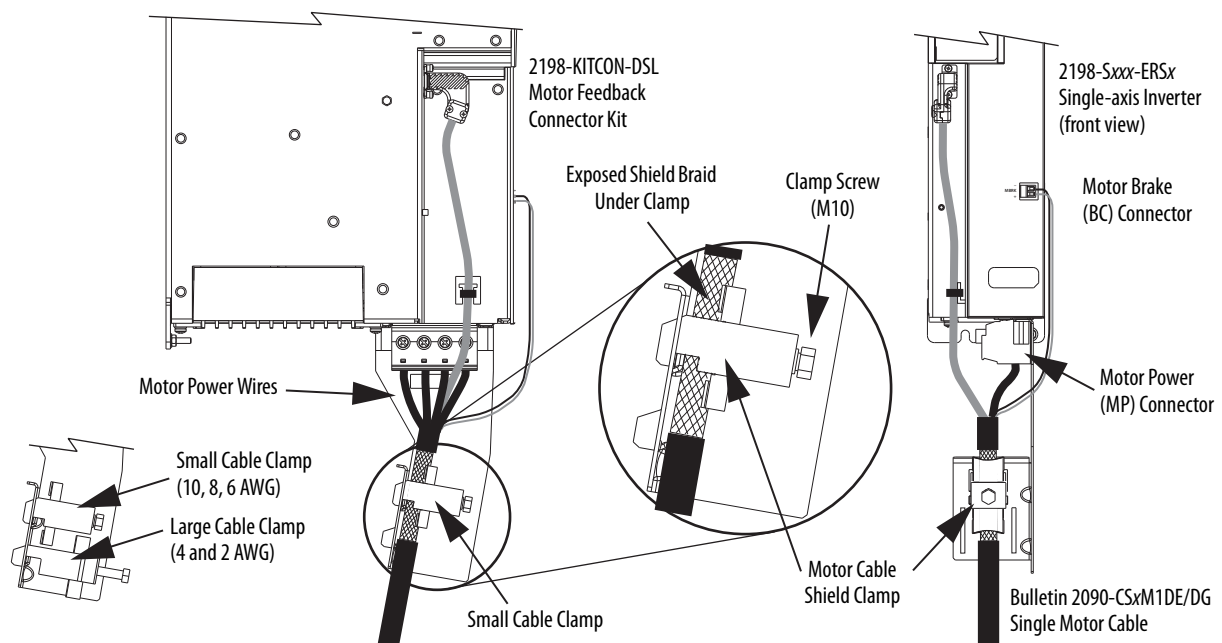
Single-axis Inverter Shield Clamp Installation

Single-axis inverters include a two-position cable-shield clamp. Use which ever clamp holds your cable shield firmly. Replacement clamps are available.

Follow these steps to apply the single-axis inverter motor-cable shield clamp.

1. Remove the larger (lower position) clamp.
2. Loosen the clamp screw.

Figure 107 - Cable Installation Example



- Position the exposed portion of the cable braid directly in line with the clamp.

IMPORTANT Make sure the clamp is aligned with the shield braid and not the heat shrink.

- Tighten the clamp screw.

Make sure the cable clamp tightens around the overall cable shield and provides a good bond between the cable shield and the drive chassis.

Torque value 5.6 N•m (50 lb•in), max.

- Repeat [step 1](#) through [step 4](#) for each drive in multi-axis configurations.

Wiring Power/Brake and Feedback Cables

Kinetix 5700 drives are also compatible with many other Allen-Bradley® motors and actuators that have separate power/brake and feedback cables. Follow these guidelines when 2090-CPxM7DF (power/brake) cables and 2090-CFBM7DF (feedback) cables are used in a new installation or reused in an existing installation with Kinetix 5700 servo drives.

Motor Power and Brake Cables

The motors and actuators in [Table 85](#) have separate power/brake and feedback cables. The motor power/brake cable attaches to the cable clamp on the drive and the power/brake conductors attach to the MP and BC connectors, respectively.

Table 85 - Motor Power Cable Compatibility

| Motor/Actuator Cat. No. | Motor Power Cables ⁽¹⁾ (with brake wires) | Motor Power Cables ⁽¹⁾ (without brake wires) |
|---|--|--|
| MPL-B15xxx-xx7xAA, MPL-B2xxx-xx7xA MPL-B3xxx-xx7xAA...MPL-B9xxx-xx7xAA | 2090-CPBM7DF-xxAAxx (standard) or 2090-CPBM7DF-xxAFxx (continuous-flex) | 2090-CPWM7DF-xxAAxx (standard) or 2090-CPWM7DF-xxAFxx (continuous-flex) |
| MPM-Bxxxx, MPF-Bxxxx, MPS-Bxxxx | | |
| MPAS-Bxxxx1-V05SxA, MPAS-Bxxxx2-V20SxA MPAI-Bxxxx, MPAR-B3xxx (series B) MPAR-B1xxx and MPAR-B2xxx (series B and C) | | |
| VPC-Bxxxxx-S VPC-B3004x-M, VPC-Bxxxxx-Y | | |
| RDB-Bxxxx-7/3 | | |
| MPAS-Bxxxxx-ALMx2C LDAT-Sxxxxxx-xDx LDAT-Sxxxxxx-xBx LDC-xxxxxx-xHTxx | N/A | |
| HPK-Bxxxx, HPK-Exxxx | Customer-supplied | |

(1) Refer to the Kinetix Motion Accessories Specifications Technical Data, publication [KNX-TD004](#), for cable specifications.

Table 86 - Legacy Motor Power Cables

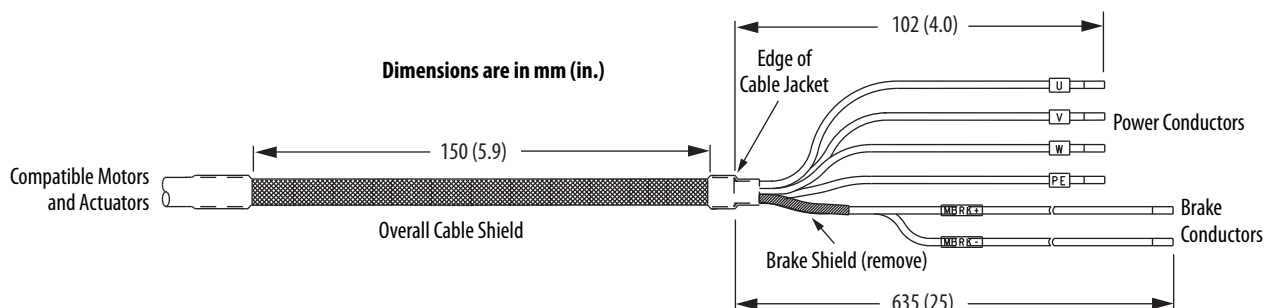
| Motor Cable | Description | Cat. No. |
|-----------------|-----------------------|---------------------|
| Standard | Power/brake, threaded | 2090-XXNPMF-xxSxx |
| | Power-only, bayonet | 2090-XXNPMP-xxSxx |
| Continuous-flex | Power/brake, threaded | 2090-CPBM4DF-xxAFxx |
| | Power-only, threaded | 2090-CPWM4DF-xxAFxx |
| | Power-only, bayonet | 2090-XXTPMP-xxSxx |

Table 87 - Induction Motor Power Cable Specifications

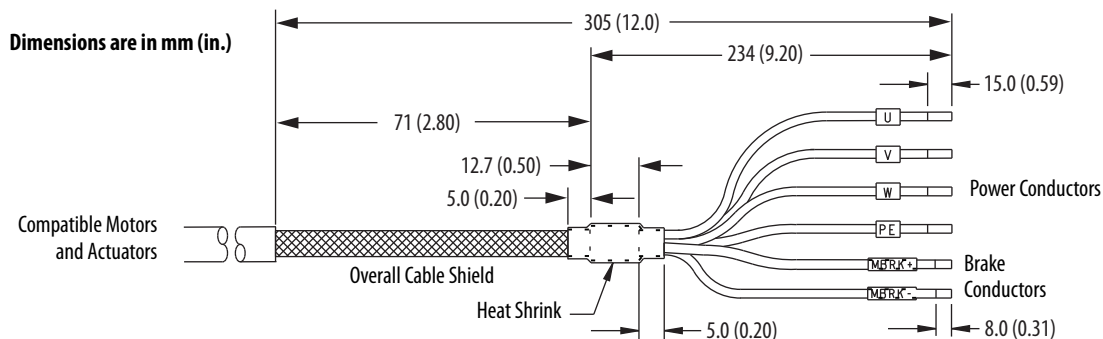
| Cable Manufacturer | Cable Series | Voltage Rating | Temperature Rating |
|--------------------|--------------|----------------|--------------------|
| Belden | 29500-29507 | 600V | 90 °C (194 °F) |
| Lapp Group | ÖLFEX VFD XL | | |
| SAB | VFD XLPE TR | | |

Motor Power/Brake Cable Series Change

Motor power and brake conductors on 2090-CPBM7DF (series A) cables have the following dimensions from the factory. If your cable is reused from an existing application, the actual conductor lengths could be slightly different.

Figure 108 - 2090-CPBM7DF (series A) Power/brake Cable Dimensions

Motor power and brake conductors on 2090-CPBM7DF (series B) 12 and 10 AWG standard, non-flex cables provide (drive end) shield braid and conductor preparation designed for compatibility with multiple Kinetix servo-drive families, including Kinetix 5700 drives.

Figure 109 - 2090-CPBM7DF (series B, 10 or 12 AWG) Power/brake Cable Dimensions

Dual-axis Inverter Power/Brake Cable Installation

Dual-axis inverters are compatible with several Allen-Bradley motor families that require 16, 14, 12, and 10 AWG power/brake cables. Refer to [Table 88](#) for the proper procedure designed for your 2090-CPxM7DF cable.



SHOCK HAZARD: To avoid hazard of electrical shock, make sure shielded power cables are grounded according to recommendations.

Table 88 - Cable Preparation for 2090-CPxM7DF Cables

| Cable Power Conductor Size AWG | Go to: |
|-----------------------------------|--|
| 16 and 14 | Cable Preparation for 16 and 14 AWG Cables |
| 12 and 10 | Cable Preparation for 12 and 10 AWG Cables |

Cable Preparation for 16 and 14 AWG Cables

For dual-axis inverters, the 2090-CPBM7DF power conductor length, 102 mm (4.0 in.), is sufficiently long to reach the MP connector plug and provides adequate stress relief. However, you must remove additional insulation from the power conductors to achieve a strip length of 10 mm (0.39 in.).

The brake conductor length, 635 mm (25 in.), is much longer than necessary. We recommend that you measure 188 mm (7.4 in.) from the edge of the cable jacket (that is covered by heat shrink) and trim off the rest.

Refer to [Figure 110](#) and on [page 167](#) for a typical installation example. For strip lengths and torque values, refer to [Table 75](#) and [Table 76](#) on [page 153](#).

Cable Preparation for 12 and 10 AWG Cables

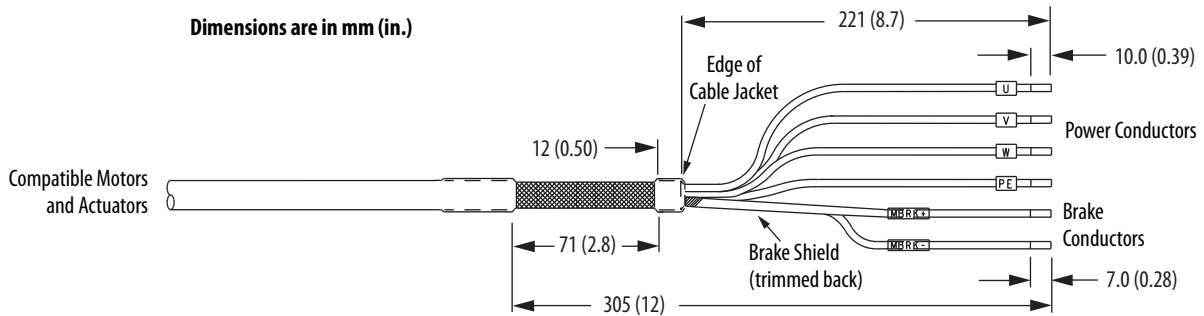
2090-CPBM7DF (series B) 12 and 10 AWG cables are designed for use with Kinetix 5700 dual-axis inverters and do not require any modifications.

For dual-axis inverters, 2090-CPBM7DF (series A) 12 and 10 AWG conductors are too short and stiff to reach the MP connector plug and provide adequate stress relief.

Follow these steps to prepare your existing (series A) 12 and 10 AWG cables.

1. Remove any heat shrink or small sections of cable jacket from your existing cable.
2. Remove additional cable jacket and shield braid from your cable following the diagram below.

Include a new 12 mm (0.5 in.) section of cable jacket and slide it down to the end of the shield braid.



3. Apply heat shrink to the small section of cable jacket.

Refer to [Figure 111](#) for typical installation examples for series A and series B cables. For strip lengths and torque values, refer to [Table 75](#) and [Table 76](#) on [page 153](#).

Dual-axis Inverter Shield Clamp Installation

Follow these steps to apply the dual-axis inverter cable shield clamp.

1. Loosen the clamp knob and determine if you need the clamp spacers.

The power/brake cable shield attaches to the dual-axis inverter cable clamp. Clamp spacers are included with the dual-axis inverters for cable diameters that are too small for a tight fit within the drive clamp alone.

The spacers are held captive by nylon rivets. Remove the rivets and spacers when your cable shield is of sufficient diameter for the clamp to hold the cable secure.

IMPORTANT Most 2090-CPxM7DF power/brake cables require the spacers. Only 10 AWG cables with brake conductors have a diameter large enough to fit in the clamp without the spacers.

2. Position the exposed portion of each cable braid directly in line with the clamp.
3. Hand tighten the clamp knob.

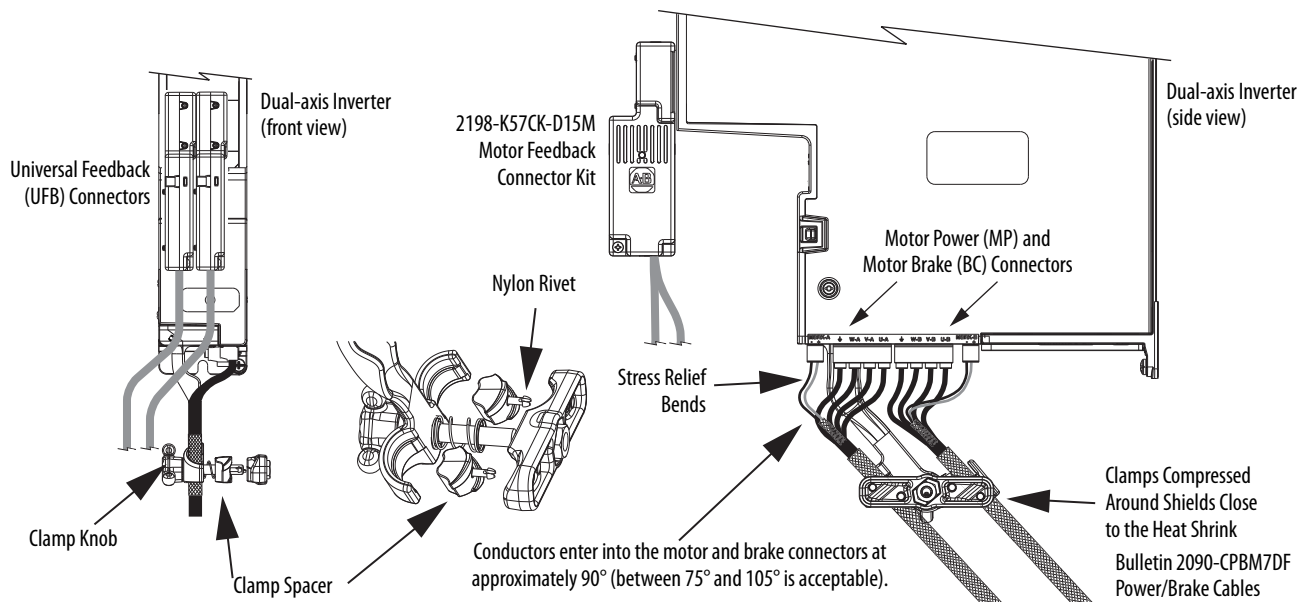
Make sure the cable clamp tightens around the cable shield and provides a good bond between the cable shield and the drive chassis.

Only finger-tight torque on the clamp knob is required. The cable should not move within the clamp under its own weight or when slight pressure is applied by hand.

IMPORTANT If the power/brake cable shield on the dual-axis inverter has a loose fit inside the shield clamp, use a clamp spacer to reduce the clamp diameter. When the clamp knob is tightened, the result must be a high-frequency bond between the cable shield and the drive chassis.

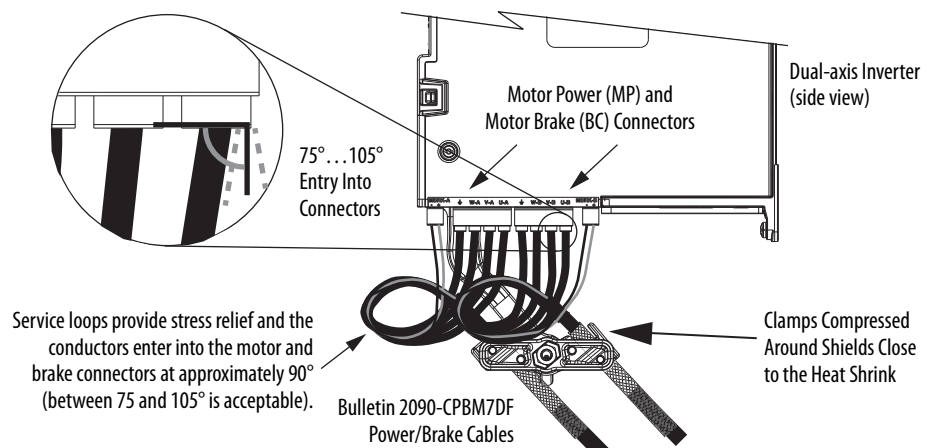
Make sure the clamp is aligned with the shield braid and not heat shrink.

Figure 110 - Dual-axis Inverter Cable Installation (16 and 14 AWG cable)



12 and 10 AWG (series A) cables, prepared as shown on [page 165](#), and series B cables have longer conductors that support service loops.

Figure 111 - Dual-axis Inverter Cable Installation (series A and B, 12 and 10 AWG cable)



4. Repeat [step 1](#) through [step 3](#) for each dual-axis inverter.

IMPORTANT Avoid sharp bends in the power and brake conductors. You must route the power and brake conductors from where they exit the clamp and enter the motor and brake connectors so that stress-relief bends or service loops are formed.

Single-axis Inverter Power/Brake Cable Installation

All single-axis inverters include a cable-shield clamp bracket that is designed to ground (bond) 2090-CPBM7DF cable shields with the drive chassis.

- 2198-S086-ERSx, 2198-S130-ERSx, and 2198-S160-ERSx single-axis inverters include a two-position cable-shield clamp that accommodates 10, 8, 6, 4, and 2 AWG power conductors. The clamp bracket is connected to the motor power connector and ships with the drive.
- 2198-S263-ERSx and 2198-S312-ERSx single-axis inverters include a single-position cable-shield clamp that accommodates 4 and 2 AWG power conductors. The clamp bracket ships with the drive, but requires some assembly.

2090-CPBM7DF (series B) 10 AWG cables are designed for use with Kinetix 5700 single-axis inverters and do not require any modifications.



SHOCK HAZARD: To avoid hazard of electrical shock, make sure shielded power cables are grounded according to recommendations.

For single-axis inverters, the 2090-CPBM7DF (series A) cable power conductors, 102 mm (4.0 in.), require adjustment only when the smaller (upper position) clamp is used. The upper position is for smaller cables (10, 8, and 6 AWG). The lower position is for larger cables (4 and 2 AWG). We recommend that you measure from the edge of the cable jacket (that is covered with heat shrink) and trim the power conductors as shown in [Table 89](#).

Table 89 - Power Conductor Trimmed Length

| Power Conductor Size AWG | Power Conductor Length mm (in.) |
|-----------------------------|------------------------------------|
| 6 and 8 | 75 (2.9) |
| 10 | No trimming required |
| 2 and 4 | 85 (3.3) |

The (series A) 2090-CPBM7DF brake conductor length, 635 mm (25 in.) is longer than necessary. Measure from the edge of the heat shrink and trim the brake conductors as shown in [Table 90](#).

Table 90 - Brake Conductor Trimmed Length

| Power Conductor Size AWG | Brake Conductor Length mm (in.) |
|-----------------------------|------------------------------------|
| 6, 8, 10 | 315 (12.4) |
| 2 and 4 | 375 (14.7) |

See [Figure 112](#) on [page 170](#) for a typical series-A installation example. For strip lengths and torque values, see [Table 76](#) and [Table 77](#) on [page 153](#) and [Table 78](#) on [page 155](#).

Single-axis Inverter Shield Clamp Installation

Follow these steps to apply the 2198-S086-ERSx, 2198-S130-ERSx, and 2198-S160-ERSx single-axis inverter motor-cable shield clamp when using 2090-CPBM7DF motor power cables.

1. Remove the larger (lower position) clamp or small (upper position) clamp, depending on the power conductor size used in your application.

IMPORTANT Make sure to use the proper size clamp depending on cable diameter.

2. Loosen the clamp screw.
3. Position the exposed portion of the cable braid directly in line with the clamp.

IMPORTANT Make sure the clamp is aligned with the shield braid and not heat shrink.

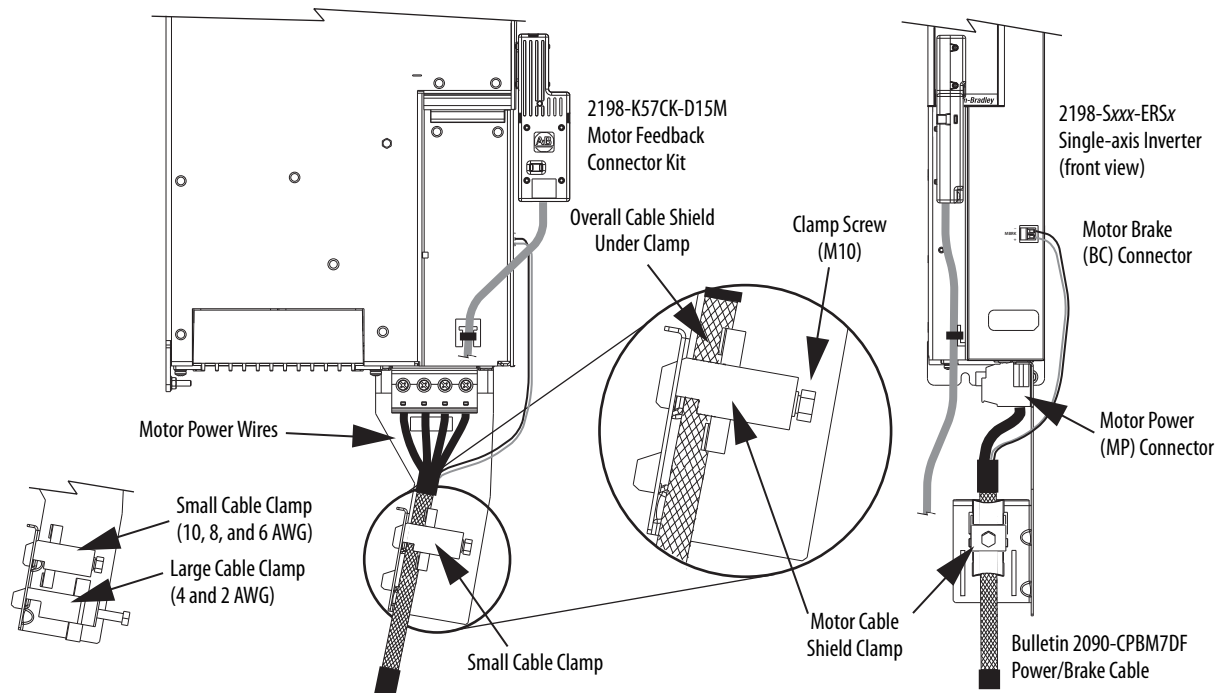
4. Tighten the clamp screw.

Make sure the cable clamp tightens around the overall cable shield and provides a good bond between the cable shield and the drive chassis.

Torque value 5.6 N•m (50 lb•in), max.

In [Figure 112](#), 10 AWG (series A) cables are prepared per [Table 89](#) and [Table 90](#) on [page 169](#), and series B cables do not require preparation.

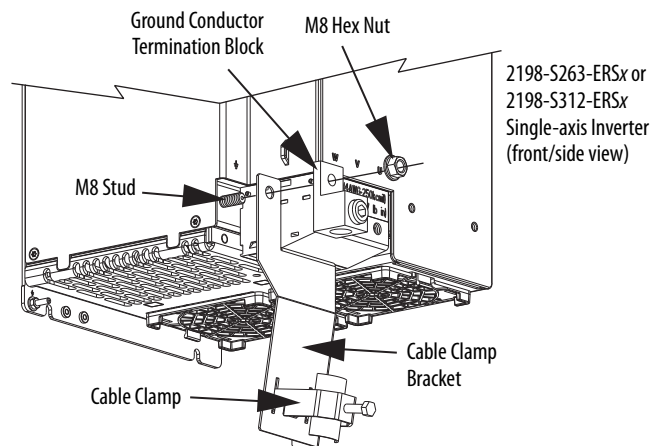
Figure 112 - Single-axis Inverter Cable Installation (series A and B, 10 AWG cables)



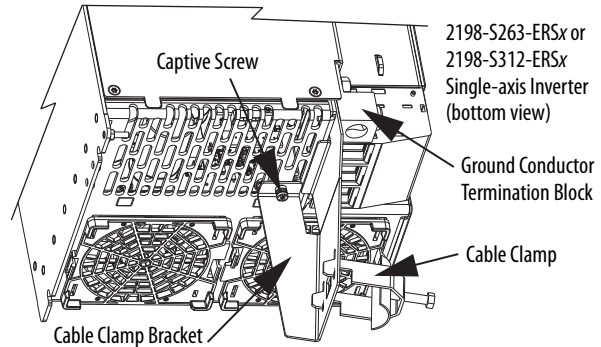
5. Repeat [step 1](#) through [step 4](#) for each drive in multi-axis configurations.

Follow these steps to apply the 2198-S263-ERSx and 2198-S312-ERSx single-axis inverter motor-cable shield clamp when using 2090-CPBM7DF motor power cables.

1. Install the clamp bracket.
 - a. Remove the M8 hex nut by using a 13 mm socket.
 - b. Remove the termination block.
 - c. Insert the cable clamp bracket over the M8 stud.
 - d. Replace the termination block and hex nut.
 - e. Tighten the hex nut to 5.6 N•m (50 lb•in), max.



2. Align the clamp-bracket captive screw with hole in chassis and tighten to 1.6 N•m (14 lb•in).



3. Loosen the clamp screw.
4. Position the exposed portion of the cable braid directly in line with the clamp.

IMPORTANT Make sure the clamp is aligned with the shield braid and not the heat shrink.

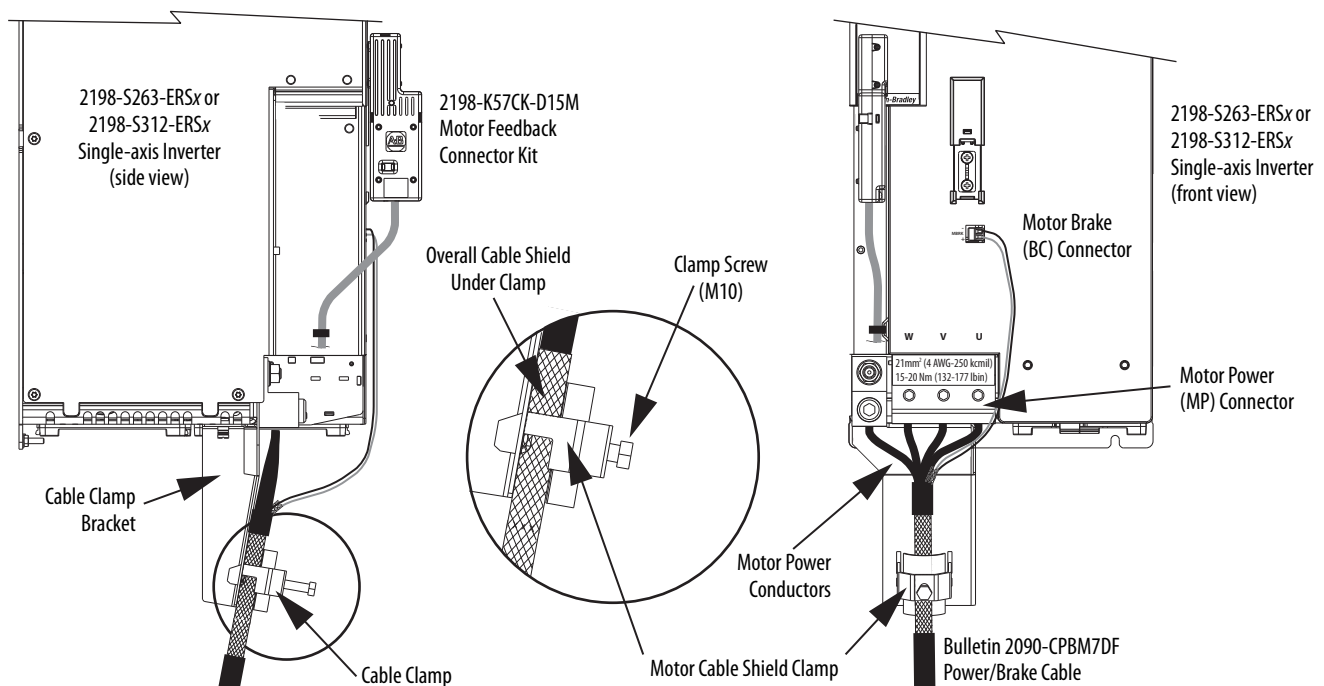
5. Tighten the clamp screw.

Make sure the cable clamp tightens around the overall cable shield and provides a good bond between the cable shield and the drive chassis.

Torque value 5.6 N•m (50 lb•in), max.

In [Figure 113](#), the Bulletin 2090 (4 and 2 AWG) cable requires no preparation.

Figure 113 - Single-axis Inverter Cable Installation (4 and 2 AWG cables)



6. Repeat [step 1](#) through [step 5](#) for each drive in multi-axis configurations.

Motor Feedback Connections

You can connect motor feedback to the 2-pin motor feedback (MF) connector or the 15-pin universal feedback (UFB) connector with the associated feedback connector kit.

Table 91 - Feedback Connector Kit Options

| Connector Kit Cat. No. | Kinetix 5700 Drive Feedback Connectors | Encoder Feedback Type | Description |
|--------------------------------|--|---|---|
| 2198-H2DCK (series B or later) | Motor feedback (MF) | Single-turn or multi-turn absolute | Converts the 15-pin Hiperface feedback signals from the encoder to 2-pin DSL feedback signals at the drive. |
| 2198-K57CK-D15M | Universal feedback (UFB) | Single-turn/ multi-turn absolute, incremental, or EnDat | Feedback signals pass straight through encoder to drive for motor feedback or auxiliary feedback. |

Feedback cables attach to the connector kit and are wired to the connector inside the connector kit. Bulletin 2090 feedback cables require preparation to make sure the shield clamp attaches properly and conductors route smoothly to the connector terminals.

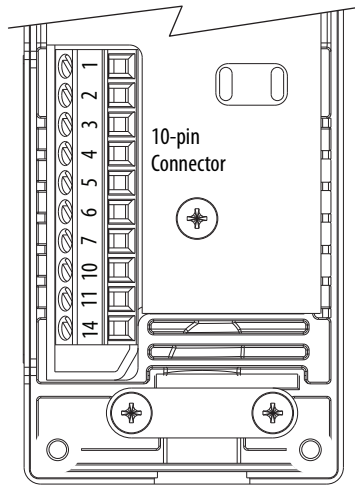
All of the current and legacy feedback cables listed below are compatible with the 2198-H2DCK converter kit and 2198-K57CK-D15M connector kit.

Table 92 - Compatible Motors and Actuators

| Motor/Actuator Families | Single-turn or Multi-turn Absolute Encoders | | Incremental Encoders | |
|--|---|---|--|---|
| | Motor /Actuator Cat. No. | Feedback Cable Cat. No. | Motor/Actuator Cat. No. | Feedback Cable Cat. No. |
| Kinetix MPL servo motors | MPL-B15xxx...MPL-B2xxx-V/E MPL-B3xxx...MPL-B9xxx-M/S | 2090-CFBM7DF-CEAAxx 2090-CFBM7DD-CEAAxx 2090-CFBM7DF-CERAAxx (standard) or 2090-CFBM7DF-CEAFxx 2090-CFBM7DD-CEAFxx 2090-CFBM7DF-CDAFxx (continuous-flex) | MPL-B15xxx...MPL-B2xxx-H MPL-B3xxx...MPL-B45xxx-H | 2090-XXNFMF-Sxx (standard) 2090-CFBM7DF-CDAFxx (continuous-flex) |
| Kinetix MPM servo motors | MPM-Bxxxx-M/S | | N/A | |
| Kinetix MPF servo motors | MPF-Bxxxx-M/S | | N/A | |
| Kinetix MPS servo motors | MPS-Bxxxx-M/S | | N/A | |
| Kinetix VPC servo motors | VPC-Bxxxx-S VPC-B3004x-M VPC-Bxxxx-Y | | N/A | |
| Kinetix HPK servo motors | HPK-Bxxxxx-M/S | | N/A | |
| Kinetix MPAS/MPMA integrated linear stages | MPAS-Bxxxx-VxxSxA (ballscrew) | | MPAS-Bxxxx-ALMx2C (direct drive) | |
| Kinetix MPAR electric cylinders | MPAR-Bxxxx | | N/A | |
| Kinetix MPAL heavy-duty electric cylinders | MPAL-Bxxxx | | N/A | |
| LDAT-Series integrated linear thrusters | LDAT-Sxxxxx-xDx | | LDAT-Sxxxxx-xBx | |
| LDC-Series™ iron-core linear motors | N/A | | LDC-xxxxx-xHTxx | |
| Kinetix RDB direct-drive motors | RDB-Bxxxx-7/3 | 2090-XXNFMF-Sxx 2090-CFBM7DF-CDAFxx | N/A | |

Table 93 - Legacy Motor Feedback Cables

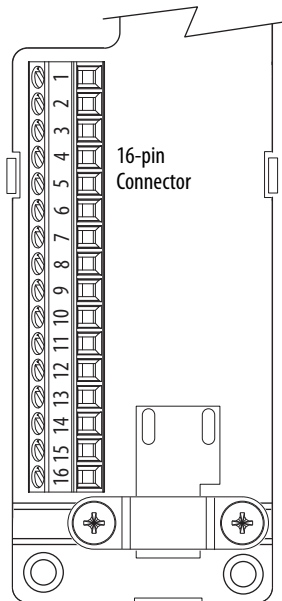
| Motor Cable | Description | Cable Cat. No. |
|-----------------|----------------------------|-------------------------------------|
| Standard | Encoder feedback, threaded | 2090-XXNFMF-Sxx 2090-UXNFBMF-Sxx |
| | Encoder feedback, bayonet | 2090-UXNFBMP-Sxx 2090-XXNFMP-Sxx |
| Continuous-flex | Encoder feedback, bayonet | 2090-XXTFMP-Sxx |
| | Encoder feedback, threaded | 2090-CFBM4DF-CDAFxx |

Figure 114 - 2198-H2DCK Converter Kit Pinout

| Terminal | Signal | Wire Color | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|----------|------------------------|--------------|--------------------------|-----------------------------|
| 1 | SIN+ | Black | 5.0 (0.2) | 0.22...0.25 (1.9...2.2) |
| 2 | SIN- | White/Black | | |
| 3 | COS+ | Red | | |
| 4 | COS- | White/Red | | |
| 5 | DATA+ | Green | | |
| 6 | ECOM ⁽¹⁾ | White/Gray | | |
| 7 | EPWR_9V ⁽²⁾ | Orange | | |
| 10 | DATA- | White/Green | | |
| 11 | TS | White/Orange | 5.0 (0.2) | 0.22...0.25 (1.9...2.2) |
| 14 | EPWR_5V ⁽²⁾ | Gray | | |

(1) The ECOM and TS- connections are tied together and connect to the cable shield.

(2) The converter kit generates 9V and 5V from a 12V supply coming from the drive. The 9V supply is used by 9V encoders in 460V motors and actuators.

Figure 115 - 2198-K57CK-D15M Connector Kit Pinout

| Terminal | Signal | | Wire Color | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|----------|---------------------|-----|--------------|--------------------------|-----------------------------|
| 1 | SIN+ | AM+ | Black | 5.0 (0.2) | 0.22...0.25 (1.9...2.2) |
| 2 | SIN- | AM- | White/Black | | |
| 3 | COS+ | BM+ | Red | | |
| 4 | COS- | BM- | White/Red | | |
| 5 | DATA+ | IM+ | Green | | |
| 6 | ECOM ⁽¹⁾ | | White/Gray | | |
| 7 | EPWR_9V | | Orange | | |
| 8 | S3 | | White/Yellow | | |
| 9 | CLK+ | | Brown | | |
| 10 | DATA- | IM- | White/Green | | |
| 11 | TS | | White/Orange | | |
| 12 | S1 | | White/Blue | | |
| 13 | S2 | | Yellow | | |
| 14 | EPWR_5V | | Gray | | |
| 15 | CLK- | | White/Brown | | |
| 16 | Drain | | N/A | | |

(1) The ECOM and TS- connections are tied together and connect to the cable shield.

Motor Feedback Cable Preparation

Observe the lead preparation guidelines for each of the connector kits.

IMPORTANT This length of wire is needed to provide a service loop for the longest wires terminated at the terminal block. However, most wires need to be trimmed shorter, depending on the terminal they are assigned to.

Figure 116 - Lead Preparation for 2198-H2DCK Converter Kit

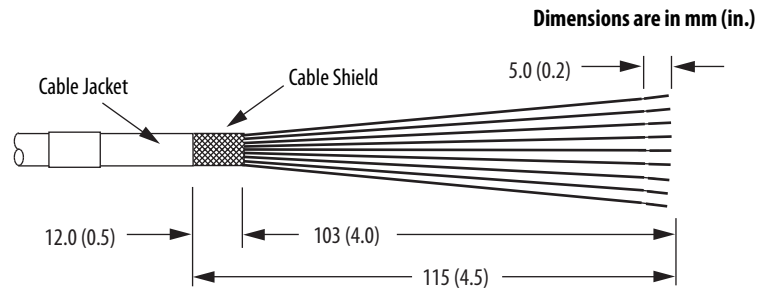
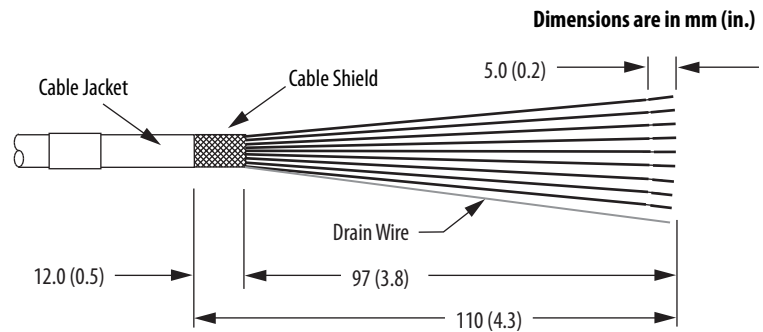


Figure 117 - Lead Preparation for 2198-K57CK-D15M Connector Kit



IMPORTANT For the 2198- K57CK-D15M universal connector kit, if your 2090-Series motor cable does not include a drain wire, you must create one from the overall shield during wire preparation and connect it to pin 16.

Apply the Converter Kit/Connector Kit Shield Clamp

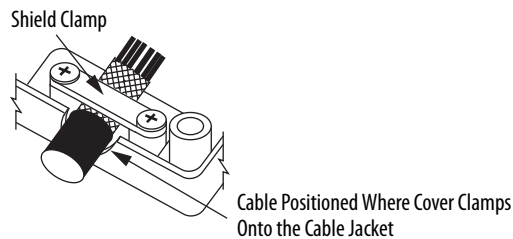
Follow these steps to apply the shield clamp.

1. Apply the shield clamp to the 12 mm (0.5 in.) of exposed cable shield.

IMPORTANT Cable preparation and positioning/wiring that provides a high-frequency bond between the shield braid/drain wire and ground is required to optimize system performance.

Also, make sure that the cable is positioned where the cover clamps onto the jacket for added stress relief.

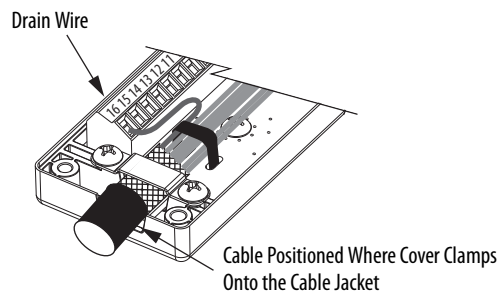
- a. For the 2198- H2DCK converter kit, the shield clamp achieves a high-frequency bond between the shield braid and ground. Apply 0.30 N•m (2.6 lb•in) torque to the clamp screws.



- b. For the 2198- K57CK-D15M connector kit, you must attach the drain wire to pin 16 to achieve a high-frequency bond.

IMPORTANT If your 2090-Series motor cable does not include a drain wire, you must create one from the overall shield braid.

Apply 0.34 N•m (3.0 lb•in) torque to the clamp screws.



2. Route and insert each wire to its assigned terminal.

Include a service loop, as shown on [page 177](#), and refer to the connector pinout on [page 173](#).

3. Tighten each terminal screw.

Apply 0.22...0.25 N•m (1.9...2.2 lb•in) torque to each screw.

4. Gently pull on each wire to make sure it does not come out of its terminal; reinsert and tighten any loose wires.

5. Attach the tie wrap for added stress relief.

Table 94 - 2090-CFBM7DF-CEAxxx Feedback Cables

| Rotary Motors | MPL-B15xxx...MPL-B2xxx-V/Ex4/7xAA MPL-B3xxx...MPL-B9xxx-M/Sx7xAA MPF-Bxxx-M/S, MPS-Bxxx-M/S MPM-Bxxxxx-M/S, VPC-Bxxxxx-S, VPC-B3004x-M HPK-Bxxxxx-M/S, HPK-Exxxxx-M/S | 2198-H2DCK Converter Kit Pin | 2198-K57CK-D15M Connector Kit Pin | Rotary Motors | VPC-Bxxxxx-Y | 2198-K57CK-D15M Connector Kit Pin |
|---------------|--|---------------------------------|--------------------------------------|---------------|--------------|--------------------------------------|
| | Linear Actuators MPAS-Bxxxxx-VxxSxA MPAR-Bxxxxx MPAI-Bxxxxx LDAT-Sxxxxxx-xDx | | | | | |
| 1 | SIN+ | 1 | 1 | 1 | — | 1 |
| 2 | SIN— | 2 | 2 | 2 | — | 2 |
| 3 | COS+ | 3 | 3 | 3 | CLK+ | 9 |
| 4 | COS— | 4 | 4 | 4 | CLK— | 15 |
| 5 | DATA+ | 5 | 5 | 5 | DATA+ | 5 |
| 6 | DATA— | 10 | 10 | 6 | DATA— | 10 |
| 9 | EPWR_5V | — | 14 | 9 | EPWR_9V | 7 |
| 10 | ECOM | 6 ⁽¹⁾ | 6 ⁽¹⁾ | 10 | ECOM | 6 ⁽¹⁾ |
| 11 | EPWR_9V | 7 | 7 | 11 | — | — |
| 12 | ECOM | 6 | 6 | 12 | ECOM | 6 |
| 13 | TS | 11 | 11 | 13 | TS | 11 |

(1) The ECOM and TS- connections are tied together and connect to the cable shield.

Table 95 - 2090-XXNFMF-Sxx or 2090-CFBM7DF-CDAxxx Feedback Cables

| Rotary Motors | MPL-B15xxx...MPL-B2xxx-Hx4/7xAA MPL-B3xxx...MPL-B45xxx-Hx4/7xAA | RDB-Bxxxx-7/3 | 2198-K57CK-D15M Connector Kit Pin |
|---------------|--|---------------|--------------------------------------|
| | Linear Actuators MPAS-Bxxxxx-ALMx2C LDAT-Sxxxxxx-xBx LDC-xxxxxx-xHTxx | | |
| 1 | AM+ | SIN+ | 1 |
| 2 | AM— | SIN— | 2 |
| 3 | BM+ | COS+ | 3 |
| 4 | BM— | COS— | 4 |
| 5 | IM+ | DATA+ | 5 |
| 6 | IM— | DATA— | 10 |
| 9 | EPWR_5V | EPWR_5V | 14 |
| 10 | ECOM | ECOM | 6 ⁽¹⁾ |
| 12 | ECOM | ECOM | 6 |
| 13 | TS | TS | 11 |
| 15 | S1 | — | 12 |
| 16 | S2 | — | 13 |
| 17 | S3 | — | 8 |

(1) The ECOM and TS- connections are tied together and connect to the cable shield.

A mounting bracket is included with the 2198-H2DCK converter kit to secure the kit to the drive. Install the mounting bracket in the bottom mounting position on the kit, and the kit mounting holes on the drive.

Figure 118 - Wiring the 2198-H2DCK Feedback Converter Kit

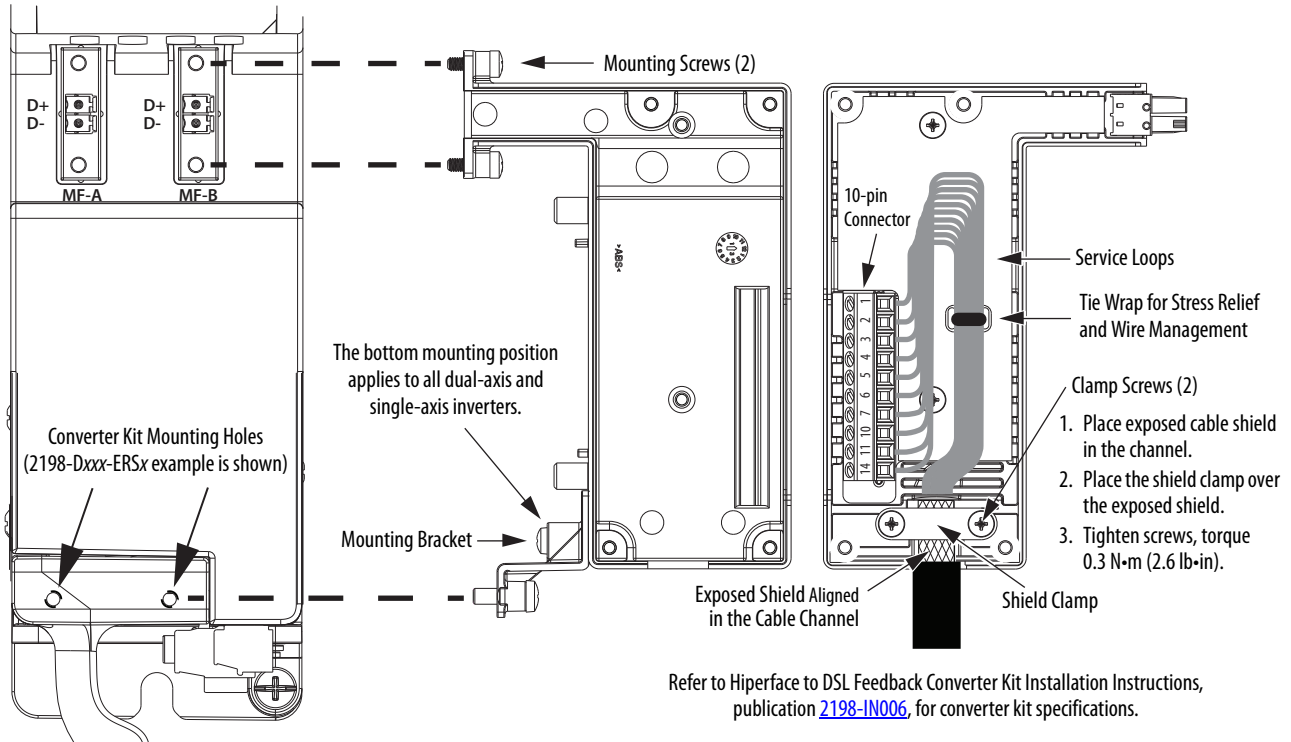
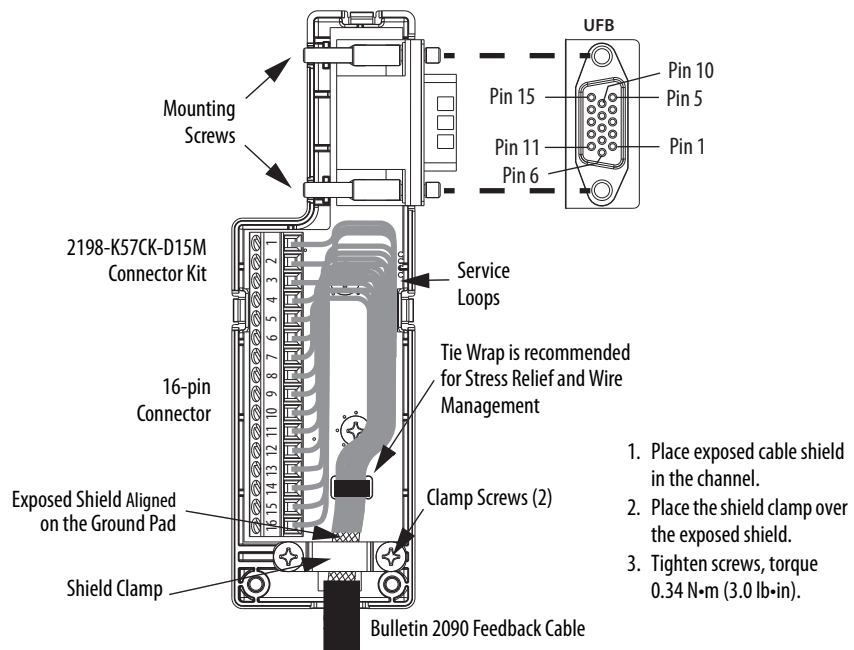


Figure 119 - Wiring the 2198-K57CK-D15M Feedback Connector Kit



Refer to Universal Feedback Connector Kit Installation Instructions, publication [2198-IN010](#), for connector kit specifications.

Customer-supplied Motor Power Cables

For 2198-S263-ERSx and 2198-S312-ERSx single-axis inverters that are paired with motors that require power cables greater than 2 AWG and up to 250 kcmil, customer supplied cable is necessary.

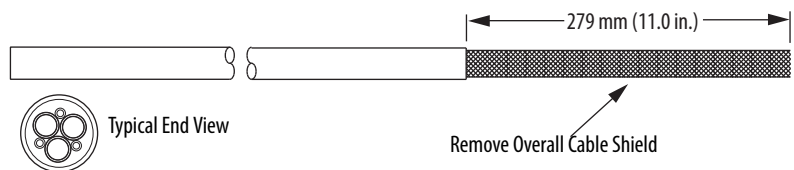
IMPORTANT The cable clamp bracket and shield clamp, included with your drive, does not apply to customer supplied cables larger than 2 AWG.

We recommend six conductor cables with three conductors for power and another three conductors that can be twisted together to form a suitable ground wire.

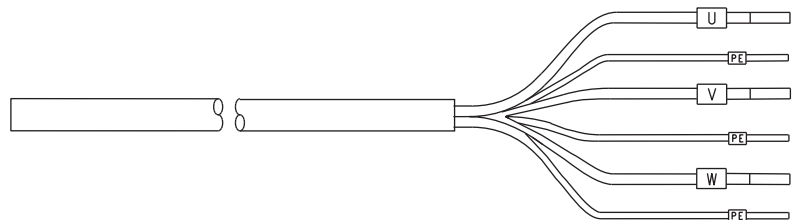
Follow these steps to prepare customer-supplied motor power cables.

1. Remove 279 mm (11.0 in.) of the cable jacket.

In addition, remove the same amount of shield braid, copper foil, or other overall shielding.

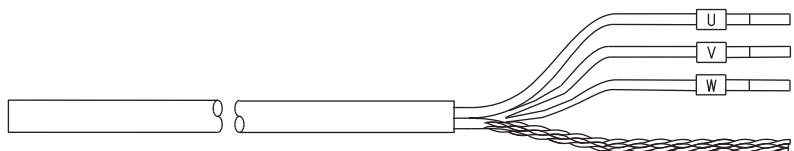


2. Separate the power conductors from the ground conductors.

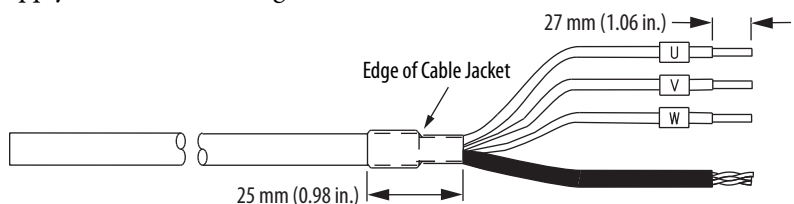


In this example, the power conductors are insulated and the ground conductors are not.

3. Twist the three ground conductors together to form a single ground conductor.

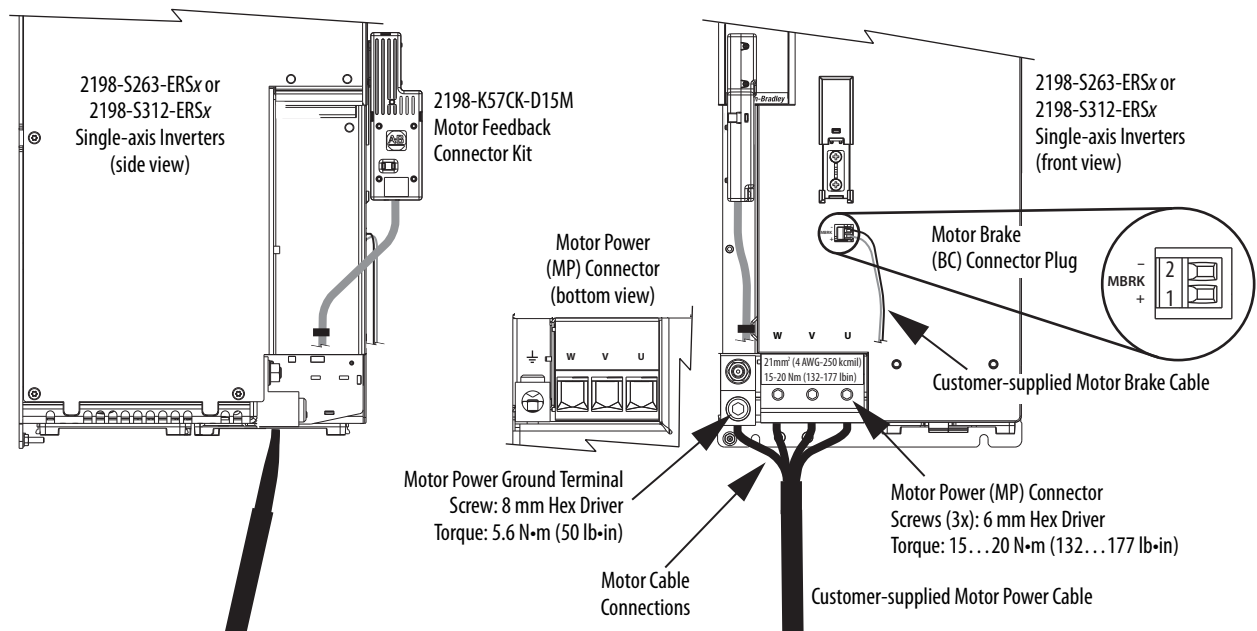


4. Apply heat shrink to the ground conductor.



5. Apply heat shrink over the cable jacket and the four insulated conductors.
6. Trim the insulation to leave a strip length of 27 mm (1.06 in.)

Figure 120 - MP and BC Connector Wiring (single-axis inverters)



Prepare the customer-supplied motor power cable (see [page 178](#)), then attach motor power and ground wires to the motor power connector and ground terminal. Plug in motor feedback and brake connectors, as required for your application.

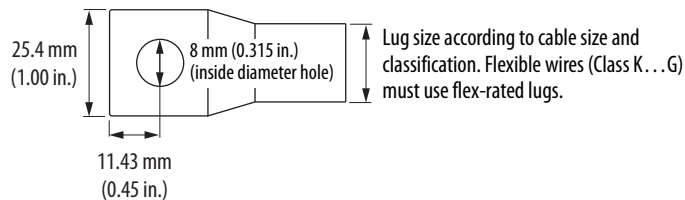
IMPORTANT The supplied ground terminal is suitable for use with 16...120 mm² (6 AWG...250 kcmil) Class B and C power cables and all Allen-Bradley Bulletin 2090 motor cables. A customer-supplied lug is required for all other applications.

Table 96 - Motor Power Connector Specifications (single-axis inverters)

| Drive Module Cat. No. | Pin | Signal/Wire Color | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Terminal Torque Value N·m (lb·in) |
|----------------------------------|------------------|--|---|-----------------------|-----------------------------------|
| 2198-S263-ERSx 2198-S312-ERSx | U V W ⏏ | U Brown V Black W Blue ⏏ Green/Yellow | 21.1...120 (4...250 kcmil) | 27.0 (1.06) | 15...20 (132...177) |

If you replace the ground-conductor termination block with a lug, the lug size must not exceed these maximum dimensions.

Figure 121 - Maximum Customer-supplied Lug Dimensions



Motor brake conductors are customer supplied. We recommend unshielded cable up to 90 m (295 ft).

Table 97 - Motor Brake (BC) Connector Specifications

| Drive Module Cat. No. | Pin | Signal | Recommended Wire Size (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|----------------------------------|------|--------|-----------------------------------|--------------------------|-----------------------------|
| 2198-S263-ERSx 2198-S312-ERSx | BC-1 | MBRK+ | 16 | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) |
| | BC-2 | MBRK- | | | |

TIP Motors used with 2198-S263-ERSx and 2198-S312-ERSx inverters typically use a brake coil that is not 24V DC. In this case, use a customer-supplied auxiliary relay to power the customer-supplied brake coil.

Accessory Module Connections

Follow these guidelines when wiring the 2198-CAPMOD-2240 capacitor module, 2198-CAPMOD-DCBUS-IO extension module, and 2198-DCBUSCOND-RP312 DC-bus conditioner module:

- Wire module status (MS) output connections to digital input Bus Capacitor OK, Bus Conditioner OK, or the Logix 5000™ controller (optional).
- Flexible bus-bars (included with 2198-CAPMOD-DCBUS-IO extension modules) are required whenever two accessory modules are mounted side-by-side in 208 A systems. If your system does not include the extension module, order the 2198-KITCON-DCBUSCOND or 2198-KITCON-CAPMOD2240 replacement kit.
- Refer to [DC-bus Power Supply with Capacitor Module](#) wiring example on [page 345](#).
- Refer to [Regenerative Bus Supply with DC-bus Conditioner Module](#) wiring example on [page 349](#).
- Refer to [Kinetix 5700 Accessory Module Status Indicators](#) on [page 279](#) for troubleshooting the module status indicators and relay output.

IMPORTANT To improve system performance, run wires and cables in the wireways as established in [Chapter 2](#). Connections to the DC bus must be made with the shared-bus connection system.

Figure 122 - MS Connector Wiring (capacitor module and DC-bus conditioner module)

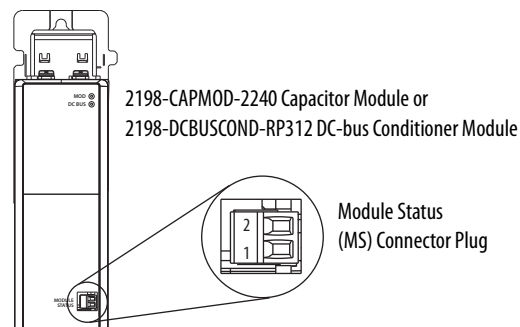


Table 98 - Accessory Module Connector Specifications

| Connector Description | Pin | Signal | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|-------------------------------|--------------|--------------|--|--------------------------|-----------------------------|
| Module Status | MS-1 MS-2 | MS MS | 0.14...1.5 (28...16) | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) |
| PELV/SELV 24V power (plug) | CP-1 CP-2 | 24V+ 24V- | 0.5...4 (20...12) | 7.0 (0.28) | 0.22...0.25 (1.9...2.2) |
| DC-bus power | Bus-bar | DC- DC+ | N/A ⁽¹⁾ | N/A ⁽¹⁾ | N/A ⁽¹⁾ |
| DC-bus studs | Bus-bar | | N/A | N/A | 18 (156) |
| | Lugs | | 53.5 (1/0 AWG) 104 A 152 (300 kcmil) 208 A | N/A ⁽²⁾ | |

(1) DC bus connections are always made from one drive module to another over the shared-bus connection system. These terminals do not receive discrete wires.

(2) Strip length for the DC-bus studs depend on the customer-supplied lugs.

External Passive-shunt Connections

Passive shunts attach to only 2198-Pxxx DC-bus power supplies. See [Passive Shunt Considerations](#) on [page 51](#) for shunts compatible with your DC-bus power supply.

Follow these guidelines when wiring your 2198-Rxxx passive shunt:

- Refer to [External Passive Shunt Modules](#) on [page 74](#) for noise zone considerations.
- Refer to [Passive Shunt Wiring Examples](#) on [page 359](#).
- Refer to the installation instructions provided with your Bulletin 2198 shunt module, publication [2198-IN011](#).

IMPORTANT To improve system performance, run wires and cables in the wireways as established in [Chapter 2](#).

Figure 123 - RC Connector Wiring

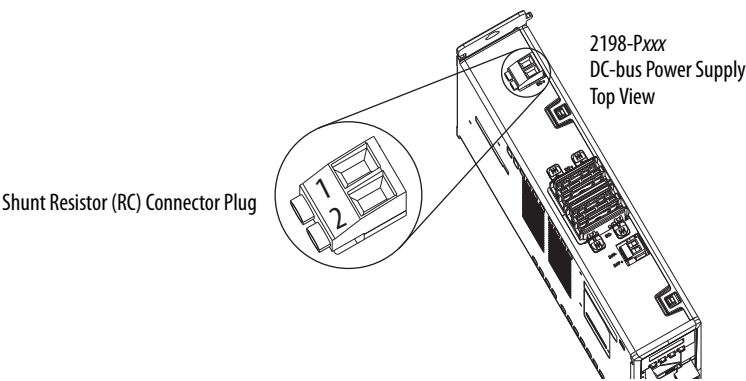


Table 99 - Shunt Resistor (RC) Connector Specifications

| DC-bus Power Supply Cat. No. | Pin | Signal | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N•m (lb•in) |
|---------------------------------|--------------|-----------|---|--------------------------|-----------------------------|
| 2198-Pxxx | RC-1 RC-2 | SH DC+ | 1.5...6 (16...10) | 12.0 (0.47) | 0.5...0.6 (4.4...5.3) |

IMPORTANT You must disconnect the internal shunt wires at the RC connector before connecting the Bulletin 2198 passive shunt resistor wires.

External Active-shunt Connections

Active shunts are available from the Rockwell Automation Encompass™ partner Powerohm Resistors, Inc. See [Active Shunt Considerations](#) on [page 52](#) for Powerohm shunts compatible with your Kinetix 5700 power supply.

| Rockwell Automation Encompass Partners | Contact Information |
|--|---|
| Powerohm Resistors, Inc. | 5713 13th Street Katy, Texas 77493 Tel: (800) 838-4694 http://www.powerohm.com |

Follow these guidelines when wiring your Powerohm active shunt:

- Refer to [External Active Shunt Modules](#) on [page 76](#) for noise zone considerations.
- Refer to [Active Shunt Wiring Examples](#) on [page 360](#).
- Refer to the installation instructions provided with your Bulletin PWBxxx and PKBxxx Powerohm shunt module.

IMPORTANT To improve system performance, run wires and cables in the wireways as established in [Chapter 2](#).

DC-bus Power Supply Active Shunt Connections

Make active shunt connections in drive systems that include the DC-bus power supply and Powerohm PKBxxx or PWBxxx active shunts at the external DC-bus studs on accessory modules.

Refer to [Wire the External DC-bus Connections](#) on [page 184](#).

Regenerative Bus Supply Active Shunt Connections

Make active shunt connections to the 2198-RPxxx regenerative bus supply at the active shunt (RC) connector or the external DC-bus studs on accessory modules, depending on the shunt type.

Connections at the Active Shunt (RC) Connector

You can make active shunt connections in drive systems that include the regenerative bus supply and Powerohm PKBxxx-800 active shunts at the Active Shunt (RC) connector.

Figure 124 - RC Connector Wiring

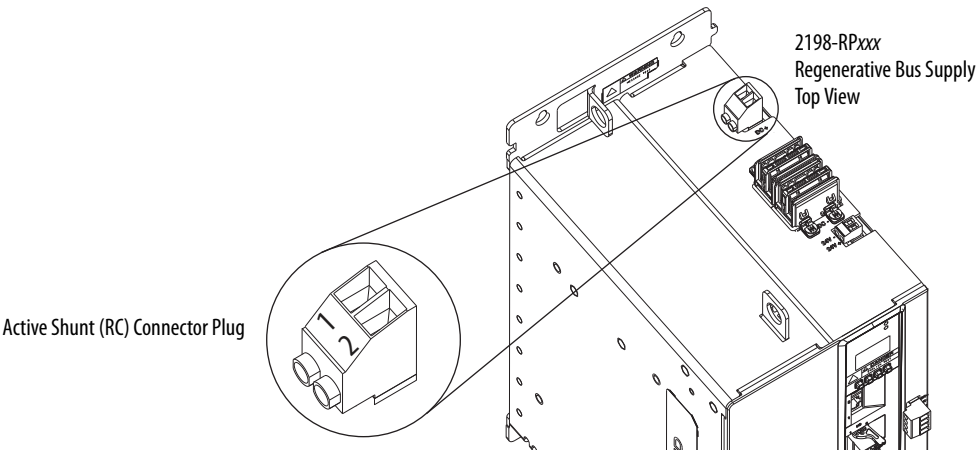


Table 100 - Active Shunt (RC) Connector Specifications

| Regenerative Bus Supply Cat. No. | Pin | Signal | Continuous ⁽¹⁾ Current, max | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|----------------------------------|--------------|------------|--|---|-----------------------|--------------------------|
| 2198-RPxxx | RC-1 RC-2 | DC- DC+ | 10 A | 2.5...6 (14...10) | 12.0 (0.47) | 0.5...0.6 (4.4...5.3) |

(1) This connector applies to only Powerohm PKBxxx-xxx active shunts rated at 7 kW or less.

IMPORTANT Due to the 10 A connector current rating, connections to the RC connector are limited to only Powerohm PKBxxx-xxx active shunts rated at 7 kW or less. All other PKBxxx-xxx and PWBxxx-xxx active shunt connections must be made to the 2198-CAPMOD-2240 capacitor module.

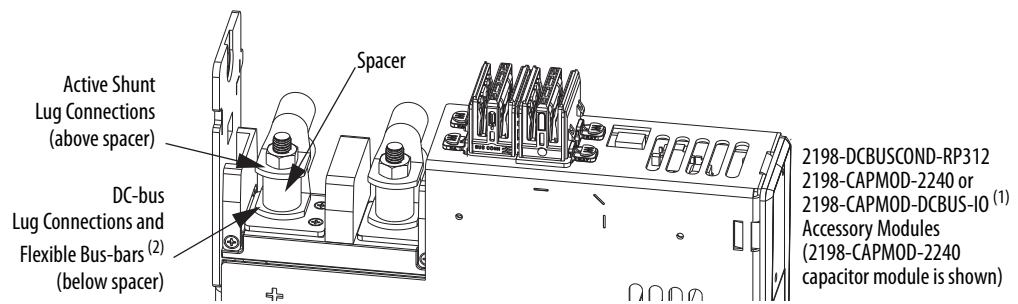
Connections at the External DC-bus Studs

You can make active shunt connections in drive systems that include the regenerative bus supply and Powerohm PKBxxx-800 or PWBxxx-800 active shunts at the external DC-bus studs on accessory modules.

Refer to [Wire the External DC-bus Connections](#).

Wire the External DC-bus Connections

Accessory modules are equipped with spacers that slide onto the M8 studs. When the system configuration includes external DC-bus and active shunt connections, external DC-bus connections are made below the spacer and active shunt connections are made above the spacer.

Figure 125 - Active Shunt Connections

- (1) An external active shunt can be wired to any of the accessory modules. See [Mount Accessory Modules](#) on [page 83](#) for more information on mounting and accessory module example configurations. The 2198-CAPMOD-2240 capacitor module is preferred because it provides additional system capacitance.
- (2) Position flexible bus-bars (when two accessory modules are used) below the DC-bus lug connections. The flexible bus-bars are used to parallel the extended DC-bus with another accessory module in 208 A systems (not required when only one accessory module is used in 104 A systems). Flexible bus-bars are included with 2198-CAPMOD-DCBUS-IO extension modules or you can order 2198-KITCON-CAPMOD2240 or 2198-KITCON-DCBUSCOND replacement kits.

Kinetix VPC Motors and the Extended Speed Feature

The extended speed feature is implemented in the Logix Designer application to prevent accidental motor operation at unsafe speeds. See [Field Weakening Mode](#) on [page 452](#) for a description of this feature.



WARNING: Kinetix VPC motor operation at speeds exceeding the bus-overvoltage speed limit can result in personal injury and/or damage to the drive. To avoid equipment damage and personal injury, an active shunt must be configured in the Logix Designer application to protect the DC-bus system from an overvoltage condition.

IMPORTANT Refer to Motion Analyzer software to verify drive/shunt system sizing. Access the tool at <https://motionanalyzer.rockwellautomation.com>.

Powerohm Bulletin PKB and PWB active-shunt modules are required for DC-bus system protection when Kinetix VPC motors are expected to operate in the extended speed region at speeds exceeding the bus-overvoltage speed limit.

Considerations for Powerohm Shunt Installation

Refer to the Powerohm documentation included with your Bulletin PKB or PWB shunt module to install, wire, and configure the module.

- To avoid nuisance thermal overload trips, configure Bulletin PKB and PWB active-shunt modules to the highest shunt turn-on voltage setting. The recommended setting for Line Voltage Level Jumper is JP5.
- Configure Bulletin PKB and PWB active-shunt modules in Internal (automatic) mode. Unless an external enable signal is provided, configure the Brake Enable Jumper in Internal (automatic) mode (JP6 is in the downward position).

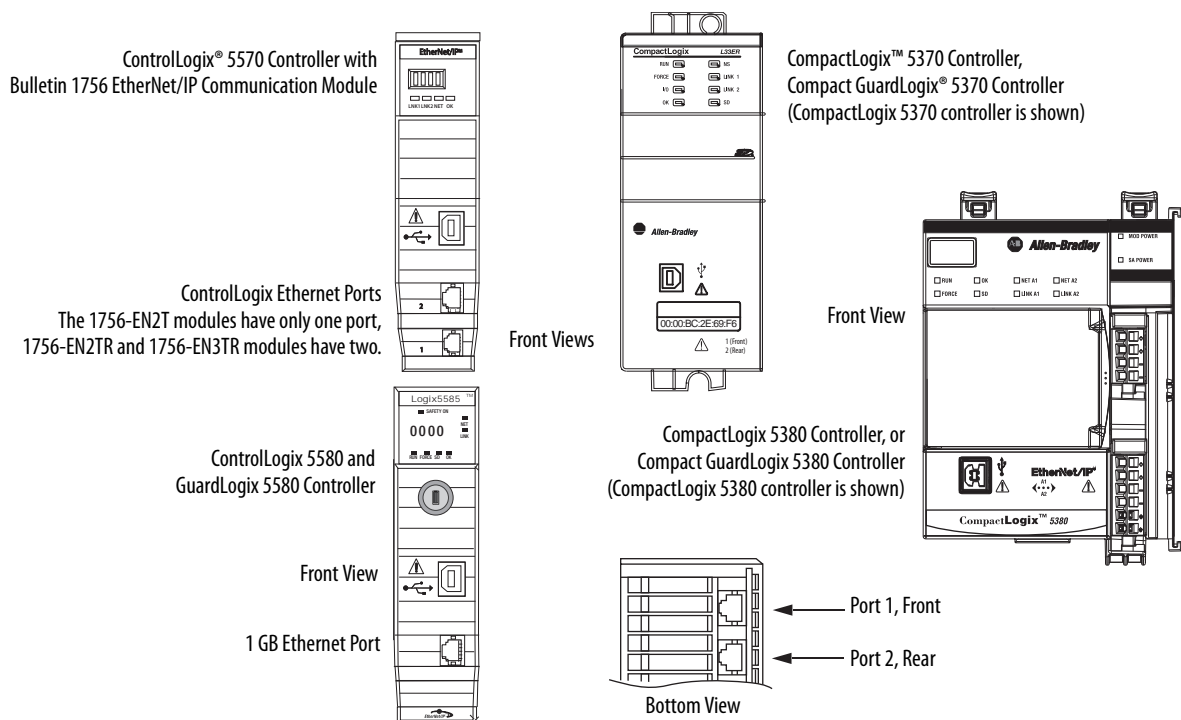
Ethernet Cable Connections

This procedure assumes that you have your Logix 5000 controller and Kinetix 5700 modules mounted and are ready to connect the network cables.

The EtherNet/IP™ network is connected by using the PORT 1 and PORT 2 connectors. Refer to [page 94](#) to locate the Ethernet connectors on your drive module. Refer to [Figure 126](#) to locate the connectors on your Logix 5000 controller.

Shielded Ethernet cable is required for EMC compliance and is available in several standard lengths. Ethernet cable lengths connecting drive-to-drive, drive-to-controller, or drive-to-switch must not exceed 100 m (328 ft). Refer to the Kinetix Motion Accessories Specifications Technical Data, publication [KNX-TD004](#), for more information.

Figure 126 - ControlLogix and CompactLogix Ethernet Port Locations



The Logix 5000 controllers accept linear, ring (DLR), and star network configurations. Refer to [Typical Communication Configurations](#) on [page 30](#) for linear, ring, and star configuration examples.

IMPORTANT When using an external Ethernet switch for routing traffic between the controller and the drive, switches with IEEE-1588 time synchronization capabilities (boundary or transparent clock) must be used to make sure switch delays are compensated.

IMPORTANT The iTRAK power supply requires an Ethernet connection for firmware upgrades by using ControlFLASH™ software. Although Ethernet is not required during normal operation, it can also be used to access real-time data, for example, event logging.

Configure and Start the Kinetix 5700 Drive System

This chapter provides procedures for configuring your Kinetix® 5700 drive system with a Logix 5000™ controller by using the Logix Designer application.

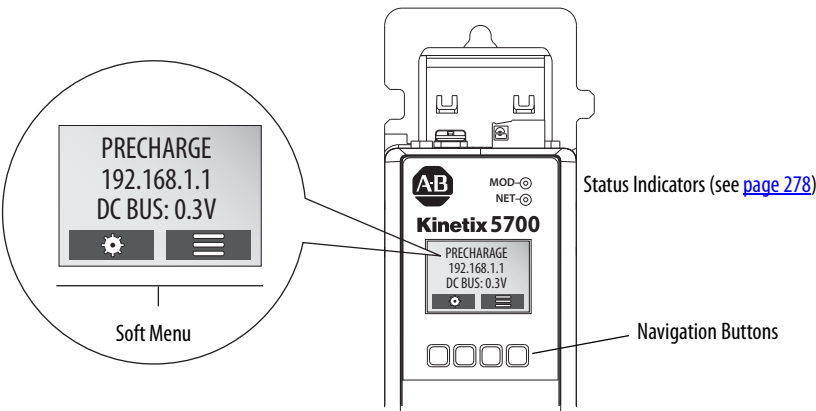
| Topic | Page |
|---|------|
| Understand the Kinetix 5700 Display | 188 |
| Configure the Drive | 198 |
| Studio 5000 Logix Designer | 198 |
| Configure the Kinetix 5700 Drive Modules | 203 |
| Configure the Motion Group | 223 |
| Configure Regenerative Bus Supply Axis Properties | 224 |
| Configure Vertical Load Control Axis Properties | 229 |
| Configure Feedback-only Axis Properties | 230 |
| Configure Induction-motor Frequency-control Axis Properties | 232 |
| Configure IPM Motor Closed-loop Control Axis Properties | 241 |
| Configure SPM Motor Closed-loop Control Axis Properties | 245 |
| Configure Induction-motor Closed-loop Control Axis Properties | 250 |
| Configure Feedback Properties | 257 |
| Download the Program | 262 |
| Apply Power to the Kinetix 5700 Drive System | 263 |
| Understand Bus-sharing Group Configuration | 264 |
| Test and Tune the Axes | 267 |

TIP Before you begin, make sure that you know the catalog number for each drive module, the Logix module and /or controller, and the motor used in your motion control application.



Understand the Kinetix 5700 Display

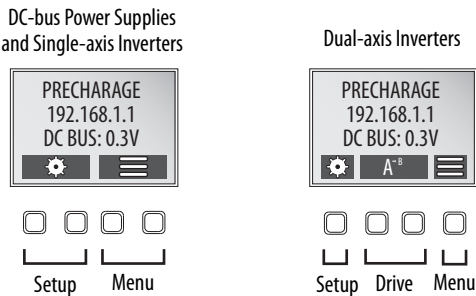
The Kinetix 5700 drives have two status indicators and an LCD status display. The indicators and display are used to monitor the system status, set network parameters, and troubleshoot faults. Four navigation buttons, directly below the display, are used to select items from a soft menu.

Figure 127 - Kinetix 5700 Drive LCD Display and Status Indicators



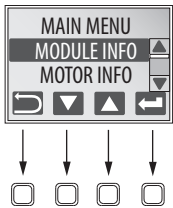
This is the Home  screen.









- The setup selections  are tied to the Setup (left-side) buttons and the menu selections  are tied to the Menu (right-side) buttons.
- For dual-axis inverters, the Drive (center) buttons toggle the display between drive A and B (A is the default drive).



The soft menu provides a changing selection that corresponds to the current screen. Use the navigation buttons to perform the following.

Each soft menu item is executed by pressing the navigation button directly below the item, as shown in this example.



| | |
|---|---|
|  | Press to go back. Pressing enough times results in the Home  screen. |
|   | Pressing either arrow moves the selection to the next (or previous) item. When changing values, pressing the up arrow increments the highlighted value. Values rollover after reaching the end of the list. |
|  | Press to select values to change, moving from right to left. Values rollover when reaching the end of the list. |
|  | Press to select a menu item. |
|  | Press to return to the Home screen. |
|  | Press to display the fault help (possible solutions in troubleshooting tables). ⁽¹⁾ |

(1) For Kinetix 5700 fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

Menu Screens

The menu screens provide information about the drives, motors, diagnostics, and the fault log. Parameters cannot be updated in the menu screens. Press one of the menu buttons to access the menu.

You can use the soft menu items and navigation buttons to view the information.

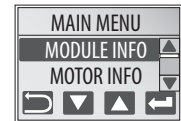


Table 101 - Navigating the Inverter Menu

| Menu/Sub Menu Selections | Attributes | Description | Example Values | |
|-------------------------------------|----------------------------------|---|---|---|
| Drive Info | Catalog number | | 2198-Dxxx-ERSx or 2198-Sxxx-ERSx | |
| | Firmware revision | | FW REV: 1.1.450167 | |
| | Hardware revision | | HW REV: 1.1 | |
| | Serial number | | SERIAL#: xxxxxxxxxxxx | |
| Motor Info | Model number | | MODEL: VPL-B1306F | |
| | Serial number | | SERIAL#: xxxxxxxxxxxx | |
| Diagnostics> Drive Diagnostics | Bus diagnostics | | BUS VOLT: 0.0V | |
| | | | BUS CUR: 0.0A | |
| | Inverter diagnostics | | INV UTIL: 0.0% | |
| | | | INV TEMP: 31.7C | |
| Diagnostics> Motor Diagnostics | Motor speed | | SPEED:0.0 RPM | |
| | Motor current | | MTR CUR:0.0A RMS | |
| | Motor utilization | | MTR UTIL:0.0% | |
| | Motor temperature | | MTR TEMP:0.00C | |
| Diagnostics> Encoder Diagnostics | Serial number | | SERIAL#xxxxxxxxxx | |
| | Resolution | | RESOLUTION: 262144 | |
| | Number of turns | | NO OF TURNS: 1 | |
| | Encoder temperature | | ENC TEMP:33.7C | |
| | Supply voltage | | SUPP VOLT:11.3V | |
| | Link quality | The link quality attribute indicates how noisy a communication link is and also indicates if there is a communication link already established at the drive end. The LINK QUAL value must always be 100%. Persistent values below 100% indicates a poor feedback ground connection. | LINK QUAL: 100.0% | |
| | Remote signal strength indicator | Similar to Link Quality, RSSI reports the quality of link as seen at the motor end by the encoder. Maintain the RSSI value between 80 and 100%. Persistent values below 80% indicates a poor feedback ground connection. | RSSI: 100.0% | |
| | Accumulated position errors | This is an aggregated number of errors in the primary position feedback channel of DSL feedback. | POS ERRORS: 1 | |
| | Channel position errors | This is an aggregated number of errors on a secondary communication channel of the DSL feedback. | CHNL ERRORS: 5 | |
| | Hardwired input status | | 1 OFF 2 OFF | 1 ON 2 ON |
| Diagnostics> Safety Diagnostics | Safety state | This attribute indicates the state of the safety supervisor object (refer to Safety Supervisor State on page 312). | SAFETY STATE:CONFIGURING INPUT CONNECTIONS:1 OUTPUT CONNECTIONS:1 | SAFETY STATE:RUNNING INPUT CONNECTIONS:1 OUTPUT CONNECTIONS:1 |
| | Input connections | This attribute indicates the number of safety controllers that have an input connection established. The input connection provides the controller with the drive's safety status. The drive supports up to three input connections. | | |
| | Output connections | This attribute indicates the number of safety controllers that have an output connection established. The output connection provides a controller with the ability to control the drive's STO function. The drive allows only one output connection. | | |

Table 101 - Navigating the Inverter Menu (continued)

| Menu/Sub Menu Selections | Attributes | Description | Example Values |
|--------------------------|---------------|---|--|
| Fault Log | Fault text | Fault code as listed in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | FLT S20 - CONV OVERLOAD FL |
| | Fault details | The problem as reported in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | The converter thermal model indicates that the temperature has exceeded the factory set capacity rating of 110%. |
| | Fault help | The Possible Solution as reported in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | <ul style="list-style-type: none"> Reduce the number of drives in the same bus group Reduce duty-cycle of commanded motion |

(1) For Kinetix 5700 fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

Table 102 - Navigating the DC-bus Power Supply Menu

| Menu/Sub Menu Selections | Attributes | Description | Example Values |
|--|-----------------------|---|--|
| Module Info | Catalog number | | 2198-Pxxx |
| | Firmware revision | | FW REV: 1.1.450167 |
| | Hardware revision | | HW REV: 1.1 |
| | Serial number | | SERIAL#: xxxxxxxxxxxx |
| Diagnostics> Converter Diagnostics | Bus diagnostics | | BUS VOLT: 0.0V |
| | | | BUS CUR: 0.0A |
| | Converter diagnostics | | CONV UTIL: 0.7% |
| | | | CONV TEMP: 31.7C |
| | Shunt utilization | | SHUNT UTIL: 0.0% |
| Fault Log | Fault text | Fault code as listed in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | FLT S18 - CONV OVERTEMP FL |
| | Fault details | The problem as reported in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | The measured converter temperature has exceeded the factory set temperature limit. |
| | Fault help | The Possible Solution as reported in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | Reduce the number of drives in the same bus group. |

(1) For Kinetix 5700 fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

Table 103 - Navigating the Regenerative Bus Supply Menu

| Menu/Sub Menu Selections | Attributes | Description | Example Values |
|--|-----------------------|---|---|
| Module Info | Catalog number | | 2198-RPxxx |
| | Firmware revision | | FW REV: 10.1.10500409 |
| | Hardware revision | | HW REV: 2.1 |
| | Serial number | | SERIAL#: xxxxxxxxxxxx |
| Diagnostics> Converter Diagnostics | Converter diagnostics | | CONV UTIL: 0.7% |
| | | | CONV TEMP: 31.7C |
| | | | SHUNT UTIL: 0.0% |
| | | | DC BUS: 0.0V |
| | | | IBUS: 0.0A |
| | | | CONV UTIL: 0.0% |
| | | | CONV TEMP: 22.6C |
| | | | PWR OUT: 0.0kW |
| | | | IGND:0.0A RMS |
| | | | AC FREQ: 0.1Hz |
| | | | IL1: 0.0A RMS |
| | | | IL2: 0.0A RMS |
| | | | IL3: 0.0A RMS |
| | | | VL1-2: 0.0V RMS |
| | | | VL2-3: 0.0V RMS |
| | | | VL3-1: 0.0V RMS |
| | | | VL1-N: 0.0V RMS |
| | | | VL2-N: 0.0V RMS |
| | | | VL3-N: 0.0V RMS |
| | | | VBUS REF: 690V |
| | | | SYNC STS: 0 |
| | | | ACT PWR: 0.0kW |
| | | | PF: 0.0 |
| | | | VAC UNBAL: 0.0% |
| | | | IAC UNBAL: 0.0% |
| | | | PHASE SEQ: 0.0 |
| | Digital Inputs | | IN1: OFF |
| | | | IN2: OFF |
| | | | IN3: OFF |
| | | | IN4: OFF |
| | Digital Outputs | | CONT ENABLE: 0 |
| | | | PWR SUP OK: 0 |
| Fault Log | Fault text | Fault code as listed in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | FLT S23 – AC PHASE LOSS |
| | Fault details | The problem as reported in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | One AC phase has been lost on the AC line to the converter. |
| | Fault help | The Possible Solution as reported in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | Check AC input voltage on all phases. |

(1) For Kinetix 5700 fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

Table 104 - Navigating the iTRAK Power Supply Menu


| Menu/Sub Menu Selections | Attributes | Description | Example Values |
|--|-----------------------|---|--|
| Module Info | Catalog number | | 2198T-W25K-ER |
| | Firmware revision | | FW: 6.1.7100254 |
| | Hardware revision | | HW REV: 1.1 |
| | Serial number | | SERIAL#: xxxxxxxxxxxx |
| Diagnostics> Converter Diagnostics | Bus diagnostics | | BUS VOLT: 0.0V |
| | Output 1 diagnostics | | OUT1 VOLT: 0.0V |
| | | | OUT1 AMPS: 0.0A |
| | | | OUT1 PWR: 0.0kW |
| | | | OUT1 UTIL: 0.0% |
| | Output 2 diagnostics | | OUT2 VOLT: 0.0V |
| | | | OUT2 AMPS: 0.0A |
| | | | OUT2 PWR: 0.0kW |
| | | | OUT2 UTIL: 0.0% |
| | Converter diagnostics | | TOTAL PWR: 0.0kW |
| Fault Log | Fault text | Fault code as listed in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | FLT S38 - FUSE BLOWN |
| | Fault details | The problem as reported in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | The internal DC-bus power fuse is blown |
| | Fault help | The Possible Solution as reported in the Kinetix 5700 Fault Codes.xlsx file. ⁽¹⁾ | Return drive for repair if fault continues |

(1) For Kinetix 5700 fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

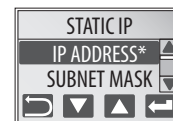
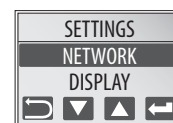
Setup Screens

The setup screens provide the means of changing drive settings, for example, the IP address. Press one of the setup buttons to access the setup screens.

You can use the soft menu items and navigation buttons to view the information and make changes.

Press  to validate your changes:

- If the change is invalid, the value doesn't change.
- If the change is valid, an asterisk appears next to the changed attribute.



IMPORTANT You must cycle control power to make network configuration changes persistent. In this example, the IP address was changed. The change takes affect and the asterisk disappears after control power is cycled. Display configuration changes take effect immediately.

Table 105 - Navigating the Inverter Settings Menu

| Settings Menu Selections | Sub Menu Selections | Attributes | Default | Description |
|--------------------------|-----------------------------------|--|-------------------------|--|
| Protected Mode | Network Config | ENABLED DISABLED | ENABLED | When Enabled (default), network configuration changes are not possible when a controller connection is open. |
| | Device Config | ENABLED DISABLED | ENABLED | When Enabled (default), only attribute writes are possible when a controller connection is open. |
| Network | ->Static IP ⁽¹⁾ | IP address | 192.168.1.1 | Indicates current IP address |
| | | Subnet mask | 255.255.255.000 | Indicates current subnet mask |
| | | Gateway | 192.168.001.001 | Indicates current gateway |
| | DHCP | On | | Turns DHCP on |
| | | Off | | Turns DHCP off |
| Display | Backlight Timeout | 30 sec... NEVER (NEVER=no timeout period, the backlight is always on) | -> 3 min ⁽¹⁾ | Sets backlight timeout period of the display |
| | Cyclic Data Select ⁽²⁾ | ->DC BUS ⁽¹⁾ | | DC bus voltage |
| | | INV UTIL | | Inverter utilization in percent |
| | | INV TEMP | | Inverter temperature in °C |
| | | MOTOR UTIL | | Motor utilization in percent |
| | | SPEED | | RPM |
| | | OUT PWR | | Output power in watts |
| | | OUT FREQ | | Output frequency in hertz |
| | | OUT CUR | | Output current in amps |
| | Set Contrast | -10...+10 | 0 | Contrast setting of the display |
| Factory Reset | Reset Defaults? | Are you sure? | | Resets drive to factory default state |
| Safety | Reset Ownership | Are you sure? | | Resets safety ownership (reset fails after 30 seconds) |
| Web | Enabled | | | Enables the web server |
| | ->Disabled | | | Disables the web server |

(1) An arrow (->) appears in front of the chosen attribute indicating that this attribute is currently configured. This is also the factory default setting.

(2) The DC bus voltage is one of several cyclic data attributes. You can select any of the Cyclic Data Select attributes to be displayed on the Home screen.

Table 106 - Navigating the DC-bus Power Supply Settings Menu

| Settings Menu Selections | Sub Menu Selections | Attributes | Default | Description |
|--------------------------|-----------------------------------|--|-------------------------|---|
| Protected Mode | Reset | ENABLED DISABLED | ENABLED | When Enabled (default), identity object or safety resets are not possible when a controller connection is open. |
| | Network Config | ENABLED DISABLED | ENABLED | When Enabled (default), network configuration changes are not possible when a controller connection is open. |
| | Flash Update | ENABLED DISABLED | ENABLED | When Enabled (default), firmware updates are not possible when a controller connection is open. |
| | Device Config | ENABLED DISABLED | ENABLED | When Enabled (default), only attribute writes are possible when a controller connection is open. |
| Network | ->Static IP ⁽¹⁾ | IP address | 192.168.1.1 | Indicates current IP address |
| | | Subnet mask | 255.255.255.000 | Indicates current subnet mask |
| | | Gateway | 192.168.001.001 | Indicates current gateway |
| | DHCP | On | | Turns DHCP on |
| | | Off | | Turns DHCP off |
| Display | Backlight Timeout | 30 sec... NEVER (NEVER=no timeout period, the backlight is always on) | -> 3 min ⁽¹⁾ | Sets backlight timeout period of the display |
| | Cyclic Data Select ⁽²⁾ | ->DC BUS ⁽¹⁾ | | DC bus voltage |
| | | CONV UTIL | | Converter utilization in percent |
| | | CONV TEMP | | Converter temperature in °C |
| | | SHUNT UTIL | | Shunt utilization in percent |
| | | OUT PWR | | Output power in watts |
| | | DC BUS CUR | | Output current in amps |
| | Set Contrast | -10...+10 | 0 | Contrast setting of the display |

(1) An arrow (->) appears in front of the chosen attribute indicating that this attribute is currently configured. This is also the factory default setting.

(2) The DC bus voltage is one of several cyclic data attributes. You can select any of the Cyclic Data Select attributes to be displayed on the Home screen.

Table 107 - Navigating the Regenerative Bus Supply Settings Menu

| Settings Menu Selections | Sub Menu Selections | Attributes | Default | Description |
|--------------------------|-----------------------------------|--|-------------------------|---|
| Protected Mode | Reset | ENABLED DISABLED | ENABLED | When Enabled (default), identity object or safety resets are not possible when a controller connection is open. |
| | Network Config | ENABLED DISABLED | ENABLED | When Enabled (default), network configuration changes are not possible when a controller connection is open. |
| | Flash Update | ENABLED DISABLED | ENABLED | When Enabled (default), firmware updates are not possible when a controller connection is open. |
| | Device Config | ENABLED DISABLED | ENABLED | When Enabled (default), only attribute writes are possible when a controller connection is open. |
| Network | ->Static IP ⁽¹⁾ | IP address | 192.168.1.1 | Indicates current IP address |
| | | Subnet mask | 255.255.255.000 | Indicates current subnet mask |
| | | Gateway | 192.168.001.001 | Indicates current gateway |
| | DHCP | On | | Turns DHCP on |
| | | Off | | Turns DHCP off |
| Display | Backlight Timeout | 30 sec... NEVER (NEVER=no timeout period, the backlight is always on) | -> 3 min ⁽¹⁾ | Sets backlight timeout period of the display |
| | Cyclic Data Select ⁽²⁾ | -> DC BUS | | DC bus voltage |
| | | CONV UTIL | | Converter utilization in % Rated |
| | | CONV TEMP | | Converter temperature in °C |
| | | PWR OUT | | Output power in Watts |
| | | IBUS | | Output current in Amps |
| | | AC FREQ | | Input frequency in Hz |
| | | IAC LINE | | AC Line current in Amps |
| | | VAC LINE | | AC Line voltage in Volts |
| | | VBUS REF | | Bus Voltage Reference in Volts |
| | | ACTV PWR | | Active power in Watts |
| | | REACT PWR | | Reactive power in kVAR |
| | | PF | | Power Factor |
| | | ACTV IREF | | Active Current reference in % Rated |
| | | REACT IREF | | Reactive current reference in % Rated |
| | Set Contrast | -10... +10 | 0 | Contrast setting of the display |
| Web | | ENABLED DISABLED | ENABLED | When Enabled (default), the drive's diagnostic webpage is accessible. |

(1) An arrow (->) appears in front of the chosen attribute indicating that this attribute is currently configured. This is also the factory default setting.

(2) The DC bus voltage is one of several cyclic data attributes. You can select any of the Cyclic Data Select attributes to be displayed on the Home screen.

Table 108 - Navigating the iTRAK Power Supply Settings Menu

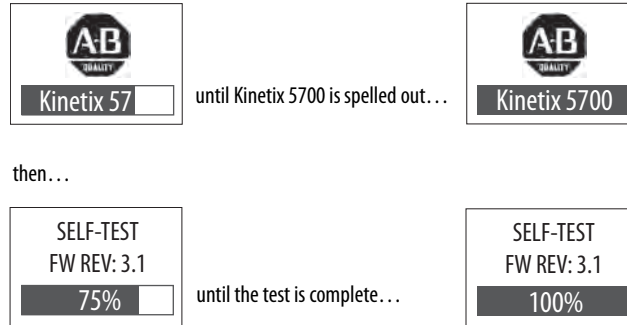
| Settings Menu Selections | Sub Menu Selections | Attributes | Default | Description |
|--------------------------|-----------------------------------|--|-------------------------|--|
| Network | ->Static IP ⁽¹⁾ | IP address | 192.168.1.1 | Indicates current IP address |
| | | Subnet mask | 255.255.255.000 | Indicates current subnet mask |
| | | Gateway | 192.168.001.254 | Indicates current gateway |
| | DHCP | On | | Turns DHCP on |
| | | Off | | Turns DHCP off |
| Display | Backlight Timeout | 30 sec . . . NEVER (NEVER=no timeout period, the backlight is always on) | -> 3 min ⁽¹⁾ | Sets backlight timeout period of the display |
| | Cyclic Data Select ⁽²⁾ | -> BUS VOLT ⁽¹⁾ | | DC bus voltage in volts |
| | | OUT1 VOLT | | Output 1 voltage in volts |
| | | OUT1 AMPS | | Output 1 current in amps |
| | | OUT1 PWR | | Output 1 power in kilowatts |
| | | OUT1 UTIL | | Output 1 utilization in percent |
| | | OUT2 VOLT | | Output 2 voltage in volts |
| | | OUT2 AMP | | Output 2 current in amps |
| | | OUT2 PWR | | Output 2 power in kilowatts |
| | | OUT2 UTIL | | Output 2 utilization in percent |
| | | TOTAL PWR | | Total power in kilowatts |
| | Set Contrast | -10 . . . +10 | 0 | Contrast setting of the display |
| Web | Enabled | | | Enables the web server |
| | ->Disabled | | | Disables the web server |

(1) An arrow (->) appears in front of the chosen attribute indicating that this attribute is currently configured. This is also the factory default setting.

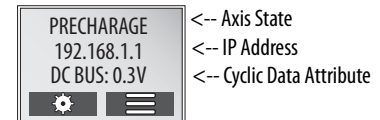
(2) The DC bus voltage is one of several cyclic data attributes. You can select any of the Cyclic Data Select attributes to be displayed on the Home screen.

Startup Sequence

On initial powerup, the drive performs a self test. Upon successful completion, the drive firmware revision is displayed.



Next, the CIP™ axis state, the IP address, and the default cyclic data attribute (in this example DC-bus voltage) appears. In addition, the setup and menu soft keys are displayed. This is the Home screen.



In this example PRECHARGE is the axis state attribute. [Table 109](#) lists the other axis states and their descriptions.

Table 109 - CIP Axis States on the Home Screen

| Axis State | Description |
|-----------------|--|
| STANDBY | The drive is waiting to receive configuration information from the controller. |
| CONNECTING | The drive is trying to establish communication with the EtherNet/IP™ controller. |
| CONFIGURING | The drive is receiving configuration information from the controller. |
| SYNCING | The drive is waiting for a successful Group Sync service. |
| STOPPED | The drive has DC bus ready, but the control loops are not enabled. |
| PRECHARGE | The drive is ready for mains input power. |
| STARTING | The drive is enabled and checking various conditions before entering the RUNNING or TESTING state. For example, the drive checks the Brake Release delay time during the STARTING state. |
| RUNNING | <ul style="list-style-type: none"> The drive is enabled, configured with an active control mode, and actively tracking a command. The drive is configured for No Control and is fully operational. |
| TESTING | The drive is actively executing a test procedure, for example, a hookup test. |
| STOPPING | The drive is decelerating to a stop as the result of a disable. |
| ABORTING | The drive is decelerating to a stop as the result of a fault or an abort request. |
| MAJOR FAULTED | The drive is faulted due to an existing or past fault condition. |
| START INHIBITED | The drive has an active condition that inhibits it from being enabled. |
| SHUTDOWN | The drive has been shut down. |

For more information on the 2198-RPxxx regenerative bus supply CIP axis states, see [Regenerative Bus Supply Sequence Operation](#) on [page 405](#).

Configure the Drive


You can include the drive in your Studio 5000 Logix Designer® application by adding it to a configured EtherNet/IP module or controller under the I/O configuration tree. After setting network parameters, you can view the drive status information in Studio 5000® environment and use it in your Logix Designer application.

Set the Network Parameters

You must program network parameters by using the LCD display.

1. From the LCD display, select SETUP>NETWORK and choose between STATIC IP and DHCP.

The default setting is STATIC IP.

2. If STATIC IP, then press  to configure the following parameters:
 - IP address
 - Gateway
 - Subnet mask

Settings are stored in nonvolatile memory. IP addressing can also be changed through the Module Configuration dialog box in RSLinx® software. Changes to the IP addressing take effect after power is cycled. The drive is factory programmed to static IP address of 192.168.1.1.

Refer to [Setup Screens](#) on [page 192](#) for help setting the network parameters.

Studio 5000 Logix Designer

For help using the Studio 5000 Logix Designer application as it applies to configuring the ControlLogix® or CompactLogix™ controllers, refer to [Additional Resources](#) on [page 13](#).

Version History

Each release of the Studio 5000 Logix Designer application makes possible the configuration of additional Allen-Bradley® motors, actuators, power supplies, and drive features not available in previous versions.

| | |
|------------------|--|
| IMPORTANT | To configure additional motors, actuators, and drive features with your Kinetix 5700 servo drive, you must have drive firmware 4.001 or later. Refer to Table 110 to determine if you need to install the Kinetix 5700 Add-on Profile. |
|------------------|--|

Table 110 - AOP Installation Requirement

| Drive Module Cat. No. | Drive Firmware Revision | Logix Designer Application Version | Kinetix 5700 AOP Needed? |
|--|--------------------------------|------------------------------------|--------------------------|
| 2198-xxxx-ERS3 (series A) | 4.001 | 26.00 or 27.00 | Yes |
| | | 28.00 or later | No |
| | 5.001 | 26.00, 27.00, 28.00 | Yes |
| | | 29.00 or later | No |
| 2198-xxxx-ERS3 (series B) 2198-xxxx-ERS4 | 7.001 or later ⁽²⁾ | 29.00 or later | No |
| 2198-xxxx-ERS3 (series B) 2198-xxxx-ERS4 | 9.001 or later ⁽²⁾ | 31.00 or later | No |
| 2198-RPxxx | 10.001 or later ⁽²⁾ | 32.00 or later | No |
| CIP Security ⁽¹⁾ for: 2198-Pxxx, 2198-RPxxx 2198-xxxx-ERS3 (series B) 2198-xxxx-ERS4 | 11.001 or later | 32.00 | Yes |

(1) For information on CIP Security™, see [CIP Security](#) on [page 12](#).

(2) These firmware enhancements are available only with the applicable Studio 5000 Logix Designer, version. There is no AOP for available for download.

Install the Kinetix 5700 Add-On Profile

Download Add-On profiles (AOP) from the Product Compatibility Download Center (PCDC) website:

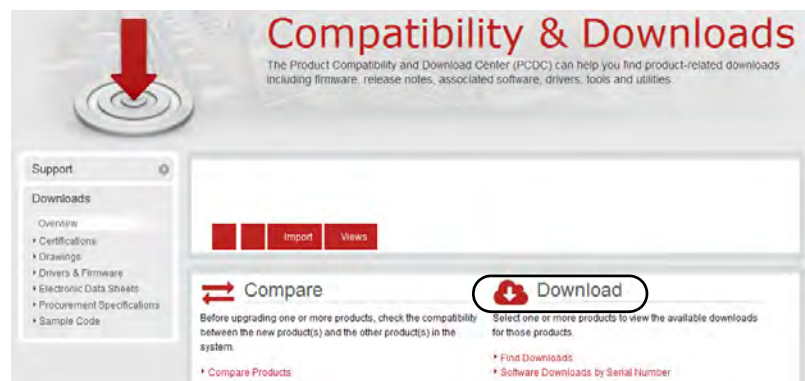
<http://compatibility.rockwellautomation.com/Pages/home.aspx>.

Follow these steps to download the Kinetix 5700 Add-On profile.

1. Go to the Product Compatibility Download Center.

The Compatibility & Downloads webpage appears.

2. Click Download.



3. Enter Kinetix 5700 in the Search PCDC window.
4. Click the appropriate firmware revision and follow prompts to download.
5. Extract the AOP zip file and run Setup.

Configure the Logix 5000 Controller

These procedures assume that you have wired your Kinetix 5700 drive system. In this example, the GuardLogix® 5580 safety controller and Compact GuardLogix 5380 controller dialog boxes are shown.

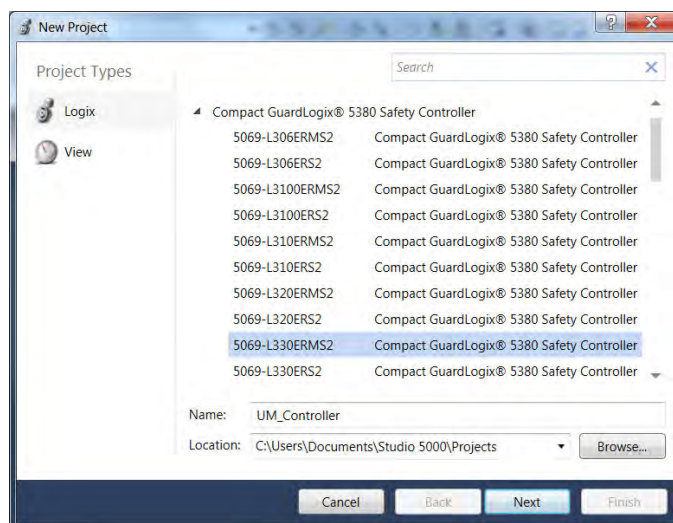
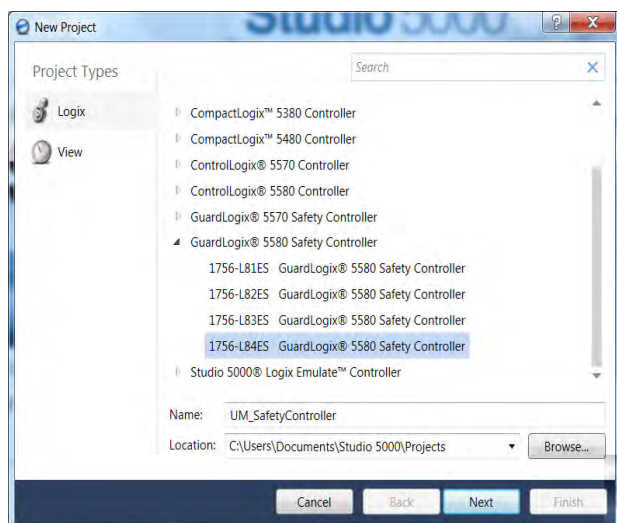
Follow these steps to configure the controller.

1. Apply power to your controller and open your Logix Designer application.



2. From the Create menu, choose New Project.

The New Project dialog box appears.



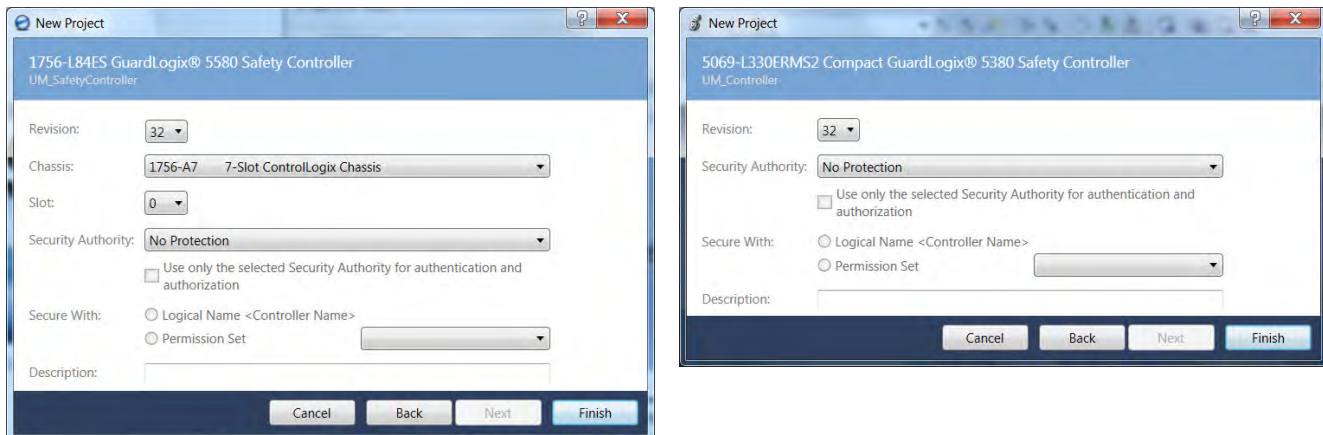
IMPORTANT If you are configuring a safety application, you must use a GuardLogix or Compact GuardLogix safety controller. If you are configuring a 2198-xxxx-ERS4 inverter in a safety application, you must use a GuardLogix 5580 or Compact GuardLogix 5380 safety controller.

In this example, the typical dialog boxes for ControlLogix and GuardLogix 5580 controllers and CompactLogix 5380 controllers with embedded Ethernet are shown.

Follow these steps to configure your Logix 5000 controller.

1. Expand the Logix 5000 controller family and select your controller.
2. Type the file Name.
3. Click Next.

The New Project dialog box appears.



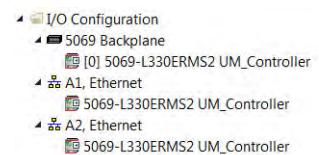
4. From the Revision pull-down menu, choose your software revision.

IMPORTANT To configure Kinetix 5700 drive systems, you must be using the Logix Designer application, version 26.00 or later.

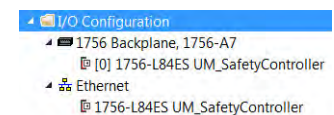
5. Click Finish.

The new controller appears in the Controller Organizer under the I/O Configuration folder.

Controller Organizer with Compact GuardLogix 5380 controller.



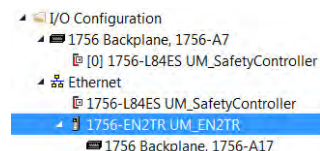
Controller Organizer with GuardLogix 5580 controller.



6. Configure the Logix 5000 controller.

Your new Logix 5000 controller appears under the I/O Configuration folder in the Controller Organizer.

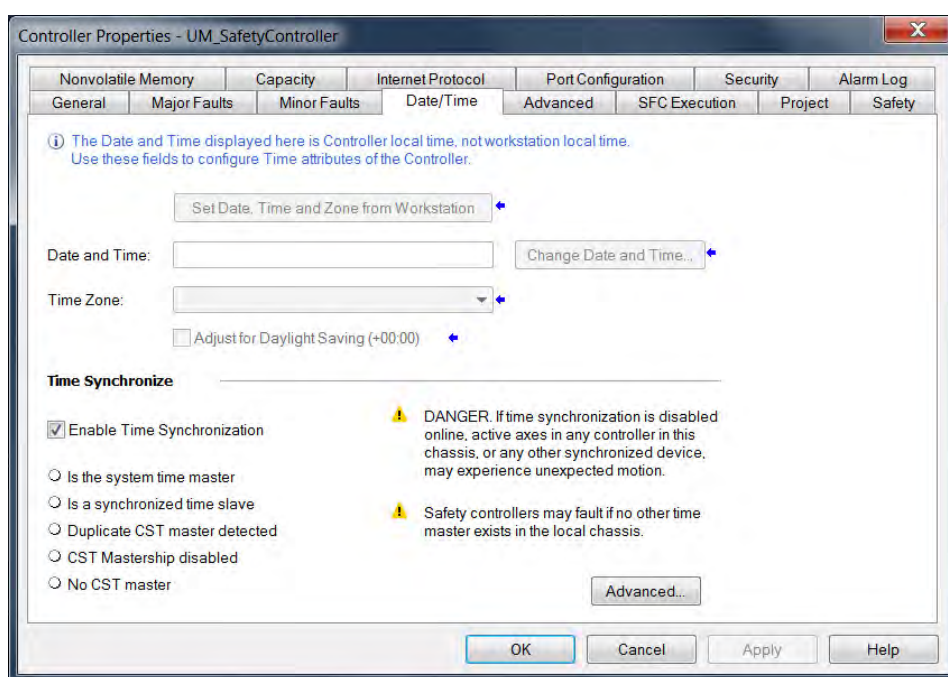
In this example, a GuardLogix 5580 controller with 1756-EN2TR communication module is used.



7. From the Edit menu, choose Controller Properties.

The Controller Properties dialog box appears.

8. Click the Date/Time tab.



9. Check Enable Time Synchronization.

The motion modules set their clocks to the module you assign as the Grandmaster.

IMPORTANT Check Enable Time Synchronization for all controllers that participate in CIP Sync™. The overall CIP Sync network automatically promotes a Grandmaster clock, unless the priority is set in Advanced.

10. Click OK.

Configure the Kinetix 5700 Drive Modules

IMPORTANT To configure Kinetix 5700 drive systems, you must be using the Logix Designer application, version 26.00 or later.

IMPORTANT The iTRAK® power supply is not configured in the Logix Designer application. For more information, see the iTRAK System User Manual, publication [2198T-UM001](#).

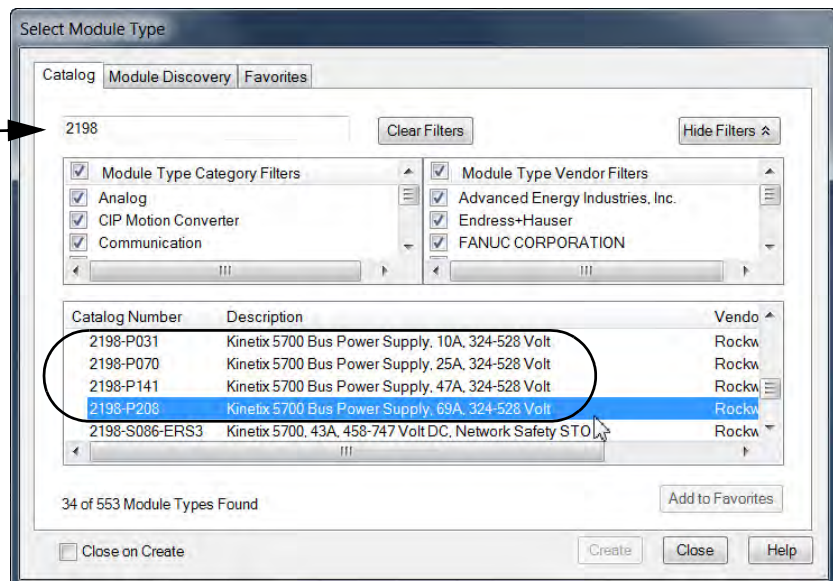
Configure the DC-bus Power Supply

Follow these steps to configure the DC-bus power supply.

1. Below the controller you just created, right-click Ethernet and choose New Module.

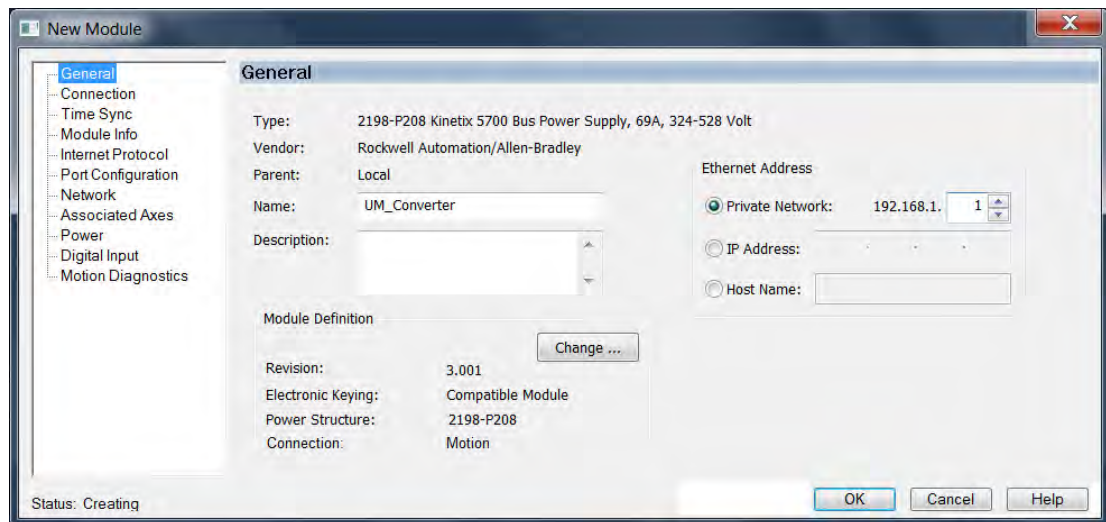
The Select Module Type dialog box appears.

Enter 2198 here to further limit your search.

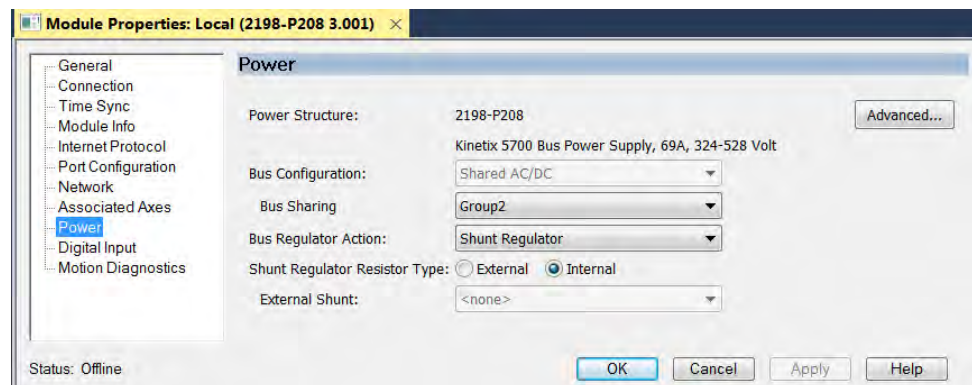


2. By using the filters, check Motion and Allen-Bradley, and select your 2198-Pxxx DC-bus power supply as appropriate for your hardware configuration.
3. Click Create.

The New Module dialog box appears.



4. Configure the new module.
 - a. Type the module Name.
 - b. Select an Ethernet Address option.
In this example, the Private Network address is selected.
 - c. Enter the address of your 2198-Pxxx DC-bus power supply.
In this example, the last octet of the address is 1.
5. Click the Power category.



IMPORTANT The Logix Designer application enforces shared-bus configuration rules for Kinetix 5700 drives.

6. From the pull-down menus, choose the power options appropriate for your hardware configuration.

| Attribute | Menu | Description |
|----------------------------------|--|--|
| Bus Configuration | Shared AC/DC ⁽¹⁾ | Applies to 2198-Pxxx DC-bus power supply (converter) modules. |
| Bus Sharing Group ⁽²⁾ | <ul style="list-style-type: none"> Group1 Group2 Group3... | Applies to any bus-sharing configuration. |
| Bus Regulator Action | Disabled | Disables the internal shunt resistor and external shunt option. |
| | Shunt Regulator | Enables the internal and external shunt options. |
| Shunt Regulator Resistor Type | Internal | Enables the internal shunt (external shunt option is disabled). |
| | External | Enables the external shunt (internal shunt option is disabled). |
| External Shunt ⁽³⁾ | <ul style="list-style-type: none"> None 2198-R004, 2198-R014 2198-R031, 2198-R127 | Selects external shunt option. Only the shunt catalog number intended for the specific DC-bus power supply is shown. |

(1) Shared AC/DC bus configuration is the default selection for DC-bus power supplies.

(2) For more information on bus-sharing groups, refer to [Understand Bus-sharing Group Configuration](#) on page 264.

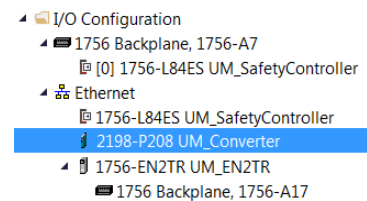
(3) Refer to the Kinetix Servo Drives Specifications Technical Data, publication [KNX-TD003](#), for more information on the Bulletin 2198 external passive shunt resistors.



ATTENTION: To avoid damage to equipment all modules physically connected to the same shared-bus connection system must be part of the same Bus Sharing Group in the Logix Designer application.

7. Click OK to close the New Module dialog box.

8. Your 2198-Pxxx DC-bus power supply appears in the Controller Organizer under the Ethernet network in the I/O Configuration folder.

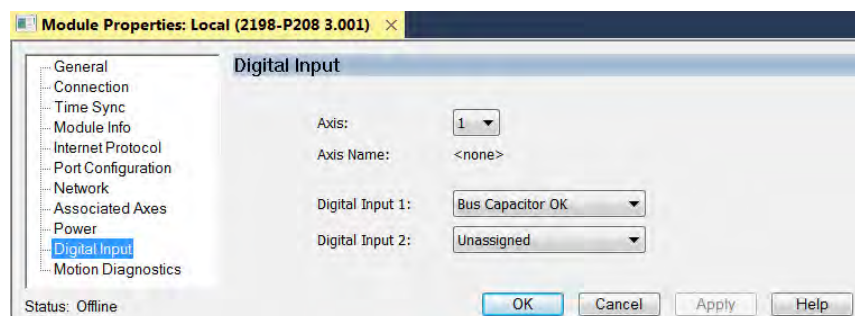


9. Click Close to close the Select Module Type dialog box.
10. Right-click the DC-bus power supply you just created in the Controller Organizer and choose Properties.

The Module Properties dialog box appears.

TIP To configure the remaining DC-bus power supply properties, you must close the New Module dialog box and reopen it as the Module Properties dialog box.

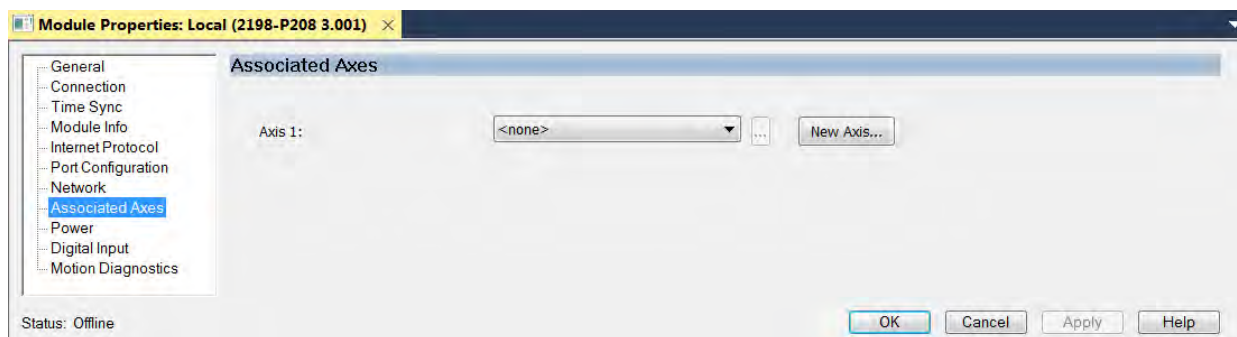
11. Click the Digital Input category.



12. From the Digital Input pull-down menu choose Bus Capacitor OK or Shunt Thermal Switch OK to monitor your capacitor module status or the shunt thermal switch, respectively, depending on your application.

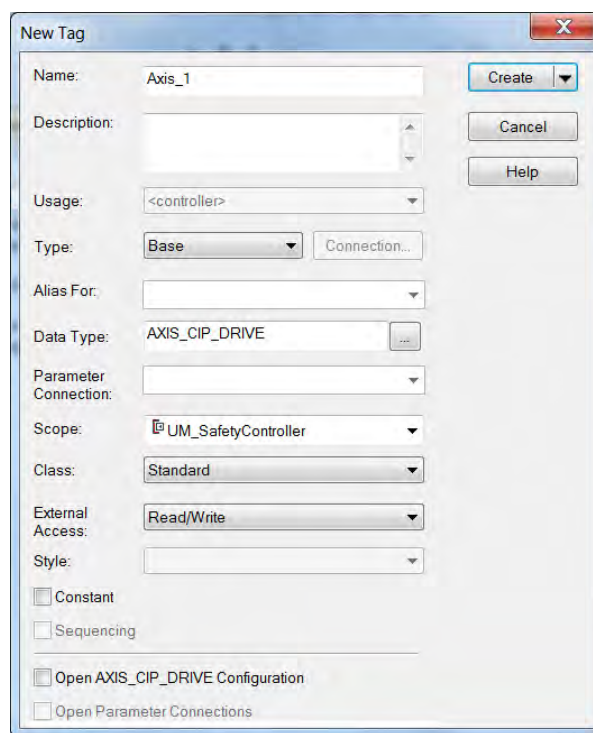
In this example, Bus Capacitor OK is chosen.

13. Click the Associated Axes category.



14. Click New Axis.

The New Tag dialog box appears.

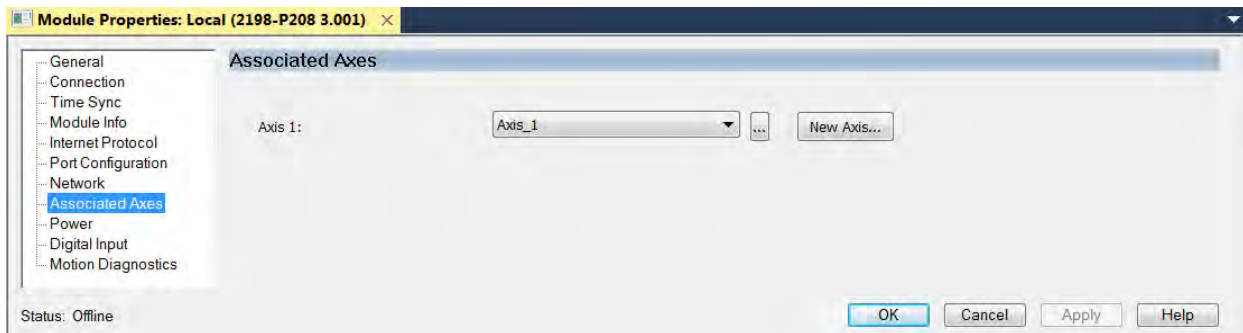


15. Type the axis Name.

AXIS_CIP_DRIVE is the default Data Type.

16. Click Create.

The axis (Axis_1 in this example) appears in the Controller Organizer under Motion Groups> Ungrouped Axes and is assigned as Axis 1.



17. Click Apply.
18. Repeat [step 1](#) through [step 17](#) if you have more than one 2198-P208 DC-bus power supply.

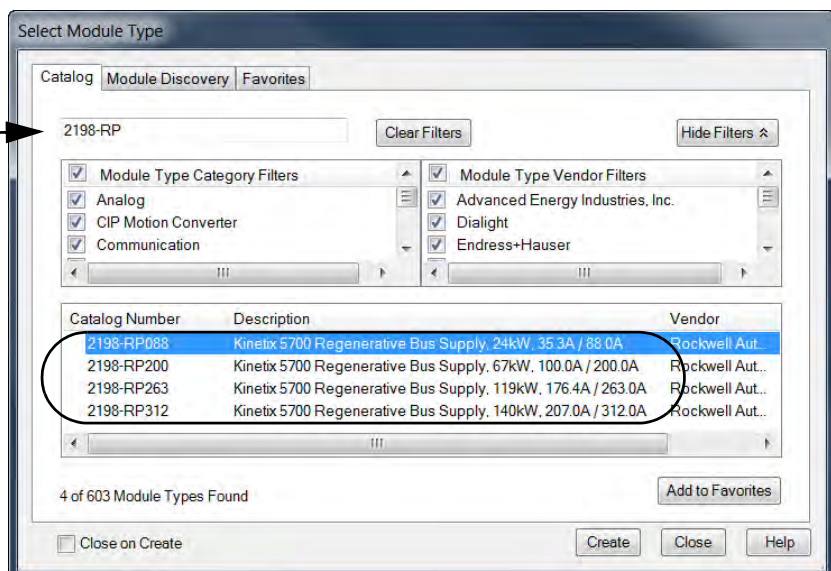
Configure the Regenerative Bus Supply

Follow these steps to configure the regenerative bus supply.

1. Below the controller you just created, right-click Ethernet and choose New Module.

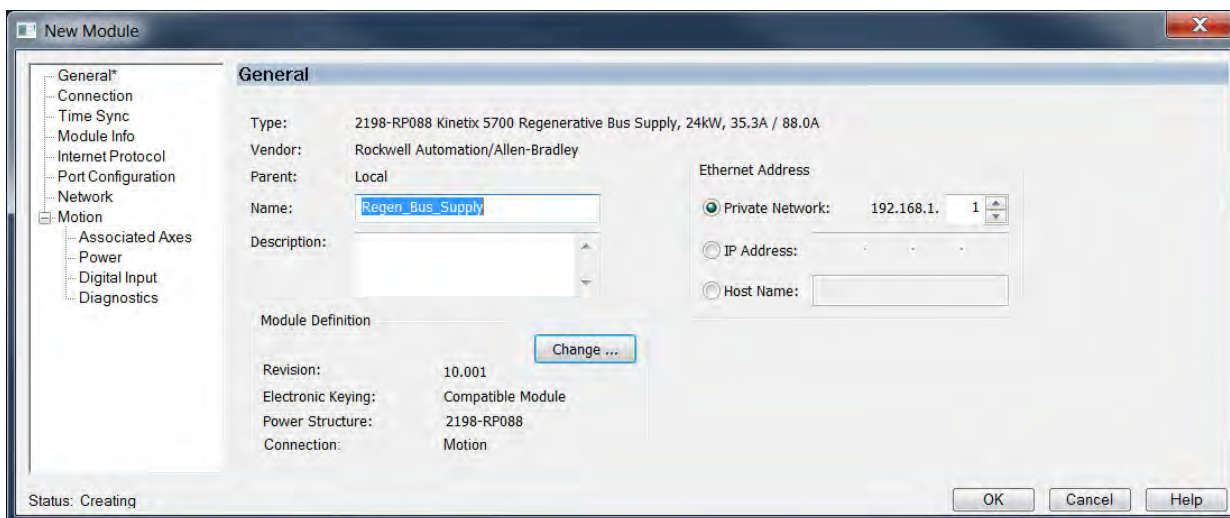
The Select Module Type dialog box appears.

Enter 2198-RP here to further limit your search.

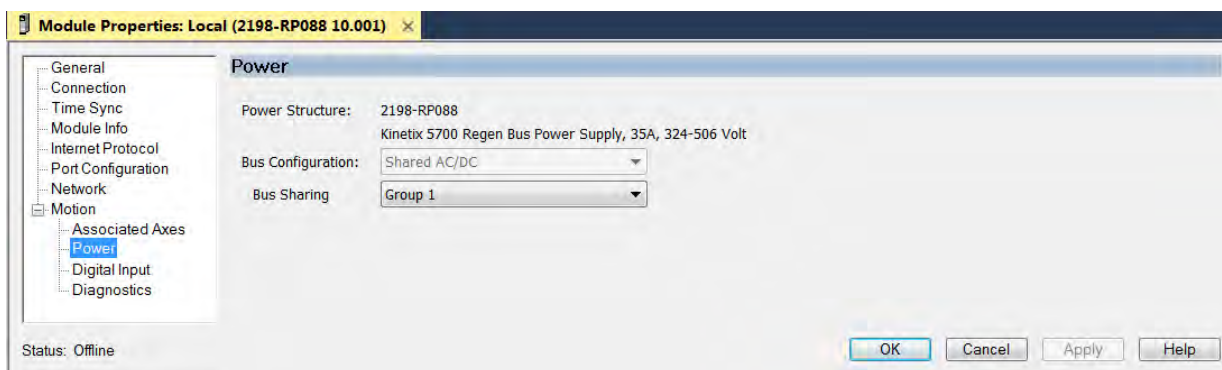


2. By using the filters, check Motion and Allen-Bradley, and select your 2198-RPxxx regenerative bus supply as appropriate for your hardware configuration.
3. Click Create.

The New Module dialog box appears.



4. Configure the new module.
 - a. Type the module Name.
 - b. Select an Ethernet Address option.
In this example, the Private Network address is selected.
 - c. Enter the address of your 2198-RPxxx regenerative bus supply.
In this example, the last octet of the address is 1.
5. Click the Power category.



IMPORTANT The Logix Designer application enforces shared-bus configuration rules for Kinetix 5700 drives.

6. From the pull-down menus, choose the power options appropriate for your hardware configuration.

| Attribute | Menu | Description |
|----------------------------------|---|--|
| Bus Configuration | Shared AC/DC ⁽¹⁾ | Applies to 2198-RPxxx regenerative bus supply modules. |
| Bus Sharing Group ⁽²⁾ | <ul style="list-style-type: none"> Group1 Group2 Group3... | Applies to any bus-sharing configuration. |

(1) Shared AC/DC bus configuration is the default selection for regenerative bus supplies.

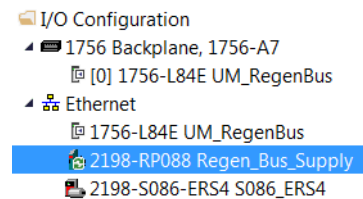
(2) For more information on bus-sharing groups, refer to [Understand Bus-sharing Group Configuration](#) on page 264.



ATTENTION: To avoid damage to equipment all modules physically connected to the same shared-bus connection system must be part of the same Bus Sharing Group in the Logix Designer application.

7. Click OK to close the New Module dialog box.

8. Your 2198-RPxxx regenerative bus supply appears in the Controller Organizer under the Ethernet network in the I/O Configuration folder.

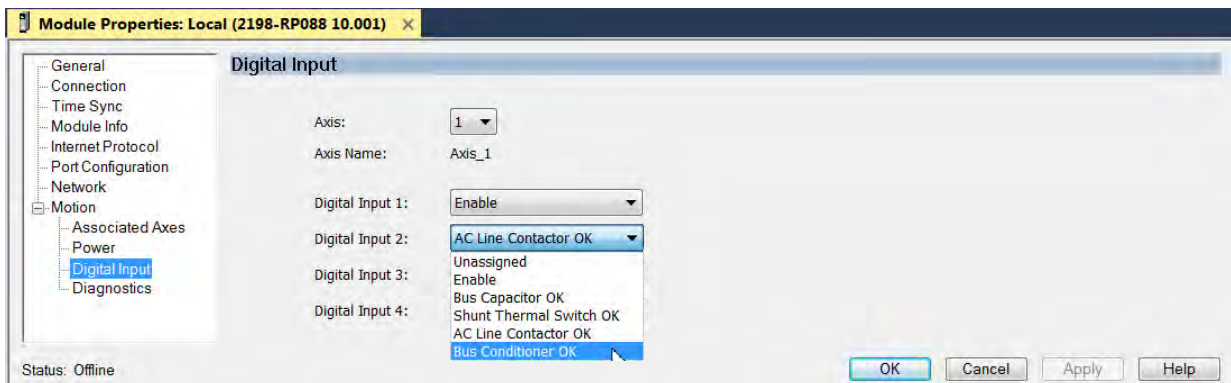


9. Click Close to close the Select Module Type dialog box.
10. Right-click the regenerative bus supply you just created in the Controller Organizer and choose Properties.

The Module Properties dialog box appears.

TIP To configure the remaining regenerative bus supply properties, you must close the New Module dialog box and reopen it as the Module Properties dialog box.

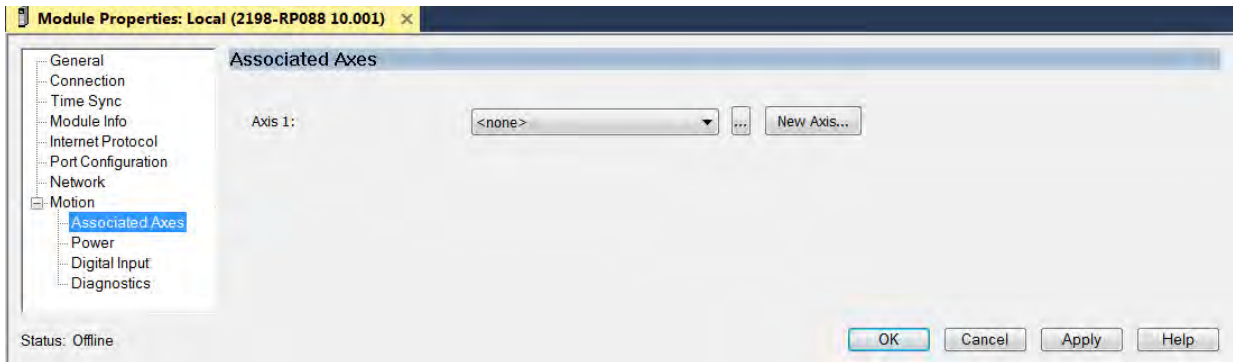
11. Click the Digital Input category.



12. From the Digital Input pull-down menu choose Bus Conditioner OK or AC Line Contactor OK to monitor your DC-bus conditioner module status or the M1 contactor status, respectively, depending on your application.

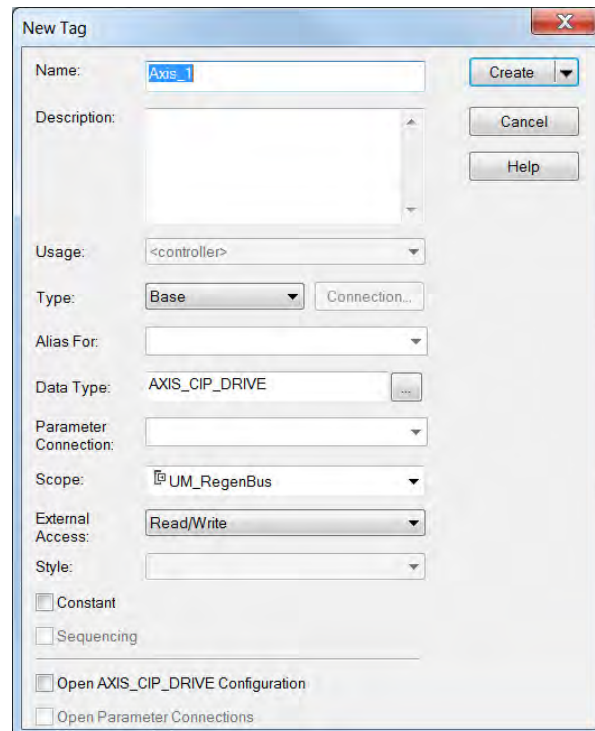
In this example, Bus Capacitor OK is chosen.

13. Click the Associated Axes category.



14. Click New Axis.

The New Tag dialog box appears.

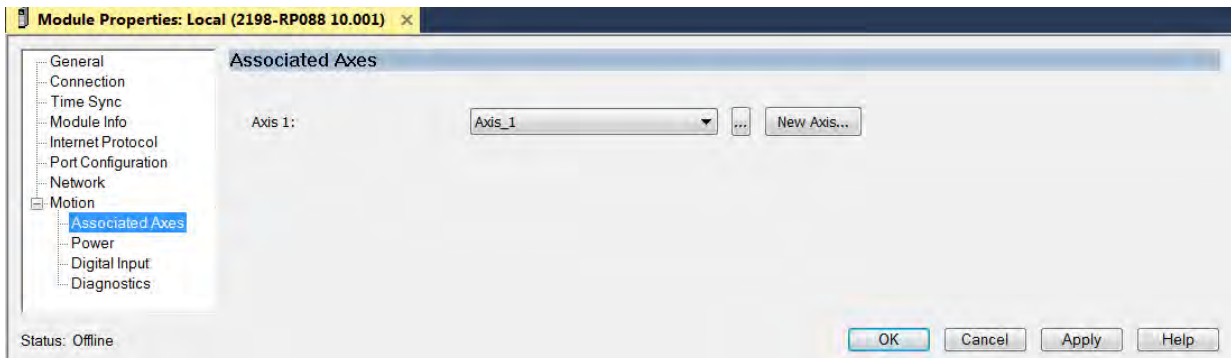


15. Type the axis Name.

AXIS_CIP_DRIVE is the default Data Type.

16. Click Create.

The axis (Axis_1 in this example) appears in the Controller Organizer under Motion Groups> Ungrouped Axes and is assigned as Axis 1.



17. Click Apply.
18. Repeat [step 1](#) through [step 17](#) if you have more than one 2198-RPxxx regenerative bus supply.

Configure the Inverter Drives

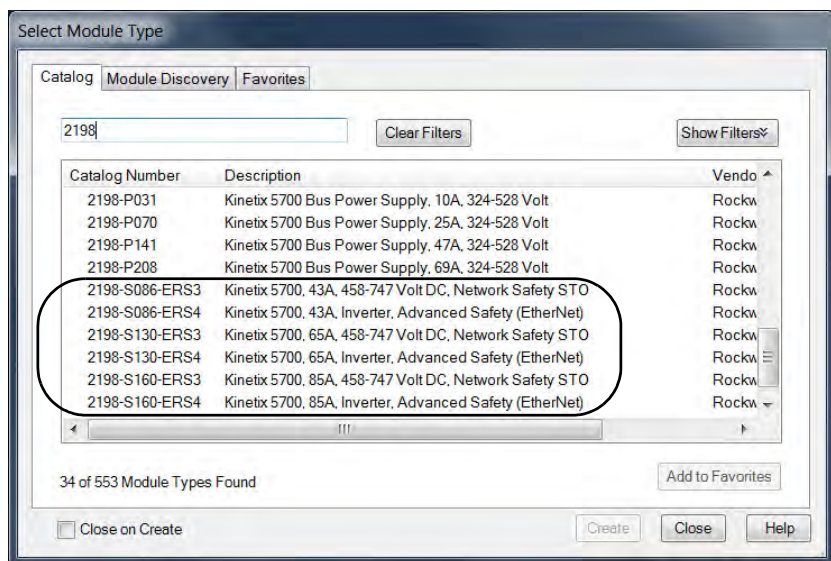
This procedure applies to single-axis and dual-axis inverters with hardwired or integrated safety connections. In this example, a 2198-D006-ERS4 dual-axis inverter is configured.

Follow these steps to configure Kinetix 5700 inverter drives.

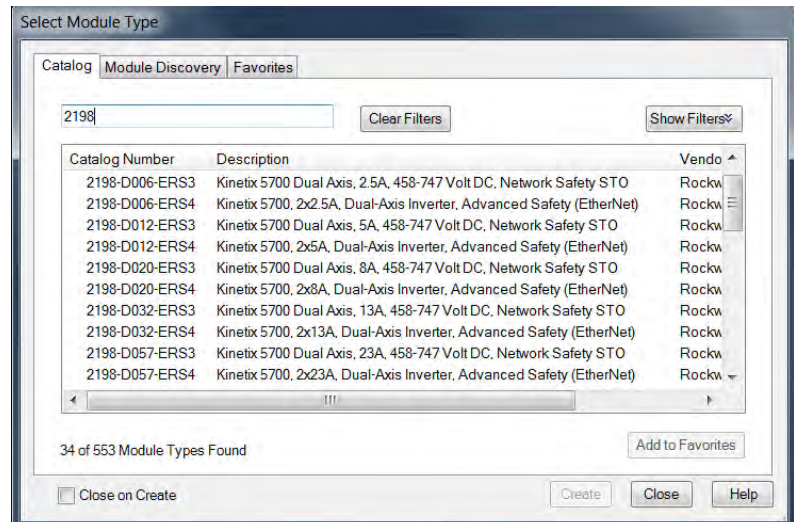
1. Above the DC-bus power supply (converter) you just created, right-click Ethernet and choose New Module.

The Select Module Type dialog box appears.

This example shows the 2198-Sxxx-ERSx single-axis inverters you can choose from.

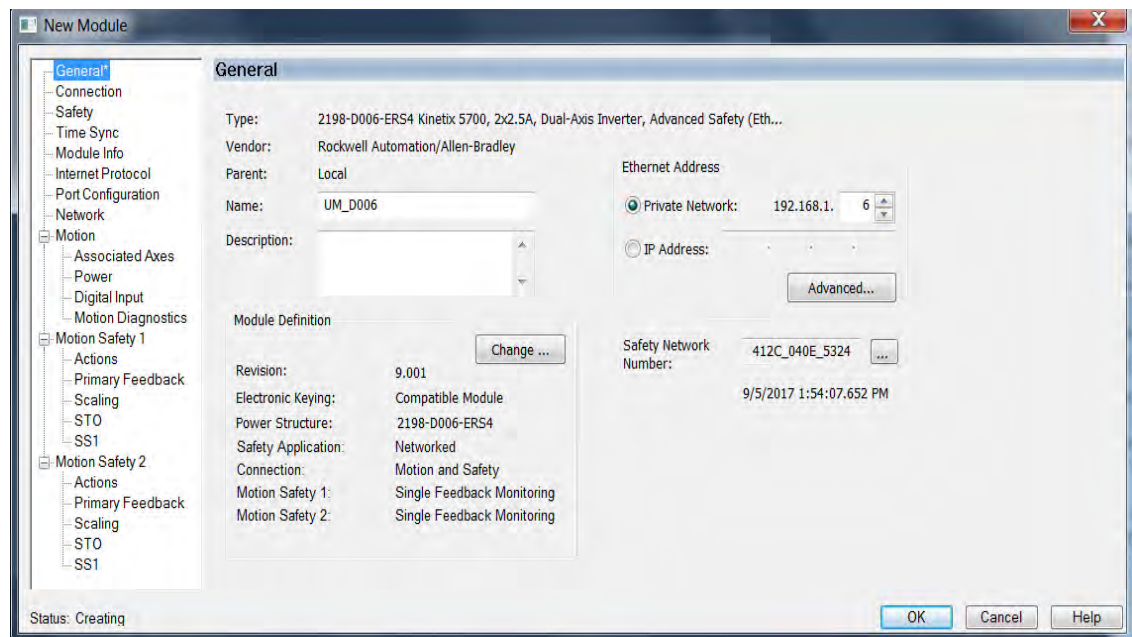


This example shows the 2198-Dxxx-ERSx dual-axis inverters you can choose from.



2. Enter 2198 to narrow your choices and select your 2198-xxxx-ERS3 or 2198-xxxx-ERS4 inverter as appropriate for your hardware configuration.
3. Click Create.

The New Module dialog box appears.



4. Configure the new drive.
 - a. Type the drive Name.
 - b. Select an Ethernet Address option.
In this example, the Private Network address is selected.
 - c. Enter the address of your 2198-xxxx-ERSx inverter.
In this example, the last octet of the address is 6.
 - d. Click Advanced if using network address translation with safety connection to add drive module configured IP address.

The fields to configure in the Module Definition dialog box are dependent on your drive, Logix Designer version, and drive firmware revision. Use the following table to navigate to the series of steps intended for your drive system.

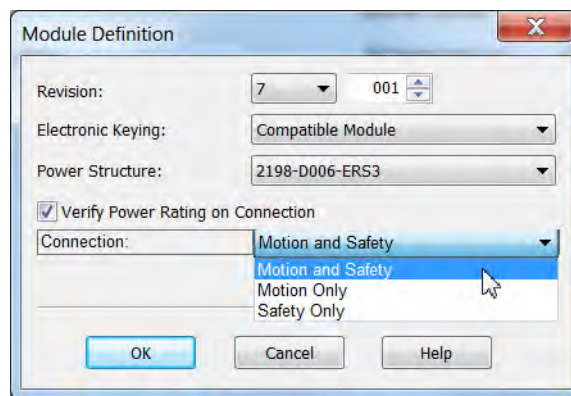
Table 111 - How to Navigate Module Definition

| For Drive Cat. No. | Logix Designer Version | Drive Firmware Revision | Go to: |
|---|------------------------|-------------------------|---|
| 2198-xxxx-ERS3 (series A) | 30 or earlier | 7 or earlier | Configure Module Definition for 2198-xxxx-ERS3 (series A) Drives on page 213 |
| 2198-xxxx-ERS3 (series B) 2198-xxxx-ERS4 | 31 or later | 9 or later | Configure Module Definition for 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) Drives on page 214 |

Configure Module Definition for 2198-xxxx-ERS3 (series A) Drives

- Under Module Definition click Change.

The Module Definition dialog box appears.



Depending on the Module Definition revision selection, alternate product features and feedback types can be selected.

- From the Connection pull-down menu, choose the Connection mode for your motion application.

TIP When 'Safety' appears in the Connection mode, integrated safety is implied.

IMPORTANT If the STO bypass jumper wires were applied during machine commissioning or maintenance, they must be removed before the drive will operate in Integrated (Networked) safety mode.

Table 112 - Module Connection Definitions

| Connection Mode | Safety Options | Description |
|-------------------|---|---|
| Motion and Safety | Integrated mode | Motion connections and integrated STO are managed by this controller. |
| Motion Only | <ul style="list-style-type: none"> Hardwired STO mode Integrated mode if there is a secondary safety controller | <ul style="list-style-type: none"> Motion connections are managed by this controller. Hardwired STO is controlled by the hardwired safety inputs or Integrated is managed by another controller that has a Safety-only connection to the drive. |
| Safety Only | Integrated mode | <ul style="list-style-type: none"> Integrated STO is managed by this controller. Motion connections are managed by another controller that has a Motion-only connection to the drive. |

The Safety Network Number (SNN) field populates automatically when the Connection mode includes an integrated Motion and Safety or Safety-only connection. For a detailed explanation of the safety network number, refer to the appropriate GuardLogix controller publication as defined in [Additional Resources](#) on [page 13](#).

- 3. Click OK to close the Module Definition dialog box.
- 4. Click Apply.
- 5. Go to [Configure the Power and Safety Categories](#) on [page 217](#).

Configure Module Definition for 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) Drives

- 1. Under Module Definition click Change.

The Module Definition dialog box appears.

Module Definition for
2198-xxxx-ERS3 (series B) inverters
(no feedback configuration).

Module Definition for
2198-xxxx-ERS4 inverters
(includes feedback configuration).

Depending on the Module Definition revision selection, alternate product features and feedback types can be selected.

- 2198-xxxx-ERS4 drives appear in only drive firmware revision 9.001 or later
 - With drive firmware revision 9.001 or later, 2198-xxxx-ERS3 (series B) drives support Timed SS1 function and STO function with configurable delay
 - 2198-xxxx-ERS3 drives do not support feedback monitoring
- 2. If you are replacing a 2198-xxxx-ERS3 (series A) drive with a 2198-xxxx-ERS3, series B drive, determine your Electronic Keying option from the pull-down menu (Compatible Module is the default setting). See [Replacing 2198-xxxx-ERS3 \(series A\) Drives with Series B Drives](#) on [page 302](#) for more information.

| Drive Cat. No. | Studio 5000 Logix Designer | Electronic Keying |
|--|----------------------------|--|
| 2198-xxxx-ERS3 (replacing series A with series B) | Version 30 or earlier | Compatible Module |
| | Version 31 or later | Exact Match (recommended) ⁽¹⁾ |

(1) See the Logix 5000 Controllers I/O and Tag Data Programming Manual, publication [1756-PM004](#), for more information on Electronic Keying settings.

3. From the Safety Application pull-down menu, choose between Hardwired for Hardwired STO mode or Networked for an integrated safety application (see [Table 113](#) on [page 215](#) for definitions).



IMPORTANT If the STO bypass jumper wires were applied during machine commissioning or maintenance, they must be removed before the drive will operate in Integrated (Networked) safety mode.

Table 113 - Safety Application Definitions

| Safety Application Mode ⁽¹⁾ | Safety Functions | Minimum Drive Module Required ⁽³⁾ | Drive Module Connection Options | Minimum Controller Required ⁽⁴⁾ |
|--|--|--|--|--|
| Hardwired | Safe Torque-off (STO) | 2198-xxxx-ERS3 (series A) | Motion Only | <ul style="list-style-type: none"> ControlLogix 5570 CompactLogix 5370 |
| Networked (integrated) | Safe Torque-off (STO) | 2198-xxxx-ERS3 (series A) | <ul style="list-style-type: none"> Motion and Safety Safety Only | GuardLogix 5570 |
| | Timed SS1 | 2198-xxxx-ERS3 (series B) | <ul style="list-style-type: none"> Motion and Safety Safety Only | <ul style="list-style-type: none"> GuardLogix 5580 Compact GuardLogix 5380 |
| | <ul style="list-style-type: none"> Timed SS1 Monitored SS1 Controller-based safety functions ⁽²⁾ | 2198-xxxx-ERS4 | <ul style="list-style-type: none"> Motion and Safety Safety Only | |

(1) For 2198-Dxxx-ERS4 (dual-axis) inverters, you must configure axes 1 and 3 as either Networked or Hardwired, they cannot be mixed.

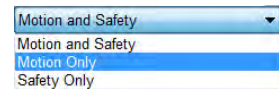
(2) See the Kinetix 5700 Safe Monitor Functions Safety Reference Manual, publication [2198-RM001](#), for more information on these Drive Safety instructions.

(3) Where a 2198-xxxx-ERS3 drive is specified, a 2198-xxxx-ERS4 drive is backwards compatible.

Where a 2198-xxxx-ERS3 (series A) drive is specified, a 2198-xxxx-ERS3 (series B) drive is backwards compatible.

(4) Where a ControlLogix or CompactLogix (non-safety) controller is specified, a GuardLogix or Compact GuardLogix controller is backwards compatible. Also, GuardLogix 5580 and Compact GuardLogix 5380 controllers are backwards compatible with GuardLogix 5570 and Compact GuardLogix 5370 controllers.

4. From the Connection pull-down menu, choose the Connection mode for your motion application (see [Table 114](#) for definitions).

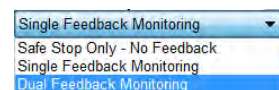


TIP When 'Safety' appears in the Connection mode, integrated safety is implied.

Table 114 - Module Connection Definitions

| Connection Mode | Safety Options | Description |
|-------------------|---|---|
| Motion and Safety | Integrated mode | Motion connections and integrated STO are managed by this controller. |
| Motion Only | <ul style="list-style-type: none"> Hardwired STO mode Integrated mode if there is a secondary safety controller | <ul style="list-style-type: none"> Motion connections are managed by this controller. Hardwired STO is controlled by the hardwired safety inputs or Integrated is managed by another controller that has a Safety-only connection to the drive. |
| Safety Only | Integrated mode | <ul style="list-style-type: none"> Integrated STO is managed by this controller. Motion connections are managed by another controller that has a Motion-only connection to the drive. |

5. From the Motion Safety x pull-down menu, choose the integrated safety type (see [Table 115](#) on [page 216](#) for definitions).



‘Motion Safety’ applies to 2198-Sxxx-ERS4 (single-axis) inverters.
 ‘Motion Safety 1’ and ‘Motion Safety 2’ applies to 2198-Dxxx-ERS4 (dual-axis) inverters.

Motion Safety and Motion Safety 1 align with Axis 1 configured in Associated Axes. Motion Safety 2 aligns with Axis 3 configured in Associated Axes.

Table 115 - Motion Safety Definitions

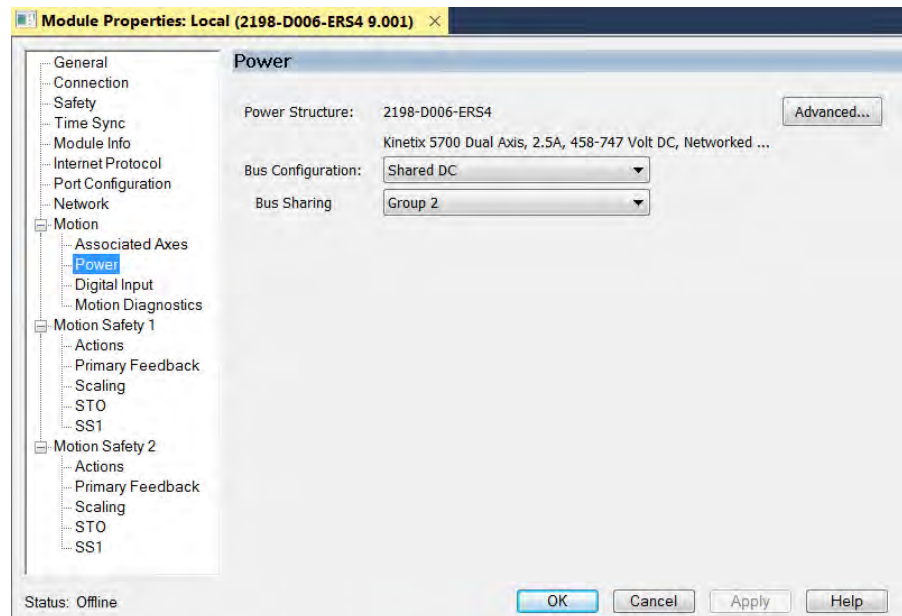
| Motion Safety Mode | Safety Application Mode | Module Connection Options | Description |
|------------------------------|-------------------------|--|---|
| STO Only | Networked | <ul style="list-style-type: none"> • Motion and Safety • Safety Only | 2198-xxxx-ERS3 (series A and B): STO function only. |
| Safe Stop Only - No Feedback | | | <ul style="list-style-type: none"> • 2198-xxxx-ERS4: STO function and Timed SS1 Safe Stop functions are available. • 2198-xxxx-ERS3 (series B): STO function and Timed SS1 Safe Stop functions are available. |
| Single Feedback Monitoring | | | Primary feedback is used in the safety object for safe monitoring. The feedback can be a SIL rated Hiperface DSL encoder, for example, a VPL-B1003P-Q or W motor used in the DSL Feedback port. This can also be a Sine/Cosine or EnDat device, for example, an MPL-B310P-M motor used in the Universal Feedback port. See the Kinetix 5700 Safe Monitor Functions Safety Reference Manual, publication 2198-RM001 , to evaluate SIL levels possible with a single feedback device. |
| Dual Feedback Monitoring | | | In addition to primary feedback, an external feedback device is used to improve SIL levels. For example, the Bulletin 842HR type encoder can be used in the Universal Feedback port as a Sine/Cosine device. See the Kinetix 5700 Safe Monitor Functions Safety Reference Manual, publication 2198-RM001 , to evaluate SIL levels possible with two feedback devices. |

The Safety Network Number (SNN) field populates automatically when the Connection mode includes an integrated Motion and Safety or Safety-only connection. For a detailed explanation of the safety network number, refer to the appropriate GuardLogix controller publication as defined in [Additional Resources](#) on [page 13](#).

6. Click OK to close the Module Definition dialog box.
7. Click Apply.

Configure the Power and Safety Categories

1. Click the Power category.



IMPORTANT The Logix Designer application enforces shared-bus configuration rules for Kinetix 5700 drives.

2. From the pull-down menus, choose the power options appropriate for your hardware configuration.

| Attribute | Menu | Description |
|--------------------------------------|---|--|
| Bus Configuration | Shared DC ⁽²⁾ | Applies to 2198-Sxxx-ERSx and 2198-Dxxx-ERSx inverter drives. |
| | Shared DC - Non-CIP Motion™ Converter ⁽³⁾ | Applies to the designated inverter in drive systems powered by the 8720MC-RPS regenerative power supply. |
| Bus Sharing Group ^{(1) (3)} | <ul style="list-style-type: none"> • Group1 • Group2 • Group3... | Applies to any bus-sharing configuration. |

(1) For more information on bus-sharing groups, refer to [Understand Bus-sharing Group Configuration](#) on page 264.

(2) Shared DC bus configuration is the default selection for single-axis and dual-axis inverters.

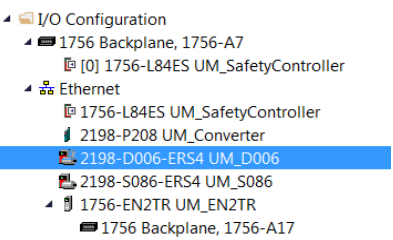
(3) Because the 8720MC-RPS unit is not an EtherNet/IP network device the Logix 5000 controller does not communicate with it. The designated inverter, configured as the Shared DC - Non-CIP Motion Converter, monitors the 8720MC-RPS unit status through a digital input (Regen OK) and communicates with the other inverters to signal when the DC-bus voltage is present.



ATTENTION: To avoid damage to equipment all modules physically connected to the same shared-bus connection system must be part of the same Bus Sharing Group in the Logix Designer application.

3. Click OK to close the Module Properties dialog box.
4. Click Close to close the Select Module Type dialog box.

Your 2198-xxxx-ERS4 inverter appears in the Controller Organizer under the Ethernet I/O Configuration folder.



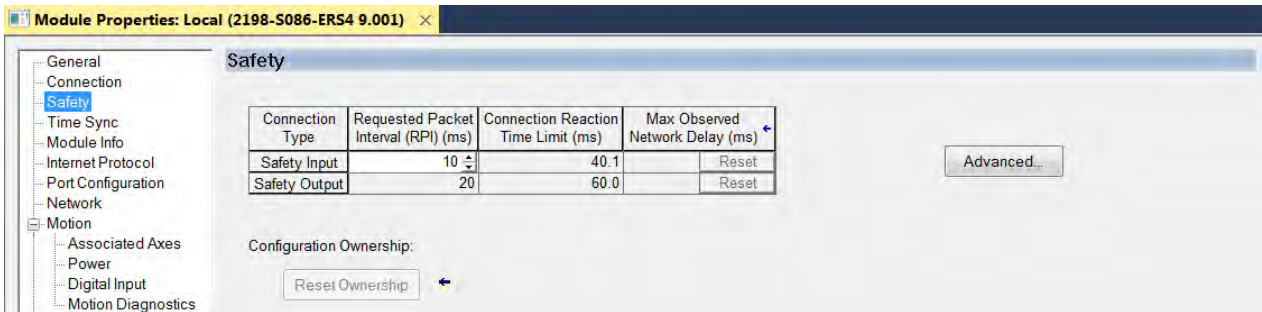
5. Right-click the drive you just created in the Controller Organizer and choose Properties.

The Module Properties dialog box appears.

TIP To configure the remaining inverter properties, you must close the New Module dialog box and reopen it as the Module Properties dialog box.

| If | Then |
|---|---|
| Your application includes integrated safety | Go to step 6 on page 218 . |
| Your application includes hardwired safety or has no safety connections | Go to Continue Inverter Configuration on page 219 . |

6. Click the Safety category.



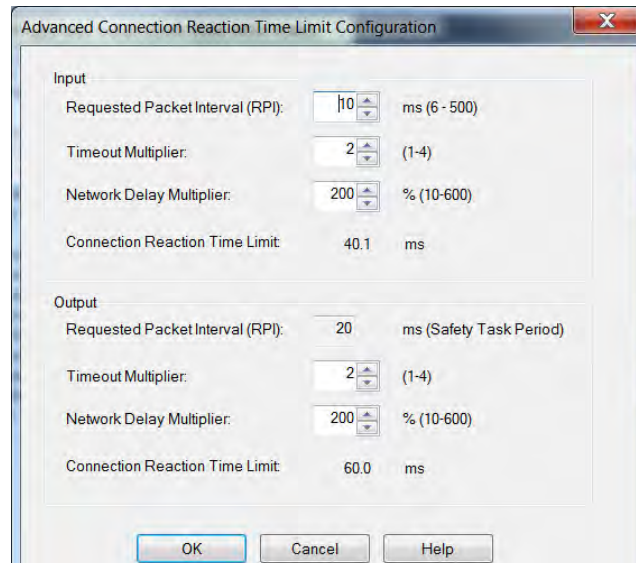
7. The connection between the owner and the 2198-xxxx-ERSx inverter is based on the following:

- Servo drive safety network number
- GuardLogix slot number
- GuardLogix safety network number
- Path from the GuardLogix controller to the 2198-xxxx-ERSx drive
- Configuration signature

If any differences are detected, the connection between the GuardLogix controller and the 2198-xxxx-ERSx inverter is lost, and the yellow yield icon appears in the controller project tree after you download the program.

8. Click Advanced.

The Advanced Connection Reaction Time Limit Configuration dialog box appears.



Analyze each safety channel to determine the appropriate settings. The smallest Input RPI allowed is 6 ms. Selecting small RPI values consumes network bandwidth and can cause nuisance trips because other devices cannot get access to the network.

For more information about the Advanced Connection Reaction Time Limit Configuration, refer to [Additional Resources](#) on [page 13](#) for the appropriate user manual for your GuardLogix or Compact GuardLogix controller.

9. Click OK to close the Advanced dialog box.
10. Click Apply to save the Safety category parameters.

Continue Inverter Configuration

After you've established your Kinetix 5700 inverters in the Logix Designer application, the feedback options need to be defined for each axis. Each physical axis supports motor and auxiliary feedback.

Table 116 - Kinetix 5700 Feedback Axis Summary

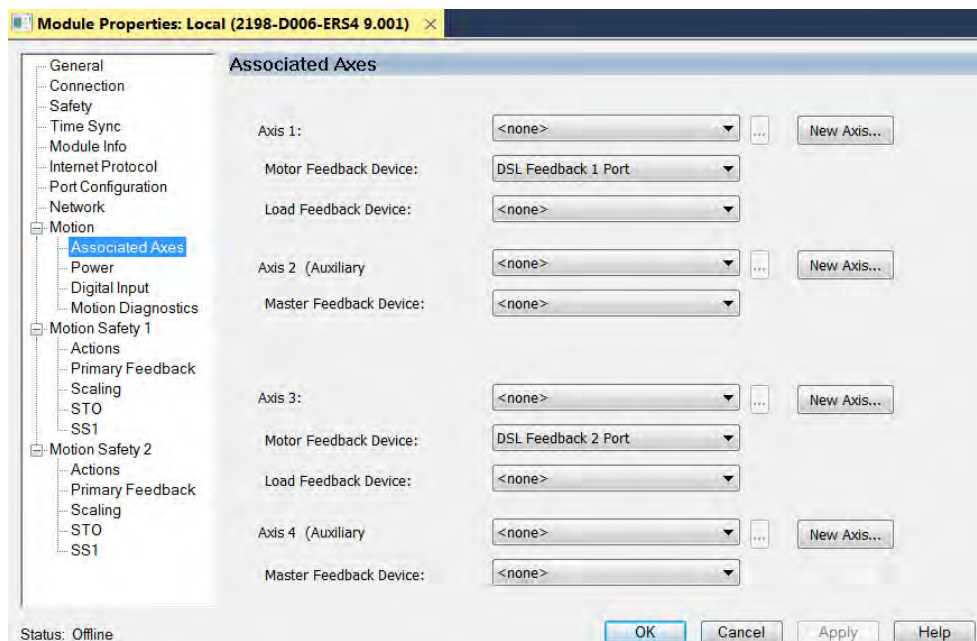
| Kinetix 5700 Inverter | Inverter Cat. No. | Motor Feedback | Auxiliary Feedback |
|-----------------------|----------------------------------|------------------|--------------------|
| Single-axis Inverters | 2198-Sxxx-ERS3 or 2198-Sxxx-ERS4 | 1 (axis 1) | 1 (axis 2) |
| Dual-axis Inverters | 2198-Dxxx-ERS3 or 2198-Dxxx-ERS4 | 2 (axis 1 and 3) | 2 (axis 2 and 4) |

Follow these steps to configure the axes for your Kinetix 5700 drive system.

1. Right-click the 2198-xxxx-ERS4 inverter you just created and choose Properties.

The Module Properties dialog box appears.

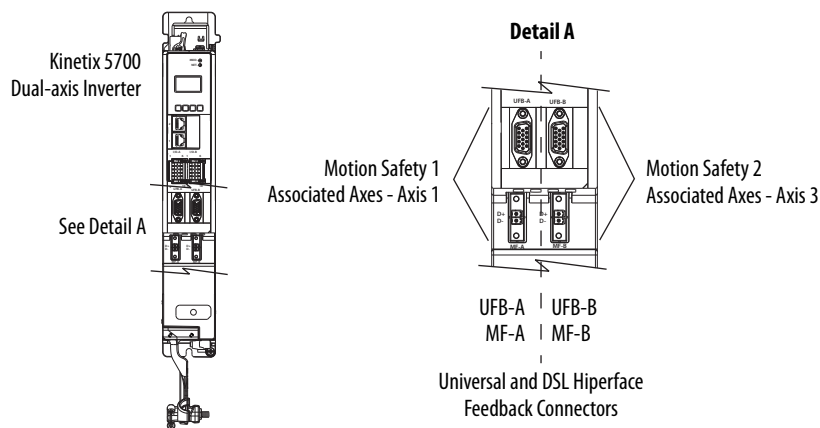
2. Select the Associated Axes category.



In this 2198-D006-ERS4 (dual-axis inverter) example, four axes are possible. Single-axis inverters support only two axes.

- Axis 1 and Axis 2 apply to Motor (DSL) Feedback Connector A (Port 1) and Universal Feedback Connector A (Port 1).
- Axis 3 and Axis 4 apply to Motor (DSL) Feedback Connector B (Port 2) and Universal Feedback Connector B (Port 2).

Figure 128 - Dual-axis Inverter Feedback



The Feedback Devices are configured for either the DSL Feedback Port or the Universal Feedback Port.

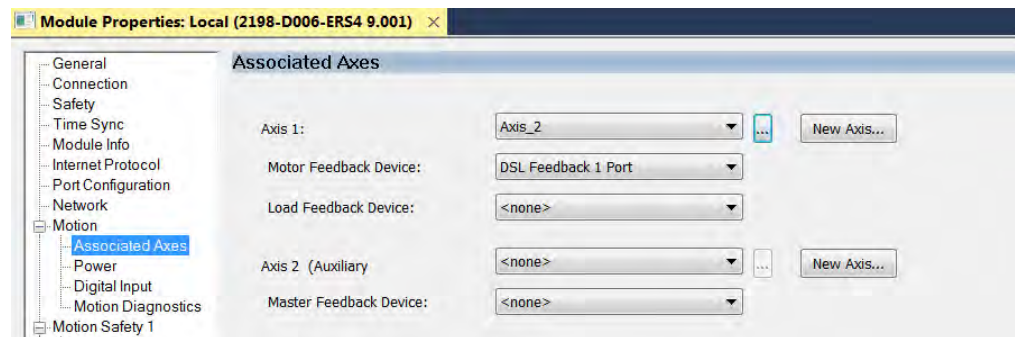
| Motor Feedback Options | Description |
|-------------------------|---|
| DSL Feedback Port | Applies to motors and actuators compatible with the 2198-KITCON-DSL connector kit and 2198-H2DCK converter kit (series B or later). These kits plug into the 2-pin motor feedback (MF) connector. |
| Universal Feedback Port | Applies to motors and actuators compatible with the 2198-K57CK-D15M universal connector kit. These kits plug into the 15-pin universal feedback (UFB) connector. |

- From the Axis x pull-down menu, choose an axis to assign to that motor feedback or auxiliary feedback device.
- From the Feedback Device pull-down menu, choose either DSL Feedback x Port or Universal Feedback x Port to associate with each axis.
- Click New Axis.

The New Tag dialog box appears.

- Type the axis Name.
AXIS_CIP_DRIVE is the default Data Type.
- Click Create.

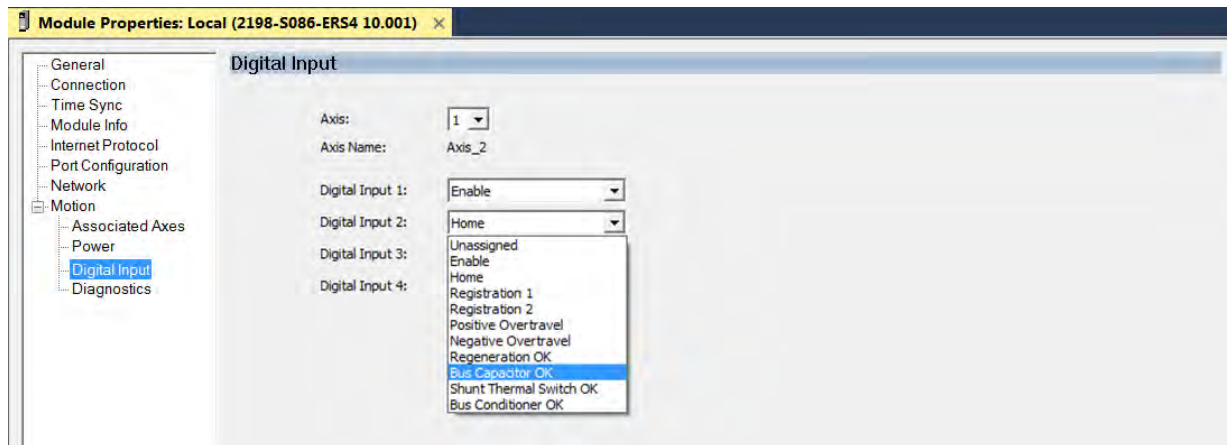
The axis (Axis_1 in this example) appears in the Controller Organizer under Motion Groups> Ungrouped Axes and is assigned as Axis 1.



TIP You can configure an axis as Feedback Only. Refer to [Configure Feedback-only Axis Properties](#) on [page 230](#) for more information.

Refer to [Configure Module Properties](#) on [page 257](#) for configuring motor feedback, load feedback, and master feedback devices.

8. Click Apply.
9. Click the Digital Input category.



10. From the Digital Input pull-down menus choose the functions appropriate for your application.

In this example, Digital Input 2 is assigned Bus Capacitor OK to monitor your 2198-CAPMOD-2240 capacitor module.

For 8720MC-RPS power supplies:

- When a 2198-Sxxx-ERSx single-axis inverter is the first drive module (adjacent to the 2198-CAPMOD-2240 capacitor module) you must configure the Digital Input category as Regeneration OK and wire the IOD connector.
- When a 2198-Dxxx-ERSx dual-axis inverter is the first drive module (adjacent to the 2198-CAPMOD-2240 capacitor module) and Axis 1 and 3 are used, you must configure the Digital Input category as Regeneration OK and wire the IOD connector for each axis.

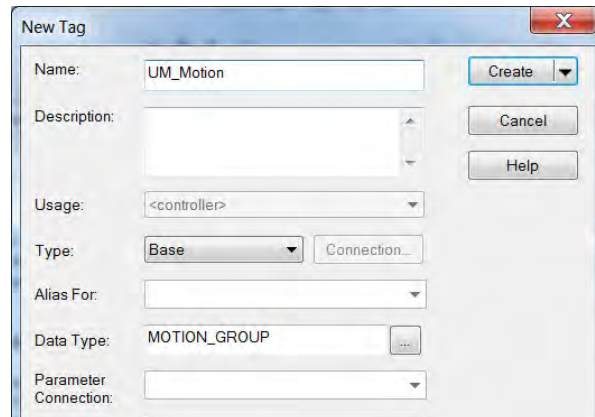
11. Click OK.
12. Repeat [step 1](#) through [step 11](#) for each 2198-xxxx-ERSx servo drive.

Configure the Motion Group

Follow these steps to configure the motion group.

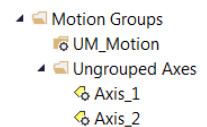
1. In the Controller Organizer, right-click Motion Groups and choose New Motion Group.

The New Tag dialog box appears.



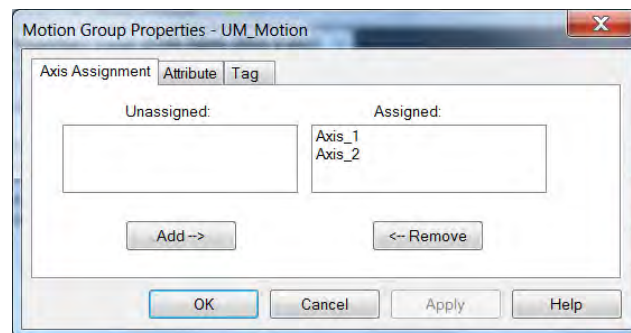
2. Type the new motion group Name.
3. Click Create.

Your new motion group appears in the Controller Organizer under the Motion Groups folder.



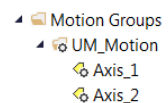
4. Right-click the new motion group and choose Properties.

The Motion Group Properties dialog box appears.



5. Click the Axis Assignment tab and move your axes (created earlier) from Unassigned to Assigned.
6. Click the Attribute tab and edit the default values as appropriate for your application.
7. Click OK.

Your axes moves to the new motion group.

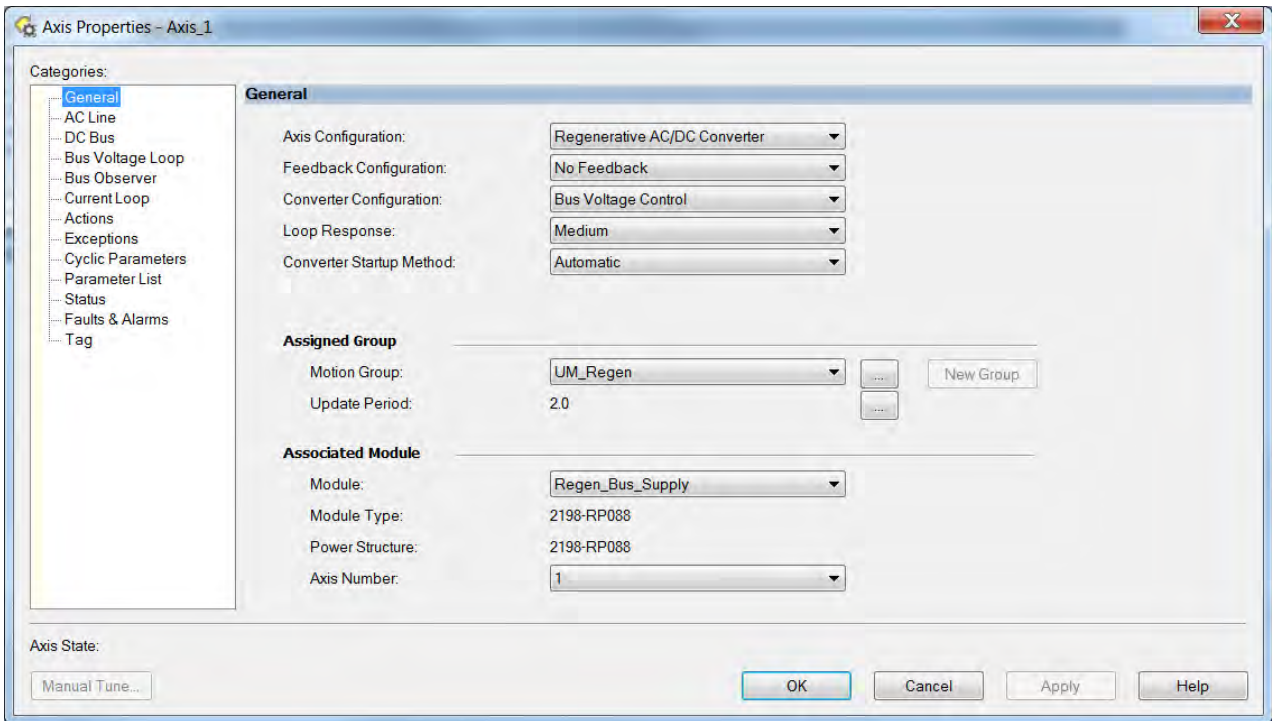


Configure Regenerative Bus Supply Axis Properties

Follow these steps to configure Axis Properties for your 2198-RPxxx regenerative bus supply.

1. In the Controller Organizer, right-click the regenerative-bus supply axis and choose Properties.
2. Select the General category.

The General dialog box appears.



3. From the Loop Response pull-down menu choose Medium (default).
Loop Response is for BusVoltageSetPoint dynamic changes during operation, not voltage regulation stiffness or stability. The default setting is appropriate for most applications.

Table 117 - Loop Response Settings

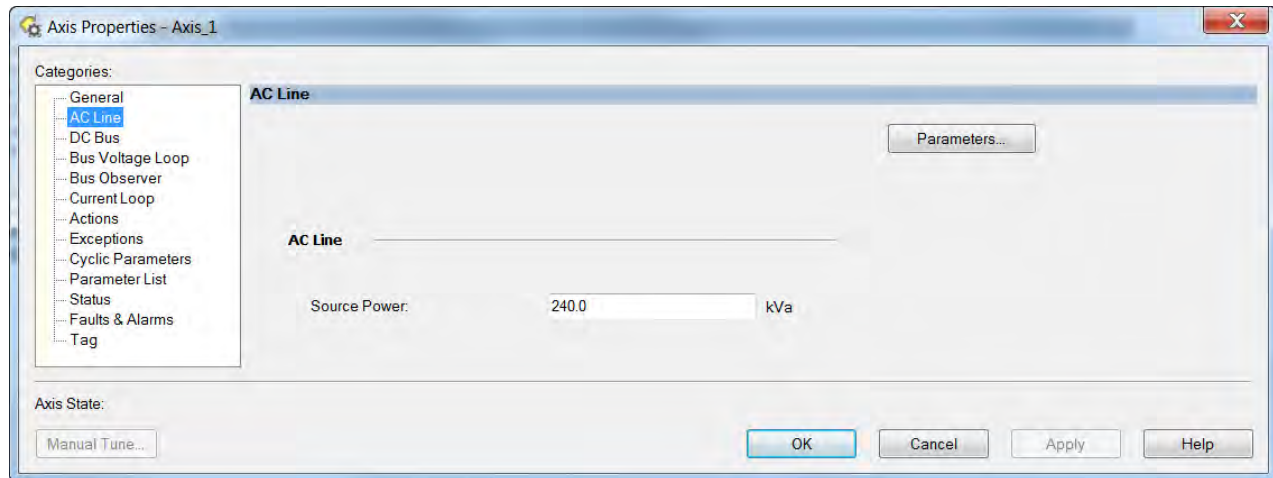
| Setting | Impact |
|---------|---|
| High | Under-damped voltage set-point step response ($Z = 0.8$) |
| Medium | Critically-damped voltage set-point step response ($Z = 1.0$) |
| Low | Over-damped voltage set-point step response ($Z = 1.5$) |

4. From the Converter Startup Method pull-down menu choose:
 - Automatic (default) for active DC-bus voltage regulation
 - Enable Request for passive AC rectification like the 2198-Pxxx DC-bus (converter) power supply

For more information on the Converter Startup Method, see [DC-bus Voltage Regulation](#) on [page 42](#).

5. Click Apply.

6. Click the AC Line category.

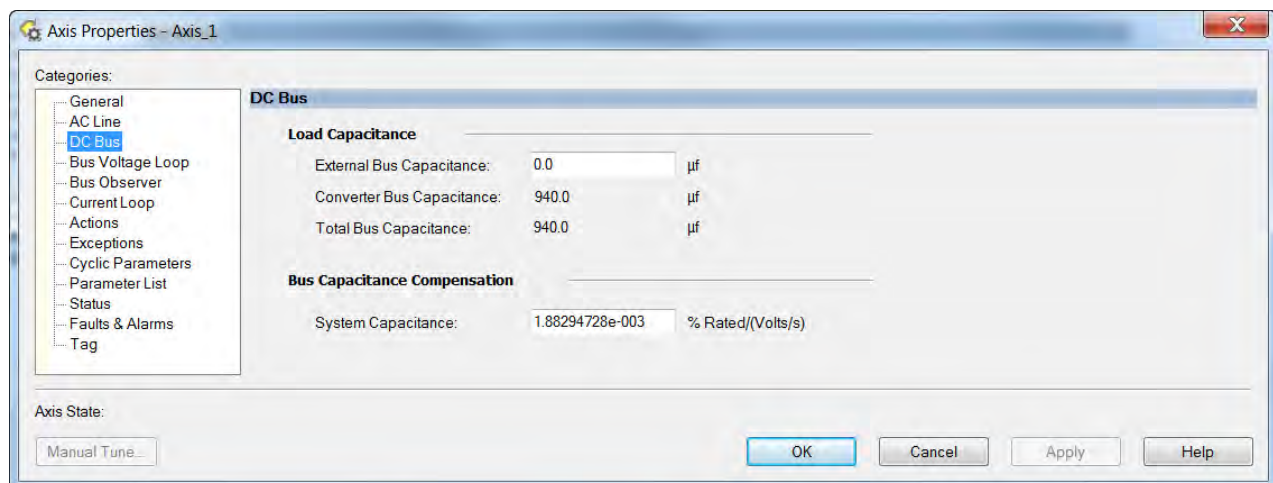


Source Power is the kVA rating of the transformer feeding the regenerative power supply. The default Source Power setting is 10 times the power rating of the regenerative power supply.

When the transformer rating is less than the regenerative power supply rating, enter the kVA rating of the transformer.

The Source Power attribute applies detuning and current limiting only when Source Power is set lower than the rating of the regenerative power supply (1/10 of default).

7. Click the DC Bus category.



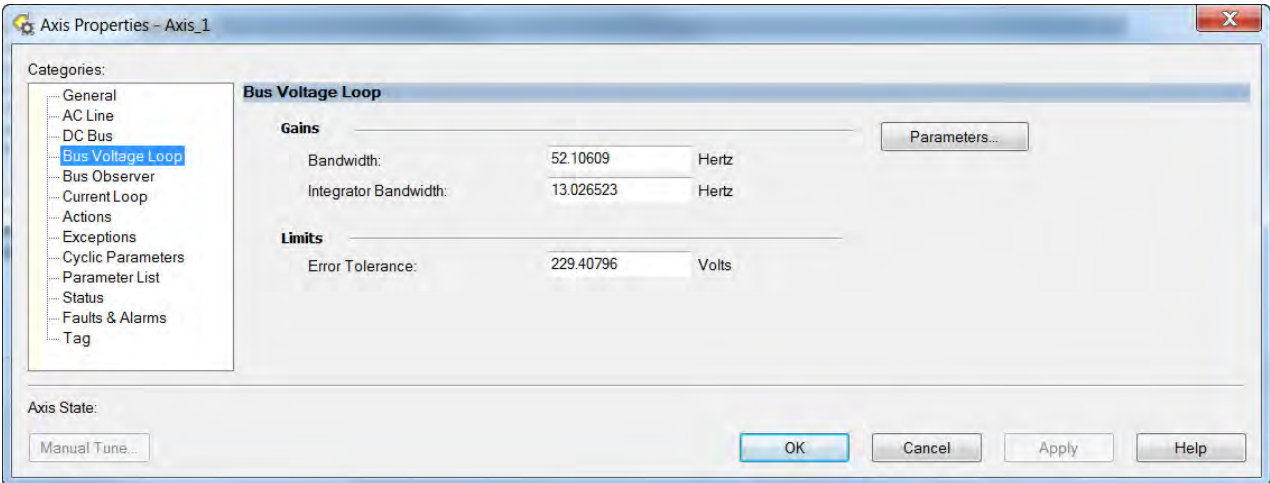
External bus capacitance is the sum of all drive and accessory module capacitance.

IMPORTANT An accurate bus capacitance value is required for proper operation.

8. Manually calculate the sum of the drive and accessory module capacitance values and enter the External Bus Capacitance value.

See [Calculate System and External-bus Capacitance](#) on [page 394](#) to calculate external bus capacitance.

9. Click the Bus Voltage Loop category.

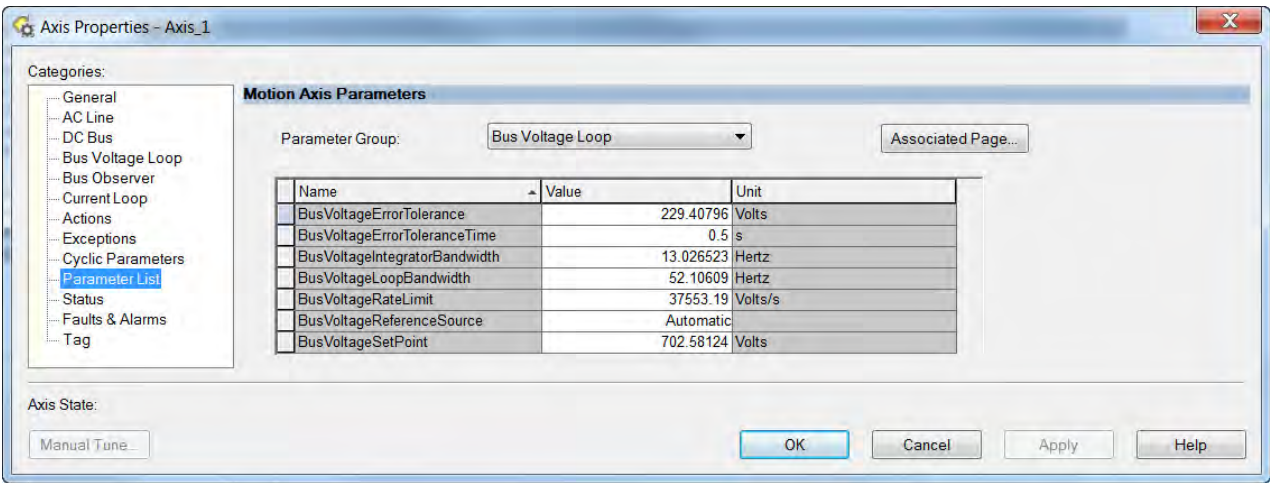


We do not recommend changing the default bandwidth values.

The default Gains are set to support peak load current. See [Detuned Gain Setting Examples](#) table on [page 228](#) for an example of a detuned gain set. Detuned gains increase system stability and can improve THD, but voltage regulation will be less stiff.

IMPORTANT Reduced voltage regulation stiffness can result in overvoltage or undervoltage faults during peak load.

10. Click Parameters.



With the default BusVoltageRateLimit, if the BusVoltageSetPoint value changes (while running) the power supply will draw peak current to change the bus voltage as fast as possible. You can reduce the rate limit to limit the current during changes to the BusVoltageSetPoint attribute without any effect to stability or load response.

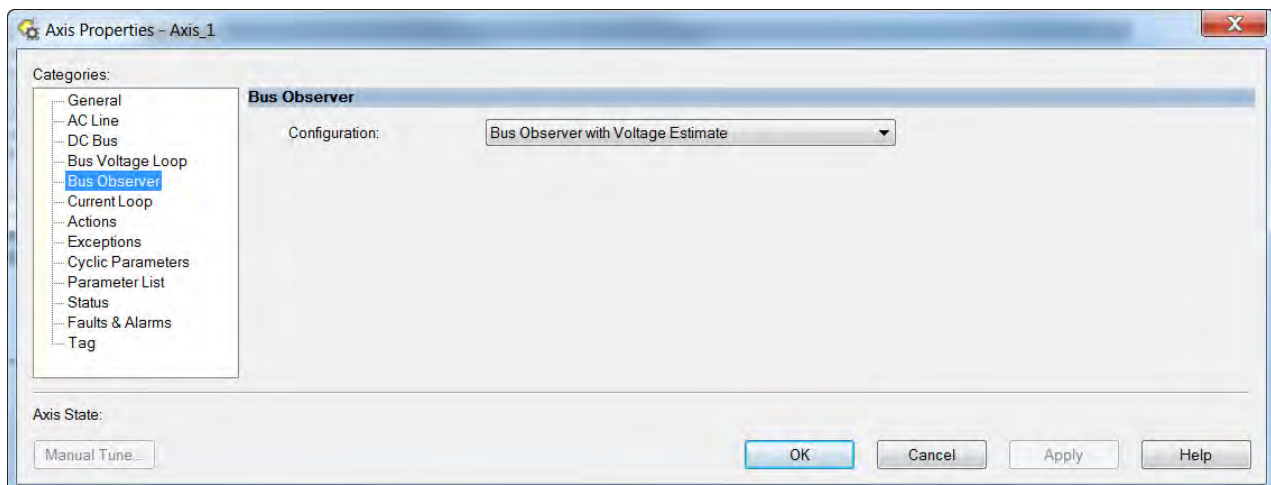
11. From the BusVoltageReferenceSource pull-down menu, choose:
 - In the Automatic (default) setting, the converter optimizes the Bus Voltage Reference for the best converter performance
 - In the Manual setting, you configure the desired Bus Voltage Set Point value for the Bus Voltage Reference signal

For more information on these Bus Voltage parameter settings, see [DC-bus Voltage Regulation](#) on [page 42](#).

12. Enter a value for the BusVoltageSetPoint.

We recommend a maximum value of 715V DC. Over 715V DC can result in higher motor-insulation stress, higher THD, and higher likelihood of over temperature fault in the regenerative bus supply.

13. Click Apply.
14. Click the Bus Observer category.



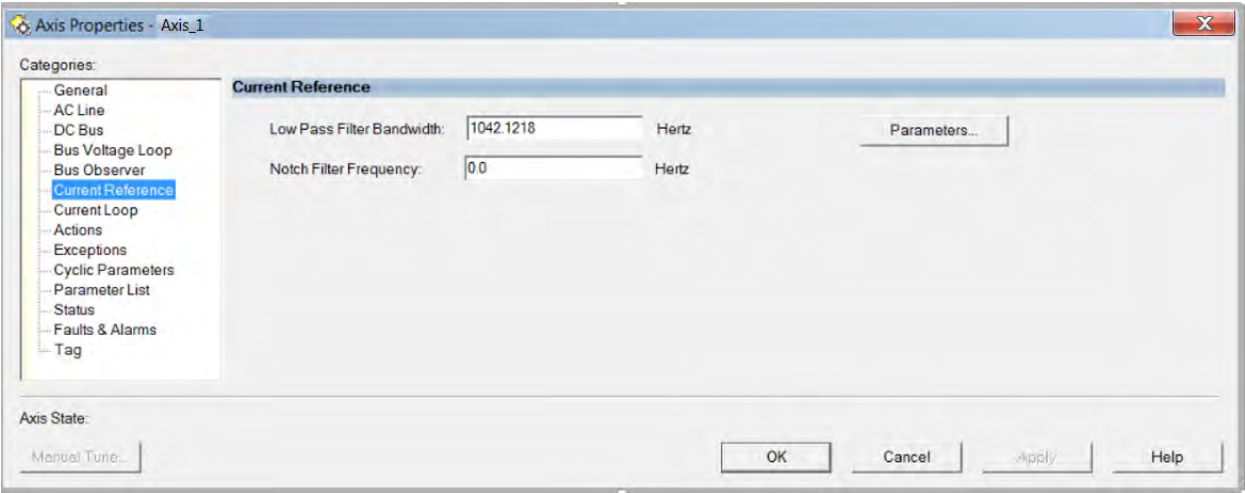
The Bus Observer setting is used for bus stiffness. If Bus Observer is disabled, you significantly increase the likelihood of getting an overvoltage fault during regeneration.

We do not recommend changing the default Bus Observer setting.

Table 118 - Bus Observer Configurations

| Configuration | Observer Operation | Impact |
|--|--|--|
| Disabled | <ul style="list-style-type: none"> Load Estimate Decoupling Disabled Voltage Feedback Filtering Disabled | <ul style="list-style-type: none"> Increased DC-bus voltage ripple Reduced current THD Reduced voltage regulation stiffness |
| Voltage Estimate Only | <ul style="list-style-type: none"> Load Estimate Decoupling Disabled Voltage Feedback Filtering Enabled | <ul style="list-style-type: none"> Reduced voltage regulation stiffness |
| Bus Observer Only | <ul style="list-style-type: none"> Load Estimate Decoupling Enabled Voltage Feedback Filtering Disabled | <ul style="list-style-type: none"> Decreased DC-bus voltage ripple Increased current THD Increased voltage regulation stiffness |
| Bus Observer with Voltage Estimate (Default) | <ul style="list-style-type: none"> Load Estimate Decoupling Enabled Voltage Feedback Filtering Enabled | <ul style="list-style-type: none"> Increased voltage regulation stiffness |

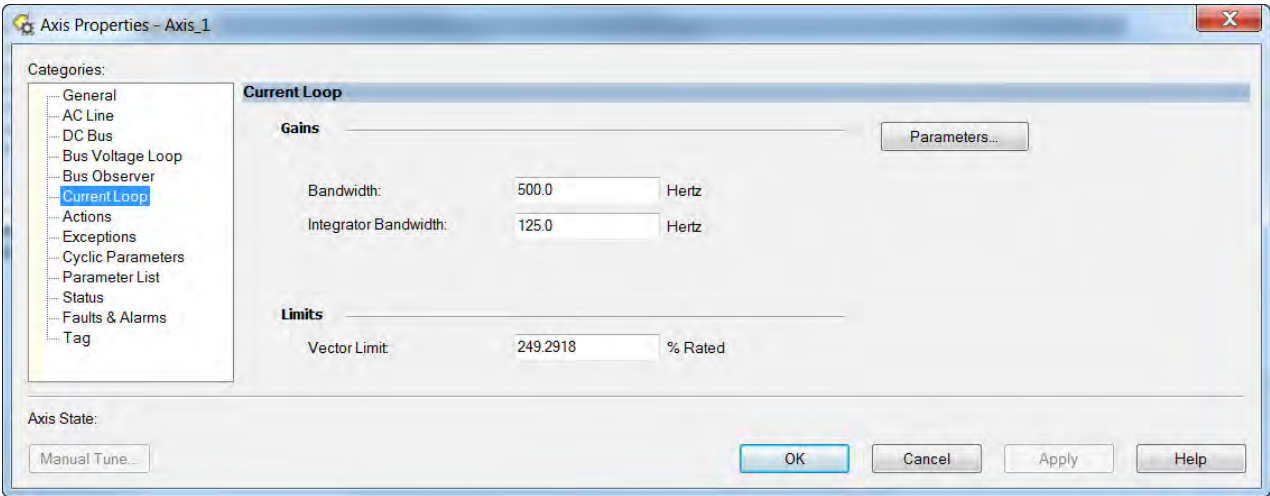
15. Click the Current Reference category.



Low Pass Filter Bandwidth adjusts the filtering of the reference to the current regulator. To minimize the effect on bus voltage regulator stability, this value should be no lower than five times the Bus Voltage Loop bandwidth.

Notch Filter Frequency can be used to address DC-bus resonances in the case of some long cable distributed DC-bus systems. Notch Filter Frequency cannot be used to address line side resonances. A value of 0.0 Hz disables the notch filter.

16. Click the Current Loop category.



We do not recommend changing the default bandwidth values.

Table 119 - Detuned Gain Setting Examples

| Gain Setting With Reduced Performance | Value |
|---------------------------------------|-------|
| Bus Voltage Loop Bandwidth | 16 |
| Bus Voltage Loop Integrator Bandwidth | 4 |
| Current Loop Bandwidth | 160 |
| Current Loop Integrator Bandwidth | 40 |

Detuning to a desired level, while maintaining stability, can be achieved by setting a current loop bandwidth and maintaining proportional spacing of 10x between the voltage and current loop, and 4x spacing from the loop bandwidth to integral loop bandwidth.

17. Click OK.

Configure Vertical Load Control Axis Properties

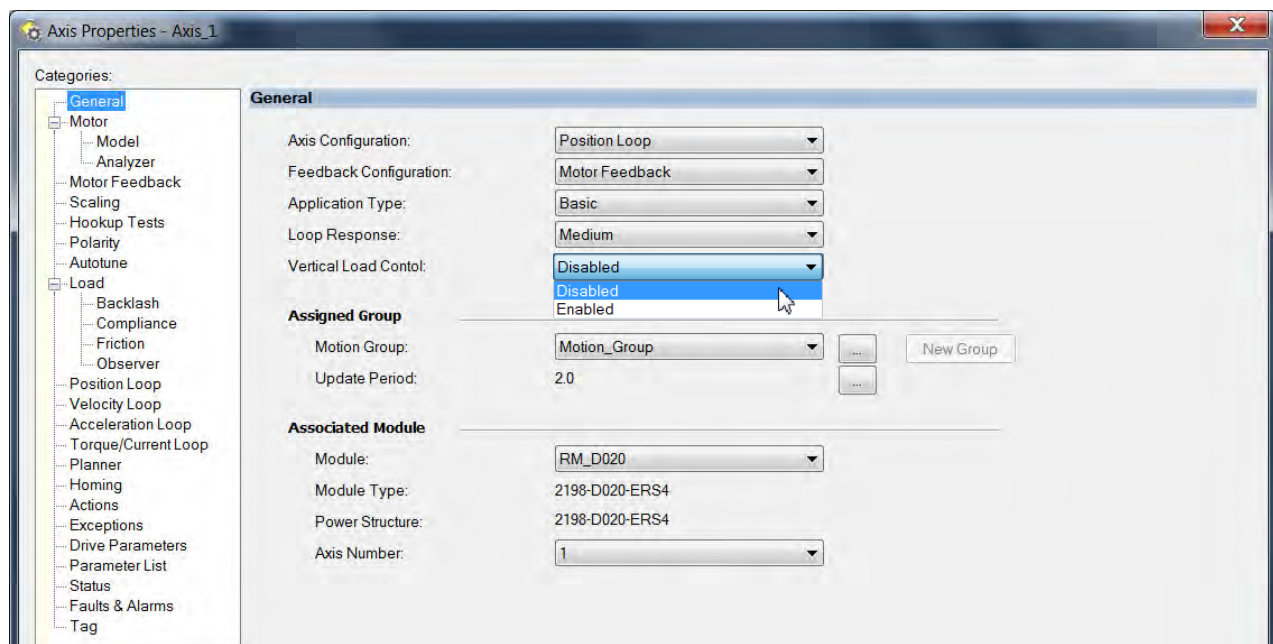
The 2198-xxxx-ERS4 servo drives (firmware 9.001 or later) support the Vertical Load Control feature. A vertical load is an axis that can move due to stored potential energy. Some examples include a robot arm, lift, or compressed spring. When set to Enabled, rather than applying Stop Category 0 stopping actions in response to most Major fault conditions, the drive brings the motor to a controlled stop and engages the holding brake prior to disabling the power structure.

When Vertical Load Control is enabled and the drive supports Torque Proving and Brake Proving functionality, the controller sets the associated Proving Configuration attribute default value to enable.

IMPORTANT Brake proving functionality is applicable only to drive control modes that are capable of generating holding torque based on a feedback device. Therefore, Brake Proving is not applicable to Frequency Control mode with Sensorless Vector control method.

For more information on controlling vertical loads, see the Vertical Load and Holding Brake Management Application Technique, publication [MOTION-AT003](#).

Figure 129 - Configure Vertical Load Control

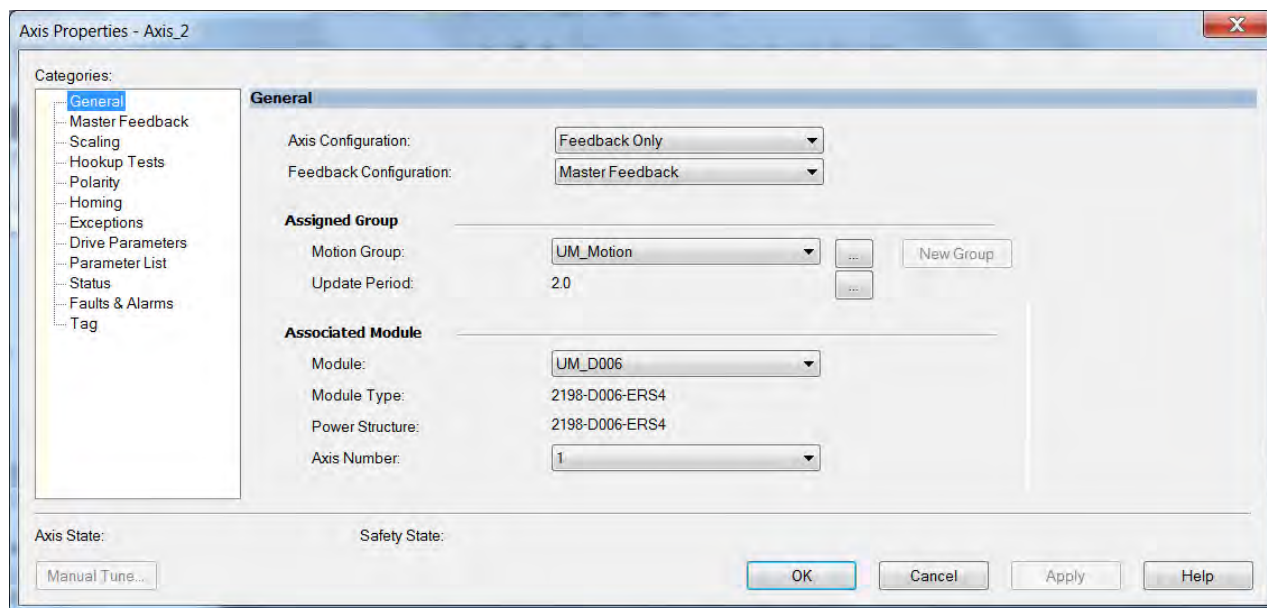


Configure Feedback-only Axis Properties

Follow these steps to configure stopping-action axis properties.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the General category.

The General dialog box appears.



3. From the Axis Configuration pull-down menu, choose Feedback Only.
4. From the Feedback Configuration pull-down menu, choose Master Feedback.
5. From the Module pull-down menu, choose the drive to associate with your Feedback Only axis.

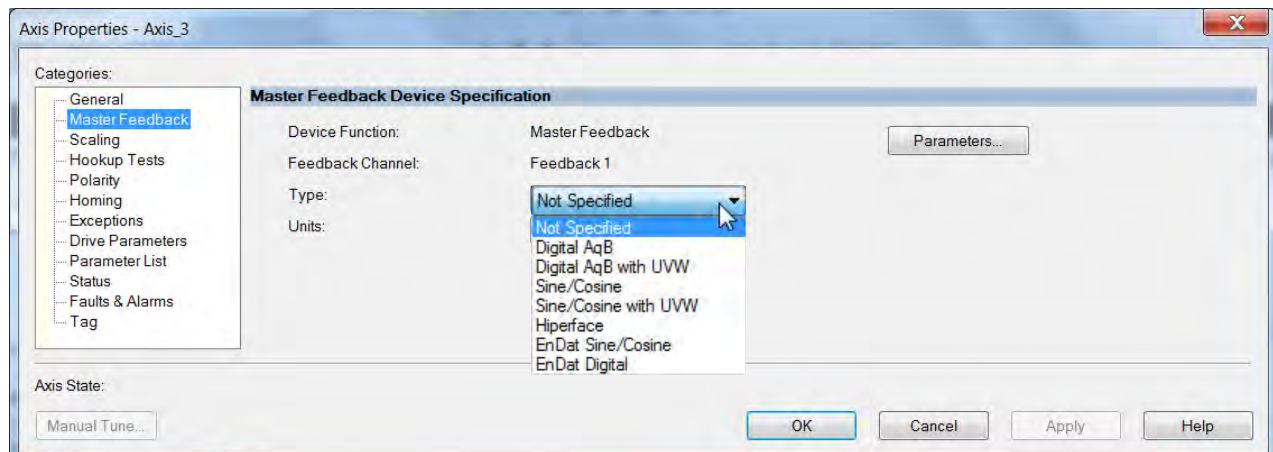
The Module Type and Power Structure fields populate with the chosen drive catalog number.

6. Click Apply.
7. Configure module properties for your Kinetix 5700 servo drive for Master Feedback.

See Configure Module Properties on [page 257](#) for configuration examples.

8. Select the Master Feedback Category.

The Master Feedback Device Specification appears.



9. From the Type pull-down menu, choose a feedback device type.

See Configure Axis Properties beginning on [page 259](#) for configuration examples.

10. Review other categories in the Controller Organizer and make changes as needed for your application.
11. Click OK.

See [Auxiliary Feedback Specifications](#) on [page 122](#) for more information on auxiliary feedback signals and Allen-Bradley auxiliary feedback encoders available for use.

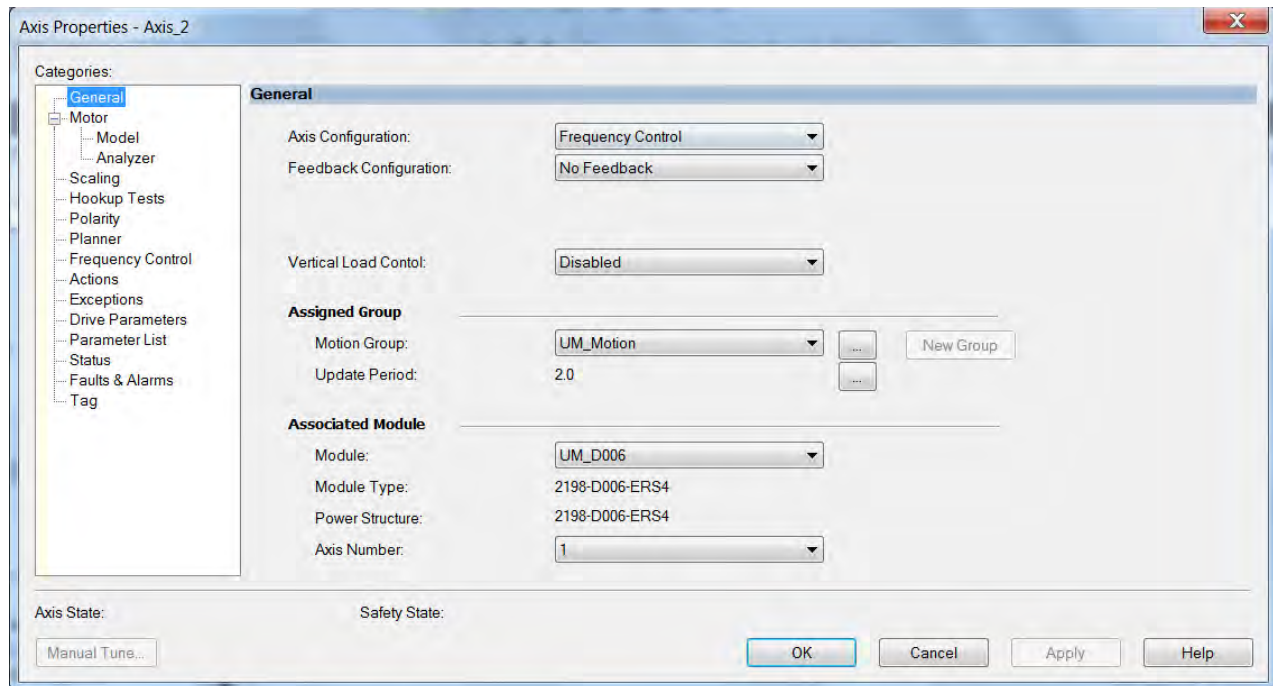
Configure Induction-motor Frequency-control Axis Properties

Follow these steps to configure induction-motor axis properties for various frequency control methods.

General and Motor Categories

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the General category.

The General dialog box appears.



3. From the Axis Configuration pull-down menu, choose Frequency Control.
4. From the Feedback Configuration pull-down menu, choose No Feedback.
5. From the Module pull-down menu, choose the drive to associate with your Frequency Control (induction motor) axis.

The Module Type and Power Structure fields populate with the chosen drive catalog number.

6. Click Apply.

7. Select the Motor category.

Axis Properties - Axis_2

Categories:

- General
- Motor**
- Model
- Analyzer
- Scaling
- Hookup Tests
- Polarity
- Planner
- Frequency Control
- Actions
- Exceptions
- Drive Parameters
- Parameter List
- Status
- Faults & Alarms
- Tag

Motor Device Specification

Data Source: Nameplate Datasheet [Parameters...]

Catalog Number: <none> [Change Catalog...]

Motor Type: Rotary Induction

Units: Rev

Nameplate / Datasheet - Phase to Phase parameters

| | | | | |
|----------------|-----|-------------|-----------------------|----------------|
| Rated Power: | 0.0 | kW | Pole Count: | 4 |
| Rated Voltage: | 0.0 | Volts (RMS) | Rated Frequency: | 60.0 Hertz |
| Rated Speed: | 0.0 | RPM | Max Speed: | 0.0 RPM |
| Rated Current: | 0.0 | Amps (RMS) | Peak Current: | 0.0 Amps (RMS) |
| | | | Motor Overload Limit: | 100.0 % Rated |

Axis State: Safety State:

[Manual Tune...] [OK] [Cancel] [Apply] [Help]

8. From the Data Source pull-down menu, choose Nameplate Datasheet.

This is the default setting.

9. From the Motor Type pull-down menu, choose Rotary Induction.

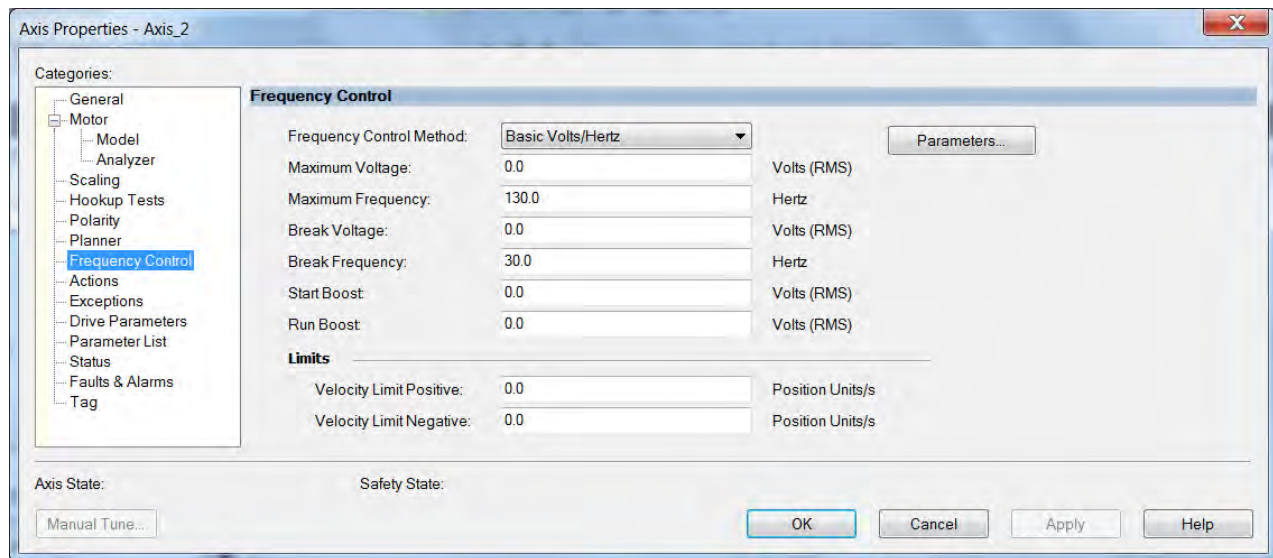
10. From the motor nameplate or datasheet, enter the phase-to-phase values for your motor.

See [Motor Category](#) on [page 426](#) for a motor performance datasheet example. Also, see Motor Nameplate Datasheet Entry for Custom Motor Applications, publication [2198-AT002](#).

11. Click Apply.

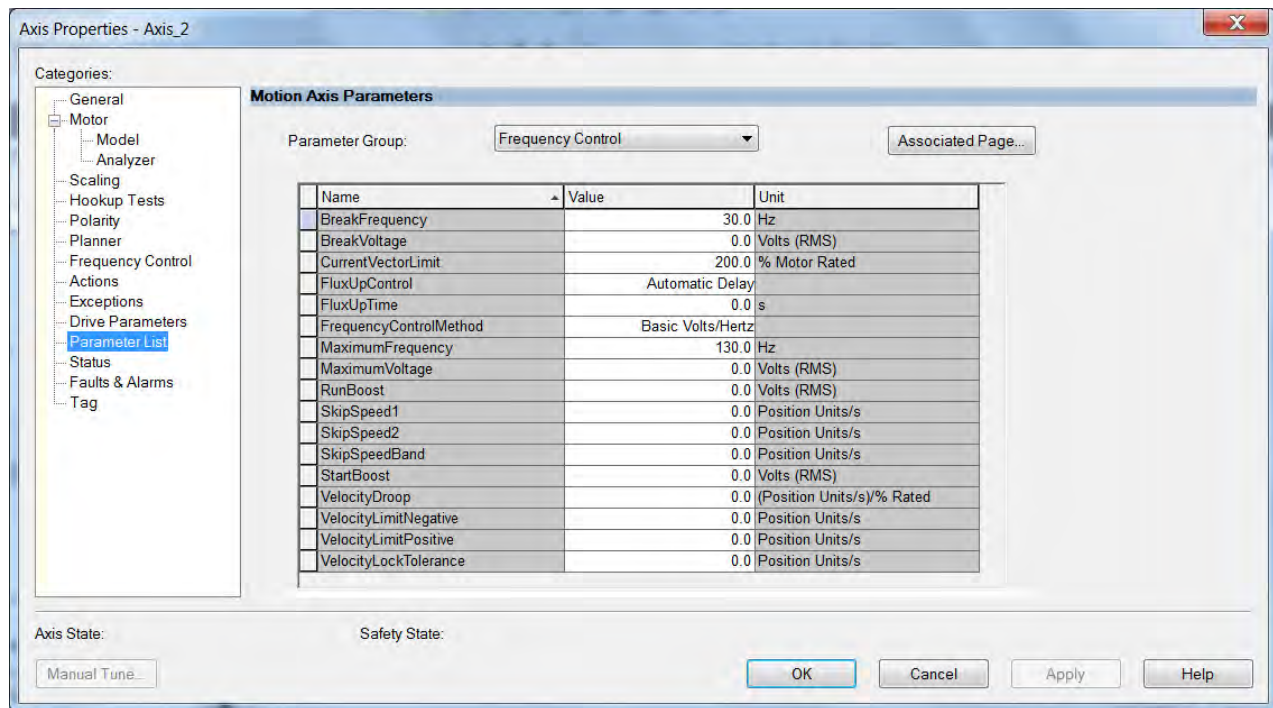
Basic Volts/Hertz Method

1. Configure the General category and Motor category as shown in [General and Motor Categories](#) on [page 232](#).
2. Select the Frequency Control category.
3. From the Frequency Control Method pull-down menu, select Basic Volts/Hertz.



4. Enter the Basic Volts/Hertz attribute values appropriate for your application.
Default values are shown.
5. Click Apply.
6. Select the Parameter List category.

The Motion Axis Parameters dialog box appears.



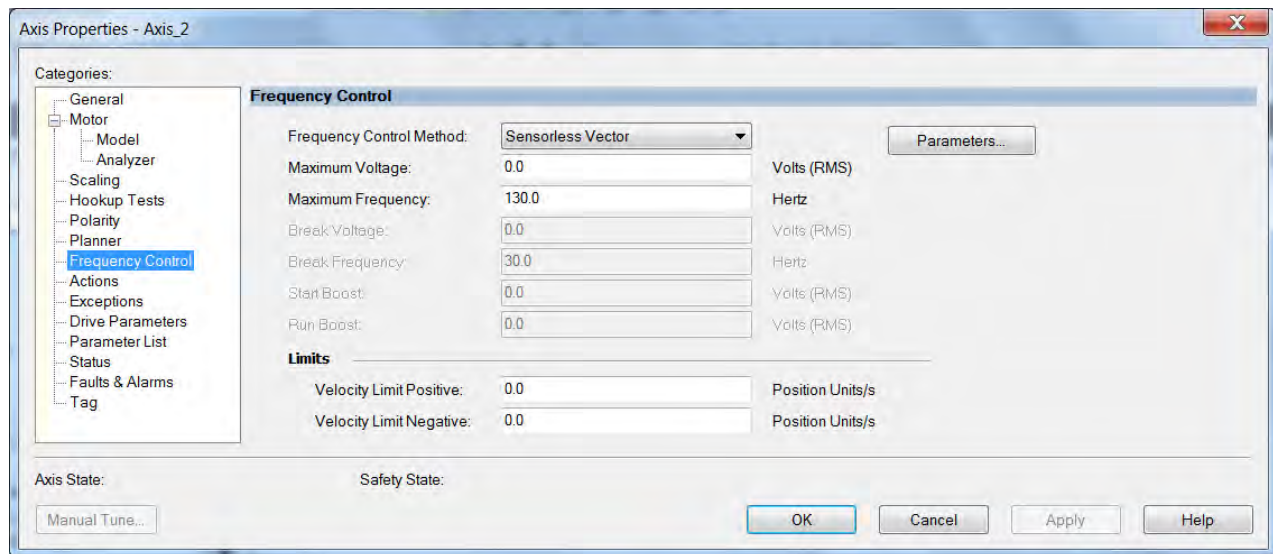
- From the Parameter Group pull-down menu, choose Frequency Control.
- Set the FluxUp, SkipSpeed, VelocityDroop, and CurrentVectorLimit attributes appropriate for your application.

See the corresponding section in Appendix F, beginning on [page 411](#), for information and configuration examples regarding all of these topics.

- Click OK.

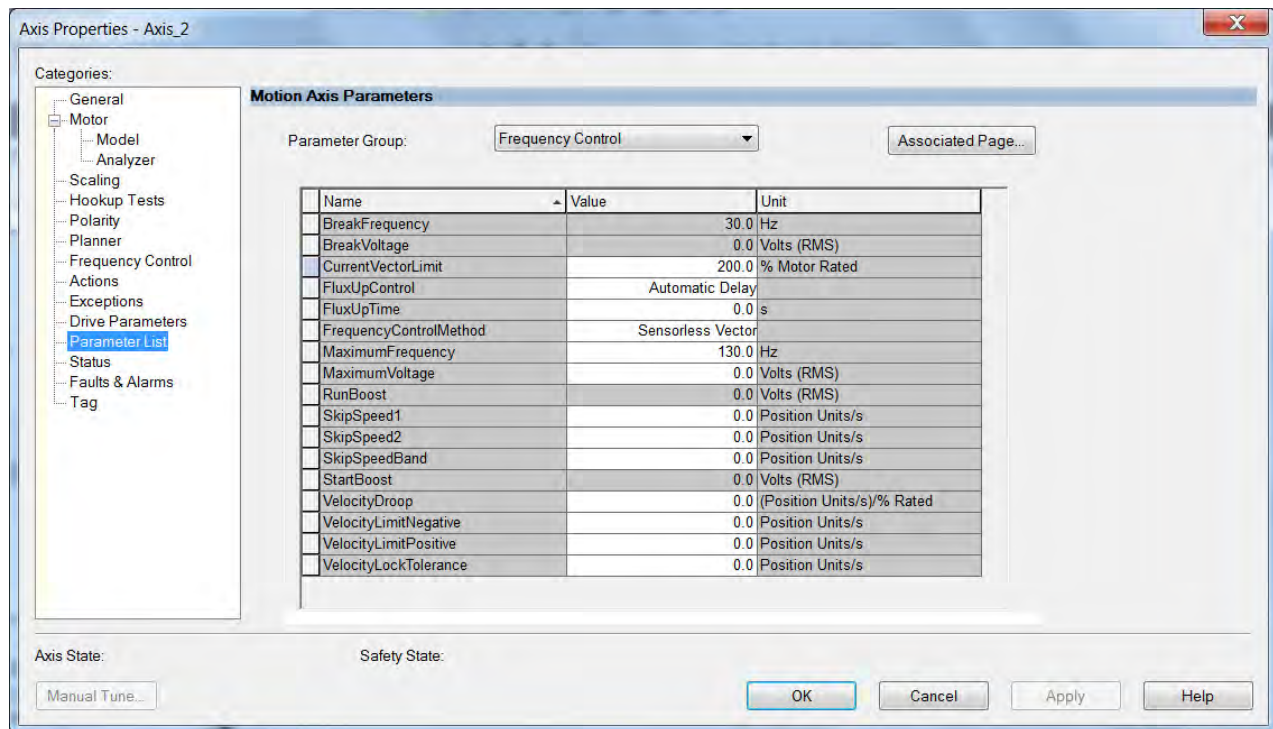
Sensorless Vector Method

1. Configure the General category and Motor category as shown in [General and Motor Categories](#) on [page 232](#).
2. Select the Frequency Control category.
3. From the Frequency Control Method pull-down menu, choose Sensorless Vector.



4. Enter the Basic Volts/Hertz attribute values appropriate for your application.
Default values are shown.
5. Click Apply.
6. Select the Parameter List category.

7. The Motion Axis Parameters dialog box appears.



8. From the Parameter Group pull-down menu, choose Frequency Control.

9. Set the FluxUp, SkipSpeed, VelocityDroop, MaximumFrequency, MaximumVoltage, and CurrentVectorLimit attributes appropriate for your application.

See the corresponding section in Appendix F, beginning on [page 411](#), for information and configuration examples regarding all of these topics.

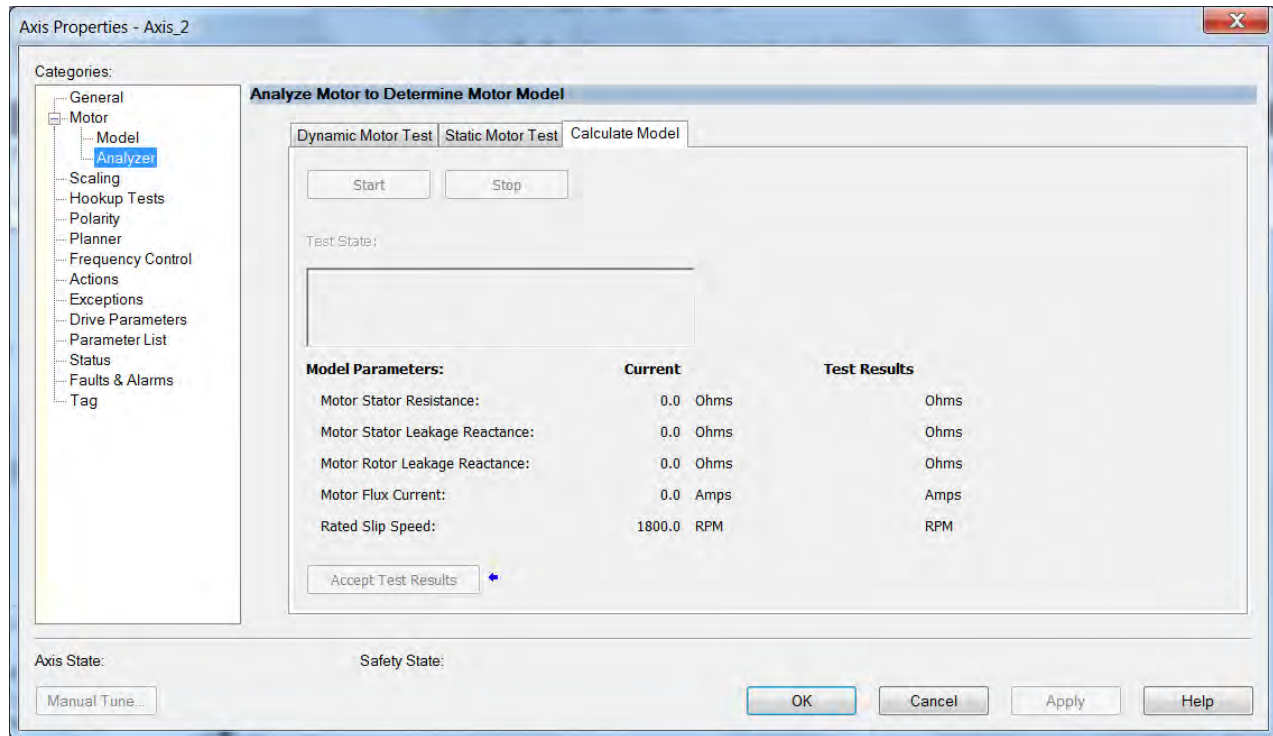
10. Click Apply.

11. Select the Motor>Model category.

Motor model attributes are automatically estimated from the Nameplate/Datasheet parameters. For improved performance, motor tests can be run.

12. Select the Motor>Analyzer category.

13. The Analyze Motor to Determine Motor Model dialog box opens.



14. Click one of the motor test tabs.

In this example, Calculate Model is chosen. See [Motor Tests and Autotune Procedure](#) on [page 428](#) for information about each of the tests.

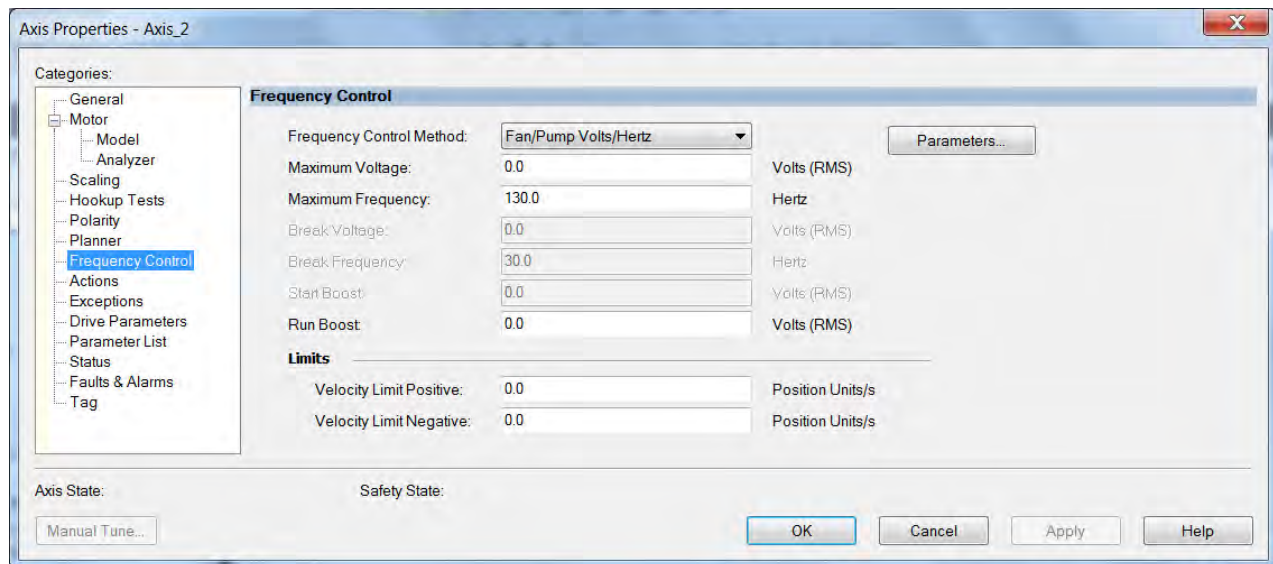
15. Click Start.

16. Click Accept Test Results.

17. Click OK.

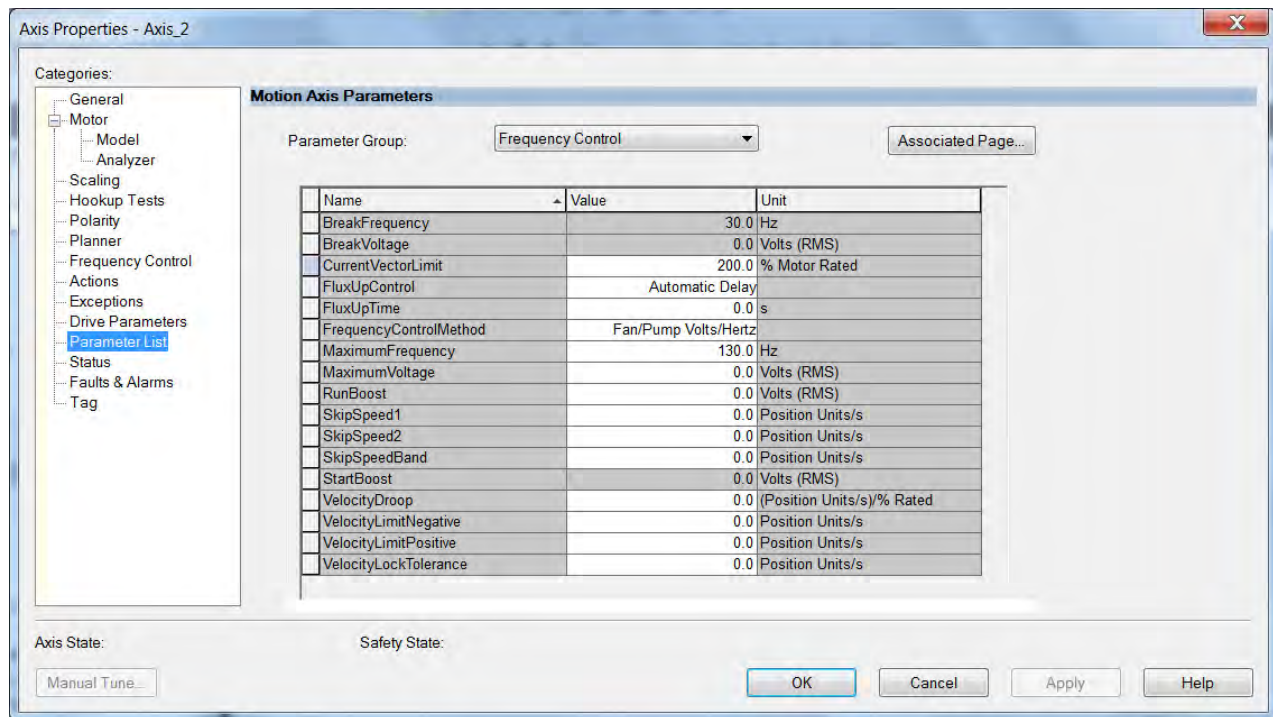
Fan/Pump Volts/Hertz Method

1. Configure the General category and Motor category as shown in [General and Motor Categories](#) on [page 232](#).
2. Select the Frequency Control category.
3. From the Frequency Control Method pull-down menu, select Fan/Pump Volts/Hertz.



4. Enter the Basic Volts/Hertz attribute values appropriate for your application.
Default values are shown.
5. Click Apply.
6. Select the Parameter List category.

The Motion Axis Parameters dialog box appears.



7. From the Parameter Group pull-down menu, choose Frequency Control.

8. Set the FluxUp, SkipSpeed, VelocityDroop, RunBoost, MaximumFrequency, MaximumVoltage and CurrentVectorLimit attributes appropriate for your application.

See the corresponding section in Appendix F, beginning on [page 411](#), for information and configuration examples regarding all of these topics.

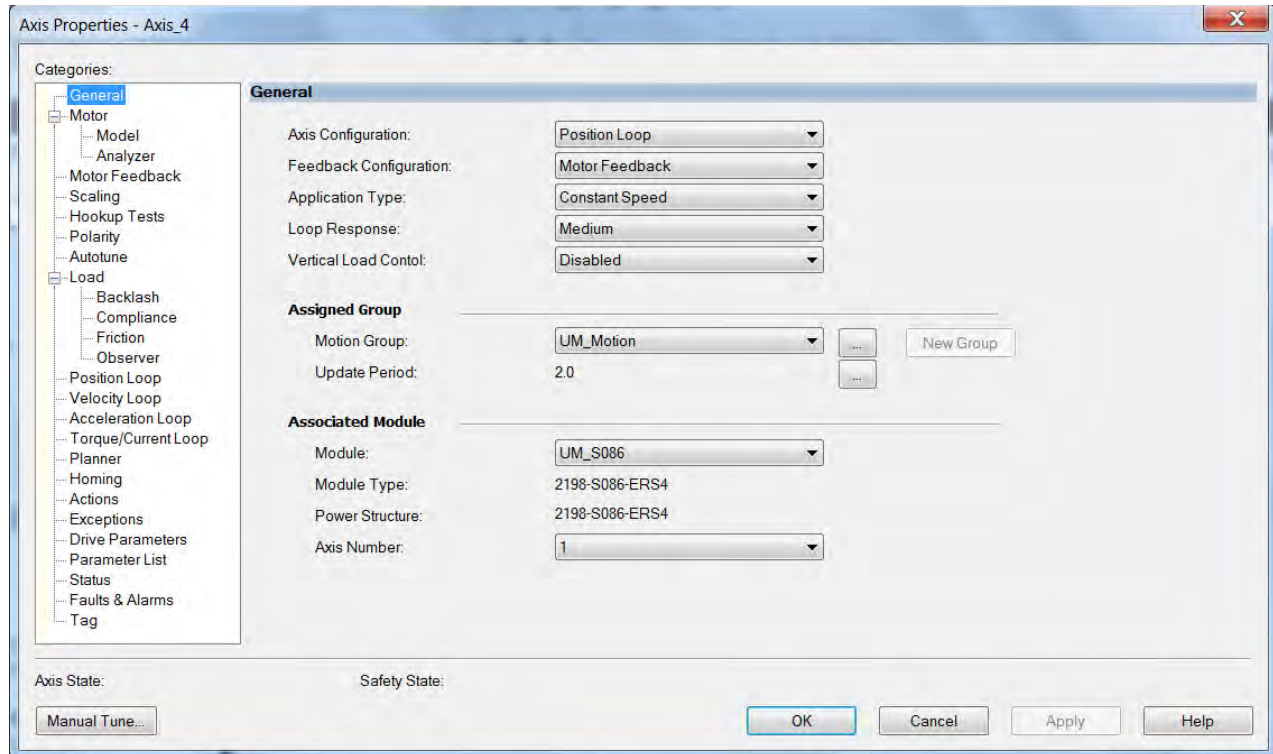
9. Click OK.

Configure IPM Motor Closed-loop Control Axis Properties

Follow these steps to configure interior permanent-magnet (IPM) motor closed-loop axis properties.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the General category.

The General and Associated Module dialog box appears.



3. From the General pull-down menus, change configuration settings as needed for your application.

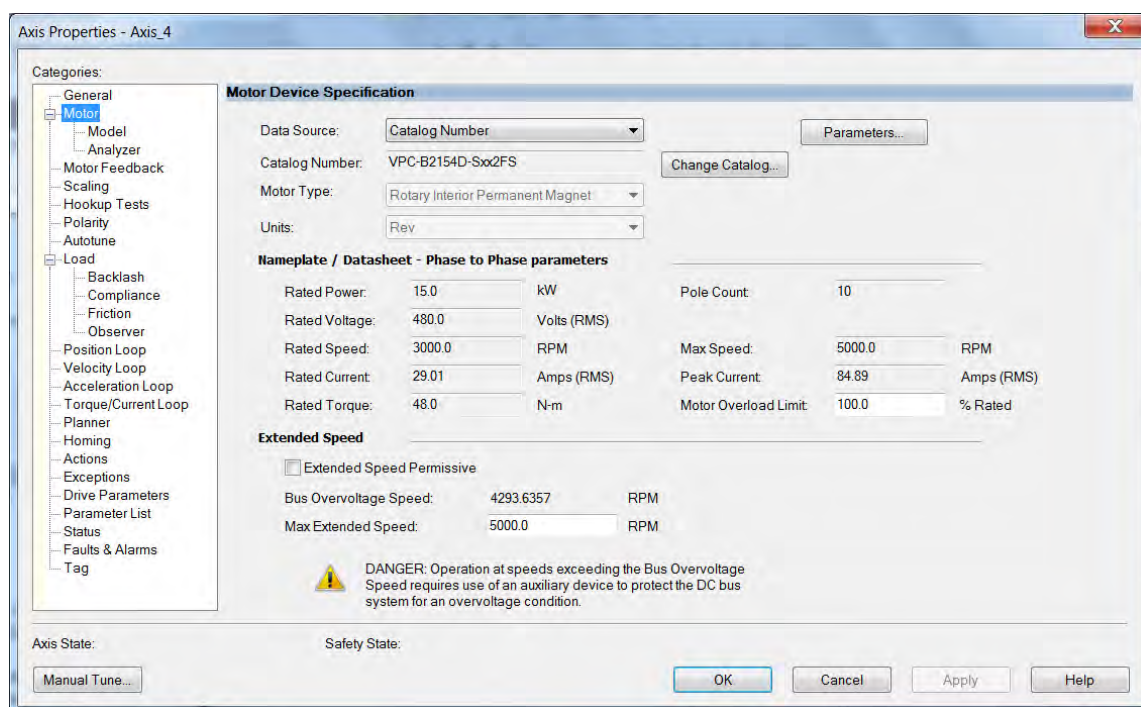
IMPORTANT Frequency Control is not supported for interior permanent magnet (IPM) motors.

4. From the Associated Module>Module pull-down menu, choose your Kinetix 5700 drive.

The drive catalog number populates the Module Type and Power Structure fields.

5. Click Apply.
6. Select the Motor category.

The Motor Device Specification dialog box appears.

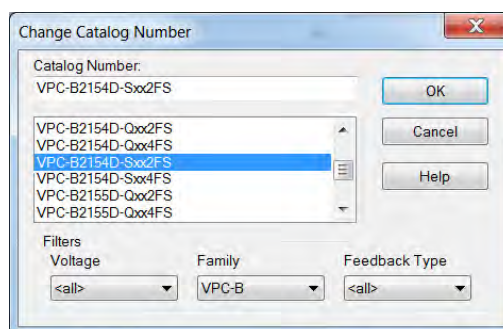


7. From the Data Source pull-down menu, choose Catalog Number.

IMPORTANT Motor NV is not a supported data source in the Logix Designer application for axes configured as interior permanent-magnet (IPM) motor closed-loop. In addition, third-party IPM motors are not supported.

8. Click Change Catalog.

The Change Catalog Number dialog box appears.



9. Select the motor catalog number appropriate for your application.
10. Click OK to close the Change Catalog Number dialog box.
11. Click Apply.

Motor data specific to your motor appears in the Nameplate / Datasheet - Phase to Phase parameters field.

12. For Extended Speed operation, check Extended Speed permissive in the Extended Speed field. See [Phase Loss Detection](#) on [page 446](#), for more information.
13. Select the Scaling category and edit the default values as appropriate for your application.

The screenshot shows the 'Axis Properties - Axis_4' dialog box with the 'Scaling' tab selected. The left sidebar lists categories: General, Motor, Model, Analyzer, Motor Feedback, Scaling (selected), Hookup Tests, Polarity, Autotune, Load, Backlash, Compliance, Friction, Observer, Position Loop, Velocity Loop, Acceleration Loop, Torque/Current Loop, Planner, Homing, Actions, Exceptions, Drive Parameters, Parameter List, Status, Faults & Alarms, and Tag.

Scaling to Convert Motion from Controller Units to User Defined Units

Load Type: Direct Coupled Rotary [Parameters...]

Transmission
Ratio I/O: 1 [] 1 [] Rev.

Actuator
Type: <none> []
Lead: 1.0 [] Millimeter/Rev []
Diameter: 1.0 [] Millimeter []

Scaling
Units: Position Units []
Scaling: 1.0 [] Position Units per 1.0 [] Motor Rev []

Travel
Mode: Unlimited []
Range: 1000.0 [] Position Units
Unwind: 1.0 [] Position Units per 1.0 [] Cycle
☐ Soft Travel Limits
Maximum Positive: 0.0 [] Position Units
Maximum Negative: 0.0 [] Position Units

Axis State: Safety State:

[Manual Tune...] [OK] [Cancel] [Apply] [Help]

14. Click Apply, if you make changes.
15. Select the Load category and edit the default values as appropriate for your application.

The screenshot shows the 'Axis Properties - Axis_4' dialog box with the 'Load' tab selected. The left sidebar lists categories: General, Motor, Model, Analyzer, Motor Feedback, Scaling, Hookup Tests, Polarity, Autotune, Load (selected), Backlash, Compliance, Friction, Observer, Position Loop, Velocity Loop, Acceleration Loop, Torque/Current Loop, Planner, Homing, Actions, Exceptions, Drive Parameters, Parameter List, Status, Faults & Alarms, and Tag.

Characteristics of Motor Load

Load Inertia/Mass
Load Coupling: Rigid []
☒ Use Load Ratio
Load Ratio: 0.0 [] Load Inertia/Motor Inertia
Motor Inertia: 0.0138 [] Kg-m²
Total Inertia: 0.0138 [] Kg-m²

Inertia/Mass Compensation
System Inertia: 0.15027143 [] % Rated/((Rev/s)²)
System Acceleration: 665.46246 [] Rev/s² @100 % Rated

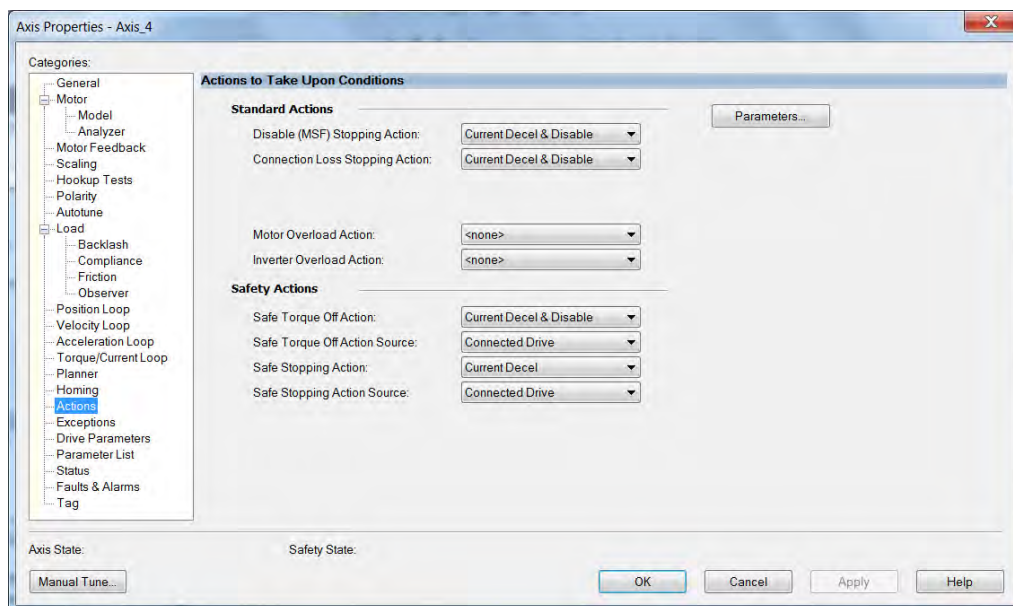
Active Load Compensation
Torque Offset: 0.0 [] % Rated

Axis State: Safety State:

[Manual Tune...] [OK] [Cancel] [Apply] [Help]

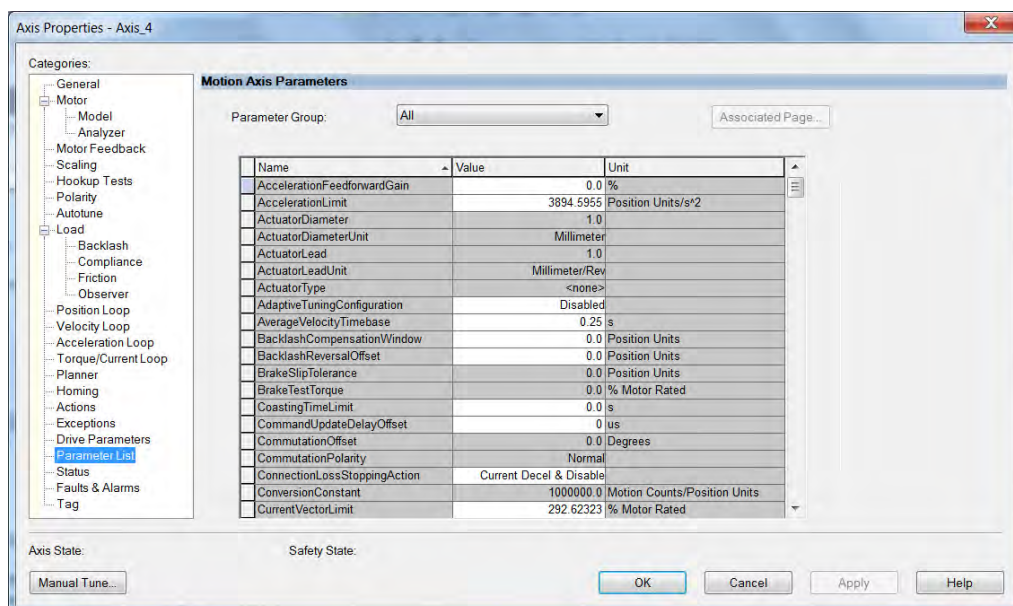
16. Click Apply, if you make changes.

17. Select the Actions category.



From this dialog box, you can program actions and change the action for exceptions (faults). Refer to [Logix 5000 Controller and Drive Module Behavior](#) on [page 283](#) for more information.

18. Select the Parameter List category.



From this dialog box you can set brake engage and release delay times for servo motors. For recommended motor brake delay times, refer to the Kinetix Rotary Motion Specifications Technical Data, publication [KNX-TD001](#).

19. Click OK.

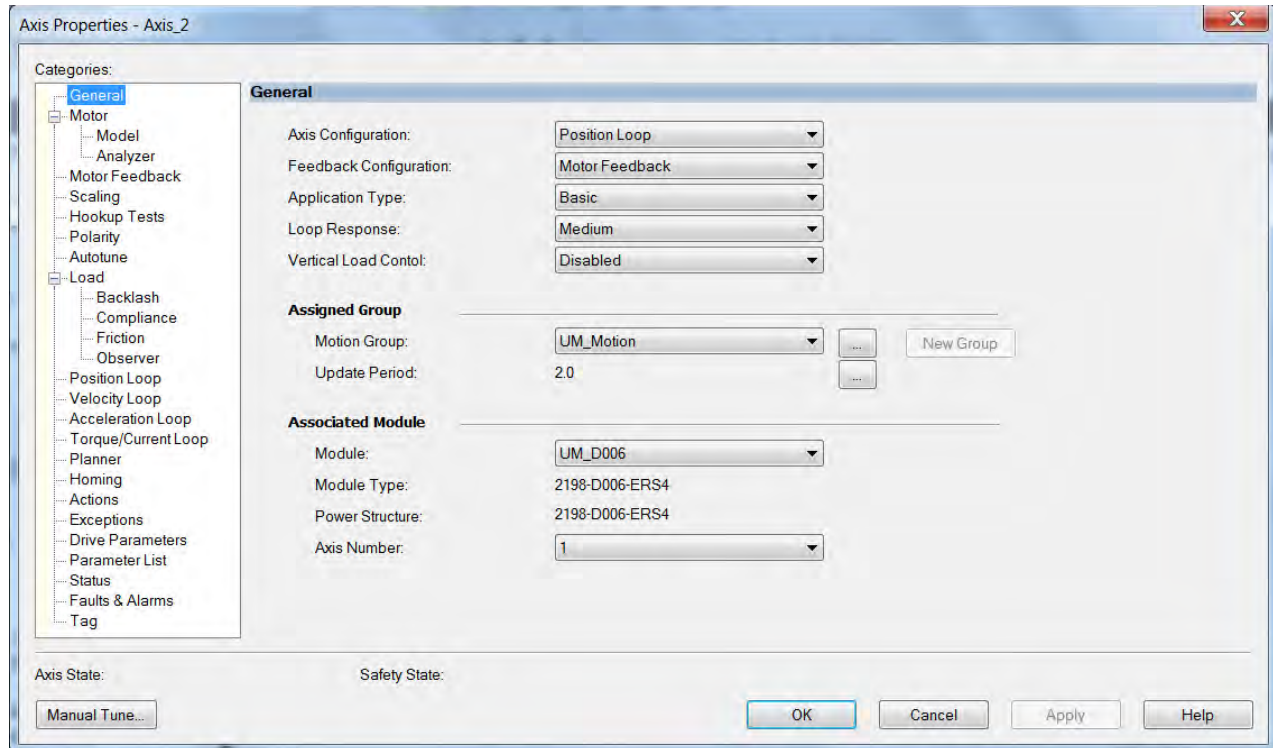
20. Repeat [step 1](#) through [step 19](#) for each servo motor axis.

Configure SPM Motor Closed-loop Control Axis Properties

Follow these steps to configure surface permanent-magnet (SPM) motor closed-loop axis properties.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the General category.

The General and Associated Module dialog box appears.



3. From the General pull-down menus, change configuration settings as needed for your application.

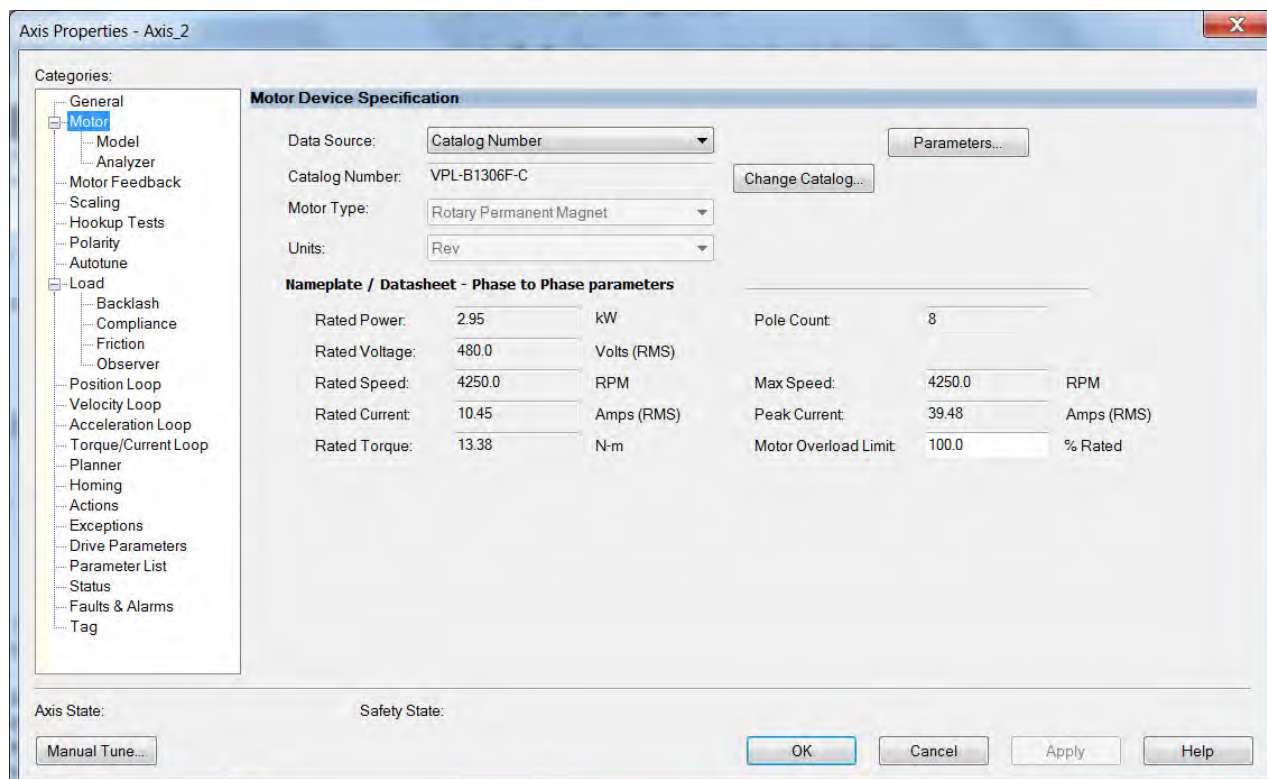
IMPORTANT Frequency Control is not supported for permanent magnet motors.

4. From the Associated Module>Module pull-down menu, choose your Kinetix 5700 drive.

The drive catalog number populates the Module Type and Power Structure fields.

5. Click Apply.
6. Select the Motor category.

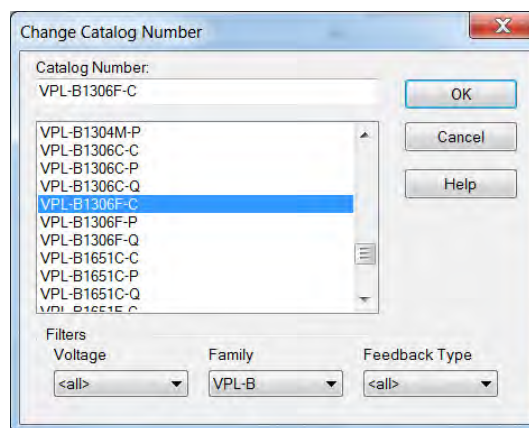
The Motor Device Specification dialog box appears.



7. From the Data Source pull-down menu, choose Catalog Number.

8. Click Change Catalog.

The Change Catalog Number dialog box appears.



9. Select the motor catalog number appropriate for your application.

To verify the motor catalog number, refer to the motor name plate.

10. Click OK to close the Change Catalog Number dialog box.

11. Click Apply.

Motor data specific to your motor appears in the Nameplate / Datasheet - Phase to Phase parameters field.

12. Select the Scaling category and edit the default values as appropriate for your application.

The screenshot shows the 'Axis Properties - Axis_4' dialog box with the 'Scaling' tab selected. The left-hand 'Categories' tree has 'Scaling' highlighted. The main panel is titled 'Scaling to Convert Motion from Controller Units to User Defined Units'. It contains several sections: 'Load Type' (Direct Coupled Rotary), 'Transmission' (Ratio J/O: 1/1 Rev), 'Actuator' (Type: <none>, Lead: 1.0 Millimeter/Rev, Diameter: 1.0 Millimeter), 'Scaling' (Units: Position Units, Scaling: 1.0 Position Units per 1.0 Motor Rev), and 'Travel' (Mode: Unlimited, Range: 1000.0 Position Units, Unwind: 1.0 Position Units per 1.0 Cycle). There are also 'Soft Travel Limits' for Maximum Positive and Negative (both 0.0 Position Units). At the bottom, there are 'Axis State' and 'Safety State' indicators, a 'Manual Tune...' button, and 'OK', 'Cancel', 'Apply', and 'Help' buttons.

13. Click Apply, if you make changes.

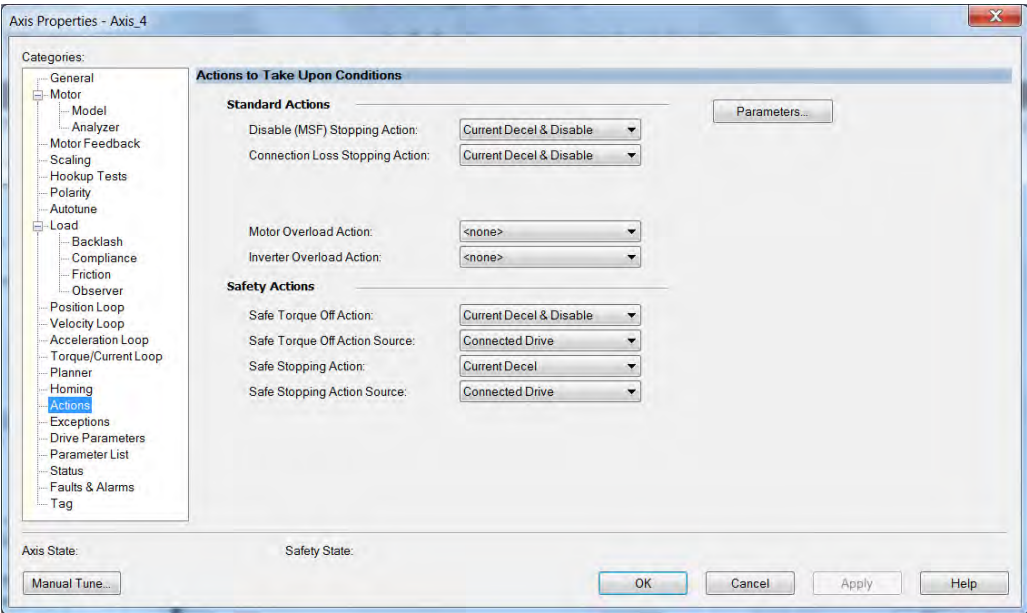
14. Select the Load category and edit the default values as appropriate for your application.

The screenshot shows the 'Axis Properties - Axis_4' dialog box with the 'Load' tab selected. The left-hand 'Categories' tree has 'Load' highlighted. The main panel is titled 'Characteristics of Motor Load'. It contains three sections: 'Load Inertia/Mass' (Load Coupling: Rigid, Use Load Ratio: checked, Load Ratio: 0.0, Motor Inertia: 0.0138 Kg-m^2, Total Inertia: 0.0138 Kg-m^2), 'Inertia/Mass Compensation' (System Inertia: 0.15027143 % Rated/(Rev/s^2), System Acceleration: 665.46246 Rev/s^2 @ 100 % Rated), and 'Active Load Compensation' (Torque Offset: 0.0 % Rated). At the bottom, there are 'Axis State' and 'Safety State' indicators, a 'Manual Tune...' button, and 'OK', 'Cancel', 'Apply', and 'Help' buttons.

15. Click Apply, if you make changes.

16. Select the Actions category.

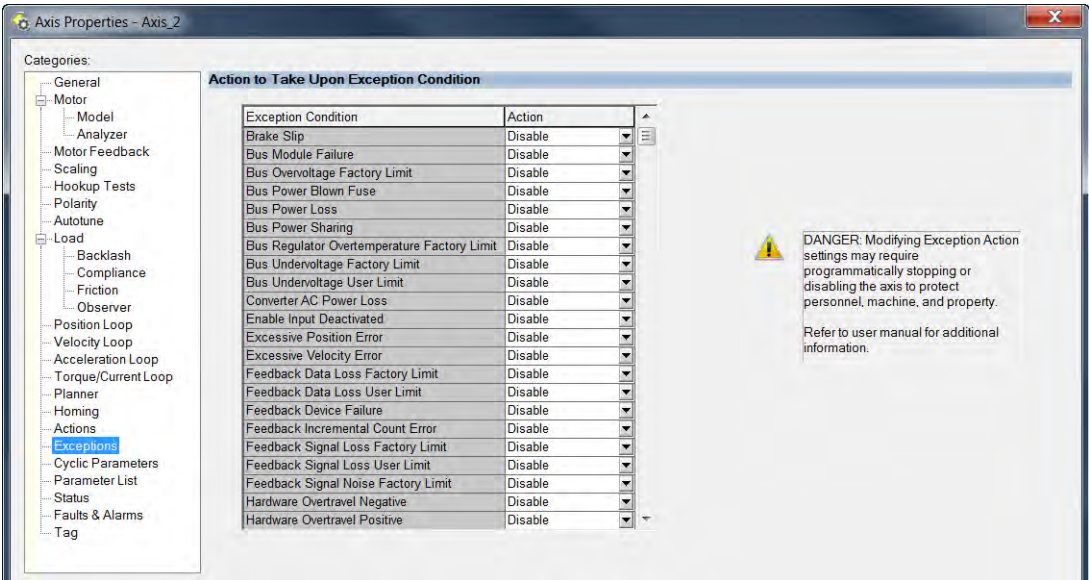
The Actions to Take Upon Conditions dialog box appears.



From this dialog box you can program actions for the drive module to take. Refer to [Logix 5000 Controller and Drive Module Behavior](#) on [page 283](#) for more information.

17. Select the Exceptions category.

The Action to Take Upon Exception Condition dialog box appears.

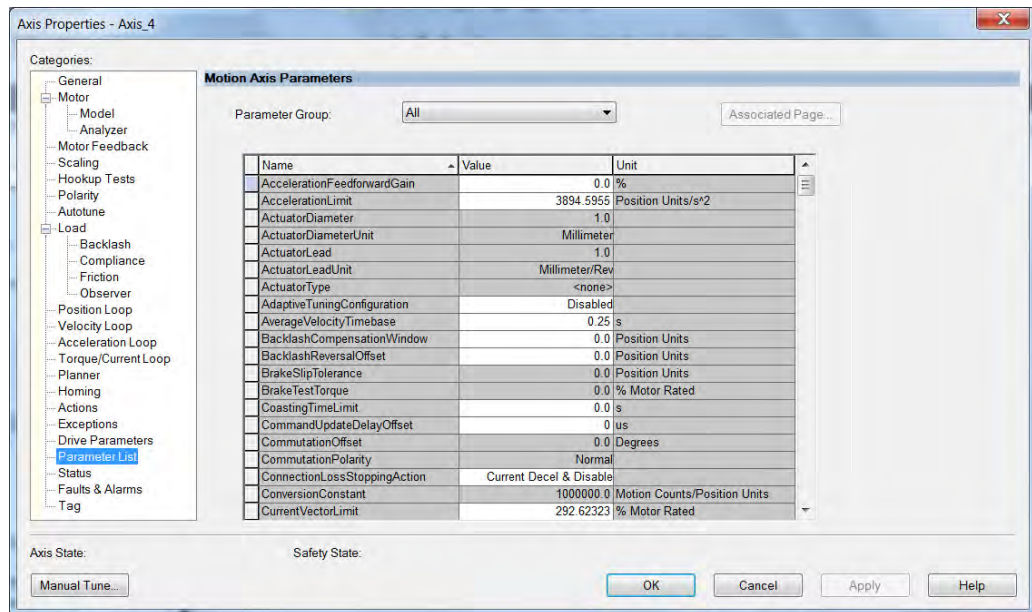


From this dialog box you can change the action for exceptions (faults). Refer to [Logix 5000 Controller and Drive Module Behavior](#) on [page 283](#) for more information.

TIP In the Logix Designer application, version 32 and later, Disable replaced StopDrive as the default Action.

18. Select the Parameter List category.

The Motion Axis Parameters dialog box appears.



From this dialog box you can set brake engage and release delay times for servo motors. For recommended motor brake delay times, refer to the Kinetix Rotary Motion Specifications Technical Data, publication [KNX-TD001](#).

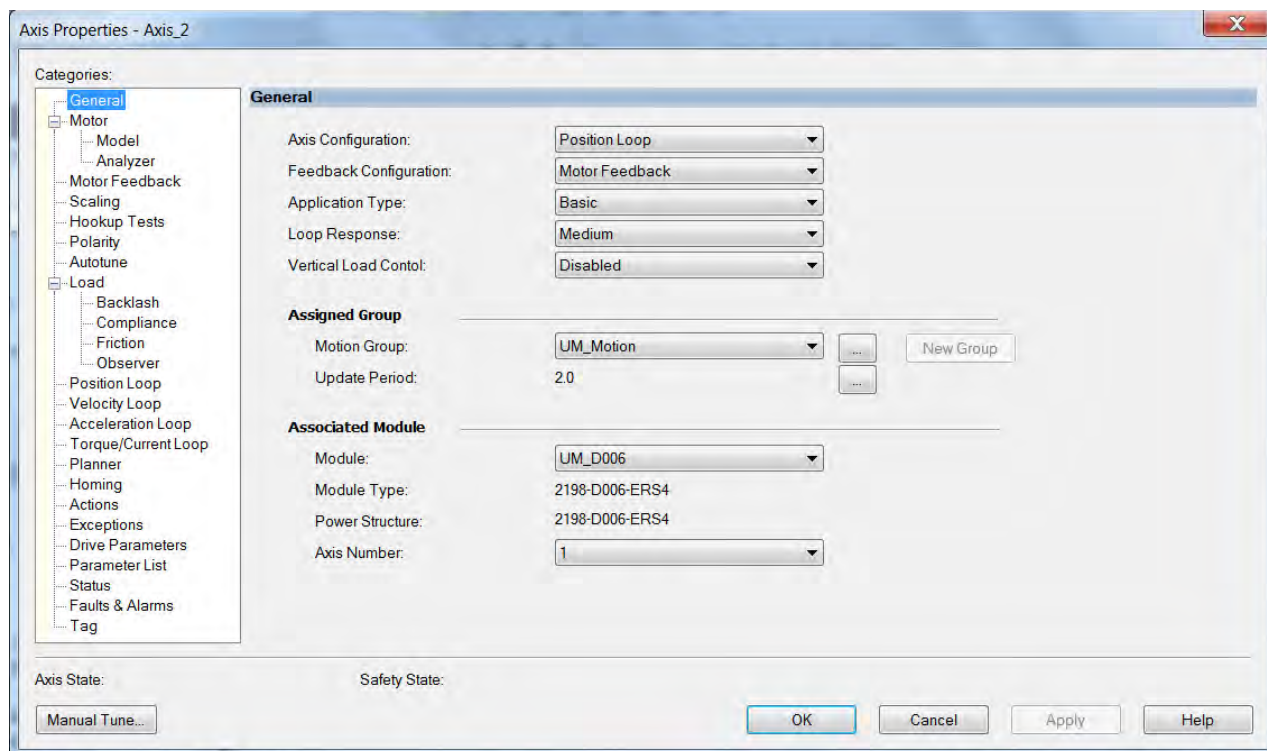
19. Click OK.**20.** Repeat [step 1](#) through [step 19](#) for each servo motor axis.

Configure Induction-motor Closed-loop Control Axis Properties

Follow these steps to configure induction-motor closed-loop control axis properties.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the General category.

The General and Associated Module dialog box appears.

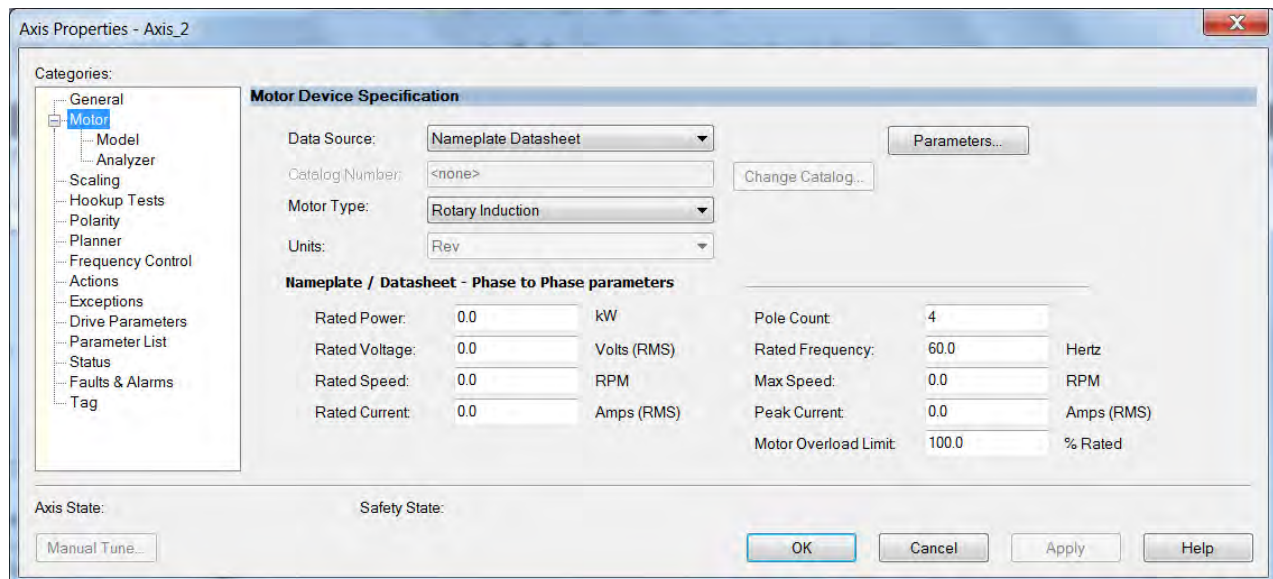


3. From the General pull-down menus, change configuration settings as needed for your application.
4. From the Associated Module>Module pull-down menu, choose your Kinetix 5700 drive.

The drive catalog number populates the Module Type and Power Structure fields.

5. Click Apply.
6. Select the Motor category.

The Motor Device Specification dialog box appears.



7. From the Data Source pull-down menu, choose Nameplate Datasheet.

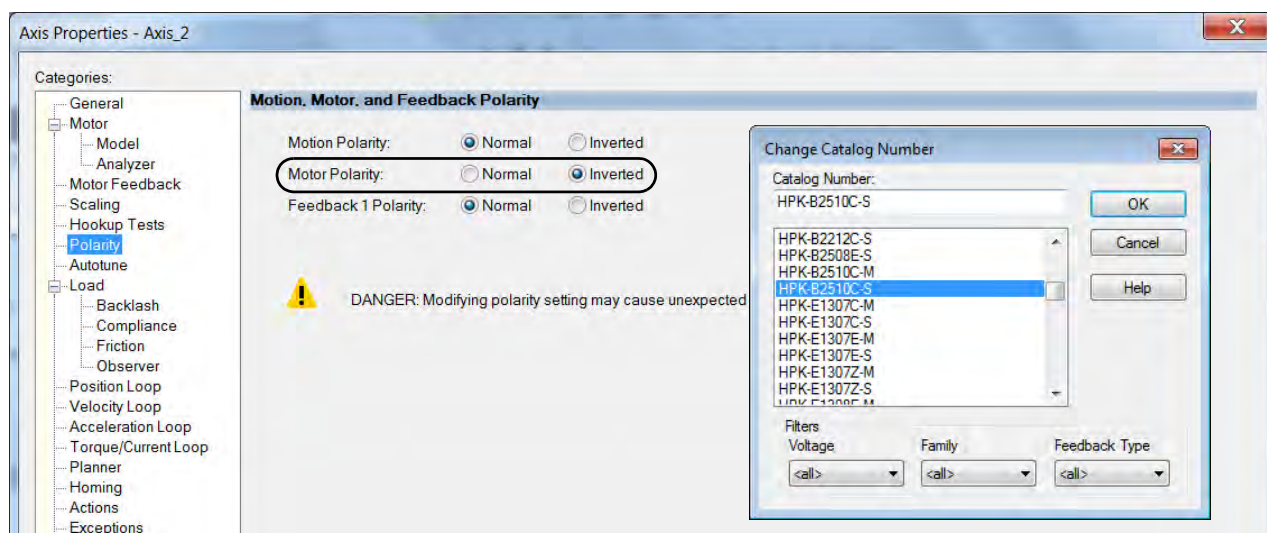
This is the default setting. If you have a Kinetix HPK asynchronous rotary motor, refer to [page 246](#) to see how to populate the Nameplate / Datasheet parameters by selecting the motor catalog number.

IMPORTANT When you configure Kinetix HPK motor parameters by selecting the motor catalog number, you must also configure the Polarity category. This requirement applies to only Kinetix HPK asynchronous motors. See Knowledgebase document [732760](#) for more information.

IMPORTANT Motor NV is not a supported data source in the Logix Designer application for axes configured as Induction-motor closed-loop.

- a. Select the Polarity category.

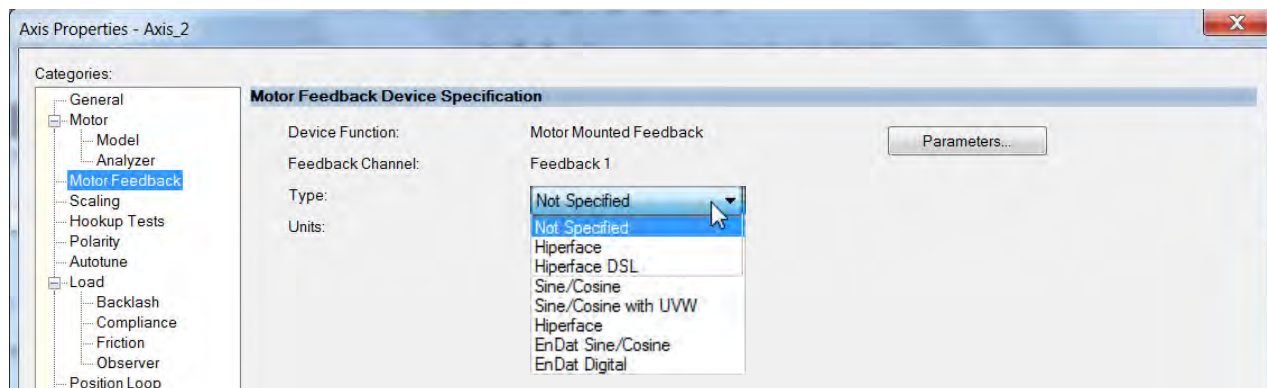
b. For Motor Polarity, click Inverted (default is Normal).



c. Click Apply and return to the Motor category.

8. From the Motor Type pull-down menu, choose Rotary Induction.
9. From the motor nameplate or datasheet, enter the phase-to-phase values for your motor.
See [Motor Category](#) on [page 426](#) for a motor performance datasheet example. Also see Motor Nameplate Datasheet Entry for Custom Motor Applications, publication [2198-AT002](#).
10. Click Apply.
11. Select the Motor Feedback category.

The Motor Feedback Device Specification dialog box appears.



12. From the Type pull-down menu, choose the feedback type appropriate for your application.
See [Configure Feedback Properties](#) on [page 257](#) for feedback configuration examples.
13. Click Apply.

14. Select the Scaling category and edit the default values as appropriate for your application.

The screenshot shows the 'Axis Properties - Axis_4' dialog box with the 'Scaling' category selected in the left-hand tree. The main area is titled 'Scaling to Convert Motion from Controller Units to User Defined Units'. It contains several sections: 'Load Type' (Direct Coupled Rotary), 'Transmission' (Ratio 1.0), 'Actuator' (Type: <none>, Lead: 1.0, Diameter: 1.0), 'Scaling' (Units: Position Units, Scaling: 1.0 Position Units per 1.0 Motor Rev), 'Travel' (Mode: Unlimited, Range: 1000.0 Position Units, Unwind: 1.0 Position Units per 1.0 Cycle), and 'Soft Travel Limits' (Maximum Positive: 0.0, Maximum Negative: 0.0). At the bottom, there are buttons for 'Manual Tune...', 'OK', 'Cancel', 'Apply', and 'Help'.

15. Click Apply, if you make changes.

16. Select the Actions category.

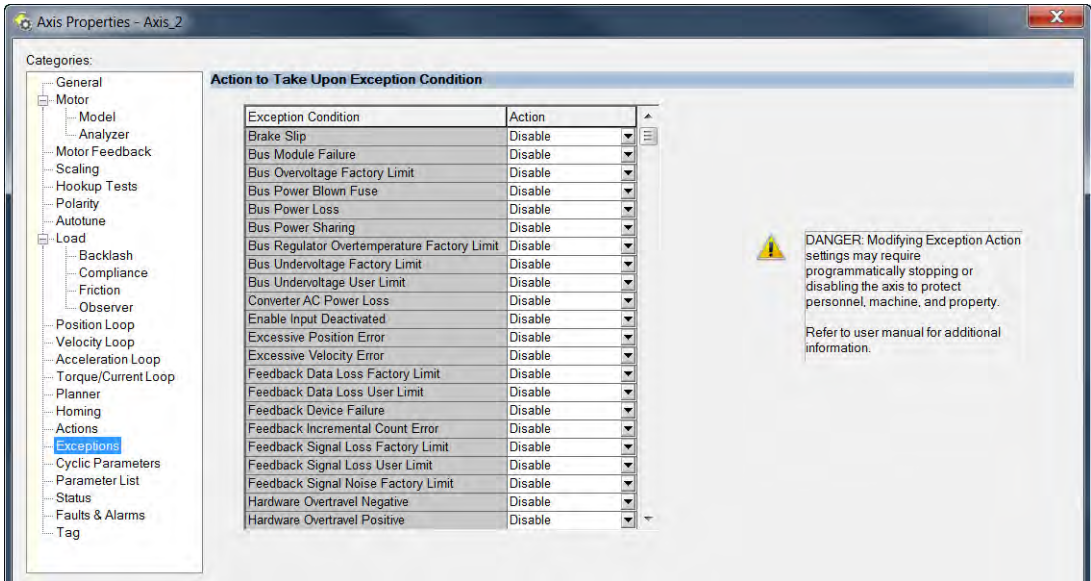
The Actions to Take Upon Conditions dialog box appears.

The screenshot shows the 'Axis Properties - Axis_4' dialog box with the 'Actions' category selected in the left-hand tree. The main area is titled 'Actions to Take Upon Conditions'. It contains two sections: 'Standard Actions' (Disable (MSF) Stopping Action: Current Decel & Disable, Connection Loss Stopping Action: Current Decel & Disable) and 'Safety Actions' (Safe Torque Off Action: Current Decel & Disable, Safe Torque Off Action Source: Connected Drive, Safe Stopping Action: Current Decel, Safe Stopping Action Source: Connected Drive). At the bottom, there are buttons for 'Manual Tune...', 'OK', 'Cancel', 'Apply', and 'Help'.

From this dialog box you can program actions for the drive module to take. Refer to [Logix 5000 Controller and Drive Module Behavior](#) on [page 283](#) for more information.

17. Select the Exceptions category.

The Action to Take Upon Exception Condition dialog box appears.

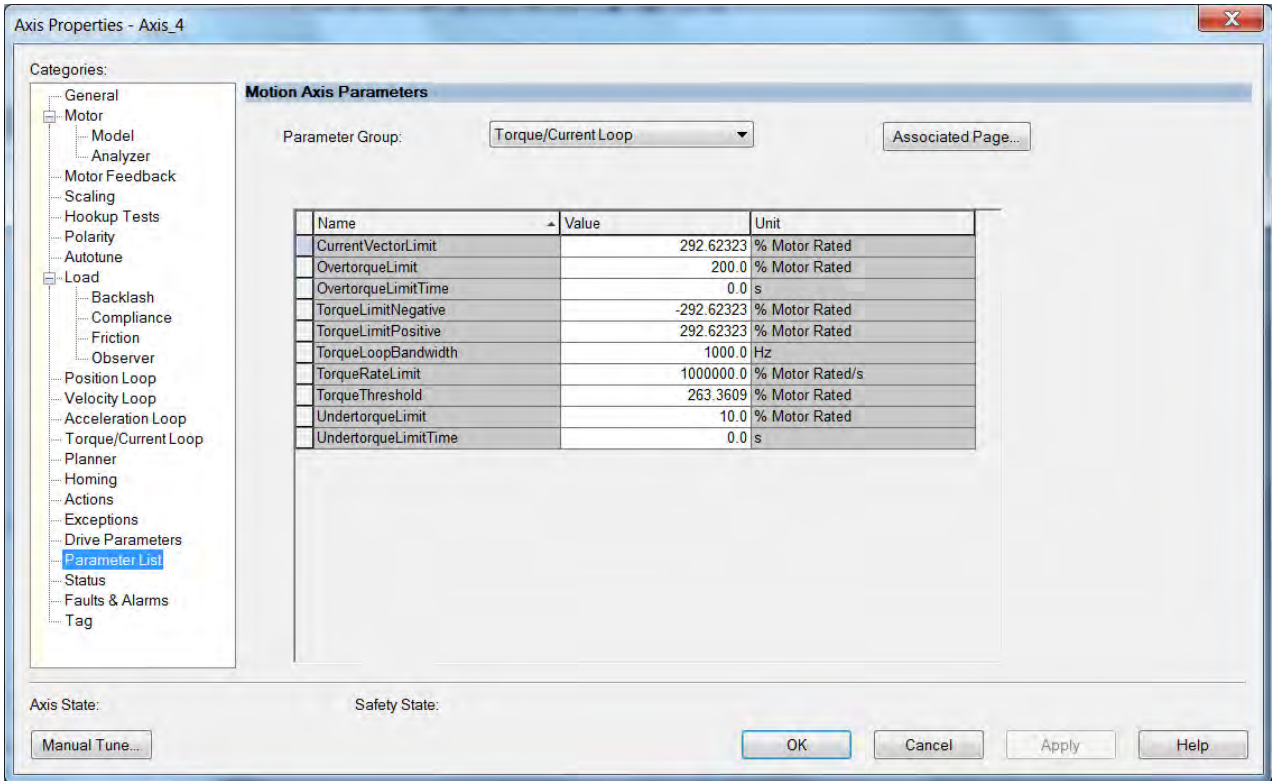


From this dialog box you can change the action for exceptions (faults). Refer to [Logix 5000 Controller and Drive Module Behavior](#) on [page 283](#) for more information.

TIP In the Logix Designer application, version 32 and later, Disable replaced StopDrive as the default Action.

18. Select the Parameter List category.

The Motion Axis Parameters dialog box appears.

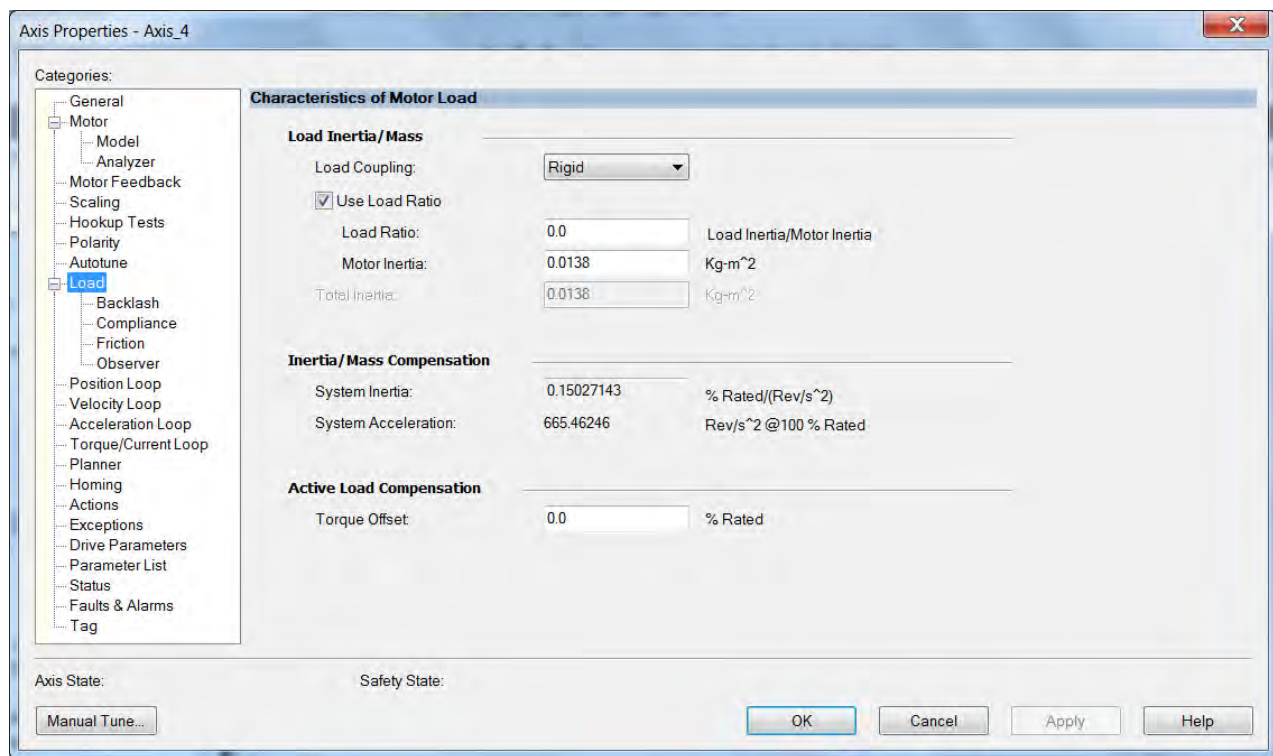


19. From the Parameter Group pull-down menu, choose Torque/Current Loop.
20. Set the FluxUp attributes appropriate for your application.

See the corresponding section in Appendix F, beginning on [page 411](#), for information and configuration examples regarding this topic.

IMPORTANT The Automatic FluxUpControl setting is recommended for best autotune results.

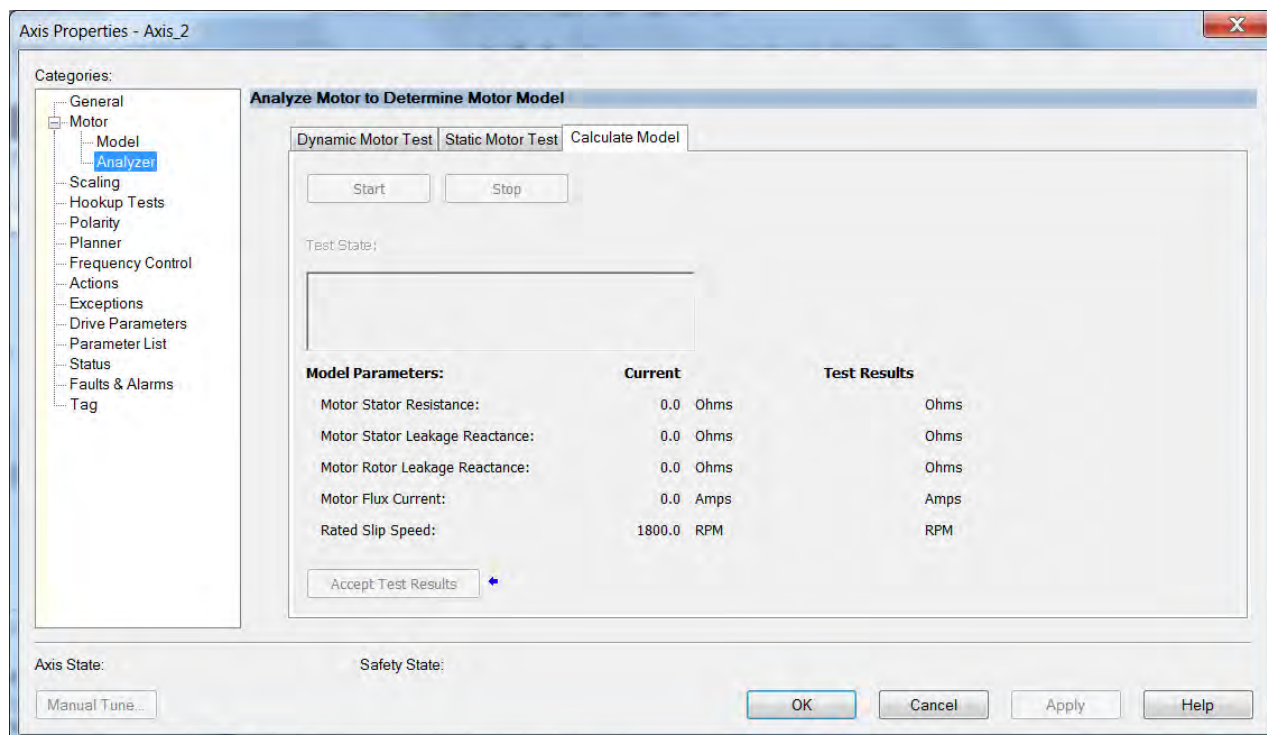
21. Click Apply.
22. Select the Load category and edit the default values as appropriate for your application.



23. Click Apply, if you make changes.
24. Click OK.
25. Select the Motor>Model category.

Motor model attributes are automatically estimated from the Nameplate/Datasheet parameters. For improved performance, motor tests can be run.

26. The Analyze Motor to Determine Motor Model dialog box opens.



IMPORTANT The Dynamic motor test cannot be run without a non-zero motor inertia.

27. Click the tab corresponding to the Motor Test you want to run.
See [Motor Tests and Autotune Procedure](#) on [page 428](#) for information about each of the tests.
28. Click Start.
29. Click Accept Test Results.
30. Click Apply.
31. Select the Autotune category.
See [Tune Induction Motors](#) on [page 273](#) for more information.
32. Repeat [step 1](#) through [step 32](#) for each induction motor axis.

Configure Feedback Properties

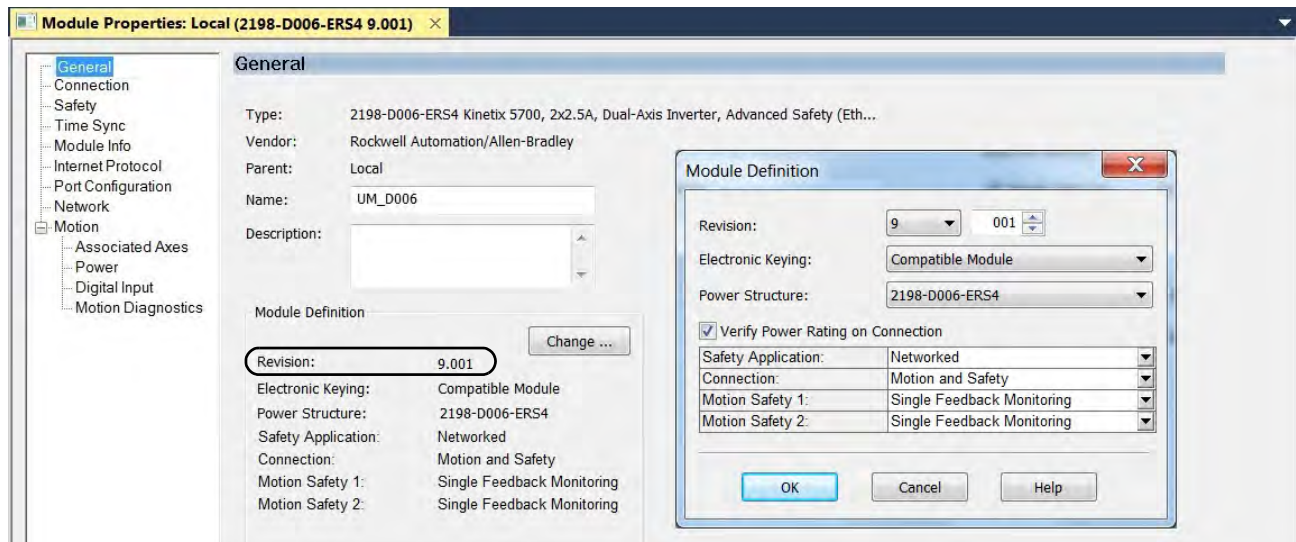
This section provides more configuration detail for module properties and axis properties when incremental feedback types are used in your application.

Configure Module Properties

Configure the module properties of your Kinetix 5700 servo drive depending on how you intend to use the feedback connectors.

1. Right-click a drive in the Controller Organizer to configure and choose Properties.

The Module Properties dialog box appears.

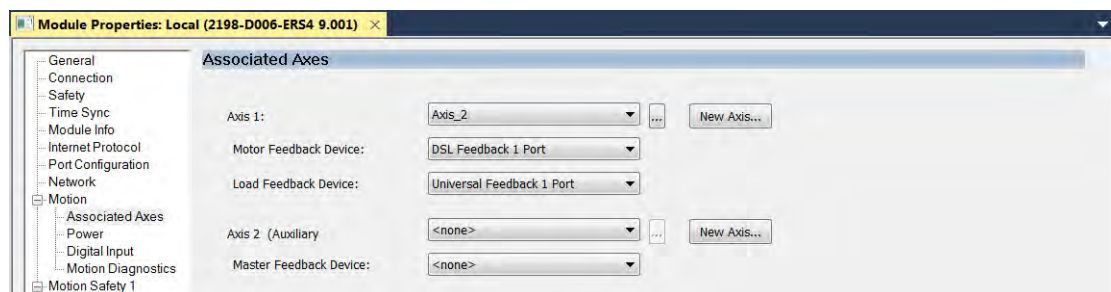


2. Under Module Definition click Change.

The Module Definition dialog box appears.

Depending on the Module Definition revision selection, alternate feedback types can be selected. However, 2198-xxxx-ERS4 drives only appear in firmware revision 9.001 or later.

3. Click the Associated Axes category.



4. Configure each axis for Motor feedback, Load feedback, and Master feedback devices appropriate for your application.

See Continue Inverter Configuration on [page 219](#) for more information on configuring module properties for dual-axis and single-axis inverters.

IMPORTANT The Logix Designer application prevents making feedback port assignments with incompatible feedback types. For example, you cannot assign the same port for multiple devices. The same port cannot be used for Motor Feedback Device, Load Feedback Device, and Master Feedback Device.

Table 120 - Motor Feedback Compatibility

| Motor Feedback Device Option | Feedback Type | | Description | Feedback Connector |
|------------------------------|--|--|---|---------------------------------|
| Universal Feedback 1 Port | <ul style="list-style-type: none"> Digital AqB Digital AqB with UVW Sine/Cosine Sine/Cosine with UVW | Incremental | Applies to Allen-Bradley Kinetix MPL (-H) rotary motors, Kinetix MPAS (direct-drive) linear actuators, LDAT-Series (-xBx) linear thrusters, and LDC-Series™ linear motors wired to the 2198-K57CK-D15M universal connector kit. | 15-pin universal feedback (UFB) |
| | <ul style="list-style-type: none"> EnDat Sine/Cosine EnDat Digital | High-resolution single-turn and multi-turn, absolute | Applies to Allen-Bradley Kinetix RDB and VPC-Bxxxxx-Y motors wired to the 2198-K57CK-D15M universal connector kit. | |
| | Hiperface | | Applies to Allen-Bradley Kinetix MPL, MPM, MPF, MPS (-M/S or -V/E), and VPC-Bxxxxx-S and VPC-B3004x-M rotary motors; Kinetix MPAS (ballscrew), MPAI, linear actuators; Kinetix HPK rotary motors; and LDAT-Series (-xDx) linear thrusters wired to the 2198-K57CK-D15M universal connector kit. | |
| DSL Feedback 1 Port | Hiperface | High-resolution single-turn and multi-turn, absolute | Applies to Allen-Bradley Kinetix MPL, MPM, MPF, MPS (-M/S or -V/E) and VPC-Bxxxxx-Q rotary motors; Kinetix MPAS (ballscrew), MPAI, linear actuators; Kinetix HPK rotary motors; and LDAT-Series (-xDx) linear thrusters wired to the 2198-H2DCK converter kit. | 2-pin motor feedback (MF) |
| | Hiperface DSL | | Applies to Allen-Bradley Kinetix VPL, VPF, VPH, VPS and VPC-Bxxxxx-Q rotary motors and Kinetix VPAR electric cylinders wired to the 2198-KITCON-DSL connector kit. | |

IMPORTANT Unprogrammed Smart feedback devices (Hiperface Sin/Cos, Hiperface DSL, EnDat Digital, and EnDat Sin/Cos) are not supported. Unprogrammed as load or feedback-only feedback types are supported. Contact your local distributor or Rockwell Automation representative for support options.

This example shows acceptable feedback port assignments.



5. Click OK.

Configure Axis Properties

In this section you configure the axis properties of your Kinetix 5700 servo drive for the type of feedback you intend use in your application.

[Table 121](#) defines valid feedback assignments for each feedback type.

Table 121 - Valid Feedback Assignments

| Feedback Type | | Permanent Magnet Motors | | Induction Motors | | |
|----------------------|--|-------------------------|---------------|------------------|---------------|-----------------|
| Hiperface DSL | High-resolution single-turn and multi-turn, absolute | Motor feedback | Load feedback | Motor feedback | Load feedback | Master feedback |
| Hiperface | | N/A | | N/A | N/A | N/A |
| Digital AqB | Incremental | N/A | N/A | N/A | N/A | N/A |
| Digital AqB with UVW | | Motor feedback | N/A | N/A | N/A | N/A |
| Sine/Cosine | | N/A | Load feedback | Motor feedback | Load feedback | Master feedback |
| Sine/Cosine with UVW | | Motor feedback | N/A | N/A | N/A | N/A |
| EnDat Sine/Cosine | High-resolution single-turn and multi-turn, absolute | Motor feedback | Load feedback | Motor feedback | Load feedback | Master feedback |
| EnDat Digital | | N/A | N/A | N/A | N/A | N/A |

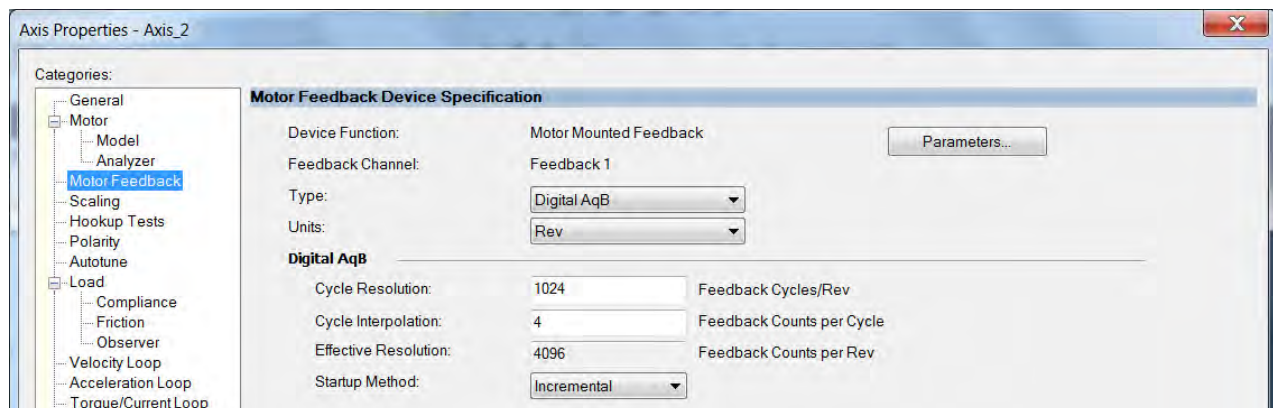
Digital AqB (TTL) Feedback

In this example, a motor feedback device is configured for Digital AqB feedback.

IMPORTANT When Motor Mounted Feedback is the Device Function, Digital AqB (without UVW) is not a valid feedback type for permanent magnet motors.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the Motor Feedback category.

The Motor Feedback Device Specification dialog box appears.



3. Configure the device function and type.

In this example, Motor Feedback is the device function and Digital AqB is the feedback type.

4. Enter values for the Digital AqB specification fields.
The only valid value for Cycle Interpolation is 4.
5. From the Startup Method pull-down menu, choose Incremental.
6. Click Apply.

TIP When the Device Function is Load-Side Feedback or Master Feedback, configuration is identical to Motor Mounted Feedback.

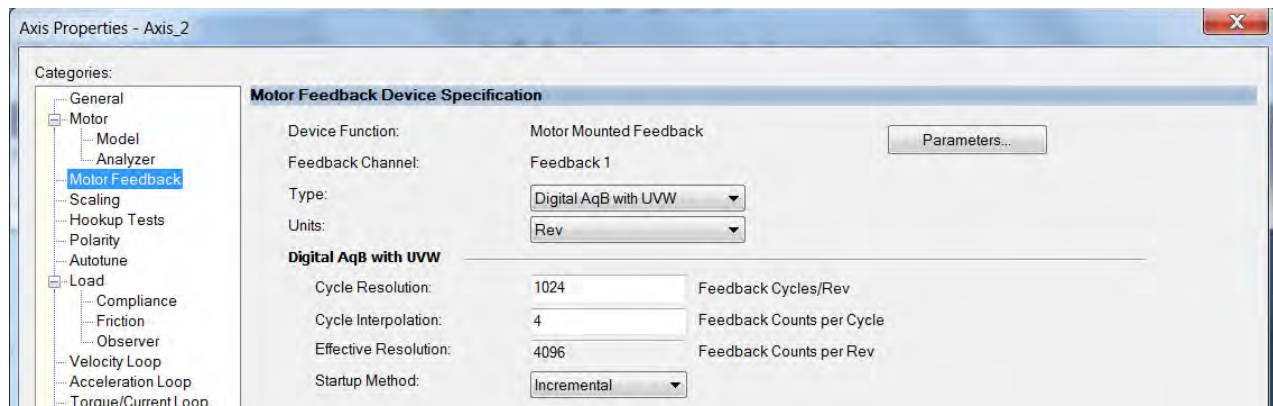
Digital AqB with UVW (TTL w/Hall) Feedback

In this example, a motor feedback device is configured for Digital AqB with UVW feedback.

IMPORTANT When Motor Mounted Feedback is the Device Function, Digital AqB with UVW is the only valid feedback type for permanent magnet motors.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the Motor Feedback category.

The Motor Feedback Device Specification dialog box appears.



3. Configure the device function and type.
In this example, Motor Feedback is the device function and Digital AqB with UVW is the feedback type.
4. Enter values for the Digital AqB with UVW specification fields.
The only valid value for Cycle Interpolation is 4.
5. From the Startup Method pull-down menu, choose Incremental.
6. From the Alignment pull-down menu, choose Not Aligned.
7. Click Apply.

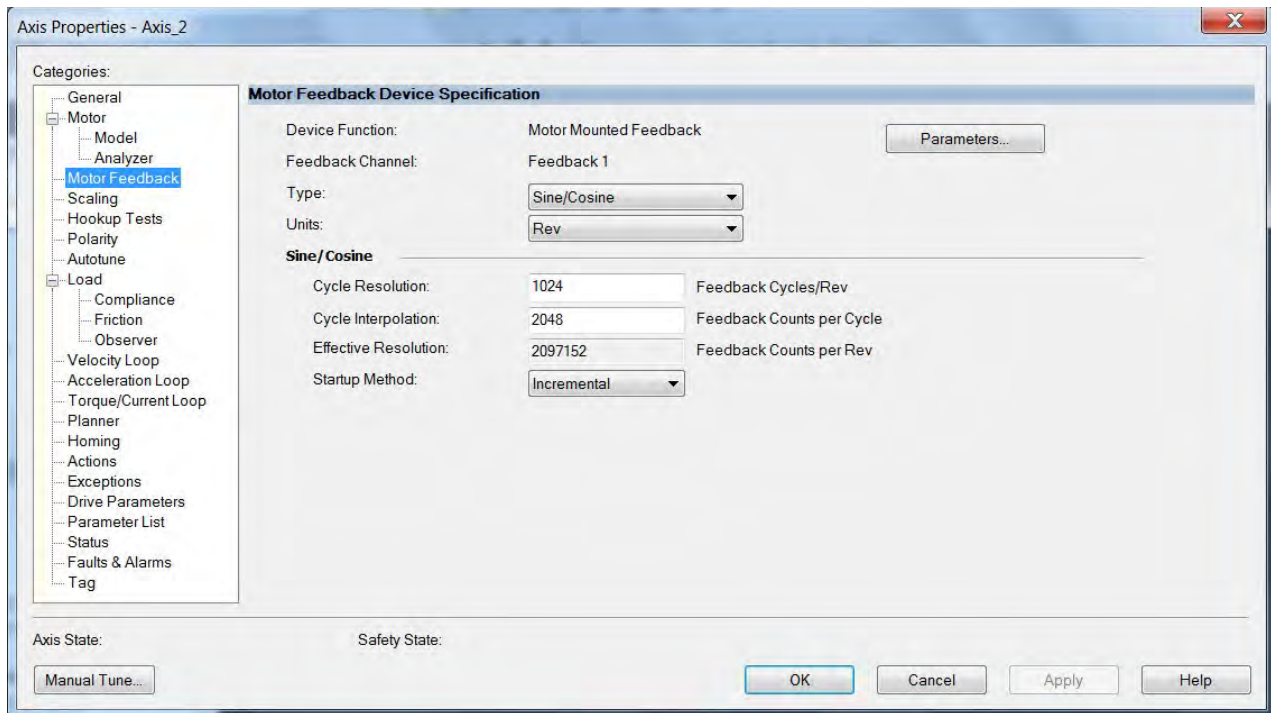
Sine/Cosine Feedback

In this example, a motor feedback device is configured for Sine/Cosine feedback.

IMPORTANT When Motor Mounted Feedback is the Device Function, Sine/Cosine is not a valid feedback type for permanent magnet motors.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the Motor Feedback category.

The Motor Feedback Device Specification dialog box appears.



3. Configure the device function and type.

In this example, Motor Feedback is the device function and Sine/Cosine is the feedback type.

4. Enter values for the Sine/Cosine specification fields.

The only valid values for Cycle Interpolation are powers of 2 from 4 through 65536.

5. From the Startup Method pull-down menu, choose Incremental.
6. Click Apply.

TIP When the Device Function is Load-Side Feedback or Master Feedback, configuration is identical to Motor Mounted Feedback.

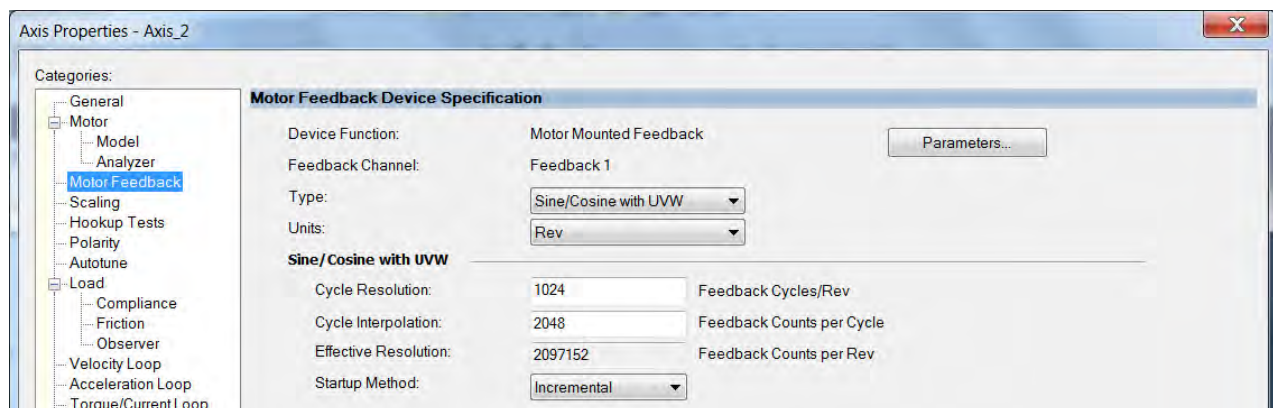
Sine/Cosine with Hall Feedback

In this example, a motor feedback device is configured for Sine/Cosine with UVW feedback.

IMPORTANT When Motor Mounted Feedback is the Device Function, Sine/Cosine with UVW is the only valid feedback type for permanent magnet motors.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the Motor Feedback category.

The Motor Feedback Device Specification dialog box appears.



3. Configure the device function and type.

In this example, Motor Feedback is the device function and Sine/Cosine with UVW is the feedback type.

4. Enter values for the Sine/Cosine with UVW specification fields.

The only valid values for Cycle Interpolation are powers of 2 from 4 through 65536.

5. From the Startup Method pull-down menu, choose Incremental.
6. From the Alignment pull-down menu, choose Not Aligned.
7. Click OK.

Download the Program

After completing the Logix Designer application and saving the file you must download your program to the Logix 5000 processor.

Apply Power to the Kinetix 5700 Drive System

This procedure assumes that you have wired and configured your Kinetix 5700 system, your Logix 5000 controller, and iTRAK power supply if present.



SHOCK HAZARD: To avoid hazard of electrical shock, perform all mounting and wiring of the Bulletin 2198 servo drives prior to applying power. Once power is applied, connector terminals can have voltage present even when not in use.

Follow these steps to apply power to the Kinetix 5700 system.

1. Disconnect the load to the motor (does not apply to iTRAK PS).



ATTENTION: To avoid personal injury or damage to equipment, disconnect the load to the motor. Make sure each motor is free of all linkages when initially applying power to the system.

2. Apply 24V DC control power.

The LCD display begins the startup sequence. Refer to [Startup Sequence](#) on [page 197](#). If the startup sequence does not begin, check the 24V control power connections.

3. When the startup sequence completes, verify that the two status indicators are steady green.
 - a. Verify that the DC-bus power supply or regenerative bus supply axis-state is PRECHARGE.
 - b. Verify the iTRAK power supply axis-state is START INHIBITED.

If the DC-bus power supply/regenerative bus supply/iTRAK power supply does not reach the specified axis state and the two status indicators are not solid green, refer to [Kinetix 5700 Status Indicators](#) on [page 278](#).

IMPORTANT Apply control power before applying three-phase AC power. This makes sure the shunt is enabled, which can prevent nuisance faults or Bus Overvoltage faults.

4. Apply mains input power and monitor the DC BUS voltage on the LCD display.

If the DC BUS does not reach the expected voltage level, check the three-phase input power connections.

TIP It can take as long as 1.8 seconds after input power is applied before the drive can accept motion commands (does not apply to iTRAK power supply).

- a. Verify that the DC-bus power supply axis-state is RUNNING.
- b. Verify that the regenerative bus-supply axis-state is RUNNING or STOPPED depending on the Converter Startup Method used (see [DC-bus Voltage Regulation](#) on [page 42](#)).

c. Verify that the iTRAK power supply axis-state is RUNNING.

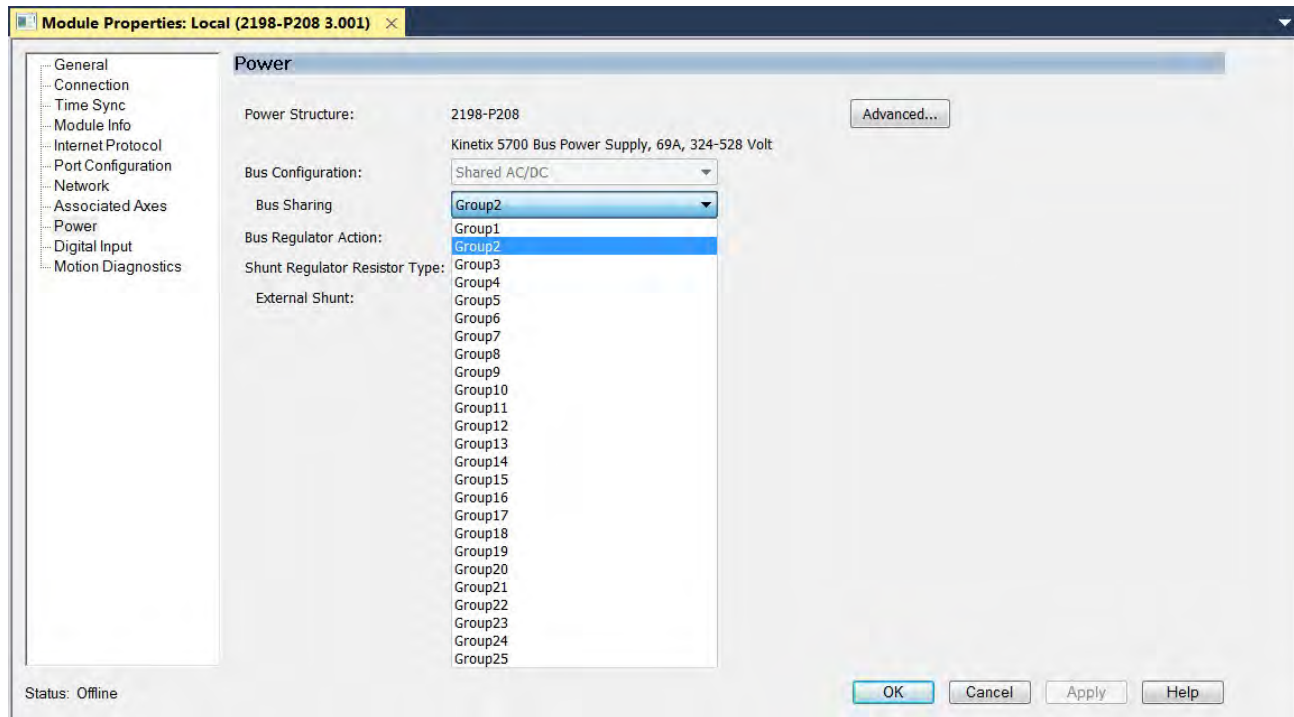
If the DC-bus power supply/regenerative bus supply/iTRAK power supply does not reach the specified axis state, refer to [Fault Code Overview](#) on [page 276](#).

Understand Bus-sharing Group Configuration

When configuring Module Properties>Power category for each Kinetix 5700 drive, you can breakout drives from one or more servo systems into multiple bus-sharing (power) groups.

A drive that faults in Group 1 does not affect the operation of Group 2, even though all of the drives in Groups 1 and 2 are in the same Motion group in the Logix Designer application. As many as 25 bus-sharing groups are possible.

Figure 130 - Bus-sharing Group Configuration



IMPORTANT The iTRAK power supply is not configured as part of a bus-sharing group in the Logix Designer application. The gateway computer monitors bus status and controls enabling and disabling the iTRAK power supply. See the iTRAK System User Manual, publication [2198T-UM001](#) for more information.

Bus-sharing Group Example

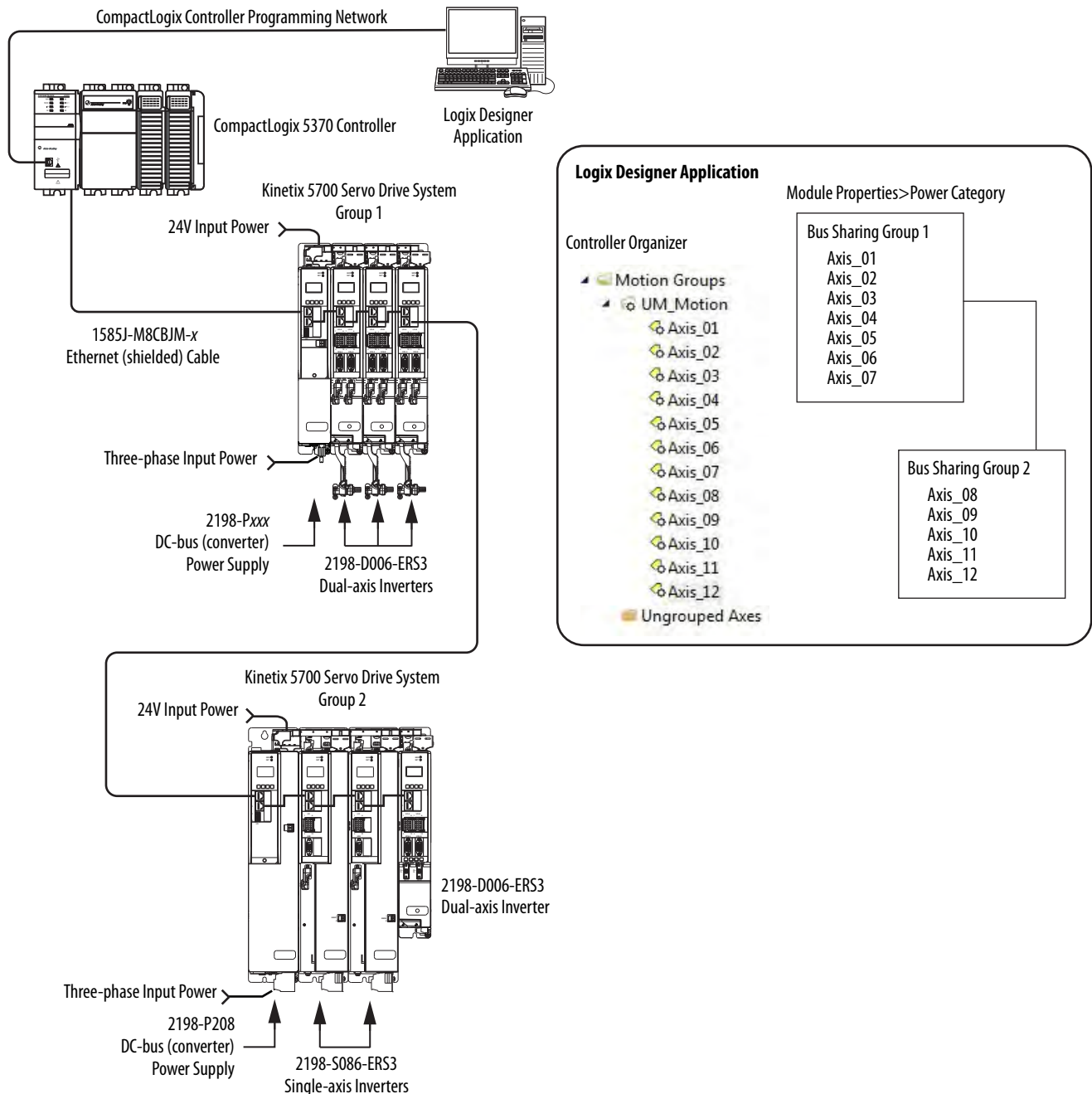
In [Figure 131](#), twelve axes are needed to support the motion application. All twelve axes are configured in the same Motion group in the Logix Designer application.

However, the twelve axes of motion are also configured as two bus-sharing groups in Module Properties>Power category. By creating two bus-sharing groups, a converter drive that faults in Group 1 only disables Group 1 drives, and has no effect on the drive operation of Group 2 drive.



ATTENTION: To avoid damage to equipment all modules physically connected to the same shared-bus connection system must be part of the same Bus Sharing Group in the Logix Designer application.

Figure 131 - Bus-sharing Group Example



Configure Bus-sharing Groups

In both groups, the Bus Configuration for the converter drive is Shared AC/DC and the Bus Configuration for the inverter drives is Shared DC.

Figure 132 - Group 1 DC-bus Power Supply (converter) Configuration

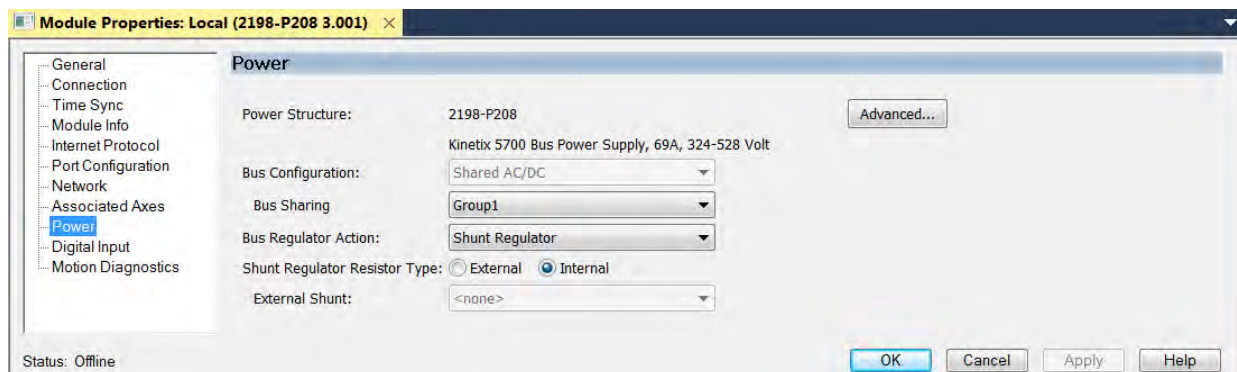


Figure 133 - Group 1 Dual-axis Inverter Configuration

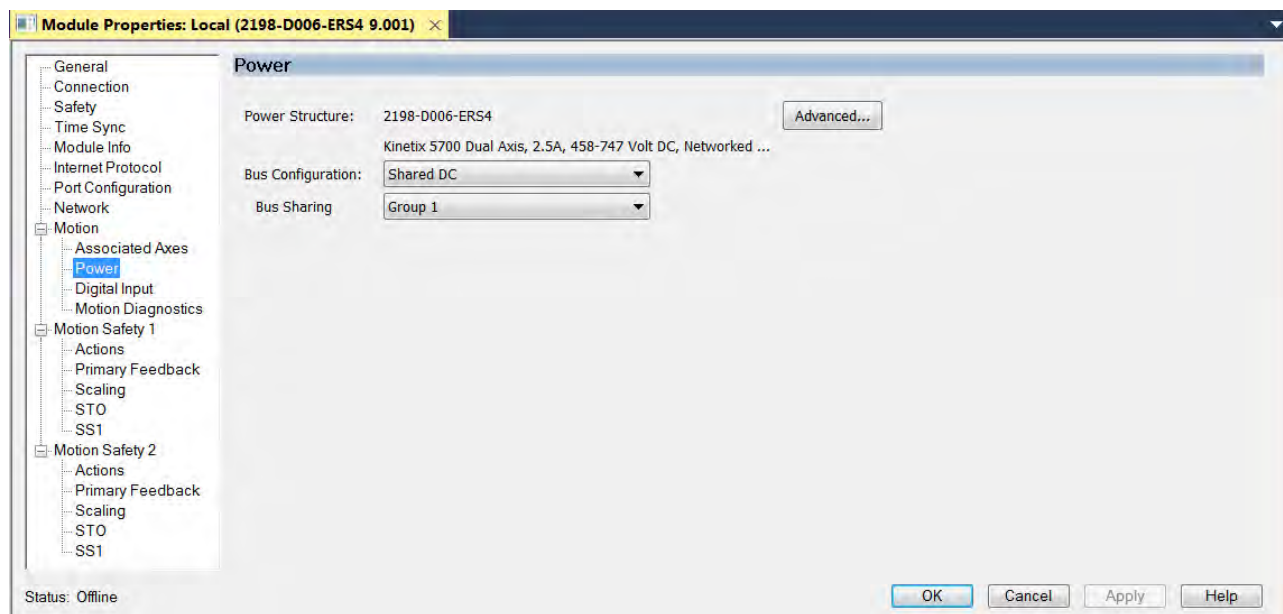


Figure 134 - Group 2 DC-bus Power Supply (converter) Configuration

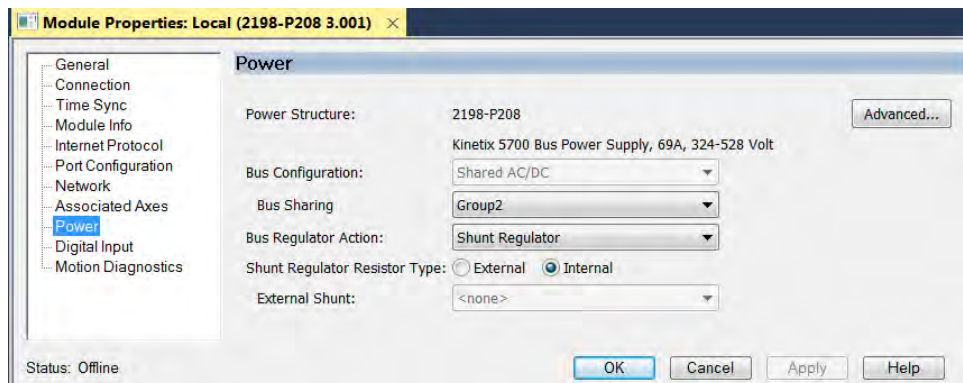
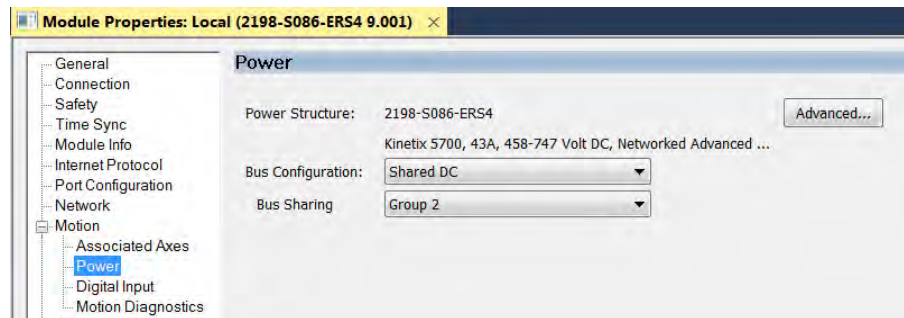
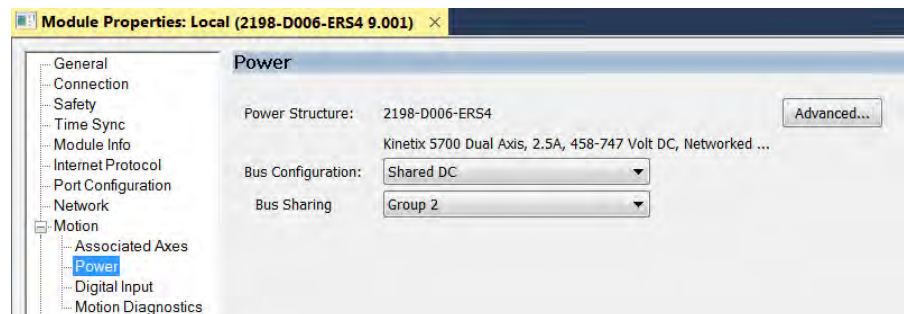


Figure 135 - Group 2 Single-axis Inverter Configuration**Figure 136 - Group 2 Dual-axis Inverter Configuration**

Test and Tune the Axes

This procedure assumes that you have configured your Kinetix 5700 drive, your Logix 5000 controller, and applied power to the system.

IMPORTANT Before proceeding with testing and tuning your axes, verify that the MOD and NET status indicators are operating as described in [Kinetix 5700 Status Indicators](#) on [page 278](#).

For help using the Logix Designer application as it applies to testing and tuning your axes with ControlLogix EtherNet/IP modules or CompactLogix 5370 controllers, refer to [Additional Resources](#) on [page 13](#).

Also, see Motor Nameplate Datasheet Entry for Custom Motor Applications, publication [2198-AT002](#), for detailed information on testing and tuning custom motors.

For testing and tuning iTRAK movers, see the iTRAK System User Manual, publication [2198T-UM001](#).

Test the Axes

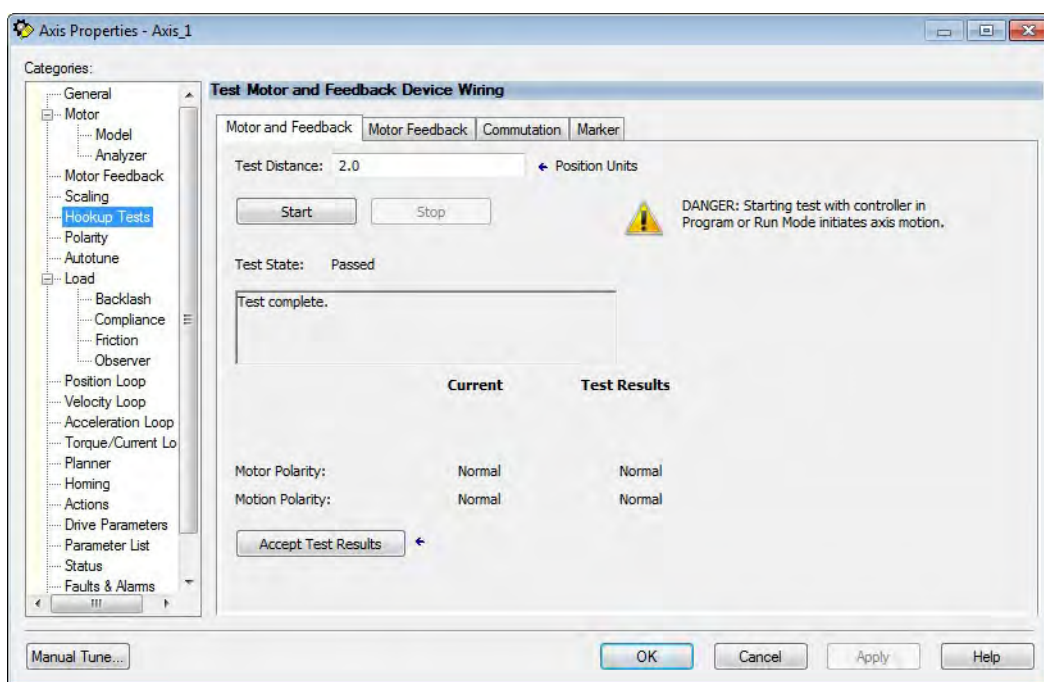
Follow these steps to test the axes.

1. Verify the load was removed from each axis.



ATTENTION: To avoid personal injury or damage to equipment, you must remove the load from each axis as uncontrolled motion can occur when an axis with an integral motor brake is released during the test.

2. In your Motion Group folder, right-click an axis and choose Properties. The Axis Properties dialog box appears.



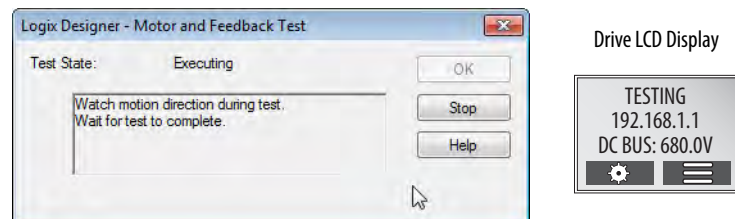
3. Select the Hookup Tests category.
4. In the Test Distance field, enter the desired test distance.

The Position Units are defined in Axis Properties>Scaling category.

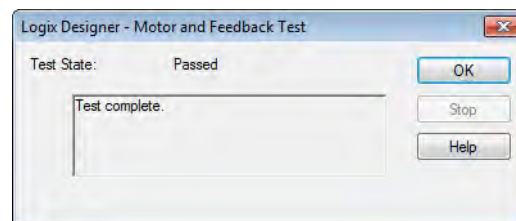
| Hookup Test | Definitions |
|--------------------|---|
| Marker | Verifies marker detection capability as you manually rotate the motor shaft. The test completes when the drive either detects the marker or when the motor moves the distance specified in the Test Distance field. If the marker remains undetected and the test completes successfully, it means the motor moved the full test distance. If the marker remains undetected and the test fails, the motor did not move the full test distance. Run this test after running the Motor Feedback and Motor and Feedback tests. |
| Commutation | Verifies the commutation offset and commutation polarity of the motor. This test applies to third-party or custom permanent-magnet motors equipped with (TTL with Hall and Sine/Cosine with Hall) incremental encoders that are not available as a catalog number in the Motion Database. See Commutation Test on page page 451 . |
| Motor Feedback | Verifies feedback connections are wired correctly as you manually rotate the motor shaft. The test completes when the drive determines that the motor moved the full distance specified in the Test Distance field. Run this test before the Motor and Feedback Test to verify that the feedback can be read properly. |
| Motor and Feedback | Verifies motor power and feedback connections are wired correctly as the drive commands the motor to rotate. Because the drive is rotating the motor, this test requires full bus power to run. Run the Motor Feedback test before running this test to verify that the feedback is being read correctly. |

5. Click the desired test to verify connections.
6. Click Start.

The Logix Designer - Motor and Feedback Test dialog box appears. The Test State is Executing. TESTING appears on the drive LCD display.



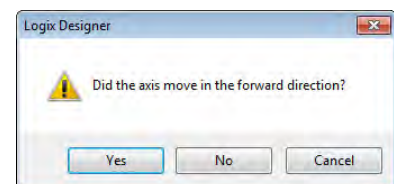
When the test completes successfully, the Test State changes from Executing to Passed.



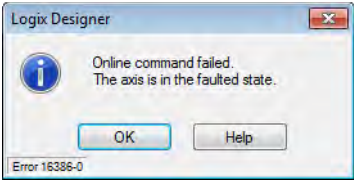
7. Click OK.

This dialog box appears asking if the axis moved in the forward direction.

8. Click Yes if you agree.
9. Click Accept Test Results.



10. If the test fails, this dialog box appears.
- a. Click OK.
 - b. Verify the DC bus voltage.
 - c. Verify unit values entered in the Scaling category.
 - d. Verify the motor power and feedback wiring.
 - e. Return to [step 5](#) and run the test again.



Tune the Axes

Choose the tuning procedure best suited for your motor type.

| Motor Type | Go directly to |
|-----------------------|---|
| Permanent magnet (PM) | Tune Permanent Magnet Motors |
| Induction | Tune Induction Motors on page 273 |

Tune Permanent Magnet Motors

The load observer feature provides high-performance motion control without having to manually tune your axis. Using load observer with a default set of gains can yield high-performance right out of the box. Most of the time, there is no need to perform an auto-tune procedure or further optimize gain settings.

Follow these steps to configure the drive for high-performance by using the load observer feature.

1. Verify that the load is connected.

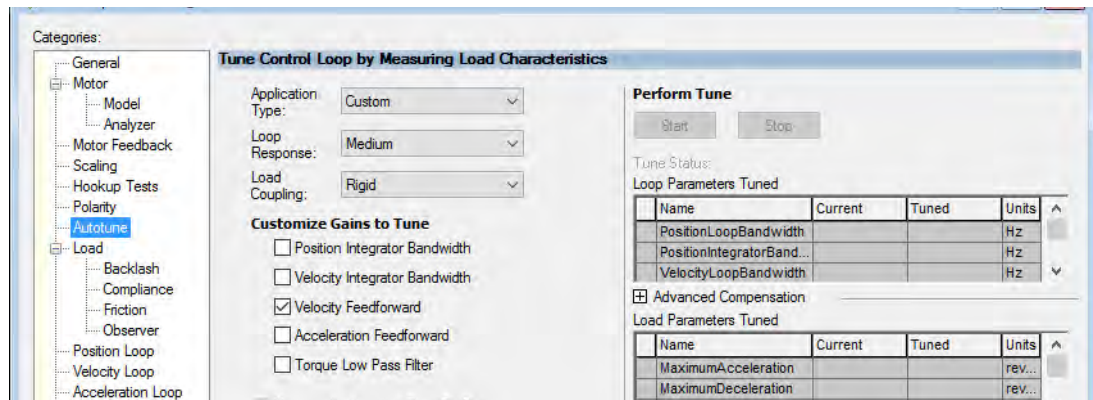
Re-attach the load if it was disconnected for the Hookup Test.



ATTENTION: If the drive has not been enabled before (new installation), verify that you have safeguards in place to safely remove power from the drive in the event of an unstable situation where the drive can produce undesired motion.

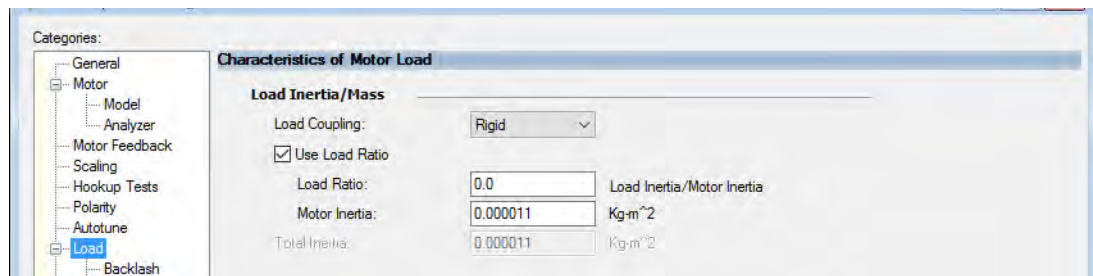
2. Click the Autotune category in the Axis Properties dialog box.
 - a. From the pull-down menus for Application Type, Loop Response, and Load Coupling, choose Custom, Medium, and Rigid settings, respectively.

- b. Verify that only the Velocity Feedforward box is checked.

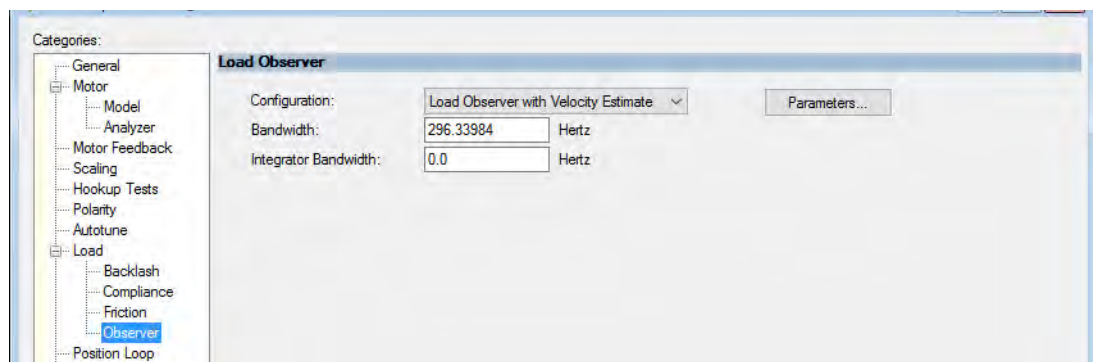


Uncheck Torque Low Pass Filter (that is checked by default).

3. Click the Load category in the Axis Properties dialog box.
- Check Use Load Ratio.
 - Set the Load Ratio = 0.

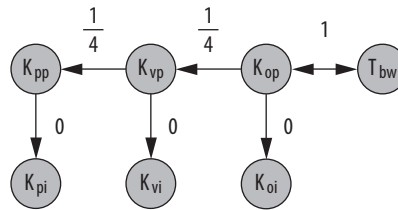


4. Click the Observer category in the Axis Properties dialog box.
- From the Configuration pull-down menu, choose Load Observer with Velocity Estimate if the axis is configured for Position Loop control.
Choose Load Observer Only if the axis is configured for Velocity Loop control.
Load Observer is not available for Torque Loop control.

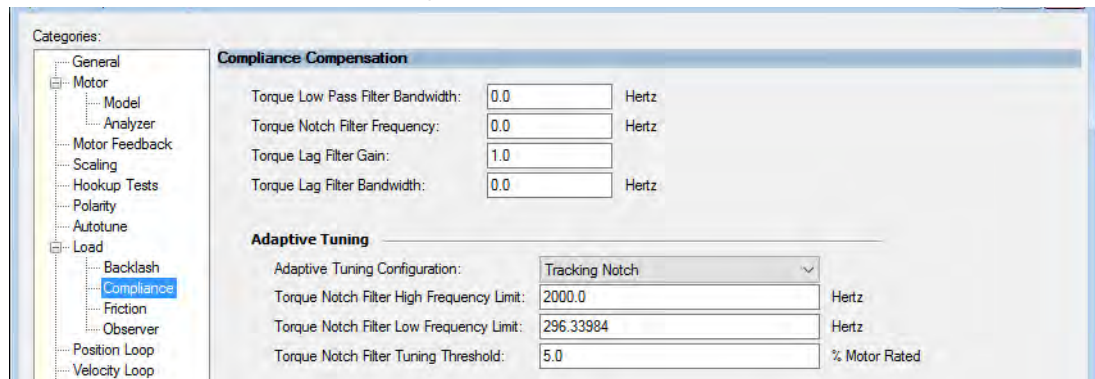


- b. Click Apply and click Yes to update all dependent attributes.

The Load Observer Bandwidth and other gains are set automatically.



5. Click the Compliance category in the Axis Properties dialog box.
 - a. From the Adaptive Tuning Configuration pull-down menu, choose Tracking Notch.



- b. Click Apply.
6. Enable the drive for a few seconds with an MSO instruction or motion direct command, followed by an MSF instruction or motion direct command, to make sure that no audible squealing noise is present.

IMPORTANT If an audible squealing noise is heard, go to Axis Properties>Load>Compliance category and set the Torque Notch Filter Frequency field (Hz) to remove the noise. Refer to Motion System Tuning Application Techniques, publication [MOTION-AT005](#) (Compensating for High Frequency Resonances), for information on how to set the Torque Notch Filter Frequency field.

7. Repeat [Test and Tune the Axes](#) for each axis.

Tune Induction Motors

IMPORTANT The Automatic FluxUpControl setting is recommended for best Autotune results.

Follow these steps to tune the induction motor axes.

1. Verify the load is removed from the axis being tuned.



ATTENTION: To reduce the possibility of unpredictable motor response, tune your motor with the load removed first, then re-attach the load and perform the tuning procedure again to provide an accurate operational response.

2. Select the Autotune category.

Axis Properties - Axis_1

Categories:

- General
- Motor
 - Model
 - Analyzer
 - Motor Feedback
 - Scaling
 - Hookup Tests
 - Polarity
 - Autotune**
 - Load
 - Backlash
 - Compliance
 - Friction
 - Observer
 - Position Loop
 - Velocity Loop
 - Acceleration Loop
 - Torque/Current Lo
 - Planner
 - Homing
 - Actions
 - Drive Parameters
 - Parameter List
 - Status
 - Faults & Alarms

Tune Control Loop by Measuring Load Characteristics

Application Type: Basic

Loop Response: Medium

Load Coupling: Rigid

Customize Gains to Tune

- ☐ Position Integrator Bandwidth
- ☐ Velocity Integrator Bandwidth
- ☒ Velocity Feedforward
- ☐ Acceleration Feedforward
- ☒ Torque Low Pass Filter

☒ Measure Inertia using Tune Profile

☒ Motor with Load ☐ Uncoupled Motor

Travel Limit: 50.0 Position Units

Speed: 2.0 Position Units/s

Torque: 100.0 % Rated

Direction: Forward Uni-directional

Perform Tune

Start Stop

Tune Status: Ready

Loop Parameters Tuned

| Name | Current | Tuned | Units |
|--------------------------|----------|-------|-------|
| PositionLoopBandwidth | 18.52124 | | Hz |
| PositionIntegratorBan... | 0.0 | | Hz |
| VelocityLoopBandwidth | 74.08496 | | Hz |

Advanced Compensation

Load Parameters Tuned

| Name | Current | Tuned | Units |
|---------------------|-------------|-------|-------|
| MaximumAcceleration | 4860.1943 | | Po... |
| MaximumDeceleration | 4860.1943 | | Po... |
| Systeminertia | 0.014940577 | | % ... |

Accept Tuned Values

Manual Tune... OK Cancel Apply Help

3. Type values for Travel Limit and Speed.

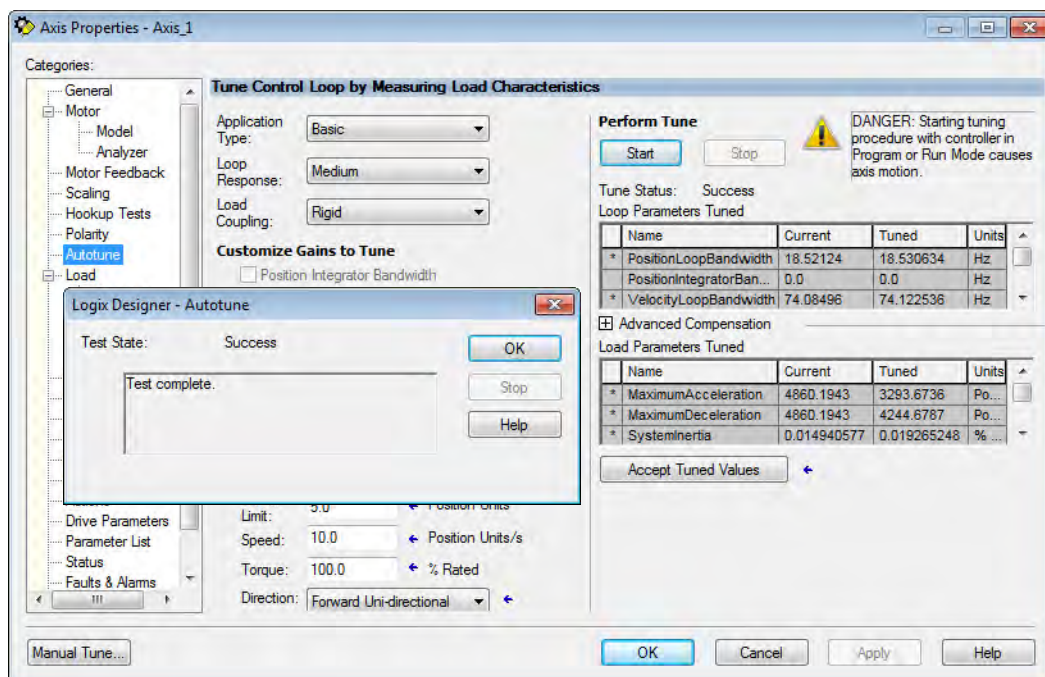
In this example, Travel Limit = 50.0 and Speed = 2.0. The actual value of programmed units depend on your application.

4. From the Direction pull-down menu, choose a setting appropriate for your application.

Forward Uni-directional is default.

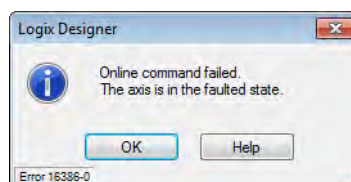
5. Edit other fields as appropriate for your application.
6. Click Start.

The Logix Designer - Autotune dialog box appears. When the test completes, the Test State changes from Executing to Success.



Tuned values populate the Loop and Load parameter tables. Actual bandwidth values (Hz) depend on your application and can require adjustment once motor and load are connected.

7. Click Accept Tuned Values.
8. Click OK to close the Logix Designer - Autotune dialog box.
9. Click OK to close the Axis Properties dialog box.
10. If the test fails, this dialog box appears.



- a. Click OK.
- b. Make an adjustment to motor velocity.
- c. Refer to the controller user manual for more information.
- d. Return to [step 6](#) and run the test again.
11. Repeat [Test and Tune the Axes](#) for each axis.

Troubleshoot the Kinetix 5700 Drive System

This chapter provides troubleshooting tables and related information for your Kinetix® 5700 drive system.

| Topic | Page |
|---|------|
| Safety Precautions | 275 |
| Interpret Status Indicators | 276 |
| Axis Troubleshooting | 280 |
| Regenerative Bus Supply Troubleshooting | 281 |
| Logix 5000 Controller and Drive Module Behavior | 283 |

Safety Precautions

Observe the following safety precautions when troubleshooting your Kinetix 5700 drive system.



ATTENTION: Capacitors on the DC bus can retain hazardous voltages after input power has been removed. Before working on the drive module, measure the DC bus voltage to verify it has reached a safe level or wait the full time interval as indicated in the warning on the front of the module. Failure to observe this precaution could result in severe bodily injury or loss of life.



ATTENTION: Do not attempt to defeat or override the module fault circuits. You must determine the cause of a fault and correct it before you attempt to operate the system. Failure to correct the fault could result in personal injury and/or damage to equipment as a result of uncontrolled machine operation.



ATTENTION: Provide an earth ground for test equipment (oscilloscope) used in troubleshooting. Failure to ground the test equipment could result in personal injury.

Interpret Status Indicators




Refer to these troubleshooting tables to identify faults, potential causes, and the appropriate actions to resolve the fault. If the fault persists after attempting to troubleshoot the system, please contact your Rockwell Automation sales representative for further assistance.

Display Interface

The LCD display provides fault messages and troubleshooting information by using the soft menu items and navigation buttons.



Under the Main Menu, select FAULT LOG by using the up/down arrows.

| | |
|---|---|
|  | Press to display the list of active fault codes. |
|  | Press again to display the fault details (the problem in troubleshooting tables). |
|  | Press to display the fault help (possible solutions in troubleshooting tables). |

Refer to [Understand the Kinetix 5700 Display](#) on [page 188](#) for more information on navigating the LCD display menu.

Fault Code Overview

The fault code tables are designed to help you determine the source of the fault or exception. When a fault condition is detected, the drive module performs the appropriate fault action, the fault is displayed, and the fault is added to a persistent fault log (along with diagnostics data). The earlier faults have priority to be displayed.

The drive module removes the fault text from the display when a Fault Reset service is sent from the controller and the fault is no longer active. If a fault condition is still active following a Fault Reset service, the fault is again posted to the display and written to the fault log.

However, there can be a delay before the fault is posted again. In a Studio 5000 Logix Designer® application, this delay results as the AxisFault tag on the drive axis being cleared until the fault is posted again. During this delay, the AxisState tag continues to indicate that the axis is faulted. Use the AxisState tag on the axis object only to determine if an axis is faulted.

Although software overtravel fault codes do not exist, software overtravel detection for the AXIS_CIP_DRIVE axis type is determined in the Logix 5000™ controller. For more information, see Integrated Motion on the EtherNet/IP™ Network Reference Manual, publication [MOTION-RM003](#).

The DC-bus power supply, regenerative bus supply, single-axis inverters, and dual-axis inverters maintain a fault log of the last 128 faults. The fault log includes time stamps and is stored in persistent memory. However, the fault log cannot be cleared on the module.

Table 122 - Fault Code Summary

| Fault Code Type ^{(1) (2)} | Description |
|------------------------------------|---|
| FLT Sxx | Standard runtime axis exceptions. The exception can apply to an individual axis or to all axes. |
| FLT Mxx | Manufacturer-specific runtime axis exception. The exception can apply to an individual axis or to all axes. |
| INIT FLT Sxx | Exceptions that prevent normal operation and occur during the initialization process. |
| INIT FLT Mxx | |
| NODE FLTxx | Exceptions that can prevent normal operation of the drive module and apply to the entire module and affect all axes. |
| NODE ALARM xx | Exceptions that can prevent normal operation of the drive module, but do not result in any action other than reporting the alarm to the controller. |
| INHIBIT Sxx | Conditions that prevent normal operation and indicate the drive module is prevented from being enabled. |
| INHIBIT Mxx | |
| ALARM Sxx | An underlying exception condition that does not result in any action other than reporting the alarm to the controller. |
| ALARM Mxx | |
| SAFE FLTxx ⁽³⁾ | Exception generated by a fault condition detected in the safety function. |

(1) Sxx refers to Standard exceptions.

(2) Mxx refers to Manufacturer-specific exceptions.

(3) For troubleshooting 2198-xxxx-ERS3 inverter SAFE FLT fault codes, refer to [Troubleshoot the Safe Torque-off Function](#) on [page 316](#) (hardwired safety) or [page 329](#) (integrated safety). For troubleshooting 2198-xxxx-ERS4 inverter SAFE FLT fault codes, refer to the Kinetix 5700 Safe Monitor Functions Safety Reference Manual, publication [2198-RM001](#).

TIP Fault codes triggered by conditions that fall outside factory set limits are identified by FL at the end of the display message. For example, FLT S07 – MTR OVERLOAD FL.

Fault codes triggered by conditions that fall outside user set limits are identified by UL at the end of the display message. For example, FLT S08 – MTR OVERLOAD UL.

Fault Codes

For Kinetix 5700 fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

SAFE FLT Fault Codes

For troubleshooting 2198-xxxx-ERS4 inverter SAFE FLT fault codes, refer to the Kinetix 5700 Safe Monitor Functions Safety Reference Manual, publication [2198-RM001](#).

Kinetix 5700 Status Indicators

These status indicators apply to the Kinetix 5700 DC-bus power supply, the regenerative bus supply, the inverters, and the iTRAK® power supply. The module status and network status indicators are just above the LCD status display.

IMPORTANT Status indicators are not reliable for safety functions. Use them only for general diagnostics during commissioning or troubleshooting. Do not attempt to use status indicators to determine operational status.

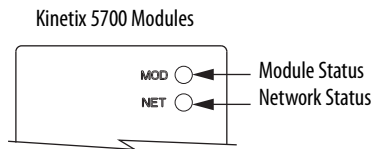


Table 123 - Module Status Indicator

| Condition | Status |
|--------------------|--|
| Steady Off | No power applied to the drive. |
| Steady Green | Drive is operational. No faults or failures. |
| Flashing Green | Standby (drive not configured) and Precharge (drive is configured). |
| Flashing Red | Major recoverable fault. The drive detected a recoverable fault, for example, an incorrect or inconsistent configuration. |
| Steady Red | Major fault. The drive detected a non-recoverable fault. |
| Flashing Green/Red | Self-test. The drive performs self-test during powerup. Once self-test is complete, Flashing Green/Red condition continues if drive is waiting for: <ul style="list-style-type: none"> Safety configuration when in Integrated STO mode Safety inputs when in Hardwired STO mode |

Table 124 - Network Status Indicator

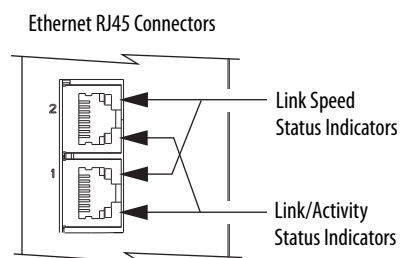
| Condition | Status |
|--------------------|--|
| Steady Off | No power applied to the drive or IP address is not configured. |
| Flashing Green | No Motion or Safety connection is established, but drive has obtained an IP address. |
| Steady Green | Motion or Safety connection is established and no timeout has occurred. Normal operation. |
| Flashing Red | Connection timeout. One or more of the connections, for which this drive is the target, has timed out. |
| Steady Red | Duplicate IP address. IP address specified is already in use. |
| Flashing Green/Red | Self-test. The drive performs self-test during powerup. Once self-test is complete, Flashing Green/Red condition continues if drive is processing a safety device ID proposal. |

Table 125 - Ethernet Link Speed Status Indicator

| Condition | Status |
|------------|----------|
| Steady Off | 10 Mbit |
| Steady On | 100 Mbit |

Table 126 - Ethernet Link/Activity Status Indicator

| Condition | Status |
|------------|------------------|
| Steady Off | No link |
| Steady On | Link established |
| Blinking | Network activity |



Kinetix 5700 Accessory Module Status Indicators

The Kinetix 5700 accessory modules include the 2198-CAPMOD-2240 capacitor module and 2198-DCBUSCOND-RP312 DC-bus conditioner module.

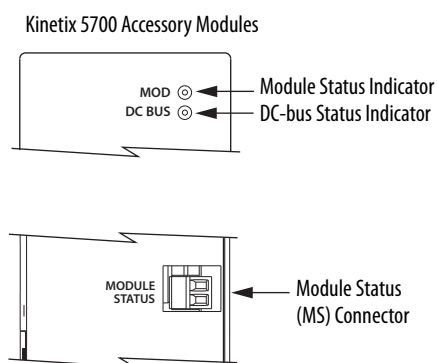
Capacitor Module

Status indicators and the module status (MS) connector are on the front of the module. The module status connector is an output suitable for wiring to a DC-bus power supply, regenerative bus supply, or inverter digital input assigned as Bus Capacitor OK, or the Logix 5000 controller.

Table 127 - Capacitor Module Status Indicators and Relay Output

| Status Indicators | Status | Relay Output ⁽¹⁾ | Description | Resolution |
|-------------------|--------------|-----------------------------|--|--|
| Module status | Steady off | Open | 24V DC is not present. | — |
| | Steady green | Closed | 24V DC is present and internal fuse is closed. | — |
| | Steady red | Open | 24V DC is present and internal fuse is open. | <ul style="list-style-type: none"> • Cycle control and bus power • Verify that AC input meets specifications • Replace the module if fault persists |
| DC-bus status | Steady off | Open | 24V DC is not present or DC-bus measures < 50V DC. | — |
| | Steady green | Closed | 24V DC is present and DC-bus measures > 50V DC. | — |

(1) Wiring the module status relay output is optional.



DC-bus Conditioner Module

Status indicators and the module status (MS) connector are on the front of the module. The module status connector is an output suitable for wiring to a DC-bus power supply, regenerative bus supply, or inverter digital input assigned as Bus Conditioner OK, or the Logix 5000 controller.

Table 128 - DC-bus Conditioner Module Status Indicators and Relay Output

| Status Indicators | Status | Relay Output | Description |
|-------------------|---------------------------|--------------|--|
| Module status | Steady off | Open | 24V DC is not present |
| | Steady green | Closed | 24V DC is present and internal fuse is closed |
| | Steady red ⁽¹⁾ | Open | <ul style="list-style-type: none"> • 24V DC is present and internal fuse is open • Over temperature event occurred |
| DC-bus status | Steady off | — | 24V DC is not present or DC-bus measures < 50V DC |
| | Steady green | — | 24V DC is present and DC-bus measures > 50V DC |

(1) Remove DC-bus power and cycle control power. If the fault persists, the internal fuse is blown and the module needs to be replaced. If the fault clears, then there was a thermal fault caused by a system issue. If the fault persists and the rest of the system is functioning properly, add more DC-bus conditioners to the system to reduce thermal stress on the module.

Axis Troubleshooting

These conditions do not always result in a fault code, but can require troubleshooting to improve servo drive performance. See the iTRAK System User Manual, publication [2198T-UM001](#) for general iTRAK troubleshooting.

Table 129 - Axis Troubleshooting

| Condition | Potential Cause | Possible Resolution |
|--|--|--|
| Axis or system is unstable. | The position feedback device is incorrect or open. | Check wiring. |
| | Unintentionally in Torque mode. | Check to see what primary operation mode was programmed. |
| | Motor tuning limits are set too high. | Run Tune in the Logix Designer application. |
| | Position loop gain or position controller accel/decel rate is improperly set. | Run Tune in the Logix Designer application. |
| | Improper grounding or shielding techniques are causing noise to be transmitted into the position feedback or velocity command lines, causing erratic axis movement. | Check wiring and ground. |
| | Motor Select limit is incorrectly set (servo motor is not matched to axis module). | <ul style="list-style-type: none"> Check setups. Run Tune in the Logix Designer application. |
| | Mechanical resonance. | <ul style="list-style-type: none"> Notch filter or output filter can be required (refer to Axis Properties dialog box, Compliance tab in the Logix Designer application). Enable adaptive tuning. See Adaptive Tuning on page 451 for more notch filter information. |
| You cannot obtain the motor acceleration/deceleration that you want. | Torque Limit limits are set too low. | Verify that torque limits are set properly. |
| | Incorrect motor selected in configuration. | Select the correct motor and run Tune in the Logix Designer application again. |
| | The system inertia is excessive. | <ul style="list-style-type: none"> Check motor size versus application need. Review servo system sizing. |
| | The system friction torque is excessive. | Check motor size versus application need. |
| | Available current is insufficient to supply the correct accel/decel rate. | <ul style="list-style-type: none"> Check motor size versus application need. Review servo system sizing. |
| | Acceleration limit is incorrect. | Verify limit settings and correct them, as necessary. |
| | Velocity Limit limits are incorrect. | Verify limit settings and correct them, as necessary. |
| | The motor is operating in the field-weakening range of operation. | Reduce the commanded acceleration or deceleration. |
| Motor does not respond to a command. | The axis cannot be enabled until stopping time has expired. | Disable the axis, wait the configured stopping time, and enable the axis. |
| | The motor wiring is open. | Check the wiring. |
| | The motor cable shield connection is improper. | <ul style="list-style-type: none"> Check feedback connections. Check cable shield connections. |
| | The motor has malfunctioned. | Repair or replace the motor. |
| | The coupling between motor and machine has broken (for example, the motor moves, but the load/machine does not). | Check and correct the mechanics. |
| | Primary operation mode is set incorrectly. | Check to see what primary operation mode was programmed. |
| | Velocity or torque limits are set incorrectly. | Check and properly set the limits. |
| | Brake connector not wired | Check brake wiring |
| Presence of noise on command or motor feedback signal wires. | Recommended grounding per installation instructions have not been followed. | <ul style="list-style-type: none"> Verify grounding. Route wire away from noise sources. Refer to System Design for Control of Electrical Noise, publication GMC-RM001. |
| | Line frequency can be present. | <ul style="list-style-type: none"> Verify grounding. Route wire away from noise sources. |
| | Variable frequency can be velocity feedback ripple or a disturbance caused by gear teeth or ballscrew, and so forth. The frequency can be a multiple of the motor power transmission components or ballscrew speeds resulting in velocity disturbance. | <ul style="list-style-type: none"> Decouple the motor for verification. Check and improve mechanical performance, for example, the gearbox or ballscrew mechanism. |

Table 129 - Axis Troubleshooting (continued)

| Condition | Potential Cause | Possible Resolution |
|---|--|---|
| No rotation | The motor connections are loose or open. | Check motor wiring and connections. |
| | Foreign matter is lodged in the motor. | Remove foreign matter. |
| | The motor load is excessive. | Verify the servo system sizing. |
| | The bearings are worn. | Return the motor for repair. |
| | The motor brake is engaged (if supplied). | <ul style="list-style-type: none"> Check brake wiring and function. Return the motor for repair. |
| | The motor is not connect to the load. | Check coupling. |
| Motor overheating | The duty cycle is excessive. | Change the command profile to reduce accel/decel or increase time. |
| | The rotor is partially demagnetized causing excessive motor current. | Return the motor for repair. |
| Abnormal noise | Motor tuning limits are set too high. | Run Tune in the Logix Designer application. |
| | Loose parts are present in the motor. | <ul style="list-style-type: none"> Remove the loose parts. Return motor for repair. Replace motor. |
| | Through bolts or coupling is loose. | Tighten bolts. |
| | The bearings are worn. | Return motor for repair. |
| | Mechanical resonance. | Notch filter can be required (refer to Axis Properties dialog box, Compliance tab in the Logix Designer application). |
| Erratic operation - Motor locks into position, runs without control or with reduced torque. | Motor power phases U and V, U and W, or V and W reversed. | Check and correct motor power wiring. |

Regenerative Bus Supply Troubleshooting

These conditions do not always result in a fault code, but can require troubleshooting to improve regenerative bus supply performance.

Table 130 - Regenerative Bus Supply Troubleshooting

| Condition | Potential Cause | Possible Resolution |
|---|---|--|
| AC current appears distorted, non-sinusoidal on oscilloscope. | AC voltage distortion. | Improve AC voltage waveform with isolation transformer or line reactor on input power. Distortion from the utility cannot be addressed. |
| | Excessive boost voltage. | Reduce the BusVoltageSetPoint or set to automatic mode. See DC-bus Voltage Regulation on page 42 , for definition of boost voltage. |
| | Current Saturation. | Normal operation, distortion improves closer to rated current. |
| | Ride through condition. | Normal operation, distortion clears once input voltage disturbance ends. |
| | Load current (<50%). | Normal operation, distortion improves closer to rated current. |
| | Excessive bus stiffness. | Detune the voltage and observer bandwidths. |
| Audible (loud) noise from regenerative bus supply. | Excessive boost voltage. | Reduce the bus voltage set point or set to automatic mode. |
| | Notching on AC line voltage. | Add isolation transformer or line reactor to isolate from notching source. |
| | Current overload. | Normal peak operation, no resolution needed. |
| | Cooling fans enabled when AC input power is applied. | Normal operation. |
| DC-bus voltage fluctuations. | Loop response. | If changed, set loop response to medium (default). |
| | Dynamic load change. | DC-bus voltage transient is normal with a peak-load step change, but adding a capacitor module can help reduce voltage transients and adding an external active shunt module can help prevent nuisance over-voltage faults. |
| | Voltage loop or observer bandwidths. | Optimal voltage loop bandwidth setting is 1/10 of the current loop bandwidth or lower. Optimal observer bandwidth is >2x the voltage loop bandwidth. |
| | Normal voltage ripple of 1...2% or approximately 7...15V. | Normal operation. |
| | External bus capacitance not entered correctly. | Enter the sum of all bus capacitance external to the regenerative bus supply into the Logix Designer application. See Calculate System and External-bus Capacitance on page 394 to calculate external bus capacitance. |

Table 130 - Regenerative Bus Supply Troubleshooting (continued)

| Condition | Potential Cause | Possible Resolution |
|--|---|--|
| Bus overvoltage on other converters sharing AC input with the regenerative bus supply as soon as DC-bus regulation is enabled. | Common mode current from regenerative bus supply interacting with common-mode filter capacitors in non-Kinetix 5700 drives. | Remove AC line filter or ground jumper from other non-Kinetix 5700 drives sharing the AC input with the regenerative bus supply. Additionally, properly sized input reactors can help reduce DC-bus pump-up on non-Kinetix 5700 drives. |
| Input overcurrent or ground current fault on non-Kinetix 5700 drives connected to the regenerative bus supply as soon as DC-bus regulation is enabled. | Single-axis inverters (catalog numbers 2198-S086-ERSx, 2198-S130-ERSx, 2198-S160-ERSx) firmware 10.3 or later is required. | Update the single-axis inverter firmware (catalog numbers 2198-S086-ERSx, 2198-S130-ERSx, 2198-S160-ERSx). |
| | Motor insulation breakdown. | Replace the motor. |
| DC bus voltage remains low (<50V) after the AC contactor closes and AC is present at the input to the regenerative bus supply. | DC-bus short circuit. | Find and resolve the DC-bus short circuit. |
| | Inverter internal short circuit. | <ul style="list-style-type: none"> Test regenerative bus supply with all inverters disconnected Replace the shorted inverter |
| | Inverter ground jumpers installed. | Remove inverter ground jumpers. |
| Actual DC bus voltage is not equal to the DC voltage set point in the Logix Designer application. | DC voltage set point too high. | Set the DC-bus voltage set point to a value <747V or use automatic mode. |
| | DC voltage set point too low. | Set the DC-bus voltage to a value > (input AC voltage rms • 1.414 • 1.05) or use automatic mode. |
| Startup draws excessive current from the AC input on DC-bus voltage regulation enable. | External bus capacitance entered incorrectly in the Logix Designer application. | Enter the sum of all bus capacitance external to the regenerative bus supply into the Logix Designer application. See Calculate System and External-bus Capacitance on page 394 to calculate external bus capacitance. |
| | Voltage rate limit set too high in the Logix Designer application. | Reduce the bus voltage rate limit in the Logix Designer application. |
| Current oscillations at no load. | Loop Response | Set the loop response to medium or low. |
| | Filter Bandwidth | Increase the filter bandwidth (if lower than 4x the voltage regulator bandwidth). |
| | Notch Frequency. | Increase the notch frequency bandwidth (if lower than 4x the voltage regulator bandwidth). |
| | Source kVA. | Set the source kVA to the actual kVA rating of the AC input transformer or input reactor. |
| AC current is limited to less than the peak rating of the regenerative bus supply. | Source kVA set too low. | Set the source kVA to the actual kVA rating of the AC input transformer or input reactor. |
| | Current loop vector limit set too low. | Set the current loop vector limit back to the default. |
| AC contactor won't close. | Stuck in configuring. | Check for messages on quick view pane of the controller organizer in the Logix Designer application. |
| | Contactor enable unplugged. | Plug in the contactor enable. |
| | AC contactor coil failure. | Replace contactor. |

Logix 5000 Controller and Drive Module Behavior

By using the Logix Designer application, you can configure how the Kinetix 5700 system responds when a module fault/exception occurs.

- TIP** The INIT FLT xxx faults are always generated after powerup, but before the drive is enabled, so the stopping behavior does not apply.
- NODE ALARM xxx faults do not apply because they do not trigger stopping behavior.
- For troubleshooting SAFE FLT fault codes, refer to [Chapter 9](#) on [page 314](#) (hardwired safety) or [page 323](#) (integrated safety).
- The iTRAK power supply cannot be configured by using the Studio 5000 Logix Designer application, but the pre-configured faults are shown on [page 288](#).

The DC-bus power supplies and servo drives support fault actions for Ignore, Alarm, Minor Fault, and Major Fault as defined in [Table 131](#). The drives also support five configurable stopping actions as defined in [Table 142](#).

Table 131 - Kinetix 5700 Module Exception Action Definitions

| Exception Action | Definition |
|------------------|--|
| Ignore | The drive module completely ignores the exception condition. For some exceptions that are fundamental to the operation of the planner, Ignore is not an available option. |
| Alarm | The drive module sets the associated bit in the Motion Alarm Status word, but does not otherwise affect axis behavior. Like Ignore, if the exception is so fundamental to the drive, Alarm is not an available option. When an exception action is set to Alarm, the Alarm goes away by itself when the exceptional condition has cleared. |
| Minor Fault | The drive module latches the exception condition, but the drive does not execute any exception action. |
| Major Fault | The drive module latches the exception condition and executes the configured exception action. |

You can configure exception behavior in the Logix Designer application from the Axis Properties dialog box, Actions category. These controller exception actions are mapped to the drive exception actions.

Table 132 - Logix Designer Exception Action Definitions

| Exception Action | Definition |
|--|---|
| Ignore | The controller completely ignores the exception condition. For some exceptions that are fundamental to the operation of the planner, Ignore is not an available option. |
| Alarm | The controller sets the associated bit in the Motion Alarm Status word, but does not otherwise affect axis behavior. Like Ignore, if the exception is so fundamental to the drive, Alarm is not an available option. When an exception action is set to Alarm, the Alarm goes away by itself when the exceptional condition has cleared. |
| Fault Status Only | Like Alarm, Fault Status Only instructs the controller to set the associated bit in the Motion Fault Status word, but does not otherwise affect axis behavior. However, unlike Alarm an explicit Fault Reset is required to clear the fault once the exceptional condition has cleared. Like Ignore and Alarm, if the exception is so fundamental to the drive, Fault Status Only is not an available option. |
| Stop Planner | The controller sets the associated bit in the Motion Fault Status word and instructs the Motion Planner to perform a controlled stop of all planned motion at the configured maximum deceleration rate. An explicit Fault Reset is required to clear the fault once the exceptional condition has cleared. If the exception is so fundamental to the drive, Stop Planner is not an available option. |
| StopDrive (v31 and earlier) Disable (v32 and later) | When the exception occurs, the associated bit in the Fault Status word is set and the axis comes to a stop by using the stopping action defined by the drive for the particular exception that occurred. In the event of a fault, there is no controller-based configuration to specify what the stopping action is. The stopping action is device dependent. |
| Shutdown | When the exception occurs, the drive brings the motor to a stop by using the stopping action defined by the drive (as in Stop Drive) and the power module is disabled. An explicit Shutdown Reset is required to restore the drive to operation. |

DC-bus Power Supply Behavior

Stopping action for exception fault codes does not apply to the DC-bus power supply. The StopDrive exception action for a DC-bus power supply means the power supply enters into a Major Fault state that opens the contactor-enable output, removing three-phase power from the Kinetix 5700 drive system. The Shutdown exception action exhibits the same behavior as Stop Drive, except the power supply enters into Shutdown as the final state and requires a Shutdown Reset to recover.

Fault actions are shown in [Table 133](#) and [Table 134](#).

TIP In the Logix Designer application, version 32 and later, Disable replaced StopDrive as the default Action.

Figure 137 - Logix Designer Axis Properties - Exceptions Category

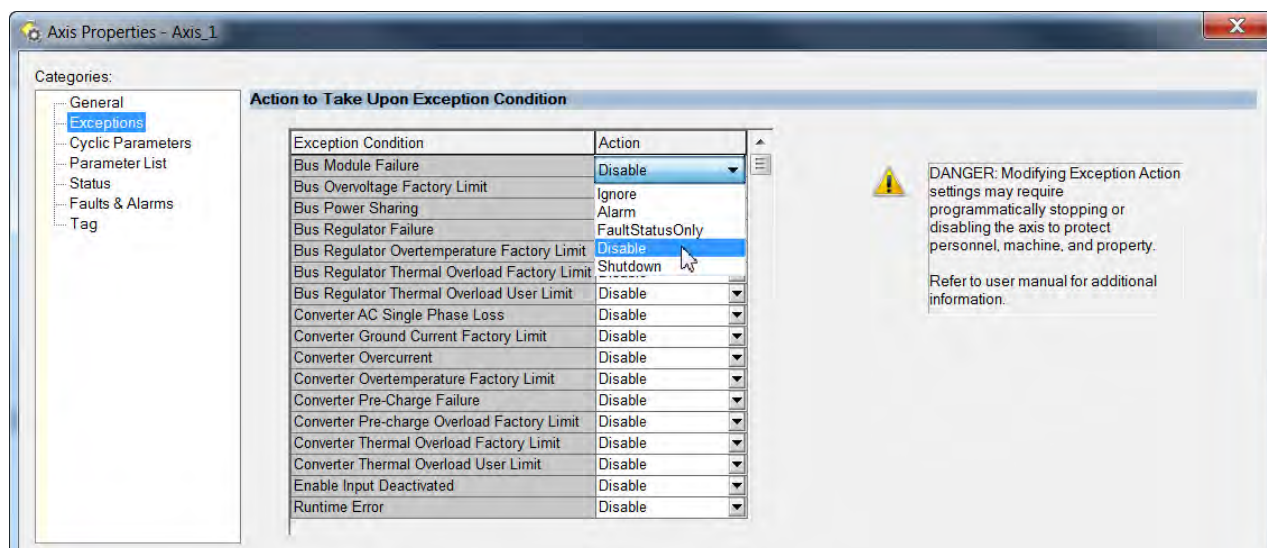


Table 133 - DC-bus Power Supply Behavior, FLT Sxx Fault Codes

| Exception Fault Code | Exception Text | Fault Action | | | |
|--|--|--------------|-------|-------------|-------------|
| | | Ignore | Alarm | Minor Fault | Major Fault |
| FLT S15 – CONV OVERCURRENT | Converter Overcurrent Fault | – | – | – | X |
| FLT S16 – GROUND CURRENT | Ground Current Factory Limit Fault | – | – | – | X |
| FLT S18 – CONV OVERTEMP FL | Converter OverTemp Factory Limit Fault | – | – | – | X |
| FLT S20 – CONV OVERLOAD FL | Converter Thermal OverLoad Factory Limit Fault | – | – | – | X |
| FLT S21 – CONV OVERLOAD UL | Converter Thermal Overload User Limit Fault | X | X | X | X |
| FLT S23 – AC PHASE LOSS | AC Single Phase Loss Fault | – | – | – | X |
| FLT S25 – PRECHARGE FAILURE | Precharge Failure Fault | – | – | – | X |
| FLT S27 – BUS REG OVERTEMP FL ⁽¹⁾ | Bus Regulator Overtemperature Factory Limit Fault | – | – | – | X |
| FLT S29 – BUS REG OVERLOAD FL | Bus Regulator Thermal OverLoad Factory Limit Fault | – | – | – | X |

Table 133 - DC-bus Power Supply Behavior, FLT Sxx Fault Codes (continued)

| Exception Fault Code | Exception Text | Fault Action | | | |
|--|---|--------------|-------|-------------|-------------|
| | | Ignore | Alarm | Minor Fault | Major Fault |
| FLT S30 – BUS REG OVERLOAD UL | Bus Regulator Thermal Overload User Limit Fault | X | X | X | X |
| FLT S31 – BUS REG FAILURE | Bus Regulator Failure | – | – | – | X |
| FLT S32 – BUS CAPACITOR MODULE FAILURE | Bus Capacitor Module Failure | X | X | X | X |
| FLT S35 – BUS OVERVOLT FL | Bus Overvoltage Factory Limit Fault | – | – | – | X |
| FLT S40 – BUS POWER SHARING FAULT | Bus Power Sharing Fault | – | – | – | X |
| FLT S61 – ENABLE INPUT | Enable Input Deactivated | – | – | – | X |

(1) Supported when shunt thermal switch is connected to the power supply digital input and configured in the Logix Designer application.

Table 134 - DC-bus Power Supply Behavior, FLT Mxx Fault Codes

| Exception Fault Code | Exception Text | Fault Action | | | |
|---|--|--------------|-------|-------------|-------------|
| | | Ignore | Alarm | Minor Fault | Major Fault |
| FLT M12 – POWER CYCLE FL ⁽¹⁾ | Converter Precharge Overload Factory Limit Fault | – | – | – | X |
| FLT M26 – RUNTIME ERROR | Runtime Error | – | – | – | X |

(1) Single-axis and dual-axis drives assert Bus Power Sharing Exception.

Table 135 - DC-bus Power Supply Behavior, NODE FLT Fault Codes

| Exception Fault Code | Exception Text | Permanent Magnet Motor | Induction Motor | Fault Action | | | | Best Available Stopping Action (applies to major faults) |
|------------------------------------|----------------------------------|------------------------|-----------------|--------------|-------|-------------|-------------|--|
| | | | | Ignore | Alarm | Minor Fault | Major Fault | |
| NODE FLT 01 – LATE CTRL UPDATE | Control Connection Update Fault | X | X | – | – | – | X | Decel/Disable |
| NODE FLT 02 – PROC WATCHDOG | Processor Watchdog Fault | X | X | – | – | – | X | Disable/Coast |
| NODE FLT 03 – HARDWARE | Hardware Fault | X | X | – | – | – | X | Disable/Coast |
| NODE FLT 05 – CLOCK SKEW FLT | Clock Skew Fault | X | X | – | – | – | X | Decel/Disable |
| NODE FLT 06 – LOST CTRL CONN | Lost Controller Connection Fault | X | X | – | – | – | X | Decel/Disable |
| NODE FLT 07 – CLOCK SYNC | Clock Sync Fault | X | X | – | – | – | X | Decel/Disable |
| NODE FLT 09 – DUPLICATE IP ADDRESS | Duplicate IP Address Fault | X | X | – | – | – | X | Disable/Coast |

Regenerative Bus Supply Behavior

Stopping action for exception fault codes does not apply to the regenerative bus supply. The Disable exception action for a regenerative bus supply means the power supply enters into a Major Fault state that opens the contactor-enable output, removing three-phase power from the Kinetix 5700 drive system. The Shutdown exception action exhibits the same behavior as Disable, except the power supply enters into Shutdown as the final state and requires a Shutdown Reset to recover.

Fault actions are shown in [Table 136](#) and [Table 137](#).

Figure 138 - Logix Designer Axis Properties - Exceptions Category

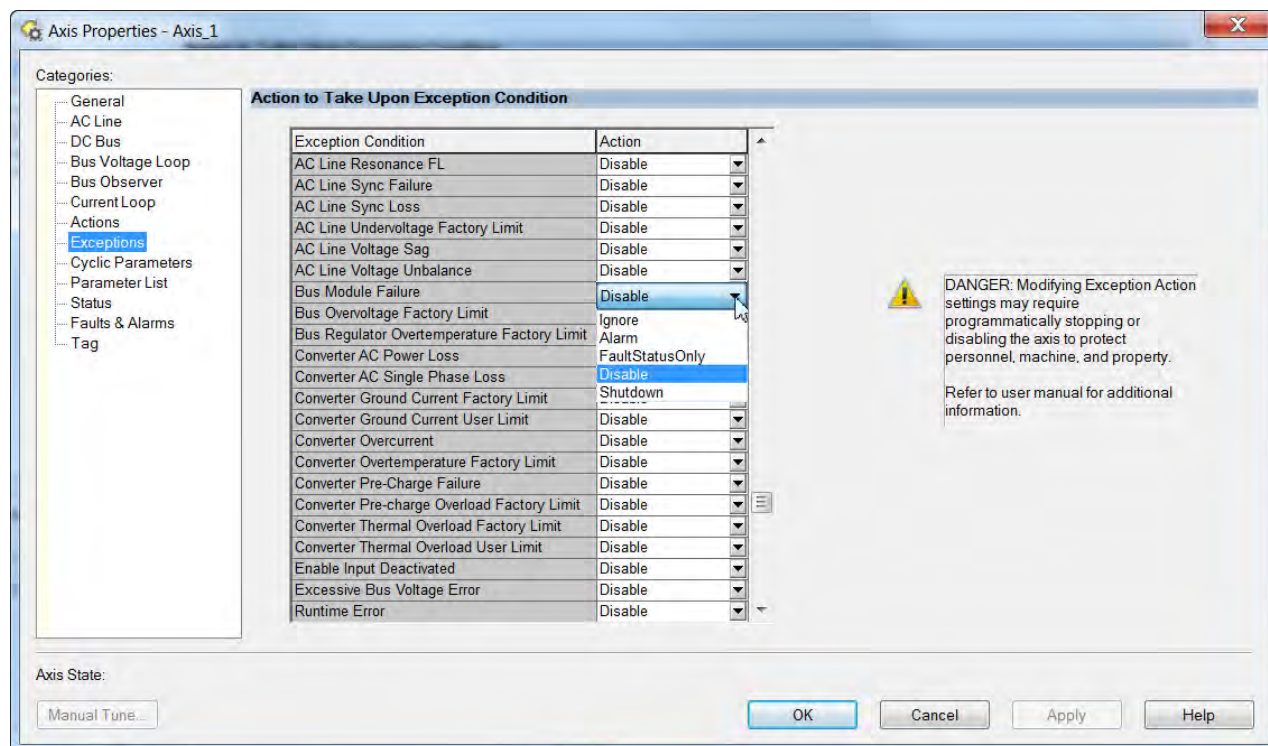


Table 136 - Regenerative Bus Supply Behavior, FLT Sxx Fault Codes

| Exception Fault Code | Exception Text | Fault Action | | | |
|--|--|--------------|-------|-------------|-------------|
| | | Ignore | Alarm | Minor Fault | Major Fault |
| FLT S15 – CONV OVERCURRENT | Converter Overcurrent Fault | – | – | – | X |
| FLT S16 – GROUND CURRENT | Ground Current Factory Limit Fault | – | – | – | X |
| FLT S17 – GROUND CURRENT UL ⁽¹⁾ | Ground Current User Limit Fault | X | X | X | X |
| FLT S18 – CONV OVERTEMP FL | Converter OverTemp Factory Limit Fault | – | – | – | X |
| FLT S20 – CONV OVERLOAD FL | Converter Thermal OverLoad Factory Limit Fault | – | – | – | X |
| FLT S21 – CONV OVERLOAD UL | Converter Thermal Overload User Limit Fault | X | X | X | X |
| FLT S22 – AC POWER LOSS | Converter AC Power Loss Fault | X | X | X | X |

Table 136 - Regenerative Bus Supply Behavior, FLT Sxx Fault Codes (continued)

| Exception Fault Code | Exception Text | Fault Action | | | |
|---|---|--------------|-------|-------------|-------------|
| | | Ignore | Alarm | Minor Fault | Major Fault |
| FLT S23 – AC PHASE LOSS | AC Single Phase Loss Fault | – | – | – | X |
| FLT S25 – PRECHARGE FAILURE | Precharge Failure Fault | – | – | – | X |
| FLT S27 – BUS REG OVERTEMP FL ⁽¹⁾ | Bus Regulator Overtemperature Factory Limit Fault | – | – | – | X |
| FLT S32 – BUS MODULE FAILURE | Bus Module Failure | X | X | X | X |
| FLT S35 – BUS OVERVOLT FL | Bus Overvoltage Factory Limit Fault | – | – | – | X |
| FLT S58 – EXCESSIVE BUS VOLTAGE ERROR | Excessive Bus Voltage Error | – | – | – | X |
| FLT S61 – ENABLE INPUT | Enable Input Deactivated | – | – | – | X |
| FLT S64 – AC LINE OVERVOLTAGE FL | AC Line Overvoltage FL | – | – | – | X |
| FLT S66 – AC LINE UNDER VOLTAGE FL ⁽²⁾ | AC Line Undervoltage FL | – | – | – | X |
| FLT S68 – AC LINE HIGH FREQUENCY FL | AC Line High Frequency FL | – | – | – | X |
| FLT S70 – AC LINE LOW FREQUENCY FL | AC Line Low Frequency FL | – | – | – | X |
| FLT S72 – AC LINE VOLTAGE UNBALANCE | AC Line Voltage Unbalance | – | – | – | X |
| FLT S73 – AC LINE CURRENT UNBALANCE | AC Line Current Unbalance | – | – | – | X |
| FLT S74 – AC LINE VOLTAGE SAG ⁽²⁾ | AC Line Voltage Sag | – | – | – | X |
| FLT S75 – AC LINE FREQUENCY CHANGE | AC Line Frequency Change | – | – | – | X |
| FLT S76 – AC LINE SYNCHRONIZATION LOSS ⁽²⁾ | AC Line Synchronization Loss | – | – | – | X |
| FLT S76 – AC LINE SYNCHRONIZATION FAILURE | AC Line Synchronization Failure | – | – | – | X |

(1) Supported when shunt thermal switch is connected to the power supply digital input and configured in the Logix Designer application.

(2) A single or three-phase open circuit can result in a number of different faults depending on the converter loading.

Table 137 - Regenerative Bus Supply Behavior, FLT Mxx Fault Codes

| Exception Fault Code | Exception Text | Fault Action | | | |
|---|--|--------------|-------|-------------|-------------|
| | | Ignore | Alarm | Minor Fault | Major Fault |
| FLT M12 – POWER CYCLE FL ⁽¹⁾ | Converter Precharge Overload Factory Limit Fault | – | – | – | X |
| FLT M26 – RUNTIME ERROR | Runtime Error | – | – | – | X |
| FLT M29 – AC LINE CONTACTOR | AC Line Contactor | – | – | – | X |
| FLT M30 – AC LINE RESONANCE FL | AC Line Resonance FL | – | – | – | X |

(1) Single-axis and dual-axis inverters assert Bus Power Sharing Exception.

iTRAK Power Supply Behavior

The iTRAK power supply exceptions behavior, as defined in [Table 138](#), is shown in the following tables.

Table 138 - iTRAK Power Supply Exception Action Definitions

| Exception Action | Definition |
|------------------|--|
| Hold | Continue regulating the iTRAK DC buses. |
| Disable | Actively discharge the iTRAK DC buses then disable the regulators. |
| Shutdown | Disable the regulators, iTRAK DC buses passively discharge. |

Table 139 - iTRAK Power Supply Behavior, FLT Sxx Fault Codes

| Exception Fault Code | Exception Text | Fault Action | | | | Stopping Action |
|---|--|--------------|-------|-------------|-------------|-----------------|
| | | Ignore | Alarm | Minor Fault | Major Fault | |
| FLT S15 – CONV OVERCURRENT ⁽¹⁾ | Converter Overcurrent Fault | – | – | – | X | Shutdown |
| FLT S18 - CONV OVERTEMP FL | Converter OverTemp Factory Limit Fault | – | – | – | X | Shutdown |
| FLT S20 - CONV OVERLOAD FL | Converter Thermal Overload Factory Limit Fault | – | – | – | X | Shutdown |
| FLT S21 – CONV OVERLOAD UL | Converter Thermal Overload User Limit Fault | X | X | X | X | Hold |
| FLT S25 - PRECHARGE FAILURE | Precharge Failure Fault | – | – | – | X | Shutdown |
| FLT S33 - BUS UNDERVOLT FL | Bus Undervoltage Factory Limit Fault | – | – | – | X | Shutdown |
| FLT S35 - BUS OVERVOLT FL | Bus Overvoltage Factory Limit Fault | – | – | – | X | Shutdown |
| FLT S38 - FUSE BLOWN | Bus Power Fuse Blown Fault | – | – | – | X | Shutdown |
| FLT S61 - ENABLE INPUT | Enable Input Deactivated | – | – | – | X | Disable |

(1) All modules in the same bus group assert a Bus Power Sharing Exception if they are enabled.

Table 140 - iTRAK Power Supply Behavior, FLT Mxx Fault Codes

| Exception Fault Code | Exception Text | Fault Action | | | | Stopping Action |
|-------------------------|----------------|--------------|-------|-------------|-------------|-----------------|
| | | Ignore | Alarm | Minor Fault | Major Fault | |
| FLT M26 - RUNTIME ERROR | Runtime Error | – | – | – | X | Shutdown |

Table 141 - iTRAK Power Supply Behavior, NODE FLT Fault Codes

| Exception Fault Code | Exception Text | Fault Action | | | | Stopping Action |
|------------------------------------|----------------------------|--------------|-------|-------------|-------------|-----------------|
| | | Ignore | Alarm | Minor Fault | Major Fault | |
| NODE FLT 02 - PROC | Processor Watchdog Fault | – | – | – | X | Shutdown |
| NODE FLT 03 - HARDWARE | Hardware Fault | – | – | – | X | Shutdown |
| NODE FLT 09 - DUPLICATE IP ADDRESS | Duplicate IP address Fault | – | – | – | X | Shutdown |

Inverter Behavior

For the single-axis inverters and dual-axis inverters, only selected exceptions are configurable. In the drive behavior tables, the controlling attribute is given for programmable fault actions.

Table 142 - Configurable Stopping Actions

| Stopping Action | Description |
|---------------------------------------|---------------|
| Ramped Decel & Hold ⁽¹⁾ | Most control |
| Current Decel & Hold | Most control |
| Ramped Decel & Disable ⁽¹⁾ | Less control |
| Current Decel & Disable | Less control |
| Disable & Coast ⁽²⁾ | Least control |

The best available stopping action is the one that maintains the most control over the motor. However, not all faults support every stopping action.

(1) Ramped Decel is available only when General > Axis Configuration is set to Velocity Loop or Frequency Control.

(2) When configured for Frequency Control (induction motors only), select Decel & Disable only when the Current Limiting feature is enabled. For more information on this feature, see [Current Limiting for Frequency Control](#) on [page 416](#).

Actions define the drive behavior in response to specific conditions. The Actions category includes Standard Actions and Safety Actions.

Table 143 - Actions Definitions

| Action Category | Action Name | Action Trigger Condition | Available Actions |
|-----------------|---------------------------------|---|---|
| Standard | Disable (MSF) Stopping Action | Execution of an MSF motion instruction. | <ul style="list-style-type: none"> • Ramped Decel & Hold • Current Decel & Hold • Ramped Decel & Disable • Current Decel & Disable • Disable & Coast |
| | Connection Loss Stopping Action | Loss of the motion connection (for example, inhibiting the module or a network cable disconnect). | <ul style="list-style-type: none"> • Ramped Decel & Disable • Current Decel & Disable • Disable & Coast |
| | Motor Overload Action | Receiving MTR OVERLOAD fault. | <ul style="list-style-type: none"> • Current Foldback • None |
| | Inverter Overload Action | Receiving INV OVERLOAD fault. | <ul style="list-style-type: none"> • Current Foldback • None |
| Safety | Safe Torque Off Action | Transition from logic 0 to 1 of the SafeTorqueOffActiveStatus axis tag, which indicates a safe torque-off action was commanded (STO). ⁽¹⁾ | <ul style="list-style-type: none"> • Ramped Decel & Disable • Current Decel & Disable • Disable & Coast |
| | Safe Stopping Action | Transition from logic 0 to 1 of the SS1ActiveStatus or SS2ActiveStatus axis tag which indicates a safe stopping action was commanded (SS1, SS2). ⁽²⁾ | <ul style="list-style-type: none"> • Ramped Decel ⁽³⁾ • Current Decel |

(1) This action is executed only if the axis tag transitions due to a requested STO, not if it was triggered by another safe-stop function (SS1, for example).

(2) See Knowledgebase document [1086747](#) for more information.

(3) Applies to only Velocity Control mode.

Standard Actions

When a controller connection loss (NODE FLT 06) occurs, it is possible with firmware revision 9.xxx that other node faults can occur first, triggering a fault action of Current Decel & Disable. Without knowing if NODE FLT 06 will occur first on a connection loss fault, we recommend that you do not change the default connection loss setting of Current Decel & Disable.

TIP Use DLR ring topology (see [Ring Topology](#) on [page 31](#)) for applications where the possibility of connection loss must be minimized.

Safety Actions

The Action Source pull-down menus include Connected Drive mode and Running Controller mode.

When configured for Connected Drive (default), the drive initiates the stopping sequence according to the selected stopping action. However, the drive must have an open connection to the motion controller for the configured stopping action to occur.

When configured for Running Controller and the controller is in Run mode, the stopping sequence is controlled by your application program in the motion controller. This provides flexibility based on your application and requires that your program provide the desired action in response to the safety function active status. If no logic is created, no stopping action will occur. If the motion controller is in Program mode (not actively running the application program), the drive ignores the Action Source and initiates the configured stopping sequence according to the corresponding Action selected in the pull-down menu.

Figure 139 - Logix Designer Axis Properties - Actions Category

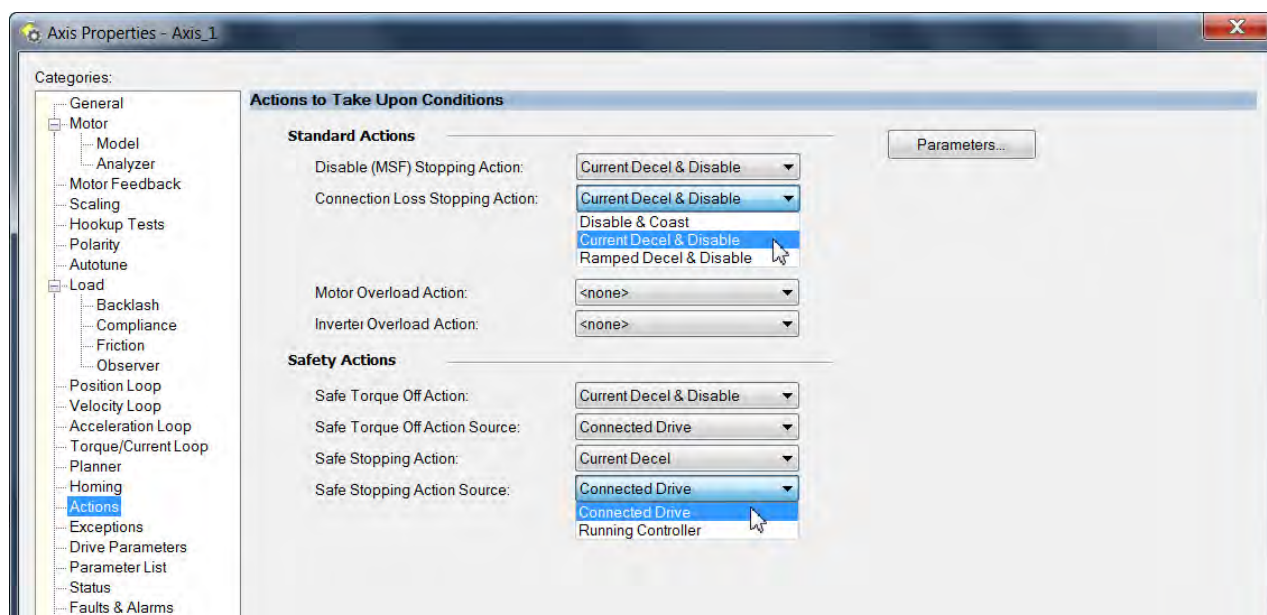


Table 144 - Drive Behavior, FLT Sxx Fault Codes

| Exception Fault Code | Exception Text | Inverter Modules 2198-xxxx | Permanent Magnet Motor | Induction Motor | Fault Action | | | | Best Available Stopping Action (applies to major faults) |
|--|---|-----------------------------------|------------------------|-----------------|--------------|-------|-------------|-------------|---|
| | | | | | Ignore | Alarm | Minor Fault | Major Fault | |
| FLT S02 – MTR COMMUTATION | Motor Commutation Fault | -ERSx | X | – | – | – | – | X | Disable/Coast |
| FLT S03 – MTR OVERSPEED FL | Motor Overspeed Factory Limit Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT S04 – MTR OVERSPEED UL | Motor Overspeed User Limit Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S05 – MTR OVERTEMP FL | Motor Overtemperature Factory Limit Fault | -ERS3 (series A) | X | – | – | – | – | – | Disable/Coast |
| | Motor Overtemperature Factory Limit Fault (If #589 vertical load control) | -ERS4 | | X | – | – | – | – | Current Decel/Disable |
| | Motor Overtemperature Factory Limit Fault (If not #589 vertical load control) | | | | – | – | – | – | Disable/Coast |
| FLT S07 – MTR OVERLOAD FL | Motor Thermal Overload Factory Limit Fault | -ERS3 (series A) | X | X | – | – | – | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | | | – | – | – | | Ramped Decel ⁽⁵⁾ /Disable |
| FLT S08 – MTR OVERLOAD UL | Motor Thermal OverLoad User Limit Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S09 – MTR PHASE LOSS | Motor Phase Loss | -ERSx | X | – | X | X | X | X | Disable/Coast |
| FLT S10 – INV OVERCURRENT | Inverter Overcurrent Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT S11 – INV OVERTEMP FL | Inverter Overtemperature Factory Limit Fault | -ERS3 (series A) | X | X | – | – | – | X | Disable/Coast |
| | Inverter Overtemperature Factory Limit Fault (If #589 vertical load control) | -ERS4 | | | – | – | – | | Current Decel/Disable |
| | Inverter Overtemperature Factory Limit Fault (If not #589 vertical load control) | | | | – | – | – | | Disable/Coast |
| FLT S13 – INV OVERLOAD FL | Inverter Thermal Overload Factory Limit Fault | -ERS3 (series A) | X | X | – | – | – | X | Disable/Coast |
| | | -ERS4 | | | – | – | – | | Current Decel/Disable |
| FLT S14 – INV OVERLOAD UL | Inverter Thermal Overload User Limit Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S16 – GROUND CURRENT | Ground Current Factory Limit Fault | -ERSx Single-axis inverters | X | X | – | – | – | X | Disable/Coast |
| FLT S22 – AC POWER LOSS | Converter AC Power Loss Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Disable |
| FLT S27 – BUS REG OVERTEMP FL ⁽¹⁾ | Bus Regulator Overtemperature Factory Limit Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT S32 – BUS CAPACITOR MODULE FAILURE | Bus Capacitor Module Failure | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S33 – BUS UNDERVOLT FL | Bus Undervoltage Factory Limit Fault | -ERS3 (series A) | X | X | – | – | – | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | X | X | – | – | – | X | Ramped Decel ⁽⁵⁾ /Disable |
| FLT S34 – BUS UNDERVOLT UL | Bus Undervoltage User Limit Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S35 – BUS OVERVOLT FL | Bus Overvoltage Factory Limit Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |

Table 144 - Drive Behavior, FLT Sxx Fault Codes (continued)

| Exception Fault Code | Exception Text | Inverter Modules 2198-xxxx | Permanent Magnet Motor | Induction Motor | Fault Action | | | | Best Available Stopping Action (applies to major faults) |
|--|---|-------------------------------|------------------------|-----------------|--------------|-------|-------------|-------------|---|
| | | | | | Ignore | Alarm | Minor Fault | Major Fault | |
| FLT S37 – BUS POWER LOSS | Bus Power Loss | -ERS3 (series A) | X | X | X | X | X | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Disable |
| FLT S38 – FUSE BLOWN | Bus Power Fuse Blown Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT S40 – BUS POWER SHARING FAULT | Bus Power Sharing Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Disable |
| FLT S41 – MTR AQB STATE FL | Feedback Signal Noise FL | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT S43 – FDBK LOSS FL ^{(2) (4)} | Feedback Signal Loss FL | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT S44 – FDBK LOSS UL ^{(2) (4)} | Feedback Signal Loss UL | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S45 – FDBK COMM FL ^{(3) (4)} | Motor Feedback Data Loss Factory Limit Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT S46 – FDBK COMM UL ^{(2) (4)} | Motor Feedback Data Loss User Limit Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S47 – FDBK DEVICE FAILURE | Feedback Device Failure | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT S49 – BRAKE SLIP FLT | Brake Slip Exception | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S50 – POS HW OTRAVEL | Hardware Overtravel - Positive | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S51 – NEG HW OTRAVEL | Hardware Overtravel - Negative | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S54 – POSN ERROR ⁽⁴⁾ | Excessive Position Error Fault | -ERS3 (series A) | X | X | X | X | X | X | Disable/Coast |
| | Excessive Position Error Fault (If #589 vertical load control) | -ERS4 | | | | | | | Current Decel/Disable |
| | Excessive Position Error Fault (If not #589 vertical load control) | | | | | | | | Disable/Coast |
| FLT S55 – VEL ERROR ⁽⁴⁾ | Excessive Velocity Error Fault | -ERS3 (series A) | X | X | X | X | X | X | Disable/Coast |
| | Excessive Velocity Error Fault (If #589 vertical load control) | -ERS4 | | | | | | | Current Decel/Disable |
| | Excessive Velocity Error Fault (If not #589 vertical load control) | | | | | | | | Disable/Coast |
| FLT S56 – OVERTORQUE LIMIT ⁽⁴⁾ | Overtorque Limit Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S57 – UNDERTORQUE LIMIT ⁽⁴⁾ | Undertorque Limit Fault | -ERS3 (series A) | X | X | X | X | X | X | Decel/Hold |
| | | -ERS4 -ERS3 (series B) | | | | | | | Ramped Decel ⁽⁵⁾ /Hold |
| FLT S61 – ENABLE INPUT | Enable Input Deactivated | -ERS3 (series A) | X | X | X | X | X | X | Disable/Coast |
| | | -ERS4 | | | | | | | Ramped Decel ⁽⁵⁾ /Disable |

(1) Supported when shunt thermal switch is connected to the inverter digital input and configured in the Logix Designer application.

(2) Applies to all compatible feedback devices, except DSL encoder feedback.

(3) Applies to DSL and Hiperface feedback devices.

(4) Does not apply to induction motors in frequency control mode.

(5) Available only in Velocity Control mode. Available stopping action is Current Decel in Position Control mode.

Table 145 - Drive Behavior, FLT Mxx Fault Codes

| Exception Fault Code | Exception Text | Inverter Modules 2198-xxxx | Permanent Magnet Motor | Induction Motor | Fault Action | | | | Best Available Stopping Action (applies to major faults) |
|--|--|-------------------------------|------------------------|-----------------|--------------|-------|-------------|-------------|---|
| | | | | | Ignore | Alarm | Minor Fault | Major Fault | |
| FLT M02 – MOTOR VOLTAGE ⁽¹⁾ | Motor Voltage Mismatch Fault | -ERSx | X | X | X | X | X | X | Disable/Coast |
| FLT M07 – FEEDBACK INCREMENTAL COUNT ERROR FAULT | Feedback Incremental Count Error Fault | -ERSx | X | X | X | X | X | X | Disable/Coast |
| FLT M26 – RUNTIME ERROR | Runtime Error | -ERSx | X | X | – | – | – | X | Disable/Coast |
| FLT M28 – SAFETY COMM ⁽²⁾ | Safety Module Communication Error | -ERSx | X | X | – | – | – | X | Disable/Coast |

(1) Does not apply to induction motors in frequency control mode.

(2) Applies to drives in Integrated STO mode.

Table 146 - Drive Behavior, NODE FLT Fault Codes

| Exception Fault Code | Exception Text | Inverter Modules 2198-xxxx | Permanent Magnet Motor | Induction Motor | Fault Action | | | | Best Available Stopping Action (applies to major faults) |
|------------------------------------|----------------------------------|-------------------------------|------------------------|-----------------|--------------|-------|-------------|-------------|---|
| | | | | | Ignore | Alarm | Minor Fault | Major Fault | |
| NODE FLT 01 – LATE CTRL UPDATE | Control Connection Update Fault | -ERS3 (series A) | X | X | – | – | – | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | | | – | – | – | | Ramped Decel ⁽¹⁾ /Disable |
| NODE FLT 02 – PROC WATCHDOG | Processor Watchdog Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |
| NODE FLT 03 – HARDWARE | Hardware Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |
| NODE FLT 05 – CLOCK SKEW FLT | Clock Skew Fault | -ERS3 (series A) | X | X | – | – | – | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | | | – | – | – | | Ramped Decel ⁽¹⁾ /Disable |
| NODE FLT 06 – LOST CTRL CONN | Lost Controller Connection Fault | -ERS3 (series A) | X | X | – | – | – | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | | | – | – | – | | Programmable per ⁽²⁾ Connection Loss Stopping Action (see Table 143 on page 289). |
| NODE FLT 07 – CLOCK SYNC | Clock Sync Fault | -ERS3 (series A) | X | X | – | – | – | X | Decel/Disable |
| | | -ERS4 -ERS3 (series B) | | | – | – | – | | Ramped Decel ⁽¹⁾ /Disable |
| NODE FLT 09 – DUPLICATE IP ADDRESS | Duplicate IP Address Fault | -ERSx | X | X | – | – | – | X | Disable/Coast |

(1) Available only in Velocity Control mode. Available stopping action is Current Decel in Position Control mode.

(2) With firmware revision 9.xxx. Do not change the default stopping action.

Notes:

Remove and Replace Drive Modules

This chapter provides remove and replace procedures for Kinetix® 5700 drive modules.

| Topic | Page |
|---|------|
| Before You Begin | 295 |
| Remove and Replace Kinetix 5700 Drive Modules | 296 |
| Start and Configure the Drive Module | 302 |



ATTENTION: This drive contains electrostatic discharge (ESD) sensitive parts and assemblies. You are required to follow static-control precautions when you install, test, service, or repair this assembly. If you do not follow ESD control procedures, components can be damaged. If you are not familiar with static control procedures, refer to Guarding Against Electrostatic Damage, publication [8000-4.5.2](#), or any other applicable ESD awareness handbook.

Before You Begin

When each drive module is installed, network settings are configured from the setup screens. Before removing the module, revisit the Network menu and make note of the static IP or DHCP settings. Refer to [Configure the Drive](#) on [page 198](#) to access those settings.

IMPORTANT If you intend to use the same Logix Designer application after replacing your drive module, the new module must be the same catalog number as the old module.

You also need these tools available before you begin removal and replacement procedures:

- Screwdrivers (to loosen/remove screws)
- Voltmeter (to make sure that no voltage exists on drive connectors)

Remove and Replace Kinetix 5700 Drive Modules

Follow these steps to remove and replace DC-bus power supplies, regenerative bus supplies, dual-axis inverters, single-axis inverters, iTRAK® power supplies, or accessory modules from the system panel.

Remove Power and All Connections

1. Verify that all control and input power has been removed from the system.



ATTENTION: To avoid shock hazard or personal injury, make sure that all power has been removed before proceeding. This system can have multiple sources of power. More than one disconnect switch can be required to de-energize the system.

2. Wait 5 minutes for the DC bus to discharge completely before proceeding.



SHOCK HAZARD: This product contains stored energy devices. To avoid the hazard of electrical shock, verify that voltage on capacitors has been discharged before attempting to service, repair, or remove this unit. Do not attempt the procedures in this document unless you are qualified to do so and are familiar with solid-state control equipment and the safety procedures in publication NFPA 70E.

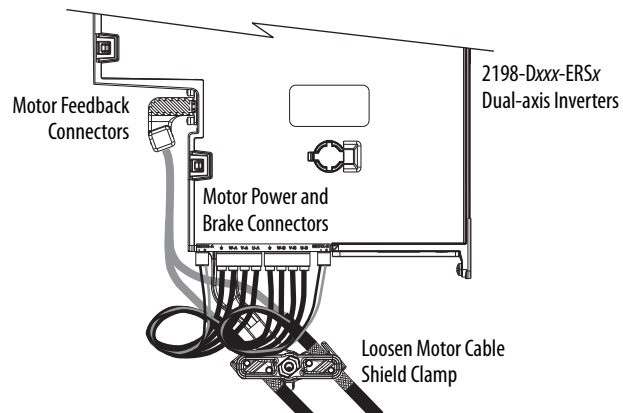
3. Using a voltmeter, verify that the DC-bus voltage has discharged, and for iTRAK power supply, verify that the output bus (ICP and IDC connectors) has discharged.
4. Label and remove all wiring connectors from the module that you are removing.

To identify each connector, refer to [Kinetix 5700 Connector Data](#) on [page 94](#).

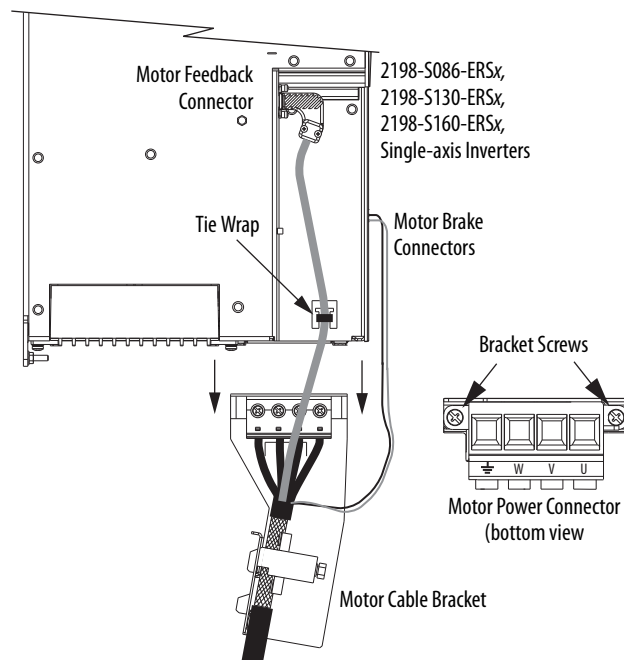
TIP For 2198-Pxxx DC-bus power supplies, you do not need to remove the shunt (RC) connector, unless there is an external shunt wired to it.

5. Unplug the DC-bus links and end caps from on top of the power supply, inverters, and accessory modules you are removing.
6. Unplug the shared-bus 24V input wiring connector, T-connectors, and bus-bars from on top of the drive module that you are removing (if applicable).

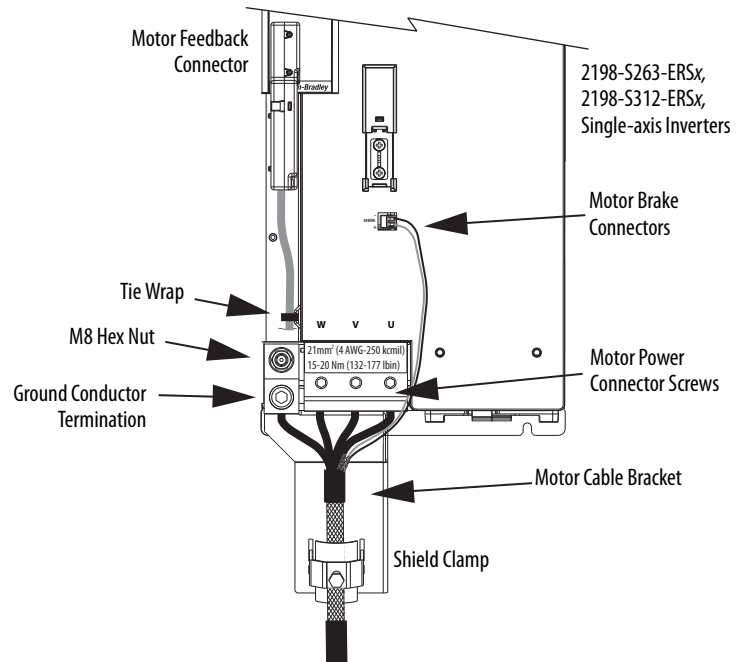
7. For 2198-Dxxx-ERSx dual-axis inverters, unplug the motor feedback, motor power, and motor brake connectors and loosen the shield clamp until you can remove the cable from the clamp.



8. Single-axis inverters differ by catalog number in how the motor cable bracket attaches to the drive, when the bracket is used.
 - a. For 2198-S086-ERSx, 2198-S130-ERSx, and 2198-S160-ERSx single-axis inverters, unplug the motor feedback and brake connectors, remove the tie wrap, and remove the motor power bracket.



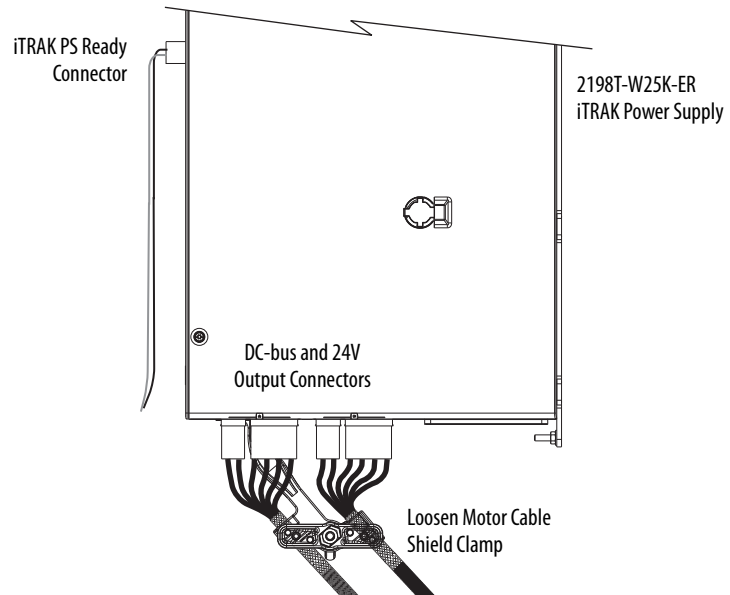
- b. For 2198-S263-ERS \times and 2198-S312-ERS \times single-axis inverters, unplug the motor feedback and brake connectors, and remove the tie wrap holding the feedback cable.



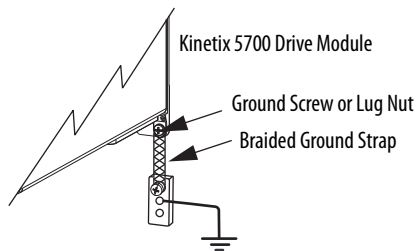
If your axis uses 2090-CPBM7DF power/brake (2 or 4 AWG) cable, remove the motor power cable and bracket from the drive (do not loosen the shield clamp). Refer to the steps and illustrations on [page 170](#) to see how the bracket is attached.

If your axis uses customer-supplied cable (larger than 2 or 4 AWG), the motor cable bracket does not apply.

9. For 2198T-W25K-ER iTRAK power supplies, unplug the iPS ready connector, 24V control power output connectors, and DC-bus output connectors.
10. Loosen the shield clamp until you can remove the cable from the clamp.



11. Remove the ground screw or lug nut and braided ground strap.



Remove the Drive Module

You can remove DC-bus power supplies, regenerative bus supplies, dual-axis inverters, single-axis inverters, iTRAK power supplies, or accessory modules from the panel in any configuration by using the same procedure.

IMPORTANT This procedure applies to any Kinetix 5700 drive module in any configuration.

Follow these steps to remove Kinetix 5700 drive modules from the panel.

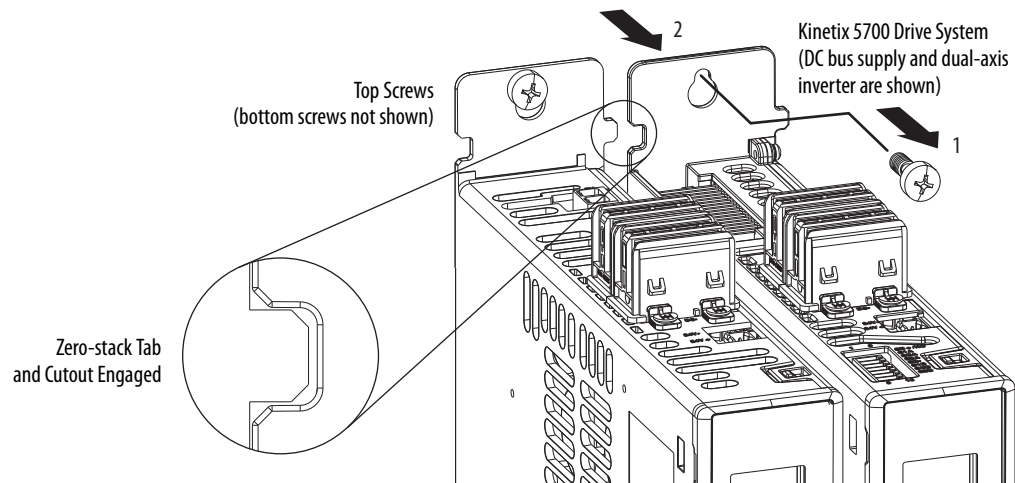
1. Loosen the top and bottom screws of the module you are removing.

Modules with 55 mm width have one top and bottom screw. Two or more top and bottom screws are present on modules of greater width.

2. Handling and positioning of the 2198-RPxxx regenerative bus supply and all other Kinetix 5700 drive modules, varies by catalog number.

Follow these steps to lift and remove the modules.

- a. For the 2198-RP088 regenerative bus supply and all other Kinetix 5700 drive modules, grasp the top and bottom of the module with both hands and pull the module straight out and away from the panel, clearing the zero-stack mounting tabs and cutouts.



- b. For the 2198-RP200, 2198-RP263, and 2198-RP312, modules, a hoist, straps, and J-hooks with a lockable clasp capable of supporting the maximum module weight is required to lift the module off the mounting screws and away from the panel.

For lifting instructions, see the Kinetix 5700 Regenerative Bus Supply Installation Instructions, publication [2198-IN014](#).

Replace the Drive Module

To replace the drive module, reverse the steps that are shown above or refer to [Mount Your Kinetix 5700 Drive Modules](#) on [page 90](#).

Table 147 - Drive Module Torque Values

| Kinetix 5700 Drive Module Cat. No. | Fasteners | Torque Value N•m (lb•in) |
|--|-------------------------------|-----------------------------|
| All Kinetix 5700 Bulletin 2198-drive modules | Module mounting screws | 4.0 (35.4) |
| | Module ground lug | |
| 2198-Pxxx, 2198-RP088, 2198-RP200 | Input power connector screws | 0.8 (7.1) |
| 2198-RP263, 2198-RP312 | | 15...20 (132...177) |
| | Input power ground screw | 5.6 (50.0) |
| 2198-Sxxx-ERSx | Shield clamp screw | 5.6 (50.0) |
| 2198-Dxxx-ERSx, 2198-Sxxx-ERSx | Feedback connector kit screws | 0.4 (3.5) |
| 2198-S086-ERSx, 2198-S130-ERSx, 2198-S160-ERSx | Motor power bracket screws | 0.8 (7.1) |
| 2198-S263-ERSx, 2198-S312-ERSx | Motor power connector screws | 15...20 (132...177) |
| | Motor power ground screw | 5.6 (50.0) |

If replacing a drive module that was configured for Integrated STO mode, refer to [Understand Integrated Safety Drive Replacement](#) on [page 330](#).

Start and Configure the Drive Module

Follow these steps to configure the replacement module.

IMPORTANT If you intend to use the same Logix Designer application after replacing your drive module, the new module must be the same catalog number as the old module.

IMPORTANT If a servo drive was previously configured by a safety controller, reset the drive to the Out of Box state. Refer to [Out of Box State](#) on [page 308](#).

1. Reapply power to the drive system.

Refer to [Apply Power to the Kinetix 5700 Drive System](#) on [page 263](#) for the procedure.

2. Configure the network settings for the drive module.

For example, if your old module was configured as Static IP, you must set the IP address, gateway, and subnet mask in the new module identical to the old module.

Refer to [Configure the Drive](#) on [page 198](#) to access those settings.

3. If you are replacing a 2198-xxxx-ERS3 (series A) drive with a 2198-xxxx-ERS3 (series B) drive, see [Replacing 2198-xxxx-ERS3 \(series A\) Drives with Series B Drives](#) for more information.
4. Download the Logix Designer application to the controller.
5. Verify that the drive system is working properly.

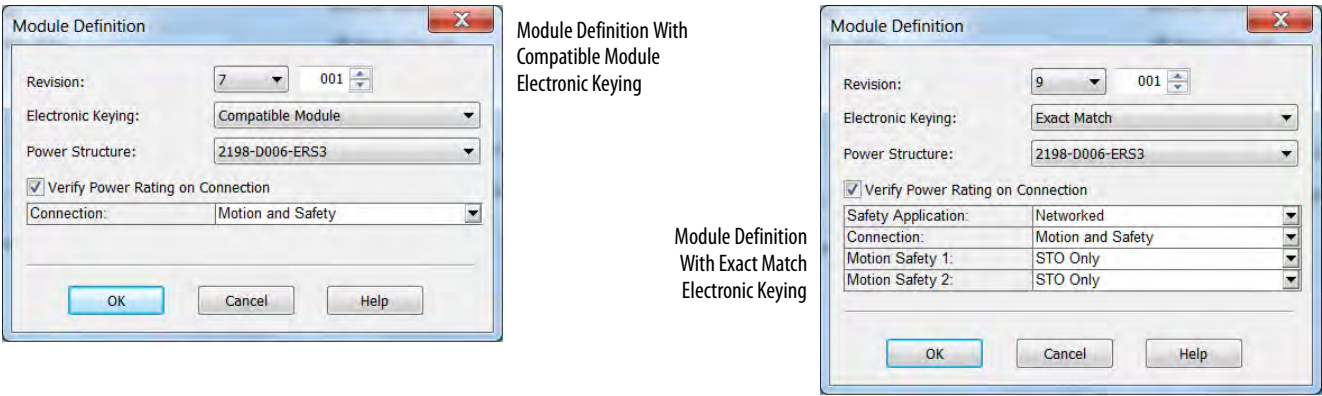
Replacing 2198-xxxx-ERS3 (series A) Drives with Series B Drives

When replacing a 2198-xxxx-ERS3 (series A) drive with a 2198-xxxx-ERS3 (series B) drive, the procedure depends on how Electronic Keying is configured in the Module Definition.

IMPORTANT If Electronic Keying in the Module Definition is configured for Exact Match, the following guidelines apply:

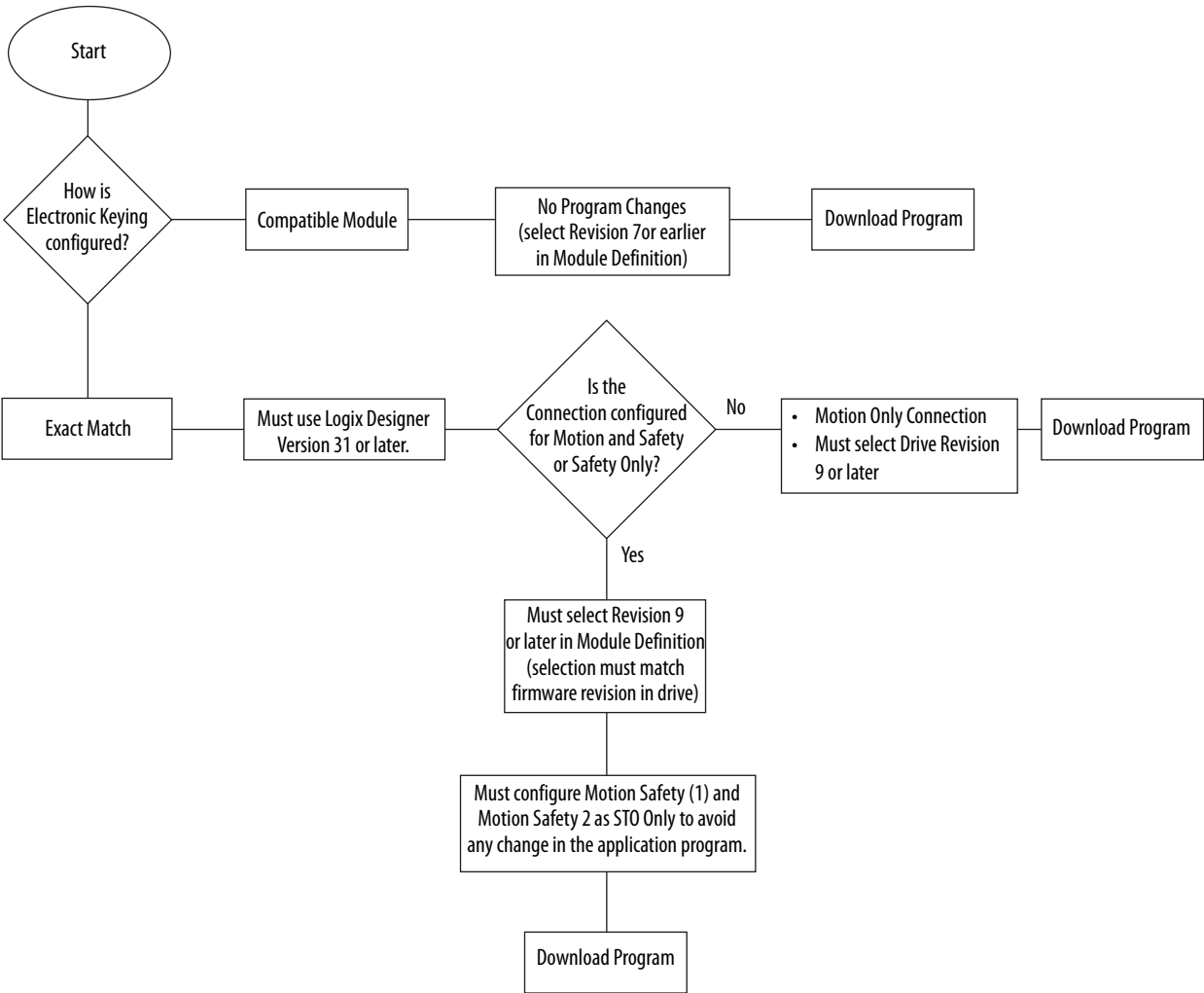
- The Module Definition Revision level must match the 2198-xxxx-ERS3 (series B) drive firmware (revision 9 or later)
- For backwards compatibility with series A drives, Motion Safety in the Module Definition of the 2198-xxxx-ERS3 (series B) drive must be configured for STO Only

Figure 140 - Module Definition for 2198-xxxx-ERS3 (series B) drives



In this flowchart, a 2198-xxxx-ERS3 series A drive (with drive firmware revision 7 or earlier) was programmed by using Studio 5000 Logix Designer®, version 30 or earlier, and is replaced by a 2198-xxxx-ERS3 series B drive (with drive firmware revision 9 or later).

Figure 141 - 2198-xxxx-ERS3 (series B) Replacement Drive Flowchart



Notes:

Kinetix 5700 Safe Torque-off Function

Use this chapter to become familiar with the safe torque-off functionality built into Kinetix® 5700 dual-axis and single-axis inverters.

| Topic | Page |
|----------------------------|------|
| Overview | 305 |
| Hardwired Safe Torque-off | 314 |
| Integrated Safe Torque-off | 323 |

Overview

The Kinetix 5700 dual-axis and single-axis inverters are equipped for hardwired safe torque-off (STO). Hardwired STO mode, as described in this chapter, applies to 2198-xxxx-ERS3 and 2198-xxxx-ERS4 dual-axis and single-axis inverters.

The Kinetix 5700 dual-axis and single-axis inverters are also equipped for integrated safe torque-off (STO) over the EtherNet/IP™ network. Integrated STO mode, as described in this chapter, applies to 2198-xxxx-ERS3 and 2198-xxxx-ERS4 dual-axis and single-axis inverters.

The integrated Monitored SS1 and Timed SS1 stopping functions are supported by the 2198-Dxxx-ERS4 dual-axis and 2198-Sxxx-ERS4 single-axis inverters. For integrated Monitored SS1 and Timed SS1 stopping function operations, see the Kinetix 5700 Safe Monitor Functions Safety Reference Manual, publication [2198-RM001](#).

Table 148 - Kinetix 5700 Functional Safety Mode Support

| Safety Mode | Dual-axis Inverters Cat. No. | Single-axis Inverters Cat. No. |
|---------------------------------|---------------------------------|-----------------------------------|
| Hardwired STO mode | 2198-Dxxx-ERS3 | 2198-Sxxx-ERS3 |
| | 2198-Dxxx-ERS4 | 2198-Sxxx-ERS4 |
| Integrated STO mode | 2198-Dxxx-ERS3 | 2198-Sxxx-ERS3 |
| | 2198-Dxxx-ERS4 | 2198-Sxxx-ERS4 |
| Monitored SS1 stopping function | 2198-Dxxx-ERS4 | 2198-Sxxx-ERS4 |
| Timed SS1 stopping function | 2198-Dxxx-ERS4 | 2198-Dxxx-ERS4 |
| | 2198-Dxxx-ERS3 (series B) | 2198-Sxxx-ERS3 (series B) |

The hardwired and integrated STO modes and SS1 stopping functions meet the requirements of Performance Level e (PL e) per ISO 13849-1 and SIL CL 3 per IEC 61508, IEC 61800-5-2 and IEC 62061.

Certification

The TÜV Rheinland group has approved 2198-Dxxx-ERSx and 2198-Sxxx-ERSx inverters with hardwired and integrated safe torque-off for use in safety-related applications up to ISO 13849-1 Performance Level e (PL e), SIL CL 3 per IEC 61508, IEC 61800-5-2, and IEC 62061, in which removing the motion producing power is considered to be the safe state.

For product certifications currently available from Rockwell Automation, go to rok.auto/certifications.

Important Safety Considerations

The system user is responsible for the following:

- Validation of any sensors or actuators connected to the system
- Completing a machine-level risk assessment
- Certification of the machine to the desired ISO 13849 performance level or IEC 62061 SIL level
- Project management and proof testing in accordance with ISO 13849

Stop Category Definition

Stop Category 0 as defined in IEC 60204 or safe torque-off as defined by IEC 61800-5-2 is achieved with immediate removal of motion producing power to the actuator.

| | |
|------------------|--|
| IMPORTANT | In the event of a malfunction, the most likely stop category is Stop Category 0. When designing the machine application, timing and distance must be considered for a coast to stop. For more information regarding stop categories, refer to IEC 60204-1. |
|------------------|--|

Performance Level (PL) and Safety Integrity Level (SIL)

For safety-related control systems, Performance Level (PL), according to ISO 13849-1, and SIL levels, according to IEC 61508 and IEC 62061, include a rating of the systems ability to perform its safety functions. All of the safety-related components of the control system must be included in both a risk assessment and the determination of the achieved levels.

Refer to the ISO 13849-1, IEC 61508, and IEC 62061 standards for complete information on requirements for PL and SIL determination.

Average Frequency of a Dangerous Failure

Safety-related systems are classified as operating in a High-demand/continuous mode. The SIL value for a High-demand/continuous mode safety-related system is directly related to the probability of a dangerous failure per hour (PFH).

PFH calculation is based on the equations from IEC 61508 and show worst-case values. [Table 149](#) provides data for a 20-year proof test interval and demonstrates the worst-case effect of various configuration changes on the data.

IMPORTANT Determination of safety parameters is based on the assumptions that the system operates in High-demand mode and that the safety function is requested at least once every three months.

Table 149 - PFH for 20-year Proof Test Interval (STO function)

| Attribute | 2198-xxxx-ERS3 Single-axis Inverters | 2198-Dxxx-ERS3 Dual-axis Inverters |
|---|---|---------------------------------------|
| PFH (1e-9) | 1.57 | 1.64 |
| HFT (hardware fault tolerance) ⁽¹⁾ | 1 | 1 |
| Proof test (years) | 20 | 20 |

(1) Hardware fault tolerance is the minimum number of faults that can cause a loss of the safety function as defined by IEC 61508-2.

Safe Torque-off Feature

The safe torque-off (STO) circuit, when used with suitable safety components, provides protection according to ISO 13849-1 (PL e), according to IEC 61508, IEC 61800-5-2, and IEC 62061 (SIL CL 3). All components in the system must be chosen and applied correctly to achieve the desired level of operator safeguarding.

The 2198-xxxx-ERS3 and 2198-xxxx-ERS4 STO circuit is designed to turn off all of the output-power transistors when the STO function is requested. You can use the 2198-xxxx-ERSx STO circuit in combination with other safety devices to achieve a Stop Category 0 stop as described in [Stop Category Definition](#) on [page 306](#), and protection-against-restart as specified in IEC 60204-1.



ATTENTION: The safe torque-off (STO) feature is suitable only for performing mechanical work on the drive system or affected area of a machine. It does not provide electrical safety.



SHOCK HAZARD: In Safe Torque-off mode, hazardous voltages can still be present at the drive. To avoid an electric shock hazard, disconnect power to the system and verify that the voltage is zero before performing any work on the drive.



ATTENTION: Personnel responsible for the application of safety-related programmable electronic systems (PES) shall be aware of the safety requirements in the application of the system and shall be trained in using the system.

Out of Box State

Kinetix 5700 servo drives are capable of safe torque-off (STO) functionality in Hardwired STO mode or Integrated STO mode. Out of the box, the Kinetix 5700 servo drives are in Hardwired STO mode, which means they are ready for hardwired connections to the safety (STO) connector. To bypass the hardwired safety function, jumper wires must be installed in the STO connector.

IMPORTANT Out of the box, Kinetix 5700 servo drives are in Hardwired STO mode.

IMPORTANT To bypass the STO feature while commissioning or testing the drive, the drive must be configured for Hardwired STO mode. Refer to [Safe Torque-off Feature Bypass](#) on [page 321](#) for a wiring example.

Out of the box, you can use Kinetix 5700 servo drives in Integrated STO mode only after a Motion and Safety or Safety-only connection has been established at least once in the Logix Designer application.

How to Recognize Hardwired STO Mode

You can read the safety control state from the axis tag AxisSafetyState, or by using an MSG command in the Logix Designer application to read the Safety Supervisor status.

In Hardwired STO mode, if STO inputs are OFF then Safety Supervisor state is Not Configured (8) and if STO inputs are ON then Safety Supervisor state is Not Configured, torque permitted (51).

Table 150 - Safety Supervisor States

| Value | Safety Supervisor State | Definition | Safety Mode |
|-------|-----------------------------------|--|----------------------------|
| 2 | Configured (no safety connection) | No active connections | Integrated |
| 4 | Running | Normal running state | Integrated |
| 7 | Configuring | Transition state | Integrated |
| 8 | Not Configured | Hardwired STO mode with torque disabled | Hardwired (out of the box) |
| 51 | Not Configured (torque permitted) | Hardwired STO mode with torque permitted | Hardwired (out of the box) |
| 52 | Running (torque permitted) | STO bypass state | Integrated |

Restore the Hardwired STO Mode by Using the Logix Designer Application

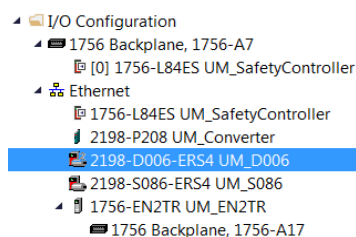
IMPORTANT This section applies to 2198-xxxx-ERS3 (series A) drives. The 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) drives are configured for Hardwired or Networked mode in the Module Definition dialog box under Module Properties>General category.

After the integrated safety connection configuration is applied to the Kinetix 5700 servo drive at least once, you can restore the drive to the Hardwired STO mode by using the Logix Designer application.

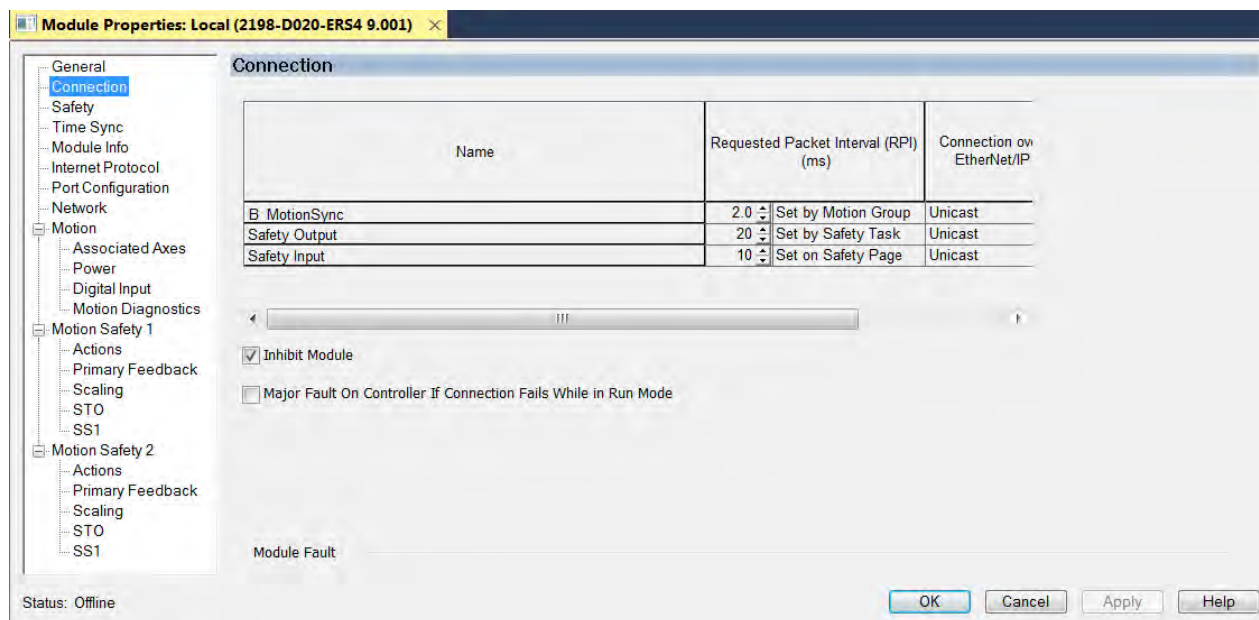
IMPORTANT Only authorized personnel should attempt Reset Ownership. The safety connection must be inhibited before the reset is attempted. If any active connection is detected, the safety reset is rejected and Reset Failed appears on the display.

Follow these steps to restore your Kinetix 5700 servo drive to the Hardwired STO mode.

1. Right-click the Kinetix 5700 servo drive you just created and choose Properties.

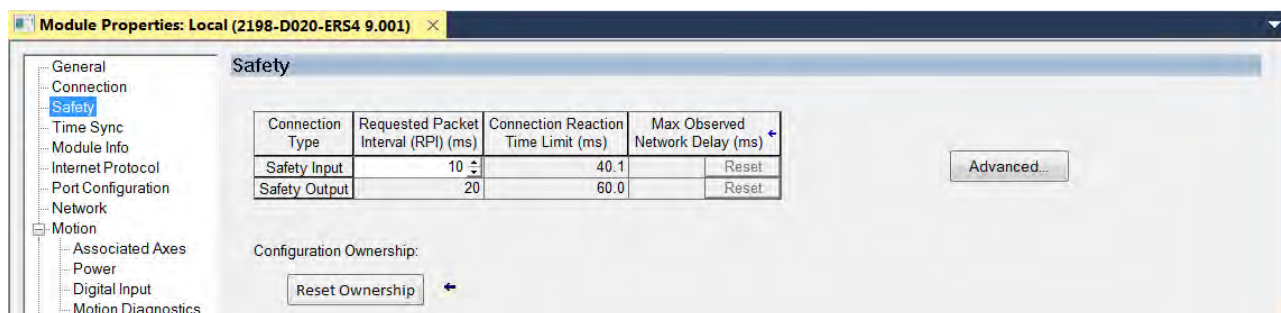


2. Select the Connection category.
The Connection category appears.



3. Check Inhibit Module.
4. Click Apply.

5. Click the Safety category.



6. In the Configuration Ownership field, click Reset Ownership.

The drive reverts back to Hardwired STO mode.

7. Click OK.

Restore Hardwired STO mode by Using the Drive Display

After the integrated safety connection configuration is applied to the Kinetix 5700 servo drive at least once, you can restore the drive to Hardwired STO mode by using the drive display and navigation buttons.

IMPORTANT Only authorized personnel should attempt Reset Ownership. The safety connection must be inhibited before the reset is attempted. If any active connection is detected, the safety reset is rejected and Reset Failed appears on the display.

Follow these steps to restore your Kinetix 5700 drive to the Hardwired STO mode.

1. Disable any Motion and Safety connections configured in the Logix Designer application.
You can do this in Module Properties or by unplugging the Ethernet cable.
2. From the Home screen on the drive display, press the settings button.
3. From the SETTINGS menu, scroll down by using the arrows and select SAFETY.
4. Press to request a Reset Ownership.
Are You Sure? appears on the display.
5. Press to acknowledge and begin the reset ownership.

If a reset ownership is requested, but not acknowledged within 30 seconds, the display automatically reverts back to the Home screen and the drive does not complete the reset ownership.

If a reset ownership is requested and acknowledged within 30 seconds, the drive reverts back to Hardwired STO mode.

Safe Torque-off Status

This section describes the safety related status data that is available to the motion controller.

IMPORTANT The status data described in this section is STANDARD data (not SAFETY data) and cannot be used as part of a safety function.

When a Kinetix 5700 add on profile (AOP) is added to a Logix Designer application I/O tree, axis tags are added to the controller tags.

This table lists the safety related STANDARD tags that are added when a new AXIS_CIP_DRIVE axis is defined.

Table 151 - Safety Related Axis Tags

| Logix Designer Tag Name | Attribute [bit] | Type | Description |
|-------------------------------------|-----------------|------|--|
| AxisFaults | 34 | DINT | |
| GuardFaultStatus | [5] | BOOL | STO fault - Hardwired |
| SafetyFaultStatus | [8] | BOOL | STO fault - Integrated |
| ModuleFaults | 163 | DINT | |
| GuardStatus | 980 | DINT | |
| GuardOKStatus | [0] | BOOL | Not STO fault - Hardwired |
| GuardGateDriveOutputStatus | [2] | BOOL | Torque allowed - Hardwired |
| GuardStopInputStatus | [3] | BOOL | Safety inputs active - Hardwired |
| GuardStopRequestStatus | [4] | BOOL | Safety input requesting STO - Hardwired |
| GuardFault | 981 | DINT | |
| GuardStopInputFault | [9] | BOOL | STO fault - Hardwired |
| GuardGateDriveFault | [2] | BOOL | Internal STO circuit fault - Hardwired |
| CIPAxisFaultsRA | 903 | DINT | |
| SafetyModuleCommunicationErrorFault | [28] | BOOL | Loss of communication to safety control |
| CIPAxisAlarmsRA | 904 | DINT | |
| SafetyModuleCommunicationErrorAlarm | [28] | BOOL | Loss of communication to safety control |
| CIPInitializationFaultsRA | 910 | DINT | |
| InvalidSafetyFirmwareFault | [14] | BOOL | Invalid safety control firmware |
| CIPStartInhibits | 676 | DINT | |
| SafeTorqueOffActiveInhibit | [5] | BOOL | Torque disabled - Integrated |
| CIPStartInhibitsRA | 912 | DINT | |
| SafeTorqueOffInhibit | [5] | BOOL | Torque disabled - Hardwired |
| AxisSafetyState | 760 | DINT | Safety supervisor state |
| AxisSafetyStatus ⁽¹⁾ | 761 | DINT | |
| SafetyFaultStatus | [0] | BOOL | Status of SI.SafetyFault |
| SafetyResetRequestStatus | [1] | BOOL | Status of SO.Reset or SO.ResetRequest |
| SafetyResetRequiredStatus | [2] | BOOL | Status of SI.ResetRequired |
| SafeTorqueOffActiveStatus | [3] | BOOL | Status of SO.SafeTorqueOff or SO.STOOutput |

Table 151 - Safety Related Axis Tags (continued)

| Logix Designer Tag Name | Attribute [bit] | Type | Description |
|----------------------------------|-----------------|------|---|
| SafeTorqueOffDisableStatus | [4] | BOOL | Status of SI.TorqueDisabled |
| SafetyOutputConnectionClosed | [30] | BOOL | 1 if all output connections are closed |
| SafetyOutputConnectionIdleStatus | [31] | BOOL | 1 if safety controller is in program mode |
| AxisSafetyFaults | 763 | DINT | |
| SafetyCoreFault | [1] | BOOL | Loss of communications to safety control |
| SafetyTorqueOffFault | [3] | BOOL | Status of SI.SafetyFault |

(1) Bits not shown are always zero.

Explicit Messages

You can use explicit messages to obtain additional diagnostic information from the safety controller by using an MSG instruction.

Safety Supervisor State

The safety supervisor state provides information on the state of the integrated safety connection and the mode of operation. There is only one safety supervisor object per drive module. Therefore, for dual-axis inverters, the safety supervisor is the same on both axes.

Table 152 - Safety Supervisor State: MSG

| Parameter | Value | Description |
|--------------|-------|----------------------|
| Service Code | 0x0E | Get attribute single |
| Class | 0x39 | Safety supervisor |
| Instance | 1 | |
| Attribute | 0x0B | Device status |
| Data Type | SINT | Short integer |

Table 153 - Safety Supervisor States

| Value | Safety Supervisor State | Definition | Safety Mode |
|-------|-----------------------------------|--|----------------------------|
| 2 | Configured (no safety connection) | No active connections | Integrated |
| 4 | Running | Normal running state | Integrated |
| 7 | Configuring | Transition state | Integrated |
| 8 | Not Configured | Hardwired STO mode with torque disabled | Hardwired (out of the box) |
| 51 | Not Configured (torque permitted) | Hardwired STO mode with torque permitted | Hardwired (out of the box) |
| 52 | Running (torque permitted) | STO bypass state | Integrated |

Safe Torque-off Mode

You can use the attribute STO Mode to check if the Kinetix 5700 inverter is in STO Bypass mode.

Table 154 - Safe Torque-off Mode: MSG

| Parameter | Value | Description |
|--------------|--------|-----------------------|
| Service Code | 0x0E | Get attribute single |
| Class | 0x5A | Safety stop functions |
| Instance | 1 or 2 | Inverter axis number |
| Attribute | 0x104 | STO mode |
| Data Type | SINT | Short integer |

Table 155 - Safe Torque-off Mode: Values

| Value | Definition |
|-------|------------------|
| 1 | Normal operation |
| 2 | STO bypass mode |

Safe Torque-off Faults

When a safety fault is indicated in any of the following tags:

- SI.SafetyFault
- Axis.SafetyFaultStatus
- Axis.SafetyTorqueOffFault

The cause of the fault can be read using an explicit message.

Table 156 - Safe Torque-off Fault Type: MSG

| Parameter | Value | Description |
|--------------|--------|-----------------------|
| Service Code | 0x0E | Get attribute single |
| Class | 0x5A | Safety stop functions |
| Instance | 1 or 2 | Inverter axis number |
| Attribute | 0x108 | STO fault type |
| Data Type | SINT | Short integer |

Table 157 - Safe Torque-off Fault Type: Values

| Value | Definition |
|-------|---------------------------------|
| 1 | No Fault |
| 3 | Circuit Error |
| 104 | Hardwired input in Network mode |

Hardwired Safe Torque-off

This section introduces you to the Kinetix 5700 hardwired safe torque-off (STO) feature that meets the requirements of Performance Level e (PL e) per ISO 13849-1 and SIL CL 3 per IEC 61508, IEC 61800-5-2 and IEC 62061.

The 2198-xxxx-ERS3 and 2198-xxxx-ERS4 inverters use the STO connector for wiring external safety devices and cascading hardwired safety connections from drive-to-drive.

Compatible Controllers

A ControlLogix® 5570, ControlLogix 5580, CompactLogix™ 5370 or CompactLogix 5380 controller is required for drive control.

The Studio 5000 Logix Designer® application provides support for programming, commissioning, and maintaining these CompactLogix and ControlLogix controllers with Kinetix 5700 drive systems.

Table 158 - Studio 5000 Logix Designer Requirements

| Studio 5000 Logix Designer Application | Kinetix Dual-axis Inverters Cat. No. | Kinetix Single-axis Inverters Cat. No. |
|--|---|---|
| Version 26 or later | 2198-Dxxx-ERS3 (series A) | 2198-Sxxx-ERS3 (series A) |
| Version 31 or later | 2198-Dxxx-ERS4 2198-Dxxx-ERS3 (series B) | 2198-Sxxx-ERS4 2198-Sxxx-ERS3 (series B) |

Description of Operation

The safe torque-off feature provides a method, with sufficiently low probability of failure, to force the power-transistor control signals to a disabled state. When disabled, or any time power is removed from the safety enable inputs, all of the drive output-power transistors are released from the ON-state. This results in a condition where the drive performs a Category 0 Stop (refer to [Stop Category Definition](#) on [page 306](#)). Disabling the power transistor output does not provide physical isolation of the electrical output that is required for some applications.

For hardwired control of the safe torque-off (STO) function:

- The STO function needs to be in Hardwired STO mode
- The appropriate wiring must be connected to the Safety (STO) connector plug

Refer to [Hardwired Safe Torque-off Electrical Specifications](#) on [page 323](#) for more information on the safety inputs.

Under normal operation, the safe torque-off inputs are energized. If either of the safety enable inputs are de-energized, then all of the output power transistors turn off. The safe torque-off response time is less than 12 ms.

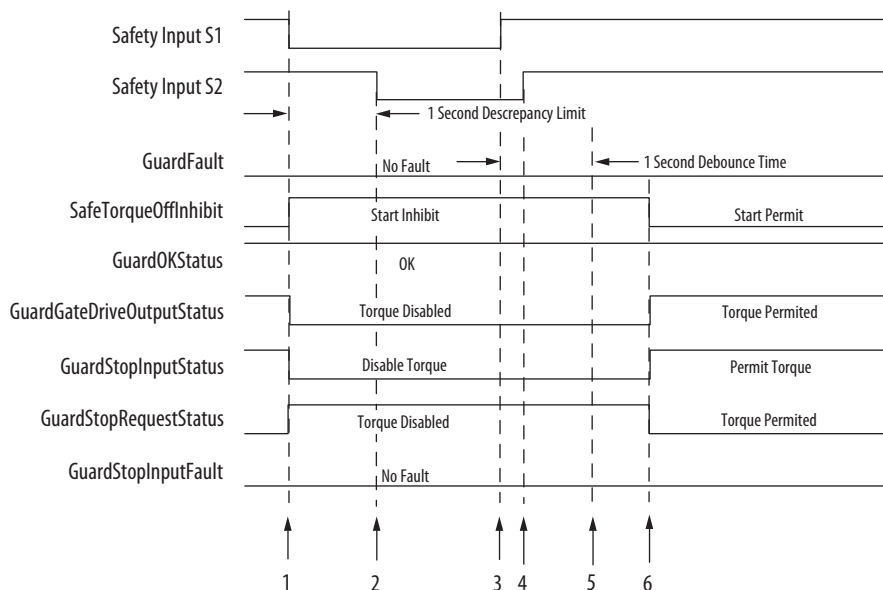


ATTENTION: Permanent magnet motors can, in the event of two simultaneous faults in the IGBT circuit, result in a rotation of up to 180 electrical degrees.



ATTENTION: If any of the safety enable inputs de-energize, the Start Inhibit field indicates the SafeTorqueOffInhibit and GuardStopRequestStatus bits of the AxisGuardStatus tag are set to 1. Both inputs must be de-energized within 1 second and re-energized within 1 second to avoid GuardStopInputFault conditions.

Figure 142 - System Operation when Inputs are Meeting Timing Requirements



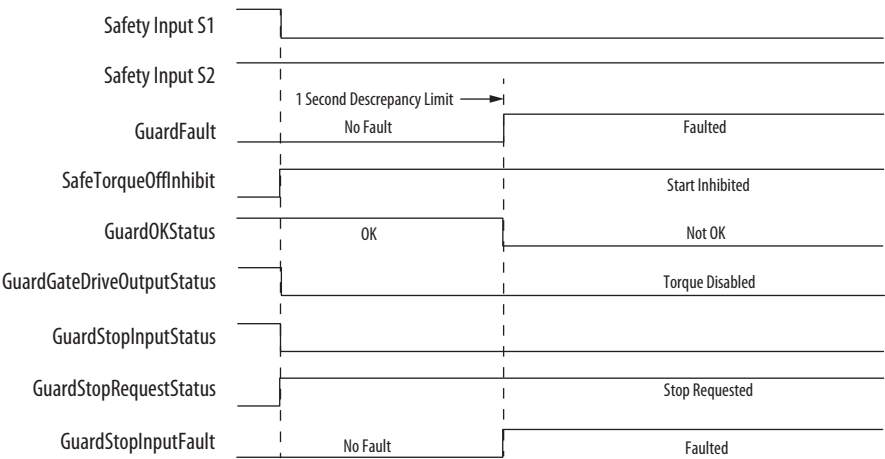
| Event | Description |
|-------|--|
| 1 | At least one input is switched-off. The GuardStopRequestStatus bit is set to 1. |
| 2 | Second input is switched-off within 1 second. This event must always occur within 1 second to prevent a GuardStopInputFault condition. |
| 3 | First input is switched-on. |
| 4 | Second input is switched-on within 1 second of event 3. |
| 5 | Both inputs are in the ON state simultaneously within 1 second. As a result, GuardStopInputFault is not posted. |
| 6 | The GuardStopRequestStatus bit sets back to 0 if event 4 occurs within a 100 ms interval after event 3. If event 4 is outside of the 100 ms interval, but within the a 1 second interval after event 3, then the GuardStop RequestStatus bit sets back to 0 after the 1 second interval following event 3 (not immediately following event 4). |

Troubleshoot the Safe Torque-off Function

For Kinetix 5700 hardwired (STO) fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

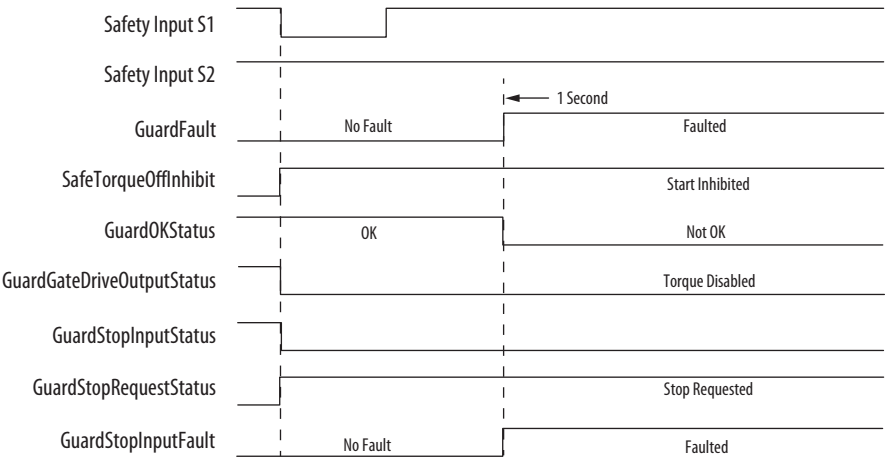
[Figure 143](#) illustrates when the safe torque-off mismatch is detected and GuardStopInputFault is posted.

Figure 143 - System Operation when Safety Enable Inputs Mismatch Occurs



When one safety input is turned off, the second input must also be turned off, otherwise a fault is asserted (see [Figure 144](#)). The fault is asserted even if the first safety input is turned on again, without the second input transitioning to the ON state.

Figure 144 - System Operation when Safety Enable Inputs Mismatch Momentarily



ATTENTION: The safe torque-off fault is detected upon demand of the safe torque-off function. After troubleshooting the STO function or performing maintenance that might affect the STO function, the STO function must be executed to verify correct operation.

IMPORTANT The GuardStopInputFault can be reset only if both inputs are in the OFF-state for more than 1 second. After the fault reset requirement is satisfied, an MAFR command in the Logix Designer application must be issued to reset the GuardStopInputFault.

Safe Torque-off Connector Data

Two rows of eight pins are provided for making drive-to-drive connections. The dual-axis inverters have pins designated for axis A and axis B. The single-axis inverters do not use STO-6, -7, -8 and STO-14, -15, -16.

Figure 145 - Pin Orientation for 16-pin Safe Torque-off (STO) Connector

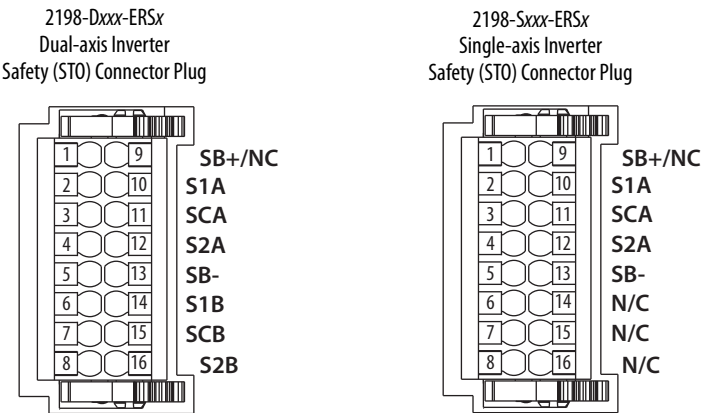


Table 159 - Safe Torque-off Connector Pinouts

| STO Pin | | Description 2198-Dxxx-ERSx | Description 2198-Sxxx-ERSx | Signal |
|---------|----|---|-------------------------------|--------|
| 1 | | Safety bypass plus signal. Connect to both safety inputs to disable safe torque-off function. | | SB+ |
| 2 | 10 | Safe stop input channel 1, axis A. | | S1A |
| 3 | 11 | Safe stop input common, axis A. | | SCA |
| 4 | 12 | Safe stop input channel 2, axis A. | | S2A |
| 5 | 13 | Safety bypass minus signal. Connect to safety common to disable safe torque-off function. | | SB- |
| 6 | 14 | Safe stop input channel 1, axis B. | N/C | S1B |
| 7 | 15 | Safe stop input common, axis B. | N/C | SCB |
| 8 | 16 | Safe stop input channel 2, axis B. | N/C | S2B |
| 9 | | N/C | N/C | — |

IMPORTANT STO-3 and STO-7 is common for the digital inputs, the safety inputs, and the encoder power supply (optional).

Wire the Safe Torque-off Circuit

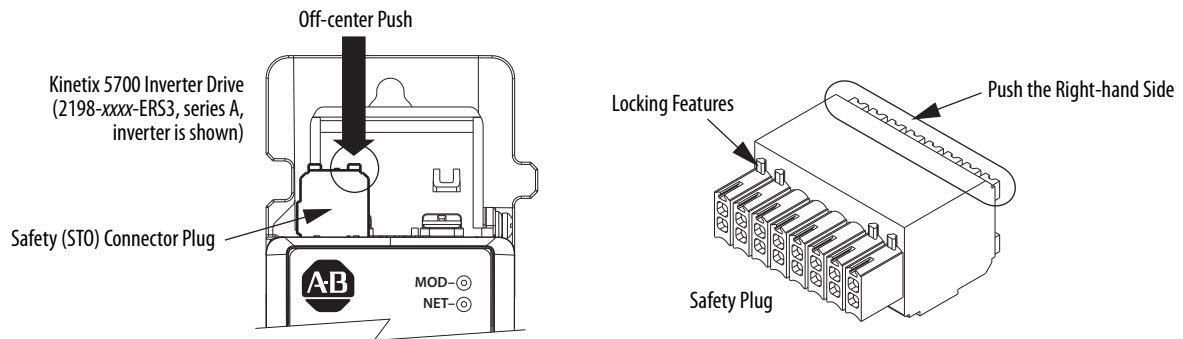
This section provides guidelines for wiring safe torque-off connections to your Kinetix 5700 drive.

IMPORTANT When replacing 2198-xxxx-ERS3 (series A) single-axis and dual-axis inverters with 2198-xxxx-ERSx (series B) inverters, you must use the series B (safety) connector plugs that are included with your series B inverter.

Install 2198-xxxx-ERS3 (series A) Safety (STO) Connector Plugs

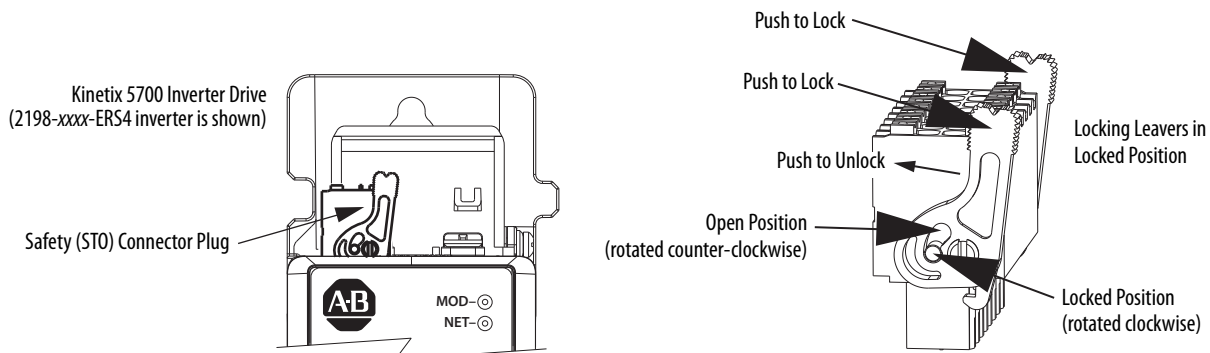
The right side of the safety connector plug requires an off-center push when inserting it into the STO connector. This applies to 2198-xxxx-ERS3 (series A) single-axis and dual-axis inverters.

IMPORTANT An off-center push is required to engage the locking features on the bottom of the safety connector plugs and seat properly with the drive STO connector. Failure to do this can result in the connector plug pulling out of the drive connector during normal operation.

Figure 146 - Insert the 2198-xxxx-ERS3 (series A) Safety Connector Plug**Install 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) Safety Connector Plugs**

The safety connector plugs have two locking levers that you push in a clockwise direction as you insert the plugs into the drive connector. This is the locked position. Rotate the levers counter-clockwise to the open position to release the connector plugs. This applies to 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) single-axis and dual-axis inverters.

IMPORTANT Push the locking levers clockwise into the locked position as you insert the STO connector plugs. Failure to do this can result in the connector plugs pulling out of the drive connector during normal operation.

Figure 147 - Insert the 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) Safety Connector Plugs

IMPORTANT The National Electrical Code and local electrical codes take precedence over the values and methods provided.

IMPORTANT To improve system performance, run wires and cables in the wireways as established in [Establishing Noise Zones](#) beginning on [page 70](#).

IMPORTANT Pins STO-1 and STO-5 (SB+ and SB-) are used to disable the safe torque-off function. When wiring to the STO connector, use an external 24V supply for the external safety device that triggers the safe torque-off request. To avoid jeopardizing system performance, do not use pin STO-1 as a power supply for the external safety device.

Safe Torque-off Wiring Requirements

The safe torque-off (STO) connector uses spring tension to secure the wire. Depress the numbered tab along side each pin to insert or release each wire. Two rows of pins are provided for drive-to-drive connections. Wire must be copper with 75 °C (167 °F) minimum rating.

IMPORTANT The National Electrical Code and local electrical codes take precedence over the values and methods provided.

IMPORTANT Stranded wires must terminate with ferrules to prevent short circuits, per table D7 of ISO 13849.

Figure 148 - Safe Torque-off (STO) Terminal Plug

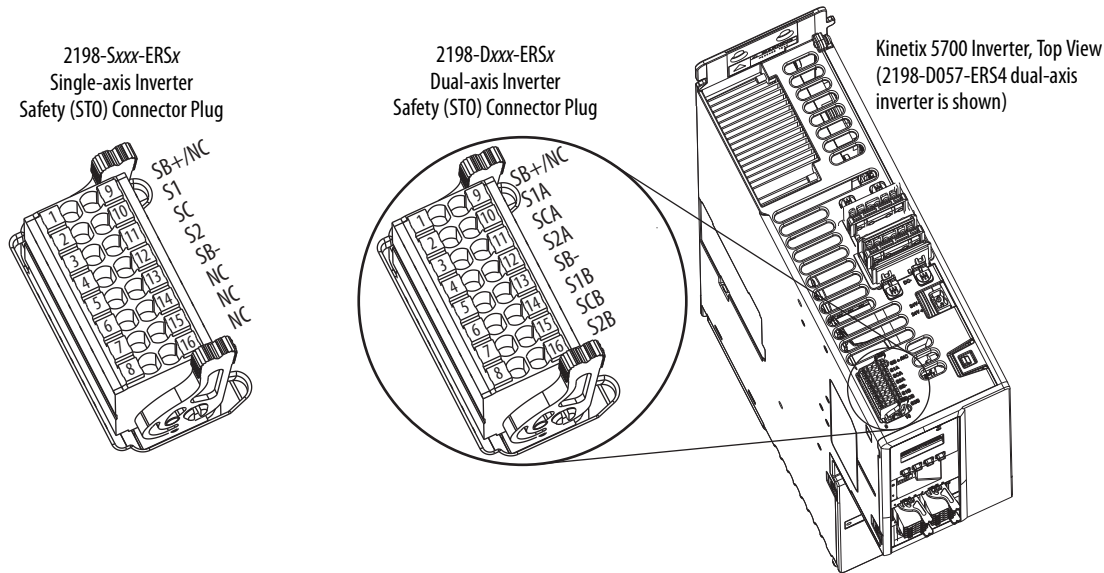


Table 160 - Safe Torque-off (STO) Connector Plug Wiring

| Safe Torque-off (STO) Connector | | Signal | | Recommended Wire Size mm ² (AWG) | Strip Length mm (in.) | Torque Value N·m (lb·in) |
|---------------------------------|----|----------------|----------------|--|--------------------------|-----------------------------|
| STO Pin | | 2198-Dxxx-ERSx | 2198-Sxxx-ERSx | | | |
| 1 | | SB+ | SB+ | 0.14...1.5 (26...16) | 10 (0.39) | N/A ⁽¹⁾ |
| 2 | 10 | S1A | S1 | | | |
| 3 | 11 | SCA | SC | | | |
| 4 | 12 | S2A | S2 | | | |
| 5 | 13 | SB- | SB- | | | |
| 6 | 14 | S1B | NC | | | |
| 7 | 15 | SCB | NC | | | |
| 8 | 16 | S2B | NC | | | |
| 9 | | NC | NC | | | |

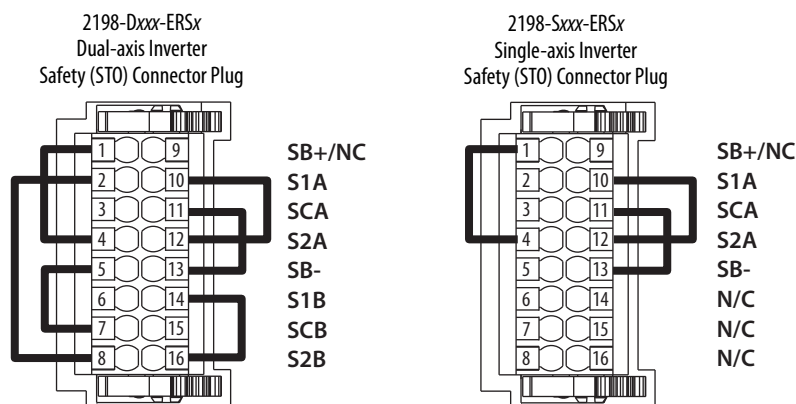
(1) This connector uses spring tension to hold wires in place.

Safe Torque-off Feature Bypass

The Kinetix 5700 inverters do not operate without a safety circuit or safety bypass wiring. For applications that do not require the safe torque-off feature you must install jumper wires to bypass the safe torque-off circuitry.

Kinetix 5700 inverters ship with a 16-pin wiring plug for wiring to safety devices. To bypass the safety function, wire these signals as shown in [Figure 149](#). With the jumper wires installed, the safe-off feature is not used.

Figure 149 - Safe Torque-off Bypass Wiring



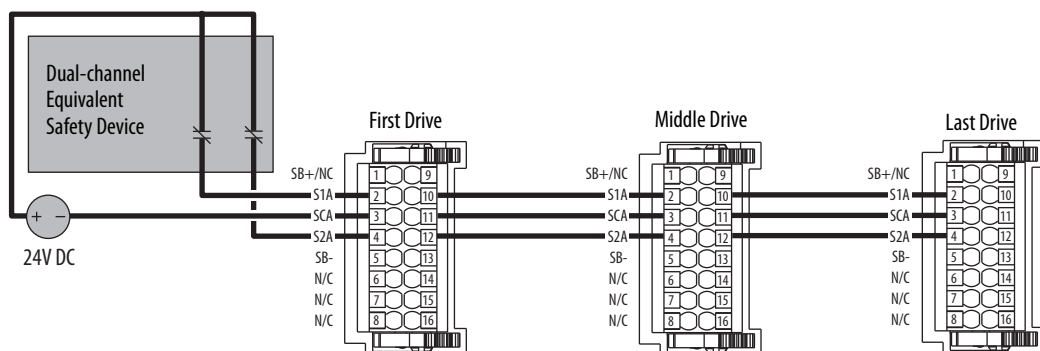
IMPORTANT If the safe torque-off function is not required, the drive safety configuration must be returned to Hardwired STO mode and the bypass jumper wires applied to the safety (STO) connector plugs.

Cascade the Safe Torque-off Signal

The total number of drives in a single cascaded safety circuit is limited by the current carrying capacity of the cascaded safety wiring. Refer to [Table 161](#) for current rating per channel, per drive.

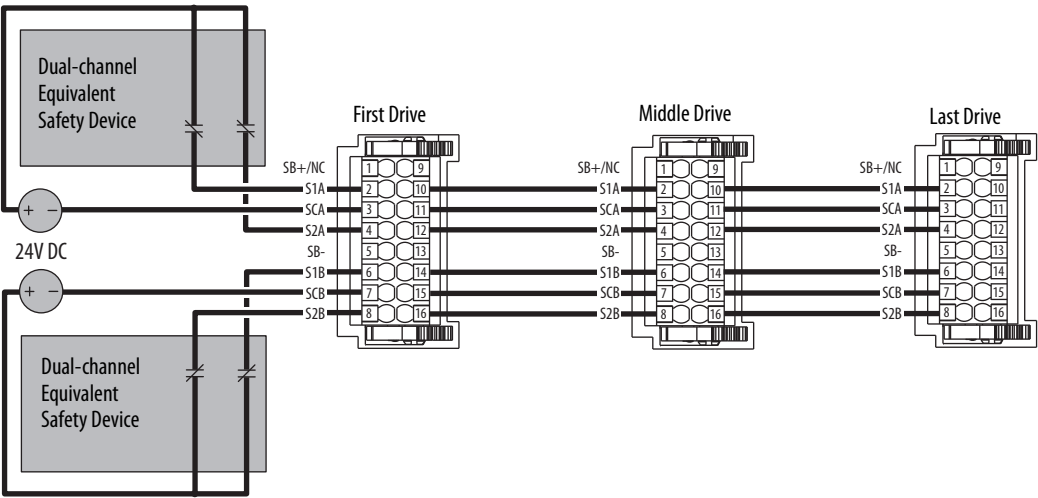
In this example, the cascaded safe torque-off (STO) wiring is for an application with three single-axis inverters and a single safety device.

Figure 150 - Cascaded STO Wiring - Single-axis Inverters



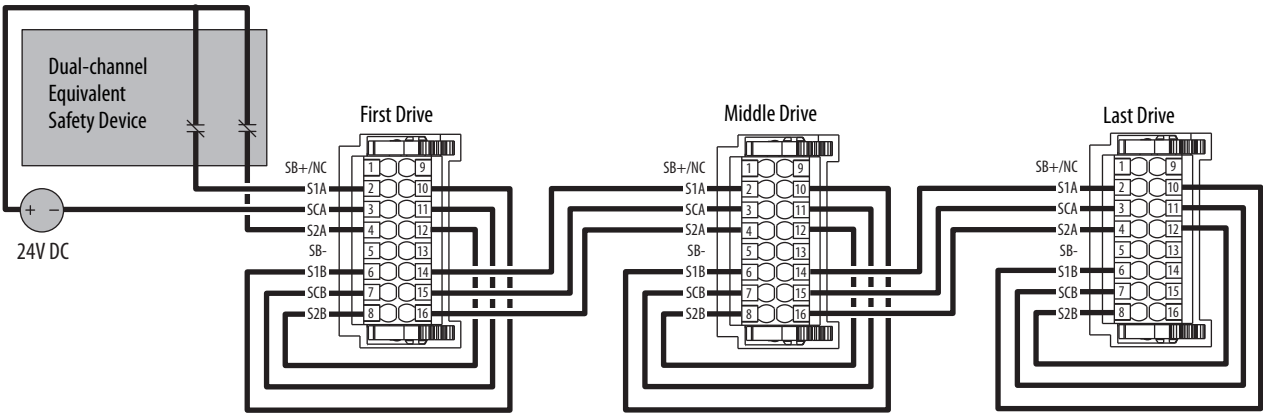
In this example, the cascaded safe torque-off (STO) wiring is for an application with three dual-axis inverters and two separate safety devices.

Figure 151 - Cascaded STO Wiring - Dual-axis Inverters with Two Safety Devices



In this example, the cascaded STO wiring is for an application with three dual-axis inverters and a single safety device for all axes.

Figure 152 - Cascaded STO Wiring - Dual-axis Inverter with Single Safety Device



Hardwired Safe Torque-off Electrical Specifications

IMPORTANT To maintain their safety rating, Kinetix 5700 inverters must be installed inside protected control panels or cabinets appropriate for the environmental conditions of the industrial location. The protection class of the panel or cabinet must be IP54 or higher.

Table 161 - Hardwired STO Electrical Specifications

| Attribute | | Value |
|--------------------------------|--|--|
| Safety inputs (per channel) | Input current | < 10 mA |
| | Input ON voltage range | 18...26.4V DC |
| | Input OFF voltage, max | 5V DC |
| | Input ON current, per input, max | 10 mA, each drive ⁽²⁾ |
| | Input OFF current, max (@ V in < 5V DC) | 2 mA |
| | Pulse rejection width | 700 μs |
| | External power supply ⁽¹⁾ | SELV/PELV |
| | Input type | Optically isolated and reverse voltage protected |

(1) SELV or PELV rated power supplies must be used to energize external safety devices connected to the Kinetix 5700 safety inputs.

(2) The maximum number of drives cascaded with safe torque-off wiring is 50.

For additional information regarding Allen-Bradley® safety products, including safety relays, light curtain, and gate interlock applications, refer to <https://ab.rockwellautomation.com/Safety>.

Integrated Safe Torque-off

This section introduces you to the Kinetix 5700 safe torque-off (STO) feature over the EtherNet/IP network that meets the requirements of Performance Level e (PL e) per ISO 13849-1 and SIL 3 per IEC 61508, IEC 61800-5-2, and IEC 62061. Integrated STO applies to 2198-xxxx-ERS3 and 2198-xxxx-ERS4 dual-axis and single-axis inverters.

In Integrated STO mode, the GuardLogix® safety controller issues the STO command over the EtherNet/IP network and the 2198-xxxx-ERS3 and 2198-xxxx-ERS4 dual-axis and single-axis inverters execute the STO command.

Compatible Safety Controllers

A GuardLogix 5570 or Compact GuardLogix 5370 safety controller is required for integrated safety control of the Kinetix 5700 safe torque-off function.

The Studio 5000 Logix Designer application, version 26.00 or later, provides support for programming, commissioning, and maintaining Logix 5000™ safety controllers with Kinetix 5700 drive systems.

The safety connection can originate from either of these controller configurations:

- Single safety controller that provides both safety and motion control
- Safety controller that controls only the safety, while a separate ControlLogix 5570, ControlLogix 5580, CompactLogix 5370, or CompactLogix 5380 controller that controls motion

Table 162 - Studio 5000 Logix Designer Requirements

| Studio 5000 Logix Designer Application | Kinetix Dual-axis Inverters Cat. No. | Kinetix Single-axis Inverters Cat. No. |
|--|--|---|
| Version 26 or later | 2198-Dxxx-ERS3 (series A) | 2198-Sxxx-ERS3 (series A) |
| Version 31 or later | 2198-Dxxx-ERS4 2198-Dxxx-ERS3 (series B) ⁽¹⁾ | 2198-Sxxx-ERS4 2198-Sxxx-ERS3 (series B) |

(1) When 2198-xxxx-ERS3 (series B) drives are used in Timed SS1 safety applications, Studio 5000 Logix Designer application, version 31, must be used.

Safety Application Requirements

Safety application requirements include evaluating probability of failure rates (PFH), system reaction time settings, and functional verification tests that fulfill SIL 3 criteria. Refer to [Average Frequency of a Dangerous Failure](#) on [page 307](#) for more PFH information.

Creating, recording, and verifying the safety signature is also a required part of the safety application development process. Safety signatures are created by the safety controller. The safety signature consists of an identification number, date, and time that uniquely identifies the safety portion of a project. This includes all safety logic, data, and safety I/O configuration.

For safety system requirements, including information on the safety network number (SNN), verifying the safety signature, and functional verification tests refer to the appropriate GuardLogix controller publication as defined in [Additional Resources](#) on [page 13](#).

IMPORTANT You must read, understand, and fulfill the requirements detailed in the GuardLogix controller systems safety reference manual prior to operating a safety system that uses a GuardLogix controller and Kinetix 5700 drive.

Description of Operation

The safe torque-off (STO) feature provides a method, with sufficiently low probability of failure, to force the power-transistor control signals to a disabled state. When the command to execute the STO function is received from the GuardLogix controller, all of the drive output-power transistors are released from the ON-state. This results in a condition where the motor is coasting. Disabling the power transistor output does not provide isolation of the electrical output that is required for some applications.

These conditions must be met for integrated control of the STO function:

- The Kinetix 5700 drive module must be added to the GuardLogix 5570 or Compact GuardLogix 5370 controller I/O Configuration.
- The module must be configured for Safety Only or Motion and Safety connections
- The safety bypass jumper wires must be removed.

IMPORTANT If the STO bypass jumper wires were applied during machine commissioning or maintenance, they must be removed before the drive will operate in Integrated STO mode.

The Kinetix 5700 drive STO function reaction time is less than 10 ms. Reaction time for the drive is the delay between the time the drive STO command receives the CIP Safety™ packet with an STO request and the time when motion producing power is removed from the motor.

Table 163 - Safe Torque-off Network Specifications

| Attribute | 2198-xxxx-ERS3 | 2198-xxxx-ERS4 |
|--|----------------------------|----------------|
| STO function reaction time | 10 ms, max | |
| Safety connection RPI, min | 6 ms | |
| Input assembly connections ⁽¹⁾ | 3 | 1 |
| Output assembly connections ⁽¹⁾ | 1 | |
| Integrated safety open request support | Type 1 and Type 2 requests | |

(1) Motion and Safety and Safety Only connections with the inverter uses 1 input assembly connection and 1 output assembly connection.

Safe Torque-off Assembly Tags

In Integrated safe torque-off (STO) mode, a GuardLogix 5570 or Compact GuardLogix 5370 safety controller commands the Kinetix 5700 safe torque-off function through the appropriate tag in the safety output assembly.

IMPORTANT The tag names listed in [Table 164](#) changed in the Logix Designer application, version 31 and later, depending on how Motion Safety is configured in the Module Definition.

Table 164 - STO Tag Name Changes in the Logix Designer Application

| STO Tag Names Studio 5000 Logix Designer (version 30 and earlier) | STO Only Tag Names Studio 5000 Logix Designer (version 31 and later) | Safe Stop Only - No Feedback Tag Names Studio 5000 Logix Designer (version 31 and later) |
|---|--|--|
| SO.SafeTorqueOff | SO.SafeTorqueOff | SO.STOOutput |
| SO.Reset | SO.Reset | SO.ResetRequest |

The SO.Command tags are sent from the GuardLogix safety output assembly to the Kinetix 5700 safety output assembly to control the safe torque-off function.

The SI.Status tags are sent from the Kinetix 5700 inverter to the GuardLogix safety input assembly and indicate the Kinetix 5700 safety control status.

The SI.ConnectionStatus tags indicate the safety input connection status.

[Table 165](#) and [Table 166](#) list the safety tags added to the controller tags when a Kinetix 5700 servo drive is added to a GuardLogix I/O Configuration and the connection is configured for Motion and Safety or Safety Only.

IMPORTANT The SO.SafeTorqueOff and SO.ResetRequest tag names change when Motion Safety in the Module Definition is configured as Safe Stop Only - No Feedback.

The attribute values listed are the Assembly Object attribute values.

Table 165 - Single-axis Inverter Integrated STO Specifications

| Logix Designer Tag Name | Safe Stop Only - No Feedback Tag Names Studio 5000 Logix Designer (version 31 and later) | Attribute [bit] | Type | Description |
|--|--|--------------------|------|--|
| SI.ConnectionStatus ^{(1) (2)} | | | DINT | |
| SI.RunMode | | [0] | BOOL | Combinations of the RunMode and ConnectionFaulted states |
| SI.ConnectionFault | | [1] | BOOL | |
| SI.Status ^{(1) (3)} | | | SINT | |
| SI.TorqueDisabled | | [0] | BOOL | 0 = Torque Permitted 1 = Torque Disabled |
| SI.SafetyFault | | [6] | BOOL | 1 = STO fault present |
| SI.ResetRequired | | [7] | BOOL | 1 = Reset is required |
| SO.Command ^{(1) (4)} | | | SINT | |
| SO.SafeTorqueOff | SO.STOOutput | [0] | BOOL | 0 = Disable Permit 1 = Permit Torque |
| SO.Reset | SO.ResetRequest | [7] | BOOL | 0 --> 1 = Reset STO fault |

(1) Bits not listed are always zero.

(2) ConnectionStatus is determined by the Safety Validator in the GuardLogix controller.

(3) Status is sent from the drive to the controller using integrated safety protocol.

(4) Commands are sent from the controller to the drive using integrated safety protocol.

IMPORTANT Only the data listed in [Table 165](#) is communicated with SIL 3 integrity.

Table 166 - Dual-axis Inverter Integrated STO Specifications

| Logix Designer Tag Name | Safe Stop Only - No Feedback Tag Names Studio 5000 Logix Designer (version 31 and later) | Attribute [bit] | Type | Description |
|--|--|--------------------|------|---|
| SI.ConnectionStatus ^{(1) (2)} | | | DINT | |
| SI.RunMode | | [0] | BOOL | Combinations of the RunMode and |
| SI.ConnectionFaulted | | [1] | BOOL | ConnectionFaulted states |
| SI.Status1 ^{(1) (3)} | | | SINT | Motion Safety 1 |
| SI.TorqueDisabled1 | | [0] | BOOL | 0 = Torque Permitted; 1 = Torque Disabled |
| SI.SafetyFault1 | | [6] | BOOL | 1 = STO Fault present |
| SI.ResetRequired1 | | [7] | BOOL | 1 = A reset is required |
| SI.Status2 ^{(1) (3)} | | | SINT | Motion Safety 2 |
| SI.TorqueDisabled2 | | [0] | BOOL | 0 = Torque Permitted; 1 = Torque Disabled |
| SI.SafetyFault2 | | [6] | BOOL | 1 = STO Fault present |
| SI.ResetRequired2 | | [7] | BOOL | 1 = A reset is required |
| SO.Command1 ^{(1) (4)} | | | SINT | Motion Safety 1 |
| SO.SafeTorqueOff1 | SO.STOOutput1 | [0] | BOOL | 0 = Disable Permit; 1 = Permit Torque |
| SO.Reset1 | SO.ResetRequest1 | [7] | BOOL | 0→>1 = Reset STO Fault |
| SO.Command2 ^{(1) (4)} | | | SINT | Motion Safety 2 |
| SO.SafeTorqueOff2 | SO.STOOutput2 | [0] | BOOL | 0 = Disable Permit; 1 = Permit Torque |
| SO.Reset2 | SO.ResetRequest2 | [7] | BOOL | 0→>1 = Reset STO Fault |

(1) Bits not listed are always zero.

(2) ConnectionStatus is determined by the Safety Validator in the GuardLogix controller.

(3) Status is sent from the drive to the controller using integrated safety protocol.

(4) The Command is sent from the controller to the drive using integrated safety protocol.

IMPORTANT Only the data listed in [Table 166](#) is communicated with SIL 3 integrity.

In these examples, the appropriate STO bit permits torque when the bit is high (see [Table 164](#) on [page 326](#) for changes in STO tag names).

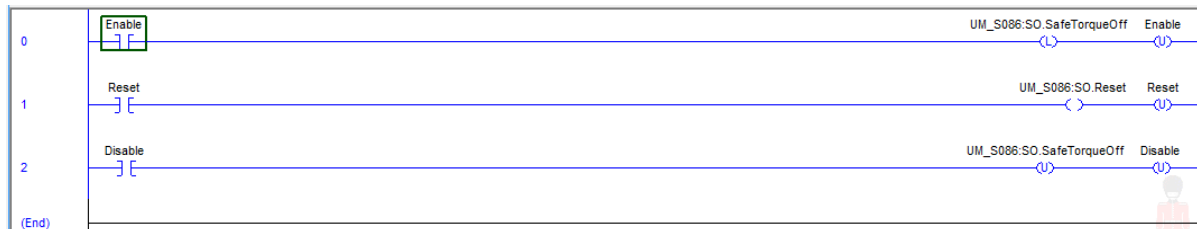
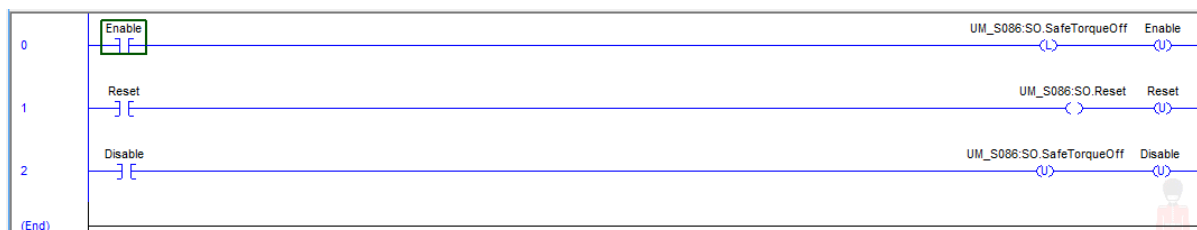
Figure 153 - STO Function (Logix Designer, version 30 or earlier)**Figure 154 - STO Function with STO Only (Logix Designer, version 31 or later)**

Figure 155 - STO Function with Safe Stop Only-No Feedback (Logix Designer, version 31 or later)



STO Fault Reset

To clear the STO Fault condition, a transition from logic 0 to 1 of the SO.Reset tag is required after the SO.SafeTorqueOff tag has transitioned from logic 0 to 1 (see [Table 164](#) on [page 326](#) for changes in STO tag names).

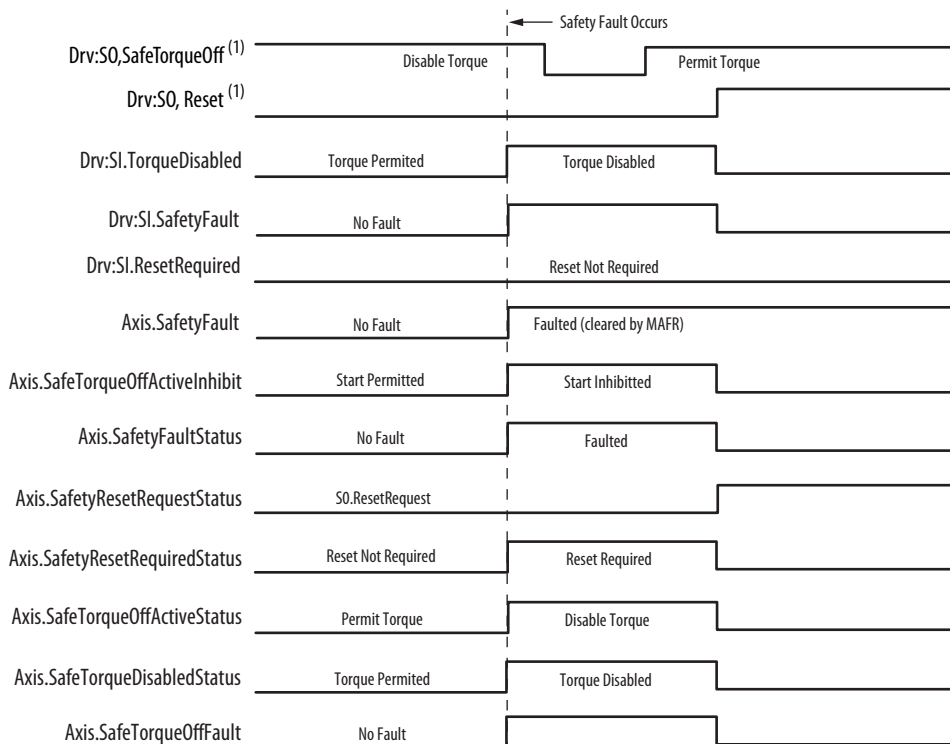
If the Kinetix 5700 servo drive safety controller detects a fault, the input assembly tag SI.SafetyFault is set to 1.

To reset Axis.SafetyFault, an MAFR command must be issued.

IMPORTANT Transition of the SO.SafeTorqueOff tag to logic 1 must always be executed prior to transition of the SO.Reset tag to logic 1.

IMPORTANT All Kinetix 5700 inverter axes enter the faulted state if any STO function fault is detected. Refer to [Table](#) on [page 330](#) for integrated safety troubleshooting.

Refer to [Figure 156](#) for an understanding of the Kinetix 5700 STO state restart functionality.

Figure 156 - Reset Safe Torque-off Fault Diagram

(1) See [Table 164](#) on [page 326](#) for STO tag name changes.

Troubleshoot the Safe Torque-off Function

For Kinetix 5700 integrated (STO) fault code descriptions and possible solutions, see the Knowledgebase Answer ID: [1091727](#).

Understand Integrated Safety Drive Replacement

GuardLogix controllers retain I/O device configuration on-board and are able to download the configuration to the replacement device.

IMPORTANT If the Kinetix 5700 replacement drive was used previously, clear the existing configuration before installing it on a safety network by resetting the drive to Hardwired STO mode. To see how this is done, refer to [Restore the Hardwired STO Mode by Using the Logix Designer Application](#) on [page 309](#).

Replacing a Kinetix 5700 servo drive that sits on an integrated safety network is more complicated than replacing standard devices because of the safety network number (SNN). The device number and SNN make up the safety device's DeviceID. Safety devices require this more complex identifier to make sure that duplicate device numbers do not compromise communication between the correct safety devices. The SNN is also used to provide integrity on the initial download to the Kinetix 5700 servo drive.

When the Logix Designer application is online, the Safety category of the Module Properties dialog box displays the current configuration ownership. When the opened project owns the configuration, Local is displayed.

A screenshot of a software interface showing the text "Configuration Ownership: Local" in a light gray box.

A communication error is displayed if the module read fails. Refer to [Replace an Integrated Safety Drive in a GuardLogix System](#) on [page 331](#) for integrated safety drive replacement information.

Replace an Integrated Safety Drive in a GuardLogix System

When you replace an integrated safety drive, the replacement device must be configured properly and the replacement drives operation must be user-verified.

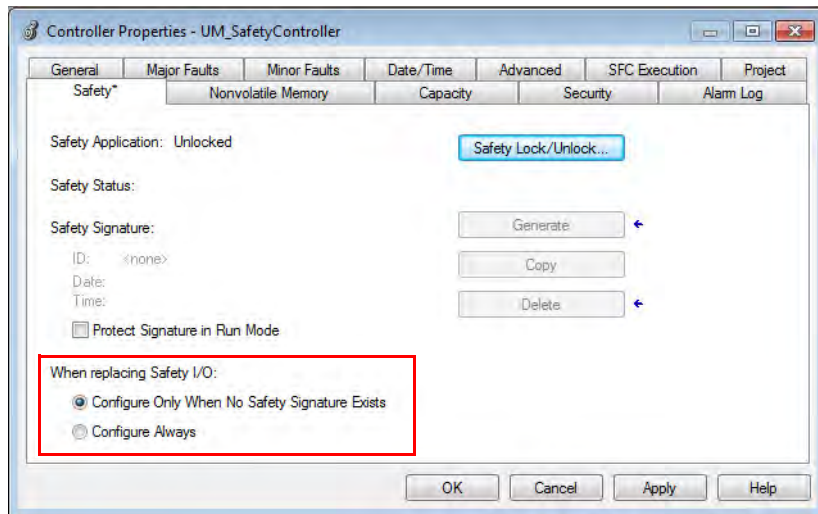


ATTENTION: During drive replacement or functional test, the safety of the system must not rely on any portion of the affected drive.

Two options for safety drive replacement are available on the Safety category of the Controller Properties dialog box in the Logix Designer application:

- Configure Only When No Safety Signature Exists
- Configure Always

Figure 157 - Safety Drive Replacement Options



Configure Only When No Safety Signature Exists

This setting instructs the GuardLogix controller to automatically configure a safety drive only when the safety task does not have a safety task signature, and the replacement drive is in an out-of-box condition, meaning that a safety network number does not exist in the safety drive.

If the safety task has a safety task signature, the GuardLogix controller automatically configures the replacement CIP Safety I/O device only if the following is true:

- The device already has the correct safety network number.
- The device electronic keying is correct.
- The node or IP address is correct.

For detailed information, refer to [Additional Resources](#) on [page 13](#) for the appropriate user manual for your GuardLogix or Compact GuardLogix controller.

Configure Always

When the Configure Always feature is enabled, the controller automatically checks for and connects to a replacement drive that meets all of the following requirements:

- The controller has configuration data for a compatible drive at that network address
- The drive is in Hardwired STO mode or has an SNN that matches the configuration



ATTENTION: Enable the Configure Always feature only if the entire integrated safety control system is not being relied on to maintain SIL 3 behavior during the replacement and functional testing of a Kinetix 5700 drive. Do not place drives that are in Hardwired STO mode on an integrated safety network when the Configure Always feature is enabled.

If other parts of the integrated safety control system are being relied upon to maintain SIL 3, make sure that the controller's Configure Always feature is disabled.

It is your responsibility to implement a process to make sure proper safety functionality is maintained during device replacement.



ATTENTION: Do not place any devices in the out-of-box condition on any integrated safety network when the Configure Always feature is enabled. For the device replacement procedure, refer to [Additional Resources](#) on [page 13](#) for the appropriate user manual for your GuardLogix or Compact GuardLogix controller.

Motion Direct Commands in Motion Control Systems

You can use the Motion Direct Command (MDC) feature to initiate motion while the controller is in Program mode, independent of application code that is executed in Run mode. These commands let you perform a variety of functions, for example, move an axis, jog an axis, or home an axis.

A typical use might involve a machine integrator testing different parts of the motion system while the machine is being commissioned or a maintenance engineer, under certain restricted scenarios in accordance with safe machine operating procedures, wanting to move an axis (like a conveyor) to clear a jam before resuming normal operation.



ATTENTION: To avoid personal injury or damage to equipment, follow these rules regarding Run mode and Program mode.

- Only authorized, trained personnel with knowledge of safe machine operation should be allowed to use Motion Direct Commands
 - Additional supervisory methods, like removing the controller key switch, should be used to maintain the safety integrity of the system after returning the safety controller to RUN mode
-

Understand STO Bypass When Using Motion Direct Commands

If a Safety-only connection between the GuardLogix safety controller and the Kinetix 5700 servo drive was established at least once after the drive was received from the factory, the drive does not allow motion while the safety controller is in Program mode by default.

This is because the safety task is not executed while the GuardLogix safety controller is in Program mode. This applies to applications running in a single-safety controller (with Motion and Safety connections). When an integrated safety drive has a Motion connection to a standard controller and a separate Safety connection to a safety controller, the standard controller can transition to Program mode while the safety controller stays in Run mode and continues to execute the safety task.

However, Kinetix 5700 drive systems are designed with a bypass feature for the STO function in single-safety controller configurations. You can use the MDC feature to allow motion while following all the necessary and prescribed steps per your machine's safety operating procedures.



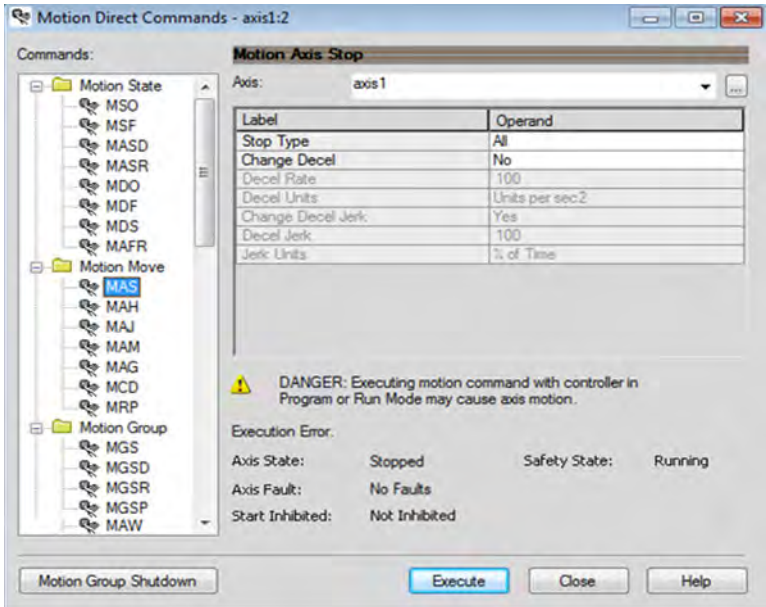
ATTENTION: Consider the consequences of allowing motion through the use of MDC when the controller is in Program mode. You must acknowledge warning messages in the Logix Designer application that warn of the drive bypassing the STO function and unintended motion can occur. The integrated safety drive does not respond to requests of the STO function if MDC mode is entered.

It is your responsibility to maintain machine safety integrity while executing motion direct commands. One alternative is to provide ladder logic for Machine Maintenance mode that leaves the controller in Run mode with safety functions executing.

Logix Designer Application Warning Messages

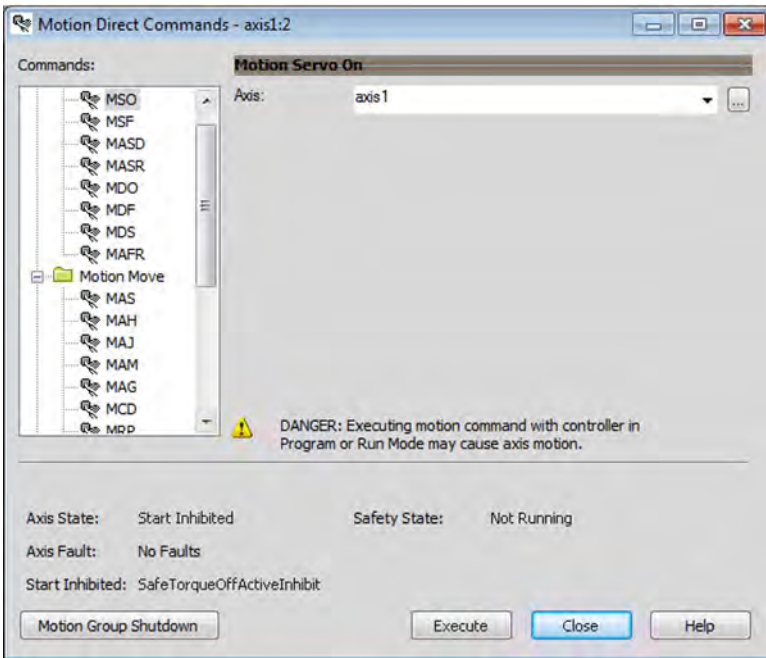
When the controller is in Run mode, executing safety functions, the Kinetix 5700 servo drive follows the commands that it receives from the safety controller. The controller reports Safety state = Running and Axis state = Stopped/Running, as shown in [Figure 158](#).

Figure 158 - Safety State Indications When Controller is in Run Mode (safety task executing)



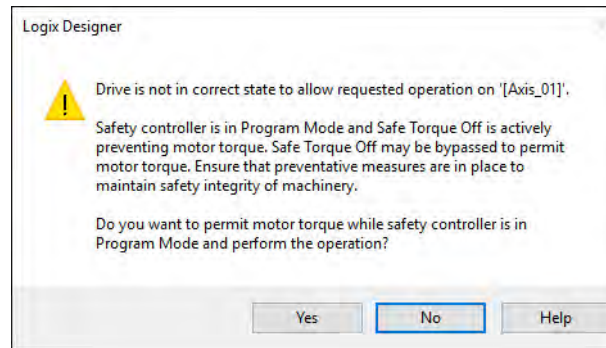
When the controller transitions to Program mode, the integrated safety drive is in the safe state (torque is not permitted). The controller reports Safety state = Not Running and Axis state = Start Inhibited, as shown in [Figure 159](#).

Figure 159 - Safety State Indications After Controller Transitions to Program Mode



When you issue a motion direct command to an axis to produce torque in Program mode, for example MSO or MDS, with the safety connection present to the drive, a warning message is presented before the motion direct command is executed, as shown in [Figure 160](#).

Figure 160 - STO Bypass Prompt When the Safety Controller is in Program Mode



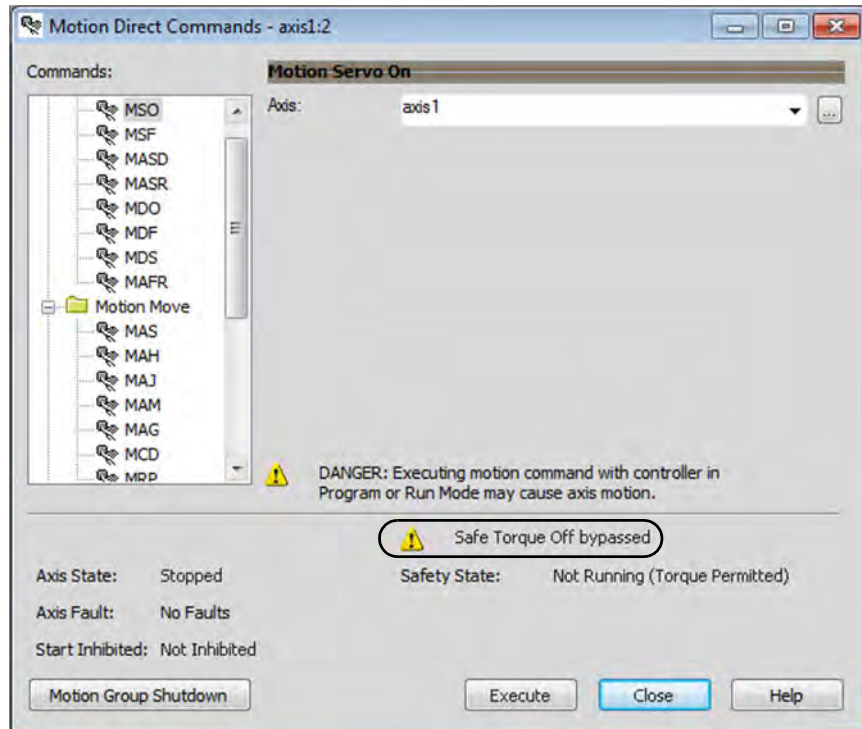
ATTENTION: Unexpected motion and the possibility of personal injury or equipment damage exists if a motion direct command is issued for one axis of any 2198-Dxxx-ERS3 dual-axis inverter. Both (A and B) inverters associated with the physical drive permit torque after you acknowledge this warning message by clicking Yes. Make sure that preventive measures are in place for both axes to maintain the safety integrity of the machine.

IMPORTANT The warning in [Figure 160](#) is displayed only the first time a motion direct command is issued.

After you acknowledge the warning message by clicking Yes, torque is permitted by the drive and a warning message is indicated in the software as shown in [Figure 161](#). The controller reports Safety state = Not Running (torque permitted), Axis state = Stopped/Running and Persistent Warning = Safe Torque Off Bypassed.

IMPORTANT Switch the controller to Run mode to exit Motion Direct Command mode and end the STO function bypass.

Figure 161 - Safety State Indications After Controller Transitions to Program Mode (MDC executing)



IMPORTANT The persistent warning message text Safe Torque Off bypassed appears when a motion direct command is executed.

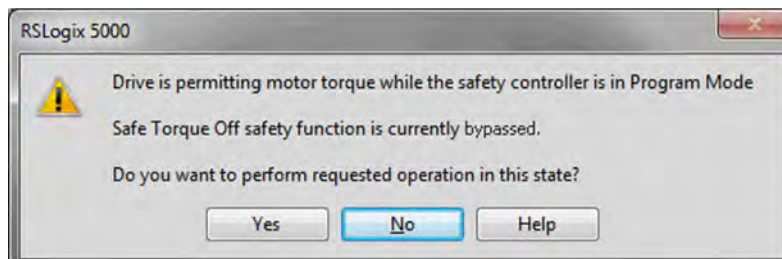
The warning message persists even after the dialog is closed and reopened as long as the integrated safety drive is in STO Bypass mode.

The persistent warning message is removed only after the integrated safety drive's Safety State is restored to the Running state.

Torque Permitted in a Multi-workstation Environment

The warning in [Figure 162](#) is displayed to notify a second user working in a multi-workstation environment that the first user has placed the integrated safety drive in the STO state and that the current action is about to bypass the STO state and permit torque.

Figure 162 - STO Bypass Prompt When MDC is Issued in Multi-workstation Environment



Warning Icon and Text in Axis Properties

In addition to the other warnings that require your acknowledgement, the Logix Designer application also provides warning icons and persistent warning messages in other Axis Properties dialog boxes when the integrated safety drive is in STO Bypass mode.

Figure 163 - Axis and Safe State Indications on the Hookup Services Dialog Box

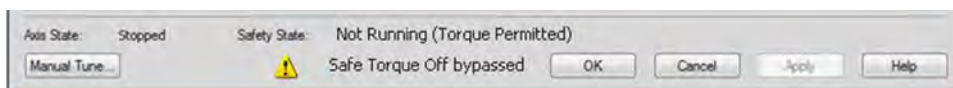


Figure 164 - Axis and Safe State Indications on Motion Direct Commands Dialog Box

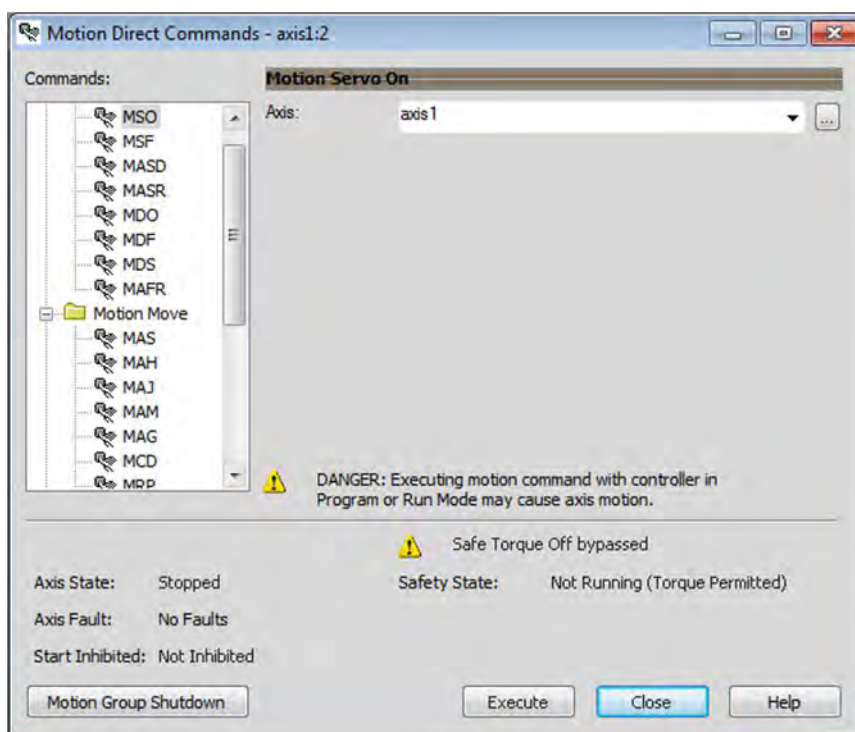
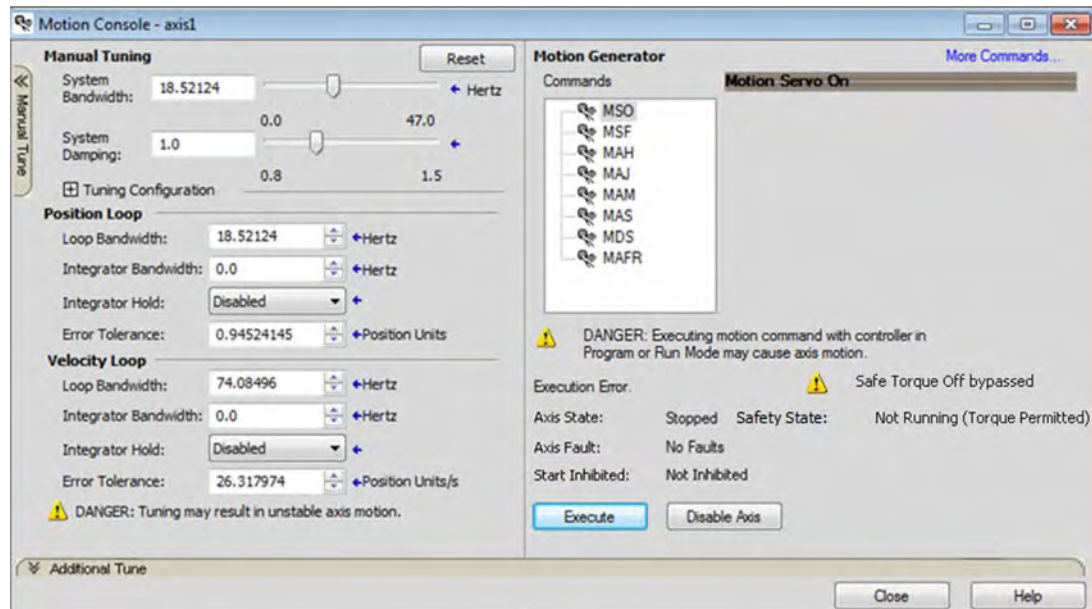


Figure 165 - Axis and Safe State Indications on the Motion Console Dialog Box



Functional Safety Considerations



ATTENTION: Before maintenance work can be performed in Program mode, the developer of the application must consider the implications of allowing motion through motion direct commands and should consider developing logic for run-time maintenance operations to meet the requirements of machine safety operating procedures.



ATTENTION: Motion is allowed and the STO function is not available when motion direct commands are used in Program mode. Motion direct commands issued when the controller is in Program mode cause the drive to bypass the STO Active condition. It is your responsibility to implement additional preventive measures to maintain safety integrity of the machinery during execution of motion direct commands in Program mode.



ATTENTION: To avoid personal injury and damage to equipment in the event of unauthorized access or unexpected motion during authorized access, return the controller to Run mode and remove the key before leaving the machine unattended.

Integrated Safe Torque-off Specifications

IMPORTANT To maintain safety rating, Kinetix 5700 drives must be installed inside protected control panels or cabinets appropriate for the environmental conditions of the industrial location. The protection class of the panel or cabinet must be IP54 or higher.

Table 167 - Integrated STO Specifications

| Attribute | Value | Logix Designer Tag Name |
|--|-------------------------------|--------------------------------|
| Safety connection RPI, min | 6 ms | N/A |
| Input assembly connections (2198-xxxx-ERS3 drives) | 3 | N/A |
| Input assembly connections (2198-xxxx-ERS4 drives) | 1 | |
| Output assembly connections | 1 | N/A |
| Integrated safety open request support | Type 1 and Type 2 requests | N/A |
| Axis safety status | Bit 0: Safety fault | Axis.SafetyFaultStatus |
| | Bit 1: Safety reset request | Axis.SafetyResetRequestStatus |
| | Bit 2: Safety Reset Required | Axis.SafetyResetRequiredStatus |
| | Bit 3: Safe torque-off active | Axis.SafeTorqueOffActiveStatus |
| | Bit 4: Safe torque disabled | Axis.SafeTorqueDisabledStatus |
| | Bit 5...31: Undefined (0) | N/A |
| Axis safety faults | Bit 1: Safety core fault | Axis.SafetyCoreFault |
| | Bit 3: Safe torque-off fault | Axis.SafeTorqueOffFault |
| | All others: Undefined (0) | N/A |

Table 168 - Single-axis Inverter STO Assembly Specifications

| Attribute | Value | Logix Designer Tag Name |
|------------------------|-------------------------------|---|
| Safety input assembly | Bit 0: Torque disabled | Drv:SI.TorqueDisabled |
| | Bit 6: Safety fault | Drv:SI.SafetyFault |
| | Bit 7: Reset required | Drv:SI.ResetRequired |
| Safety output assembly | Bit 0: Safe torque-off output | Drv:SO.SafeTorqueOff or Drv:SO.STOOutput |
| | Bit 7: Reset request | Drv:SO.Reset or Drv:SO.ResetRequest |

Table 169 - Dual-axis Inverter STO Assembly Specifications

| Attribute | Value | Logix Designer Tag Name |
|------------------------|--|---|
| Safety input assembly | Byte 0 Bit 0: Torque disabled 1 | Drv:SI.TorqueDisabled1 |
| | Byte 0 Bit 6: Safety fault 1 | Drv:SI.SafetyFault1 |
| | Byte 0 Bit 7: Reset required 1 | Drv:SI.ResetRequired1 |
| | Byte 1 Bit 0: Torque disabled 2 | Drv:SI.TorqueDisabled2 |
| | Byte 1 Bit 6: Safety fault 2 | Drv:SI.SafetyFault2 |
| | Byte 1 Bit 7: Reset required 2 | Drv:SI.ResetRequired2 |
| Safety output assembly | Byte 0 Bit 0: Safe torque-off output 1 | Drv:SO.SafeTorqueOff1 or Drv:SO.STOOutput1 |
| | Byte 0 Bit 7: Reset request 1 | Drv:SO.Reset1or Drv:SO.ResetRequest1 |
| | Byte 1 Bit 0: Safe torque-off output 2 | Drv:SO.SafeTorqueOff2 or Drv:SO.STOOutput2 |
| | Byte 1 Bit 7: Reset request 2 | Drv:SO.Reset2or Drv:SO.ResetRequest2 |

Interconnect Diagrams

This appendix provides wiring examples and system block diagrams for your Kinetix® 5700 system components.

| Topic | Page |
|--|------|
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| Contactors Wiring Examples | 358 |
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Interconnect Diagram Notes

This appendix provides wiring examples to assist you in wiring the Kinetix 5700 drive system. These notes apply to the wiring examples on the following pages.

Table 170 - Interconnect Diagram Notes

| Note | Information |
|------|---|
| 1 | For power wiring specifications, refer to Wiring Requirements on page 141 . |
| 2 | For input fuse and circuit breaker sizes, refer to Circuit Breaker/Fuse Selection on page 48 . |
| 3 | For fuse and circuit breaker sizes and other 8720MC-RPS specifications, see the 8720MC Regenerative Power Supply User Manual, publication 8720MC-RM001 . |
| 4 | The iTRAK® power supply must have three-phase power sourced from grounded-wye power distribution. |
| 5 | AC (EMC) line filter is required for CE compliance. Place line filter as close to the drive as possible and do not route very dirty wires in wireway. If routing in wireway is unavoidable, use shielded cable with shields grounded to the drive chassis and filter case. For AC line filter specifications, refer to Kinetix Servo Drives Specifications Technical Data, publication KNX-TD003 . 2198-DBRxx-F line filters are preferred. |
| 6 | Terminal block is required to make connections. |
| 7 | Cable shield clamp must be used to meet CE requirements with Bulletin 2090 power cables 2 AWG and smaller. See Customer-supplied Motor Power Cables on page 178 to meet CE when wiring 2198-S263-ERSx and 2198-S312-ERSx drives with power cables larger than 2 AWG. |
| 8 | 2198-Dxxx-ERSx dual-axis inverters include separate digital inputs, DSL feedback, universal feedback, motor power, and motor brake wiring plugs for each axis. |
| 9 | See Digital Inputs Connector Pinouts beginning on page 103 for digital input configurable functions and default settings. |
| 10 | <ul style="list-style-type: none"> When a 2198-Sxxx-ERSx single-axis inverter is the first drive module (adjacent to the 2198-CAPMOD-2240 capacitor module) you must configure the Digital Input category in the Logix Designer application as Regeneration OK and wire the IOD connector. When a 2198-Dxxx-ERSx dual-axis inverter is the first drive module (adjacent to the 2198-CAPMOD-2240 capacitor module) and Axis 1 and 3 are used, you must configure the Digital Input category in the Logix Designer application as Regeneration OK and wire the IOD connector for each axis. |

Table 170 - Interconnect Diagram Notes (continued)

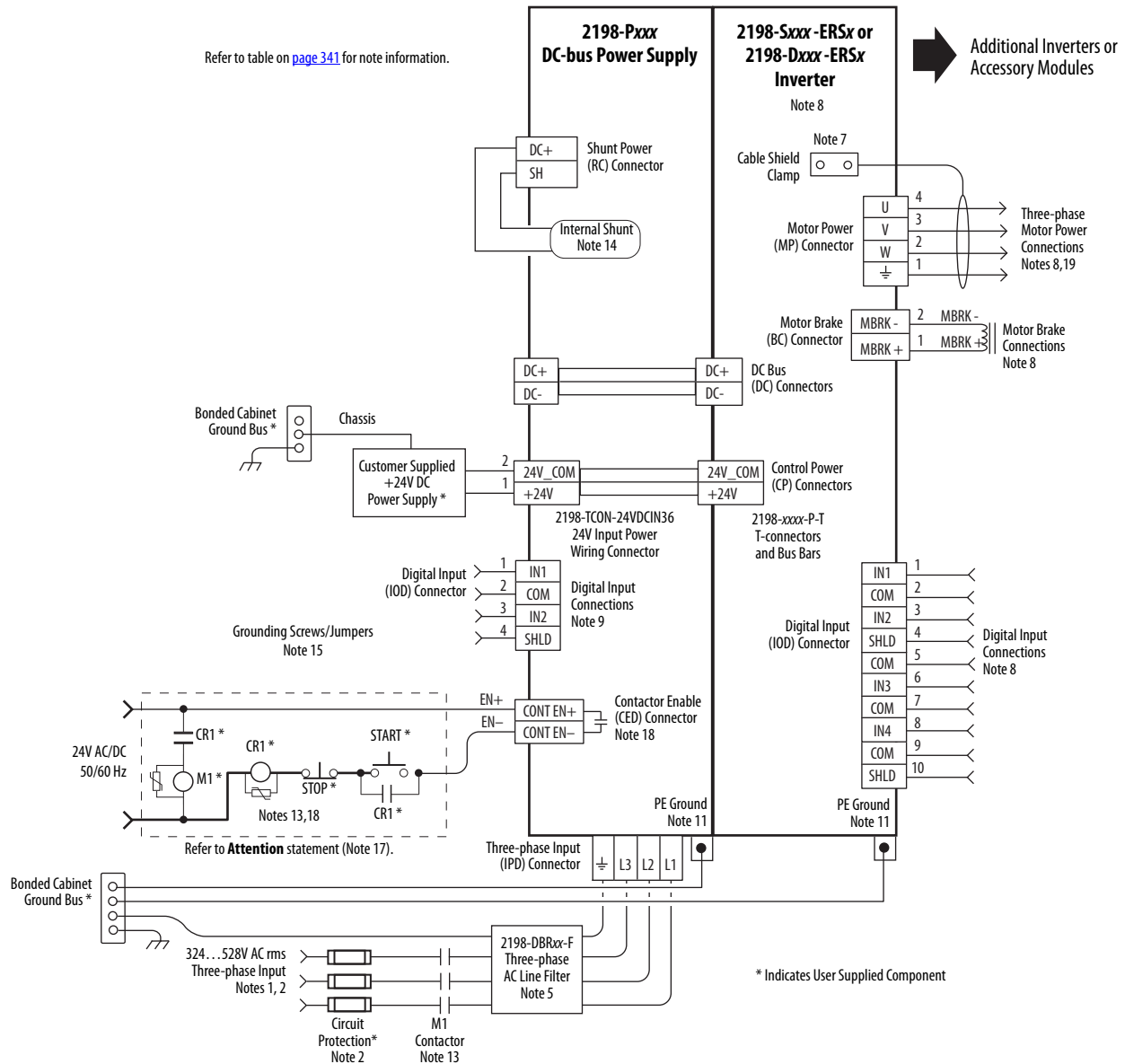
| Note | Information |
|------|--|
| 11 | PE ground connection bonded to the panel must be used to meet CE requirements. See Ground the Drive System on page 139 . |
| 12 | Contactor coil (MC) needs integrated surge suppressors for AC coil operation and must have a normally-open auxiliary contact that is terminated at TB3 (24V DC to MC input as shown). See the 8720MC Regenerative Power Supply User Manual, publication 8720MC-RM001 for contactor types and wiring examples. |
| 13 | For M1 contactor selection and specifications, refer to Contactor Selection on page 50 . |
| 14 | Internal shunt wired to the RC connector is default configuration. Remove internal shunt wires to attach external shunt wires. |
| 15 | Default configuration for ground screws or jumper is for grounded power at customer site. For impedance-grounded power configurations, remove the screws/jumper. Refer to Input Power Configurations for Kinetix 5700 Power Supplies on page 129 for more information. |
| 16 | Leave jumper between PR2 and PR3 as shown to use the internal precharge resistor. Remove jumper when external precharge/circuit is required. For more information, refer to the 8720MC Regenerative Power Supply User Manual, publication 8720MC-RM001 . |
| 17 |  ATTENTION: Implementation of control circuits and risk assessment is the responsibility of the machine builder. Reference international standards EN 1050 and EN ISO 13849-1 estimation and safety performance categories. For more information, refer to Understanding the Machinery Directive, publication SHB-900 . |
| 18 |  ATTENTION: An AC three-phase mains contactor must be wired in series between the branch circuit protection and the Kinetix 5700 system power supply. In addition, the AC three-phase contactor control string must be wired in series with the contactor-enable relay at the CED connector. Refer to Contactor Enable Relay on page 110 , for more information. The recommended minimum wire size for wiring the circuitry to the contactor-enable connector is 1.5 mm ² (16 AWG). |
| 19 | For motor cable specifications, refer to Kinetix Motion Accessories Specifications Technical Data, publication KNX-TD004 . |
| 20 | Brake connector pins are labeled plus (+) and minus (-) or F and G respectively. Power connector pins are labeled U, V, W, and $\frac{\perp}{\perp}$ (GND) or A, B, C, and $\frac{\perp}{\perp}$ (D) respectively. |
| 21 | LDAT-Series linear thrusters do not have a brake option, so only the 2090-CPWM7DF-xxAAxx or 2090-CPWM7DF-xxAFxx motor power cables apply. |
| 22 | MPAS-Bxxxx-VxxSxA (ballscrew) linear stages use the 9V supply. MPAS-Bxxxx-ALMx2C (direct-drive) linear stages use the 5V supply. |
| 23 | Mount the 8720MC-RPS unit on the same panel and as close to the Kinetix 5700 drive system as possible. DC-bus cables not to exceed 2.0 m (6.5 ft), maximum length. See the 8720MC Regenerative Power Supply User Manual, publication 8720MC-RM001 , for installation and wiring instructions. |
| 24 | The 2198-CAPMOD-2240 capacitor module is used in applications with up to 104 A maximum external DC-bus current. You can add the 2198-DCBUSCOND-RP312 DC-bus conditioner module to the left or right of the capacitor module when the external DC-bus current exceeds 104 A, up to a maximum of 208 A. |
| 25 | The Converter OK relay provides a 24V signal to non-Kinetix 5700 inverters indicating that they can draw power from the regenerative power supply and that the power supply is not faulted. This signal is intended for use with Kinetix 6000, Kinetix 6200, or Kinetix 7000 drives when migrating from the 8720MC-RPS to the 2198-RPxxx regenerative bus supply. Interposing relay can be required if more than one drive is attached. |

Power Wiring Examples

You must supply input power components. The three-phase line filter is wired downstream of the circuit protection devices. Each drive module includes the appropriate DC-bus link and connector set. The 24V supply can be jumpered from drive-to-drive by using discrete wires or the shared-bus connection system.

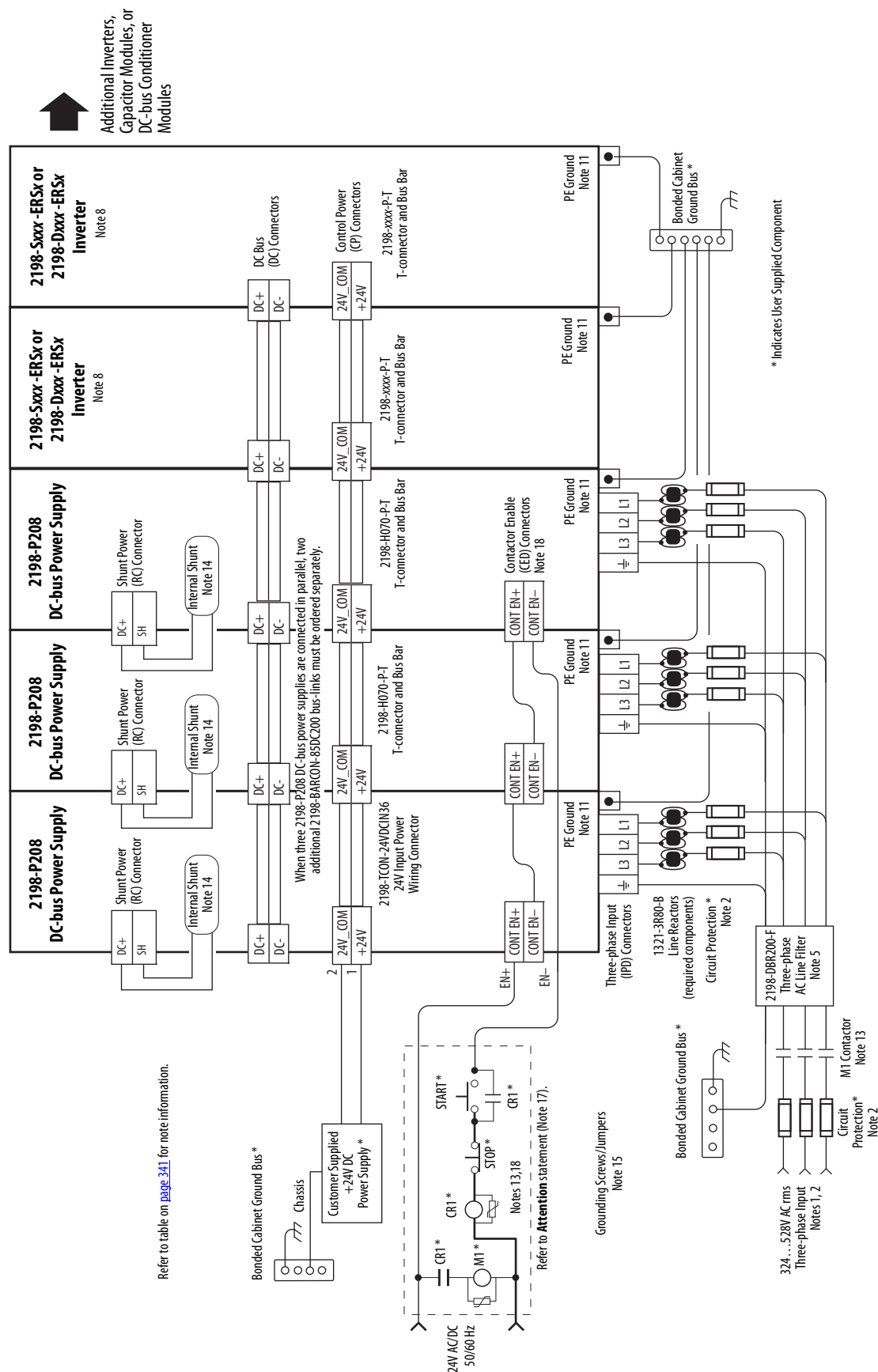
In this example, the inverter drives and optional accessory modules are downstream of a single 2198-Pxxx DC-bus power supply.

Figure 166 - DC-bus Power Supply (single converter) Configuration



In this example, the inverter drives and optional capacitor modules are downstream of three DC-bus (converter) power supplies. When two or three DC-bus power supplies are used, they must be catalog number 2198-P208. This configuration provides more power (kW) to the drive system.

Figure 167 - DC-bus Power Supply (multiple converters) Configuration



In this example, the 2198-CAPMOD-2240 capacitor module is included for energy storage and to improve dynamic performance.

Figure 168 - DC-bus Power Supply with Capacitor Module

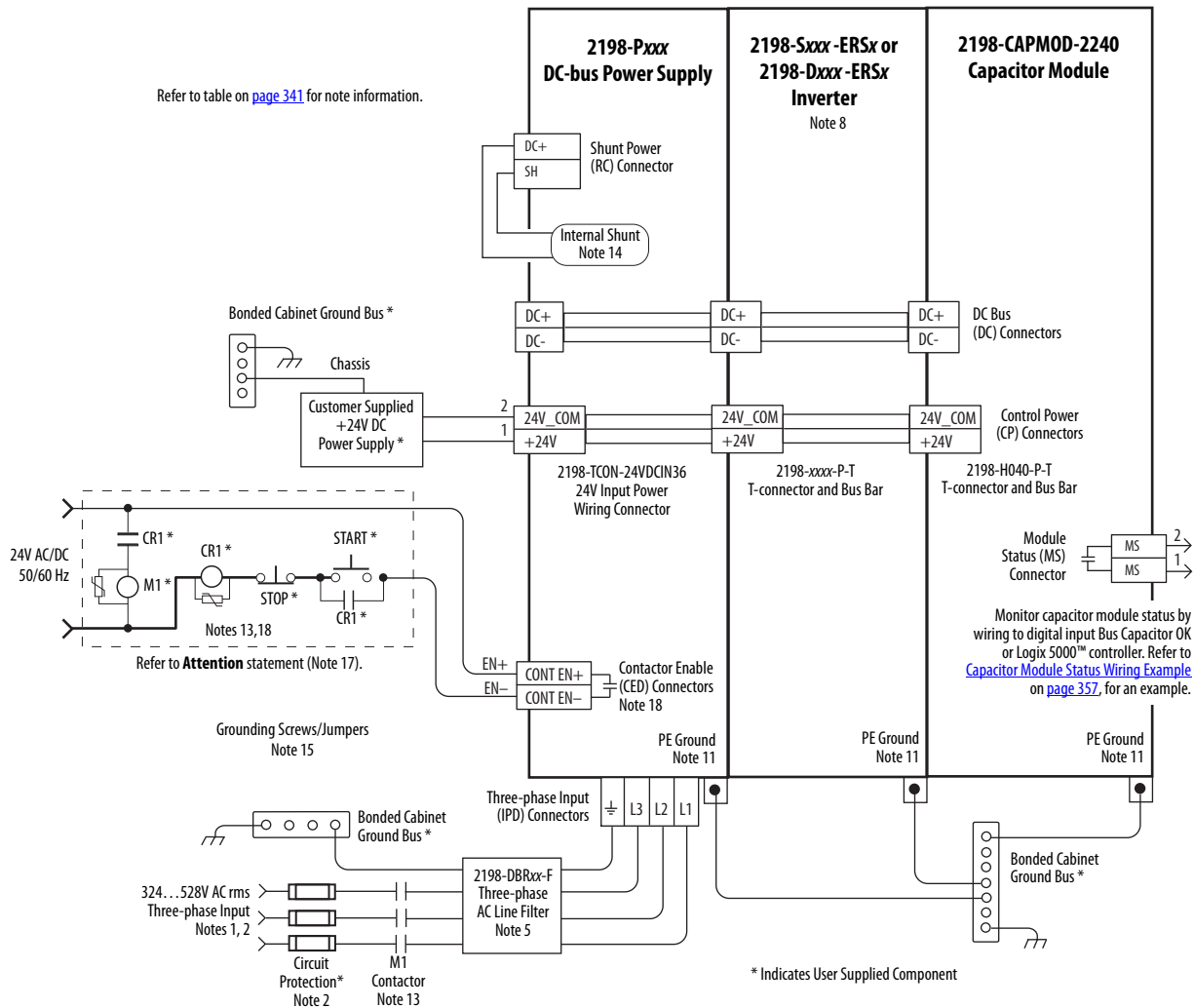
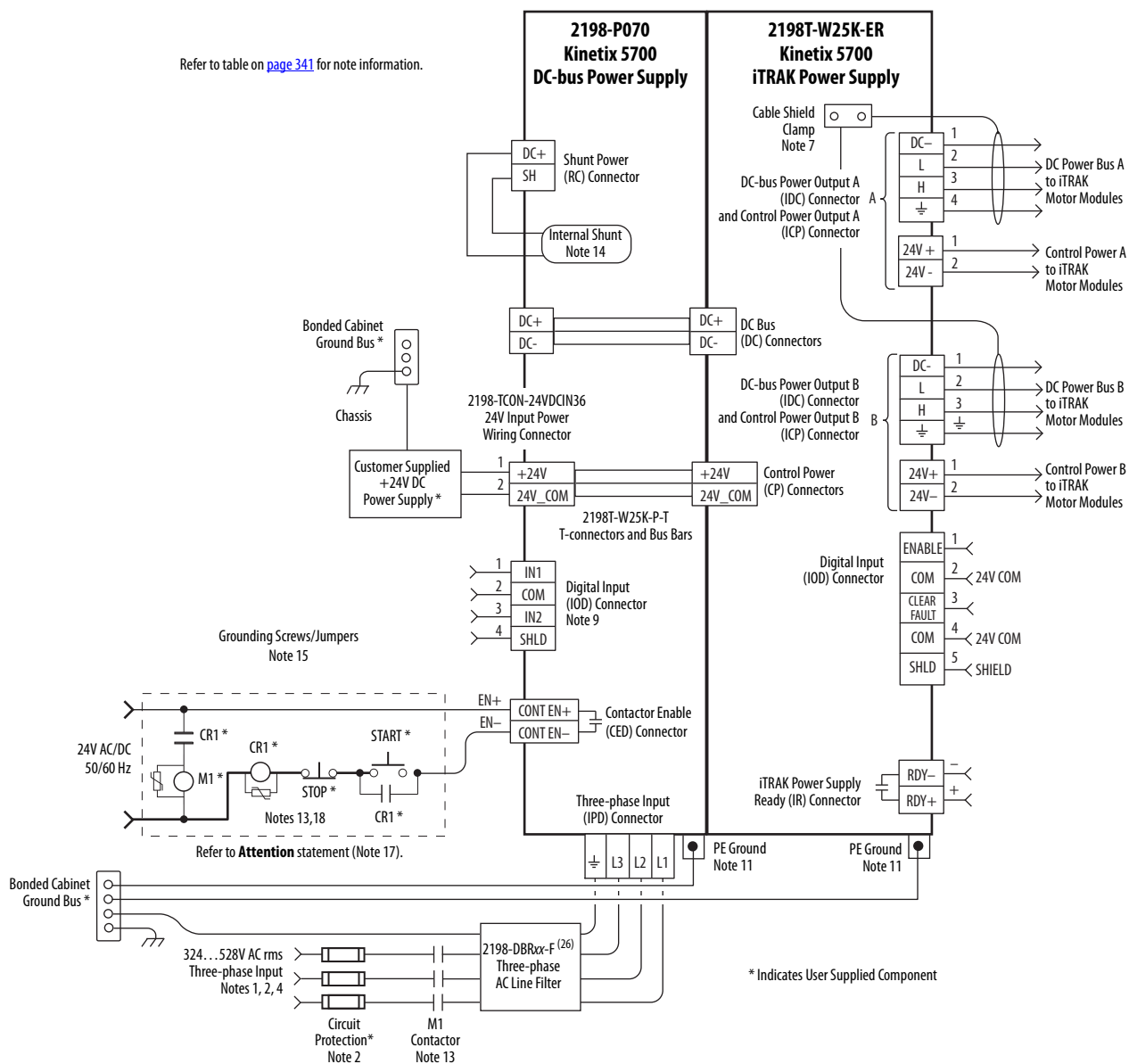


Figure 169 - DC-bus Power Supply (single iTRAK power supply) Configuration

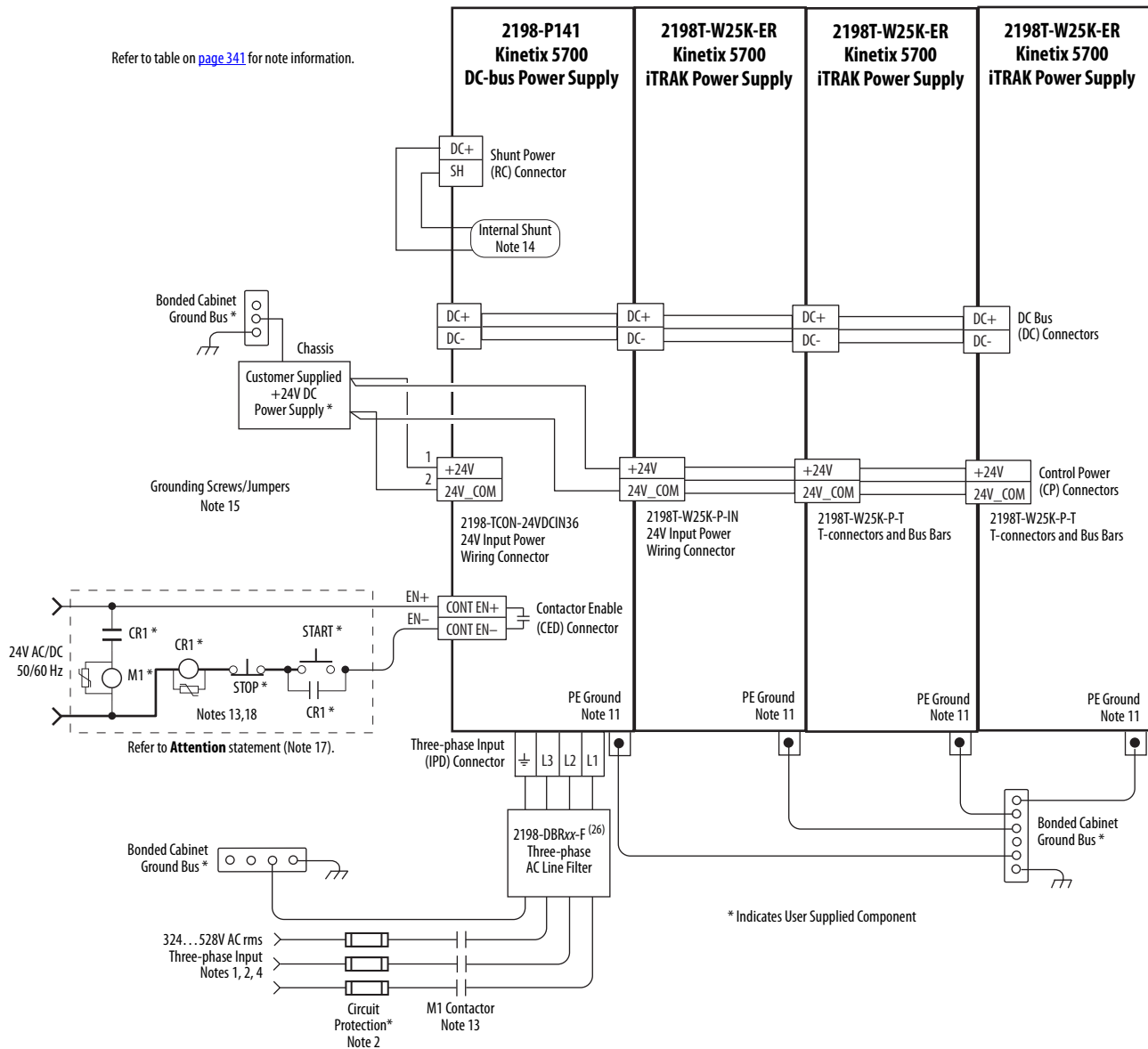


(26) AC (EMC) line filter can be required for CE compliance. Place line filter as close to the drive as possible and do not route very dirty wires in wireway. If routing in wireway is unavoidable, use shielded cable with shields grounded to the drive chassis and filter case. For AC line filter specifications, refer to Kinetix Servo Drives Specifications Technical Data, publication [KNX-TD003](#). 2198-DBRxx-F line filters are preferred.

IMPORTANT The 2198-RPxxx regenerative bus supply can replace the 2198-Pxxx DC-bus power supply in systems with the iTRAK power supply.

In this example, the DC-bus power supply 24V input-wiring connector and the three iTRAK power supply 24V input wiring connectors are wired separately. The 2198T-W25K-P-IN input wiring connector is rated for 41 A. See Appendix C on [page 391](#) to determine 24V current requirements needed for proper distribution for 24V control power.

Figure 170 - DC-bus Power Supply (multiple iTRAK power supply) Configuration

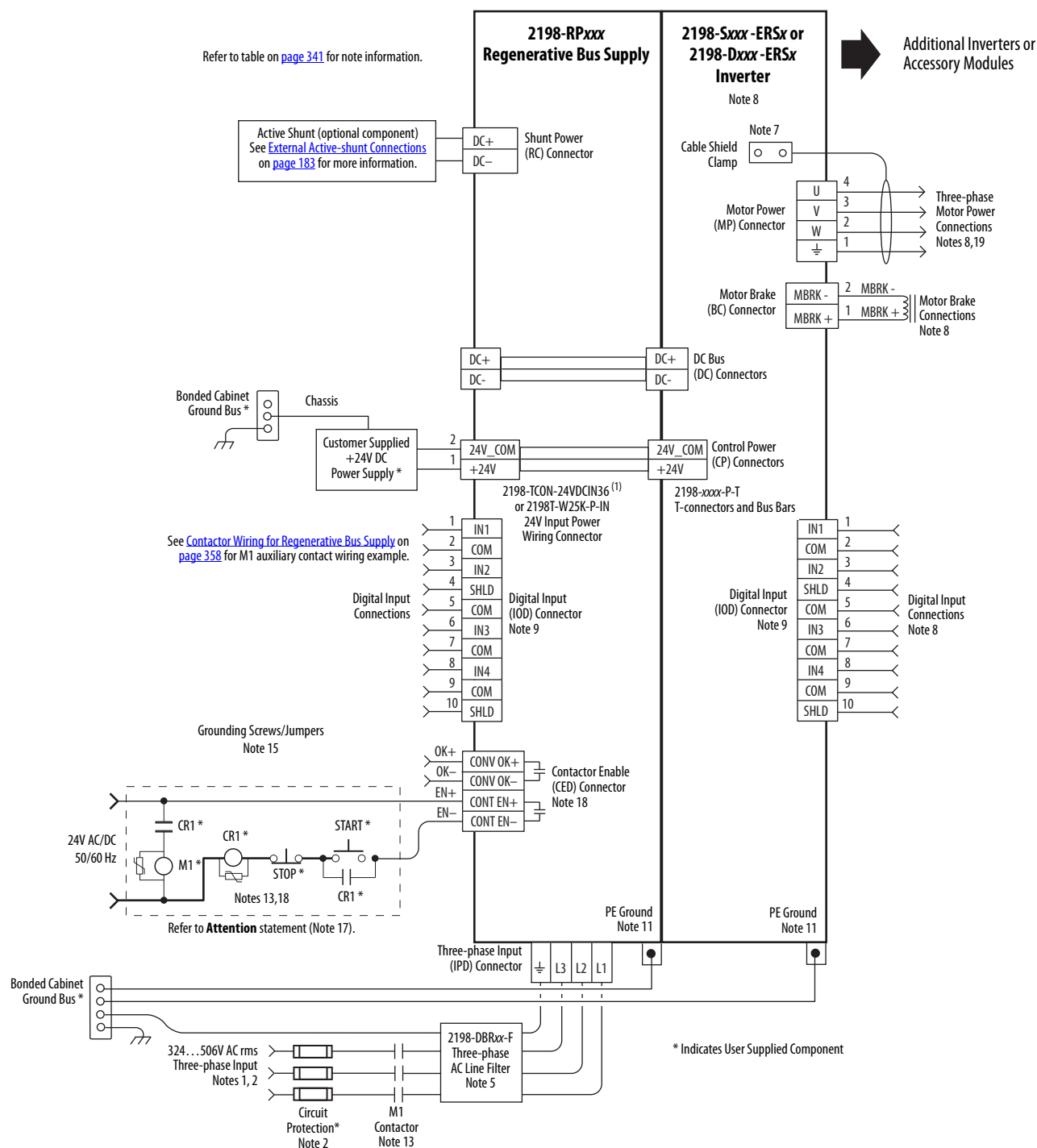


(26) AC (EMC) line filter can be required for CE compliance. Place line filter as close to the drive as possible and do not route very dirty wires in wireway. If routing in wireway is unavoidable, use shielded cable with shields grounded to the drive chassis and filter case. For AC line filter specifications, refer to Kinetix Servo Drives Specifications Technical Data, publication [KNX-TD003](#). 2198-DBRxx-F line filters are preferred.

IMPORTANT The 2198-RPxxx regenerative bus supply can replace the 2198-Pxxx DC-bus power supply in systems with the iTRAK power supply.

In this example, the inverter drives and optional accessory modules are downstream of a 2198-RPxxx regenerative bus supply.

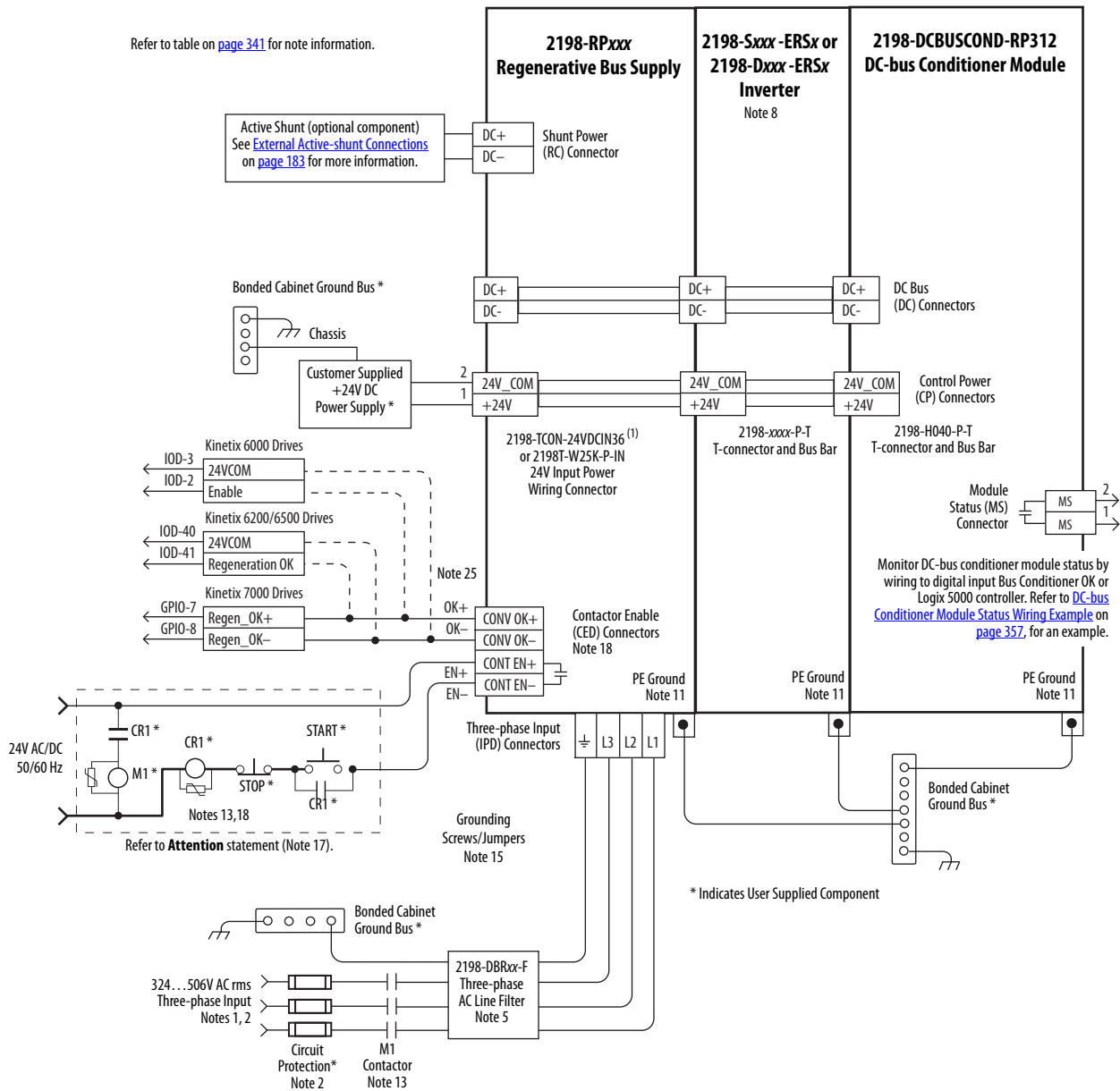
Figure 171 - Regenerative Bus Supply Configuration



- (1) Use 2198-TCON-24VDCIN36 input wiring connector with 2198-RP088 and 2198-RP200 bus supplies. Use 2198T-W25K-P-IN input wiring connector with 2198-RP263 and 2198-RP312 bus supplies. See [CP Connector Wiring - Shared Bus](#) on [page 146](#) for wiring specifications.

In this example, the 2198-DCBUSCOND-RP312 DC-bus conditioner module is included because total motor cable length exceeds 400 m (1312 ft).

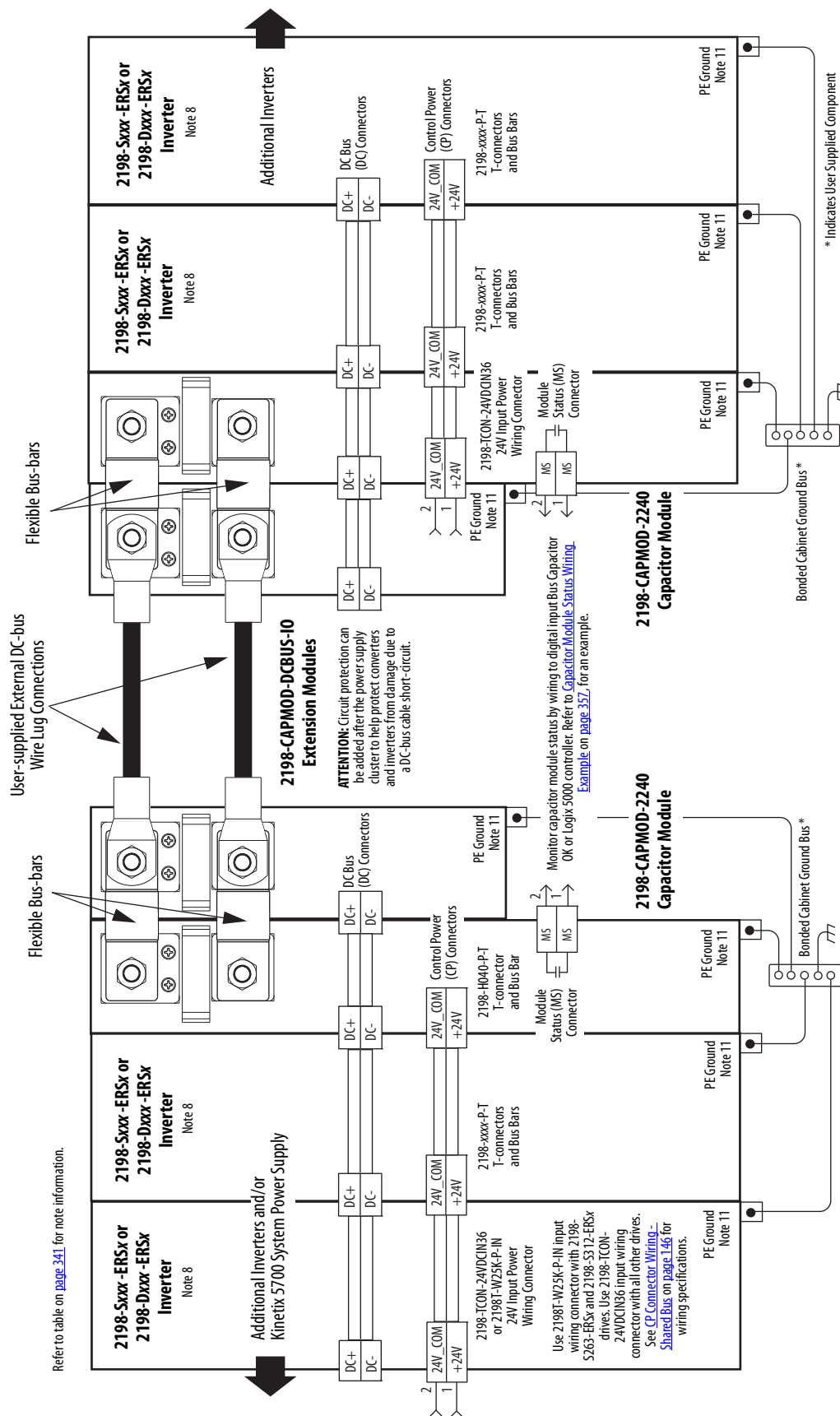
Figure 172 - Regenerative Bus Supply with DC-bus Conditioner Module



- (1) Use 2198-TCON-24VDCIN36 input wiring connector with 2198-RP088 and 2198-RP200 bus supplies. Use 2198T-W25K-P-IN input wiring connector with 2198-RP263 and 2198-RP312 bus supplies. See [CP Connector Wiring - Shared Bus](#) on [page 146](#) for wiring specifications.

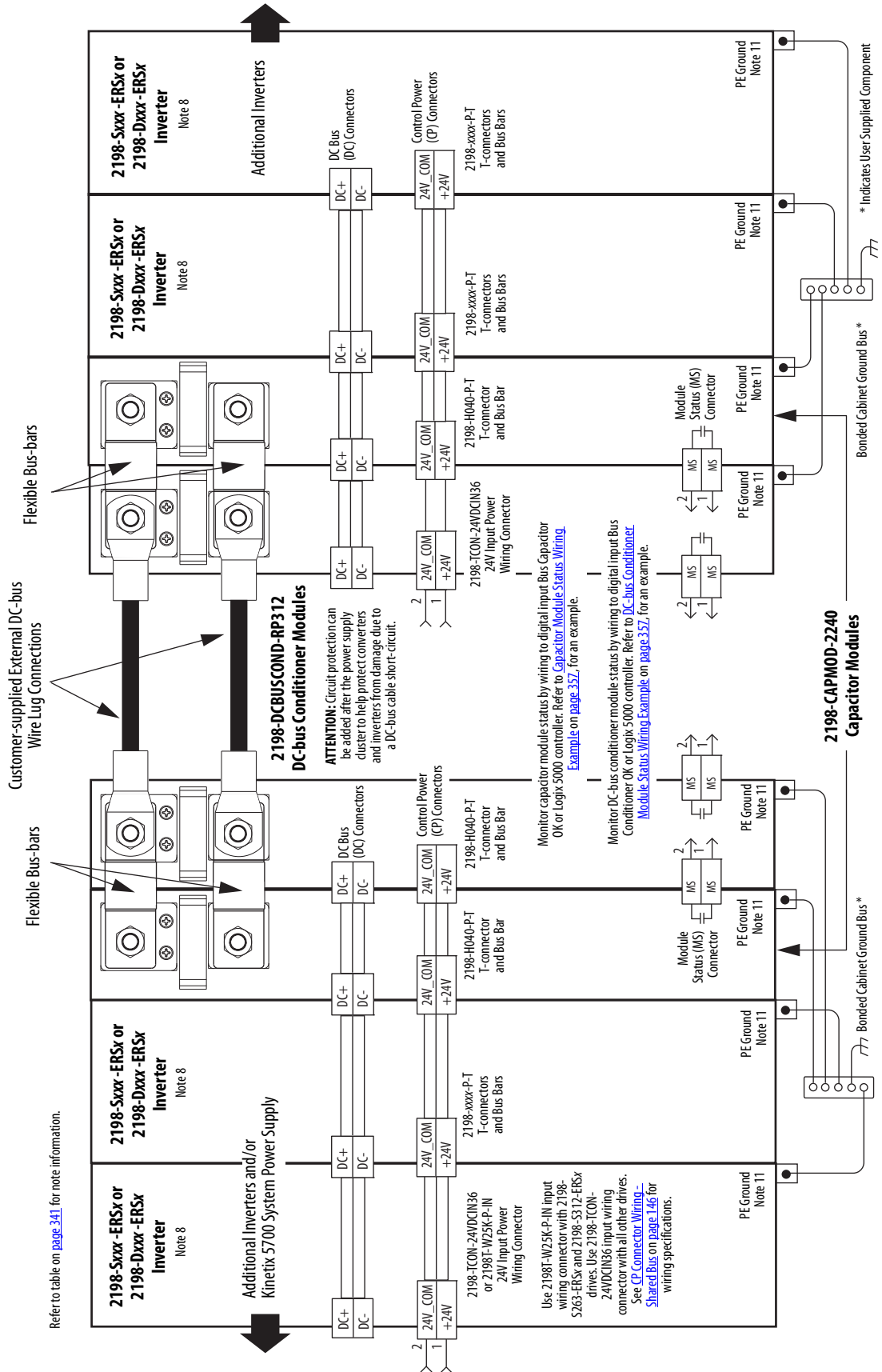
In this example, the 2198-CAPMOD-2240 capacitor module and 2198-CAPMOD-DCBUS-IO extension module are used for energy storage and to extend the DC-bus voltage to another inverter cluster. The capacitor modules are used alone when the external DC-bus current is ≤ 104 A. The extension module (or any combination of two accessory modules) is needed when the external DC-bus current is > 104 A, up to a maximum 208 A.

Figure 173 - Kinetix 5700 Extended Drive System Example (extension module)



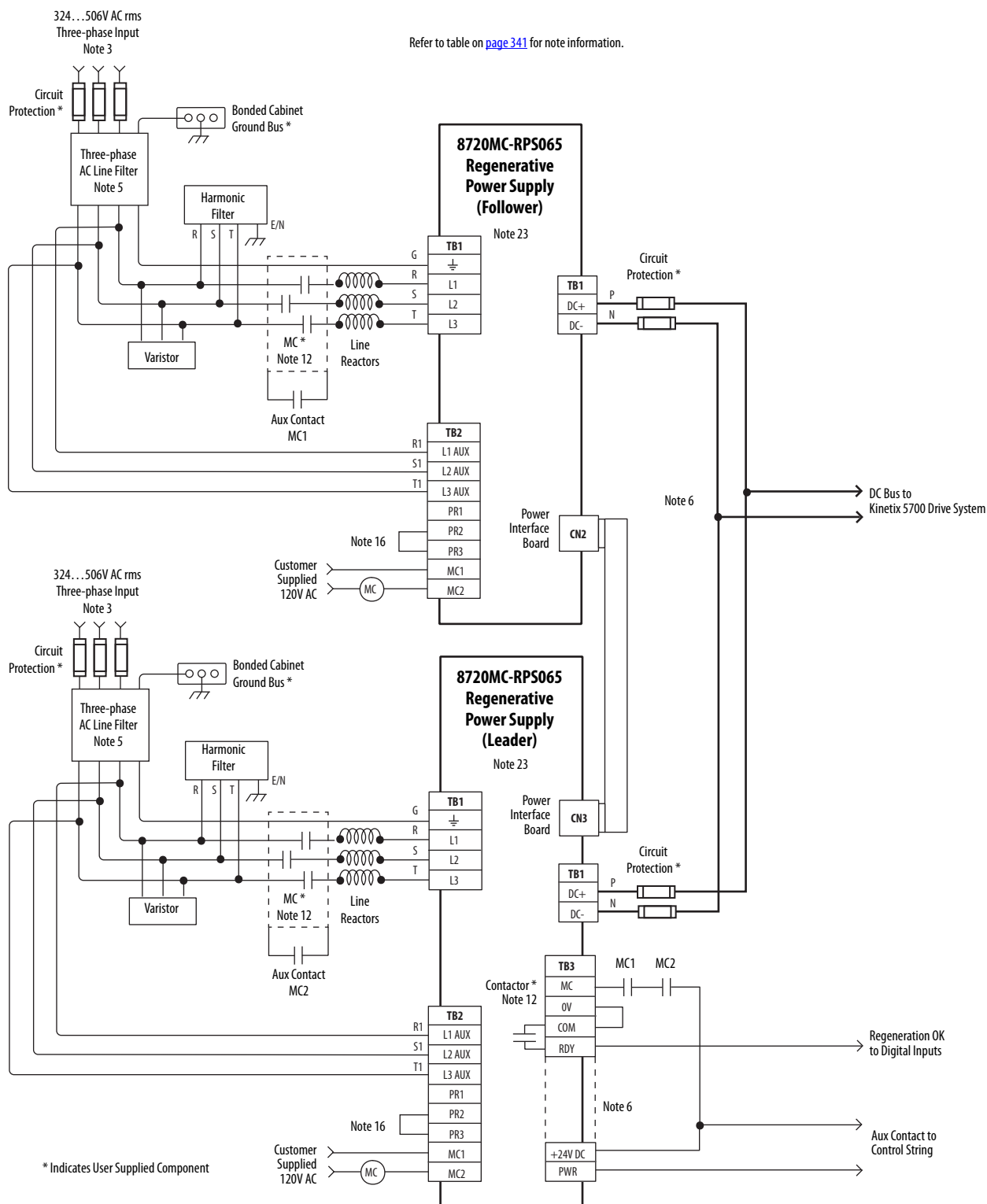
In this example, the 2198-CAPMOD-2240 capacitor module and 2198-DCBUSCOND-RP312 DC-bus conditioner module are used for energy storage and to extend the DC-bus voltage to another inverter cluster. The capacitor modules are used alone when the external DC-bus current is ≤ 104 A. The DC-bus conditioner module (or any combination of two accessory modules) is needed when the external DC-bus current is > 104 A, up to a maximum 208 A.

Figure 174 - Kinetix 5700 Extended Drive System Example (DC-bus conditioner module)



In this example, three-phase AC input power is fed to two 8720MC-RPS065 units in a leader/follower configuration. The DC-bus (TB1) terminals connect to the Kinetix 5700 DC-bus via the DC-bus conditioner module because the system current exceeds 104 A.

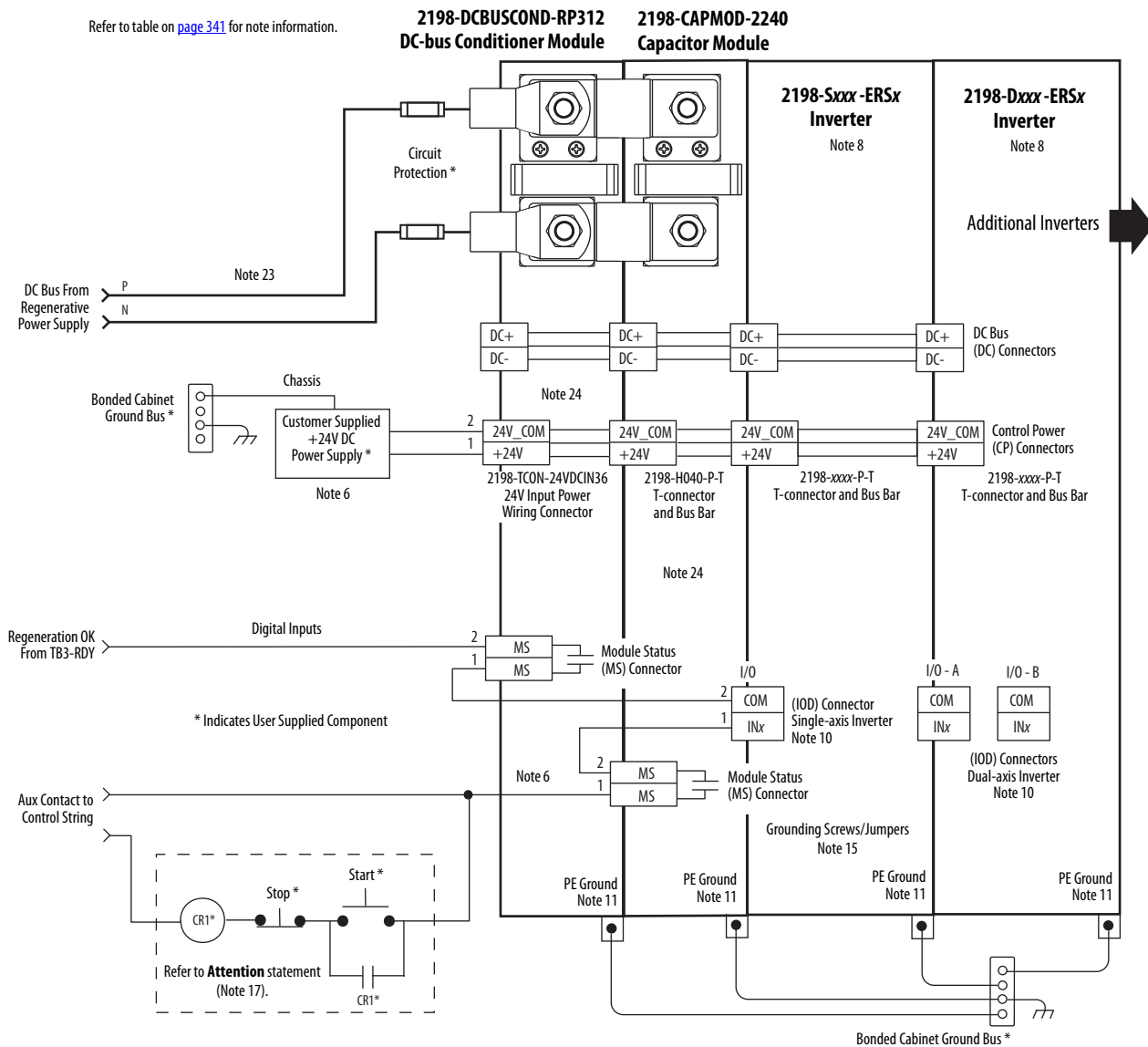
Figure 175 - 8720MC-RPS065 Leader/Follower Units with Kinetix 5700 Drive System



IMPORTANT The 8720MC-RPS regenerative power supply is not compatible with the iTRAK power supply.

8720MC-RPS065 Leader/Follower Units with Kinetix 5700 Drive System (continued)

Refer to table on [page 341](#) for note information.

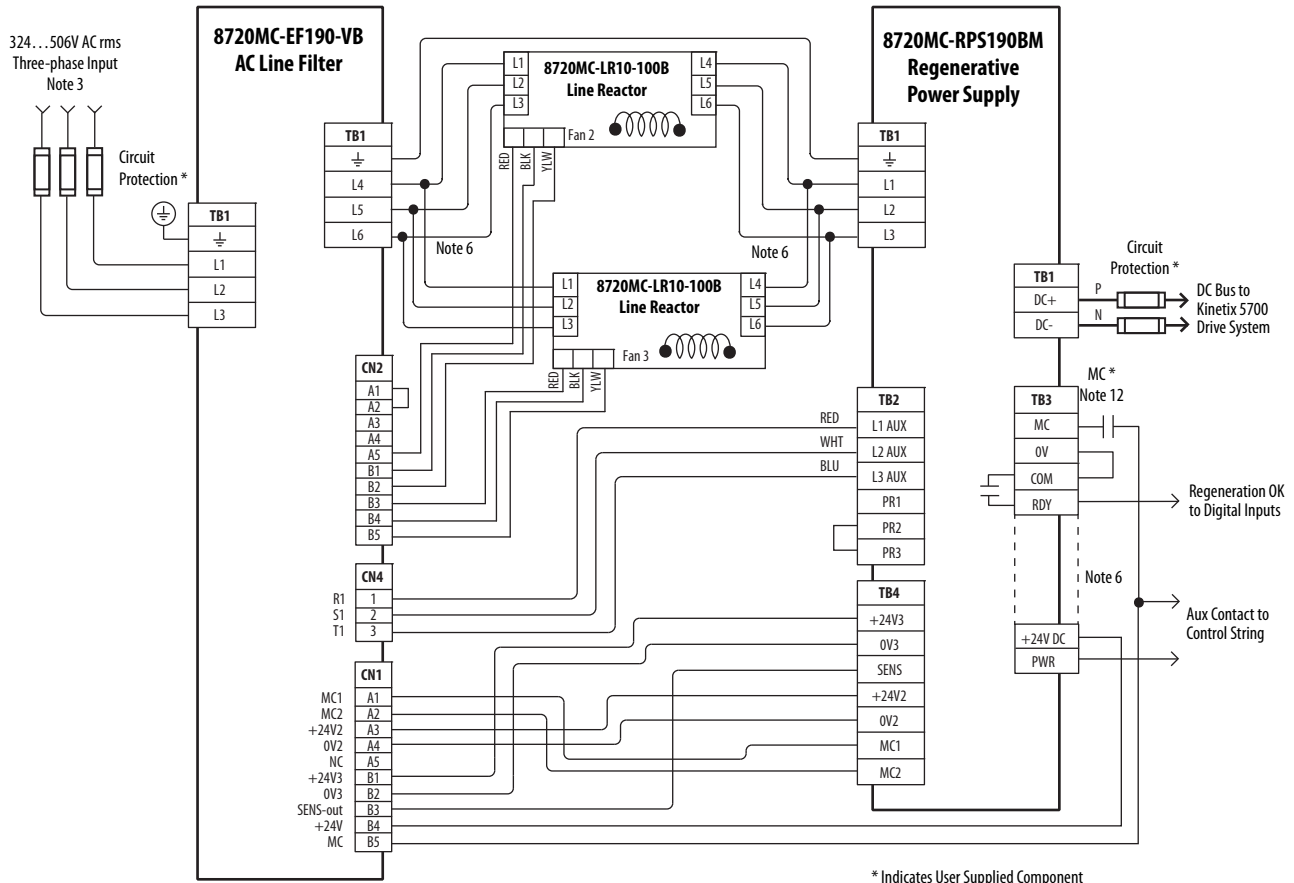


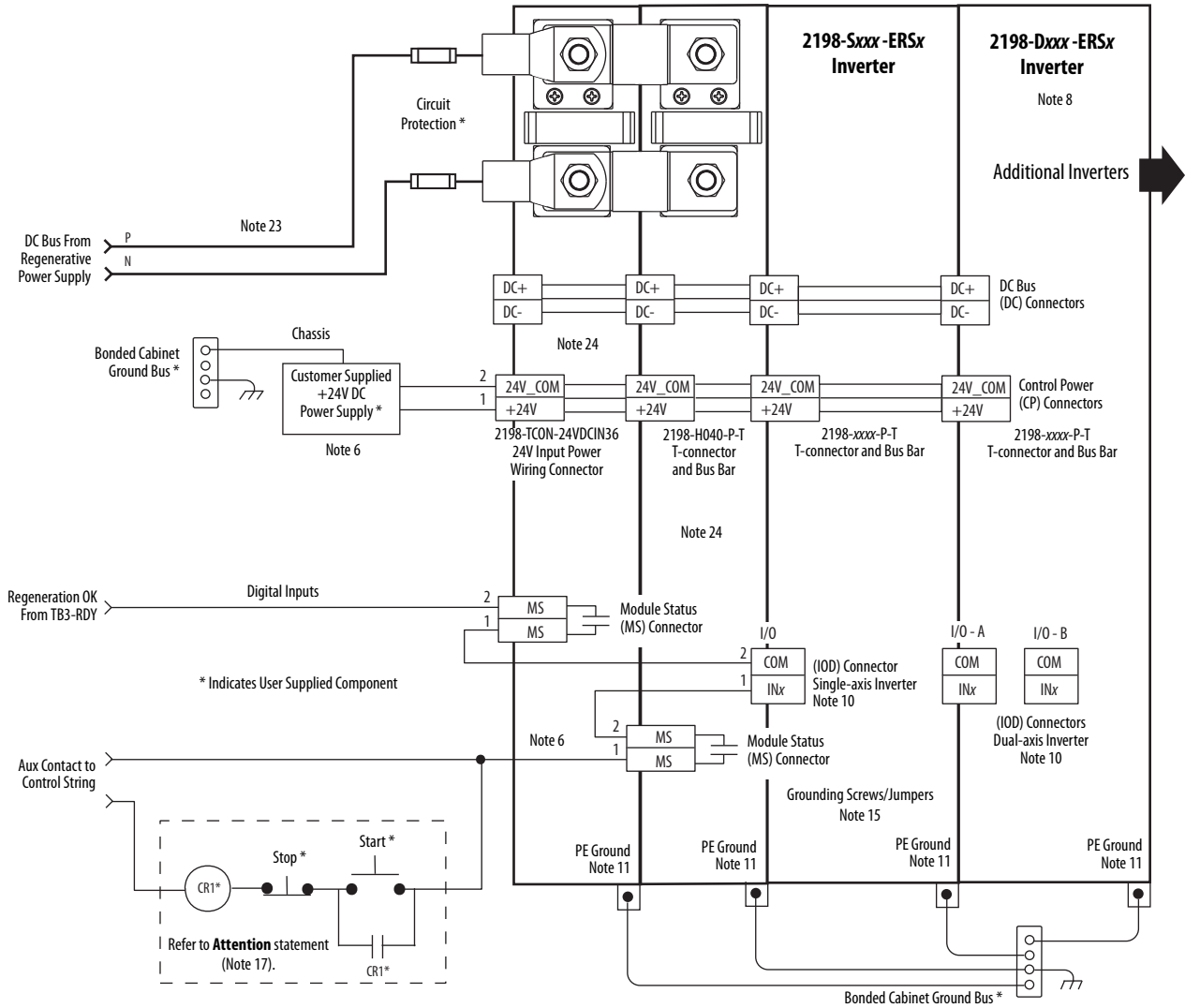
In this example, three-phase AC input power is fed to the 8720MC-RPS190 unit. The DC-bus (TB1) terminals connect to the Kinetix 5700 DC-bus via the DC-bus conditioner module because the system current exceeds 104 A.

IMPORTANT The 8720MC-RPS regenerative power supply is not compatible with the iTRAK power supply.

Figure 176 - 8720MC-RPS190 Unit with Kinetix 5700 Drive System

Refer to table on [page 341](#) for note information.

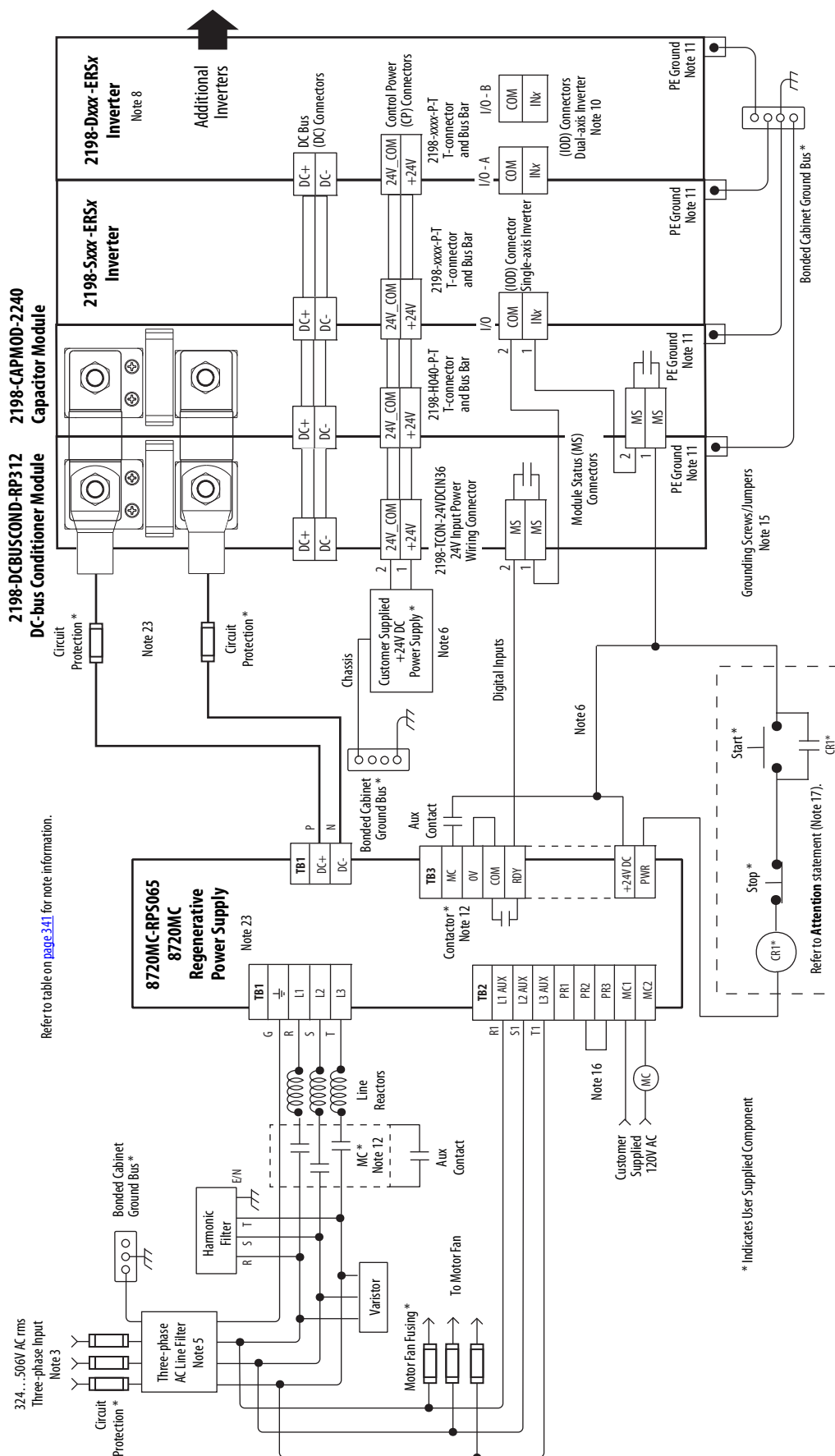


8720MC-RPS190 Unit with Kinetix 5700 Drive System (continued)Refer to table on [page 341](#) for note information.
2198-DCBUSCOND-RP312 **2198-CAPMOD-2240**
DC-bus Conditioner Module **Capacitor Module**


In this example, three-phase AC input power is fed to the Bulletin 8720MC-RPS065 regenerative power supply. The DC-bus voltage supplies the Kinetix 5700 DC-bus via the 2198-CAPMOD-2240 capacitor module. In configurations that exceed 104 A, up to a maximum of 208 A, the DC-bus conditioner module is also required.

IMPORTANT The 8720MC-RPS regenerative power supply is not compatible with the iTRAK power supply.

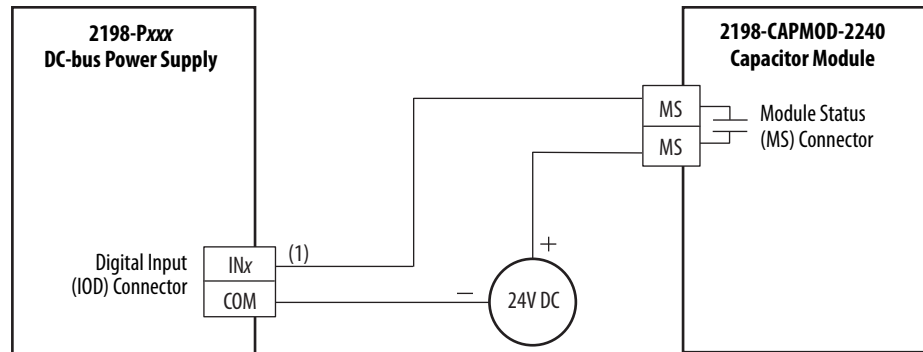
Figure 177 - 8720MC-RPS with Kinetix 5700 Drive System



Capacitor Module Status Wiring Example

You can configure either of the DC-bus power supply digital inputs as Bus Capacitor OK in the Logix Designer application to monitor the Module Status output. Refer to [page 205](#) to see how the DC-bus power supply Digital Inputs category is configured.

Figure 178 - DC-bus Power Supply with Capacitor Module



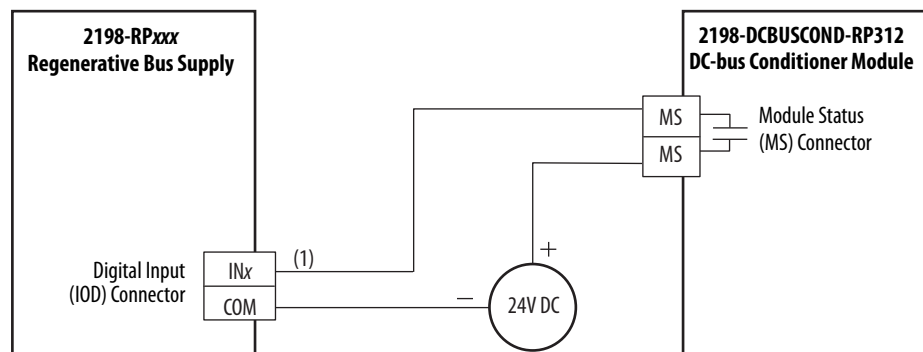
(1) Configure either of two digital inputs as Bus Capacitor OK. For DC-bus power supply configurable functions, see the [DC-bus Power Supply Configurable Functions](#) table on [page 103](#).

Refer to the Kinetix 5700 Capacitor Modules Installation Instructions, publication [2198-IN008](#), for additional installation information.

DC-bus Conditioner Module Status Wiring Example

You can configure any of the regenerative bus supply digital inputs as Bus Conditioner OK in the Logix Designer application to monitor the Module Status output. Refer to [page 209](#) to see how the regenerative bus supply Digital Inputs category is configured.

Figure 179 - Regenerative Bus Supply with DC-bus Conditioner Module



(1) Configure any one of four digital inputs as Bus Conditioner OK. For regenerative bus supply configurable functions, see the [Regenerative Bus Supply Configurable Functions](#) table on [page 104](#).

Refer to the Kinetix 5700 DC-bus Conditioner Module Installation Instructions, publication [2198-IN016](#), for additional installation information.

Contactor Wiring Examples

We recommend that you wire an Allen-Bradley® (Bulletin 100) auxiliary contactor to the 2198-RPxxx regenerative-bus supply digital input (IOD connector) and configure AC Line Contactor OK to monitor three-phase input power. Use the Normally Open (N.O.) auxiliary contact, if more than one auxiliary contact is available.

Figure 180 - Contactor Wiring for DC-bus Power Supply

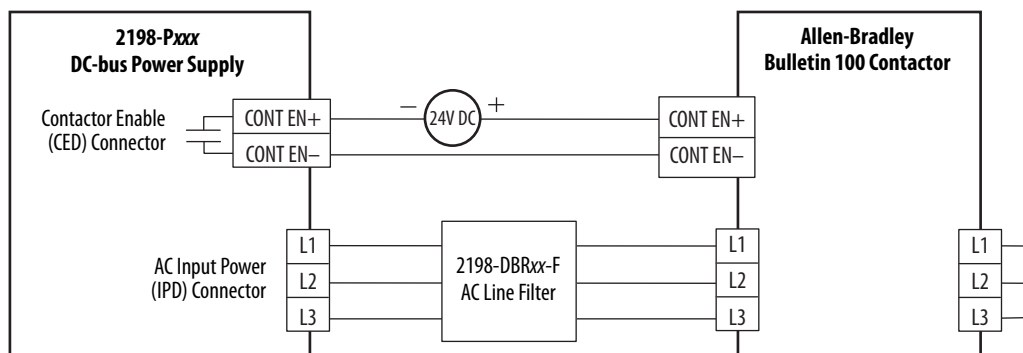
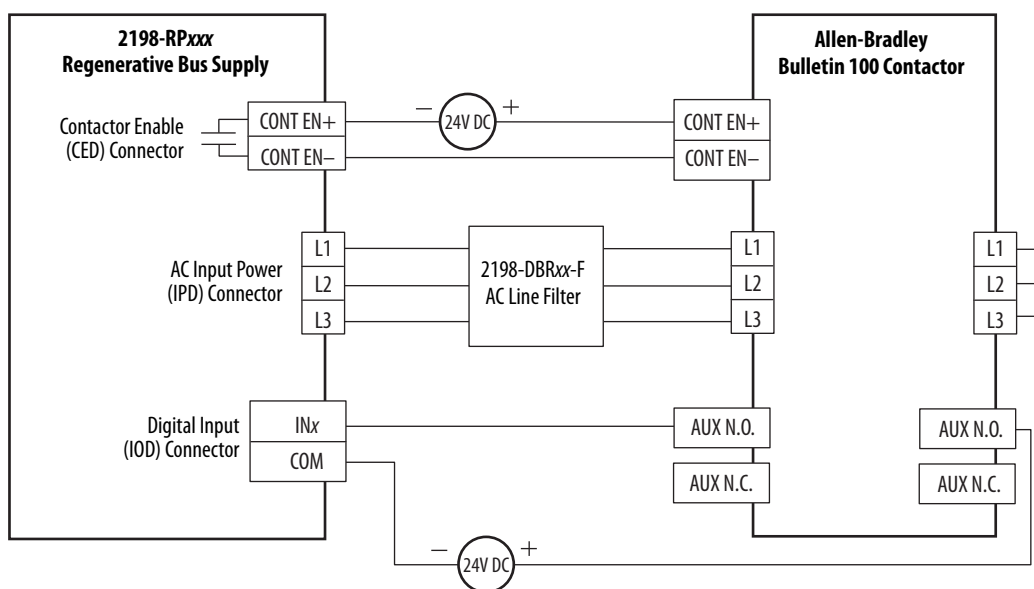


Figure 181 - Contactor Wiring for Regenerative Bus Supply



(1) Configure digital input #2 as AC Line Contactor OK (default setting). For regenerative bus supply configurable functions, see the [Regenerative Bus Supply Configurable Functions](#) table on [page 104](#).

Refer to IEC Contactor Specifications Technical Data, publication [100-TD013](#), for additional contactor related information.

Passive Shunt Wiring Examples

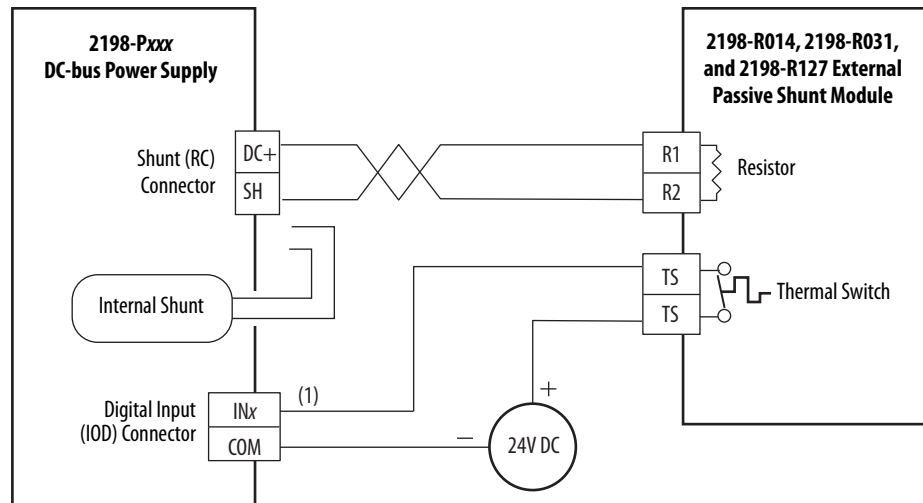
Wiring from the Bulletin 2198 shunt modules and resistor are made directly to the shunt (RC) connector. You can configure either of the DC-bus power supply digital inputs as Shunt Thermal Switch OK in the Logix Designer application. Refer to [page 205](#) to see how the DC-bus power supply Digital Input category is configured.

IMPORTANT Passive shunts attach to only 2198-Pxxx DC-bus power supplies. Before wiring the Bulletin 2198 external shunt to the RC connector, remove the wires from the internal servo-drive shunt. Do not connect both internal and external shunt resistors to the DC-bus power supply.



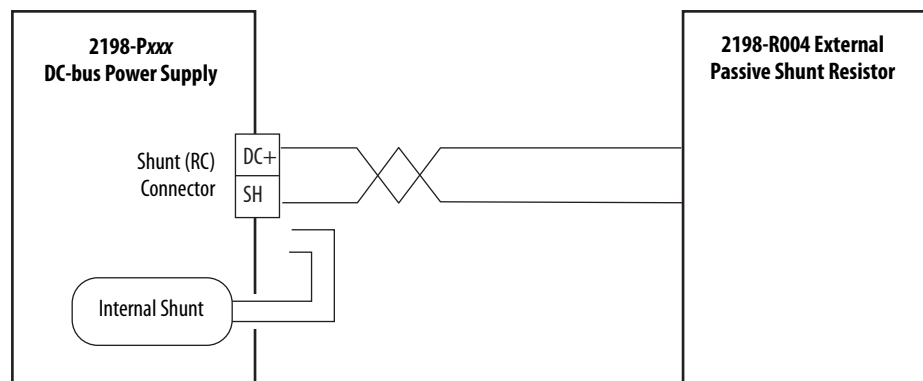
ATTENTION: To avoid damage to the Kinetix 5700 drive system, wire the 2198-R014, 2198-R031, or 2198-R127 shunt thermal switch to a digital input on the DC-bus power supply and configure the Shunt Thermal Switch OK function in the Logix Designer application.

Figure 182 - DC-bus Power Supply with External Passive Shunt Module



(1) Configure either of two digital inputs as Shunt Thermal Switch OK. For DC-bus power supply configurable functions, see the [DC-bus Power Supply Configurable Functions](#) table on [page 103](#).

Figure 183 - DC-bus Power Supply with External Passive Shunt Resistor



Refer to the Kinetix 5700 Passive Shunt Module Installation Instructions, publication [2198-IN011](#), for additional installation information.

Active Shunt Wiring Examples

Active shunts are available from the Rockwell Automation Encompass™ partner Powerohm Resistors, Inc. (<http://www.powerohm.com>).

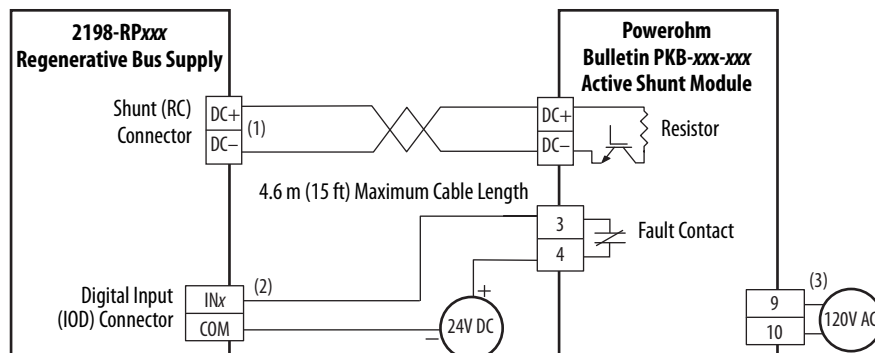
IMPORTANT Powerohm Bulletin PKBxxx active shunt modules use built-in internal brake resistors. Bulletin PWBxxx active shunt modules require appropriately sized external brake resistors.

For compatible Powerohm active shunts paired with 2198-Pxxx DC-bus power supplies and 2198-RPxxx regenerative bus supplies, see [External Active-shunt Connections](#) on [page 183](#).



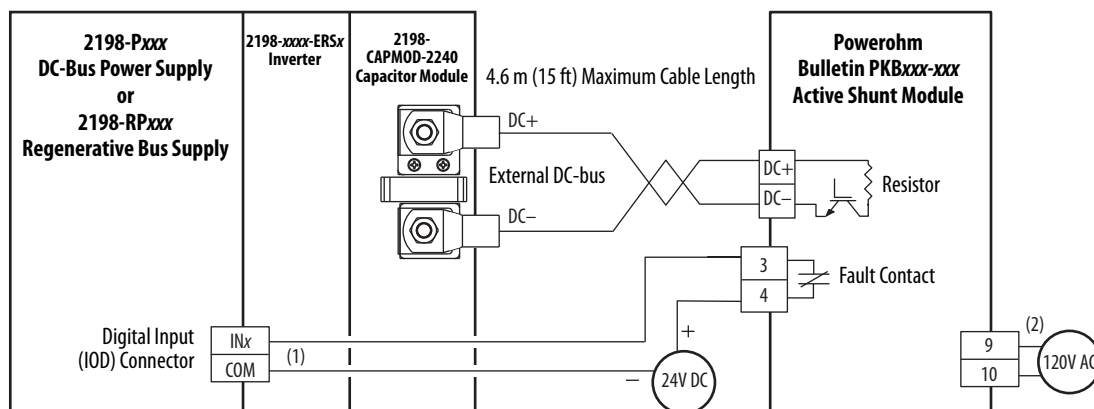
ATTENTION: To avoid damage to the Kinetix 5700 drive system, wire the active shunt thermal switch to a digital input on the power supply and configure the Shunt Thermal Switch OK function in the Logix Designer application.

Figure 184 - 2198-RPxxx Supply with External Active Shunt (built-in brake resistor)



- (1) The active shunt (RC) connector is rated for wire size up to 6 mm² (10 AWG). When conductors larger than 6 mm² (10 AWG) connect to the shunt, the drive connection must be made to the external DC-bus connections on an accessory module.
- (2) Configure any available digital input as Shunt Thermal Switch OK. See the [Digital Inputs Connector Pinouts](#) on [page 103](#).
- (3) Powerohm PKB050 and PKB050-800 shunts require 120V AC between pins 9 and 10 to supply power to the cooling fans.

Figure 185 - 2198 Power Supply with External Active Shunt (built-in brake resistor)

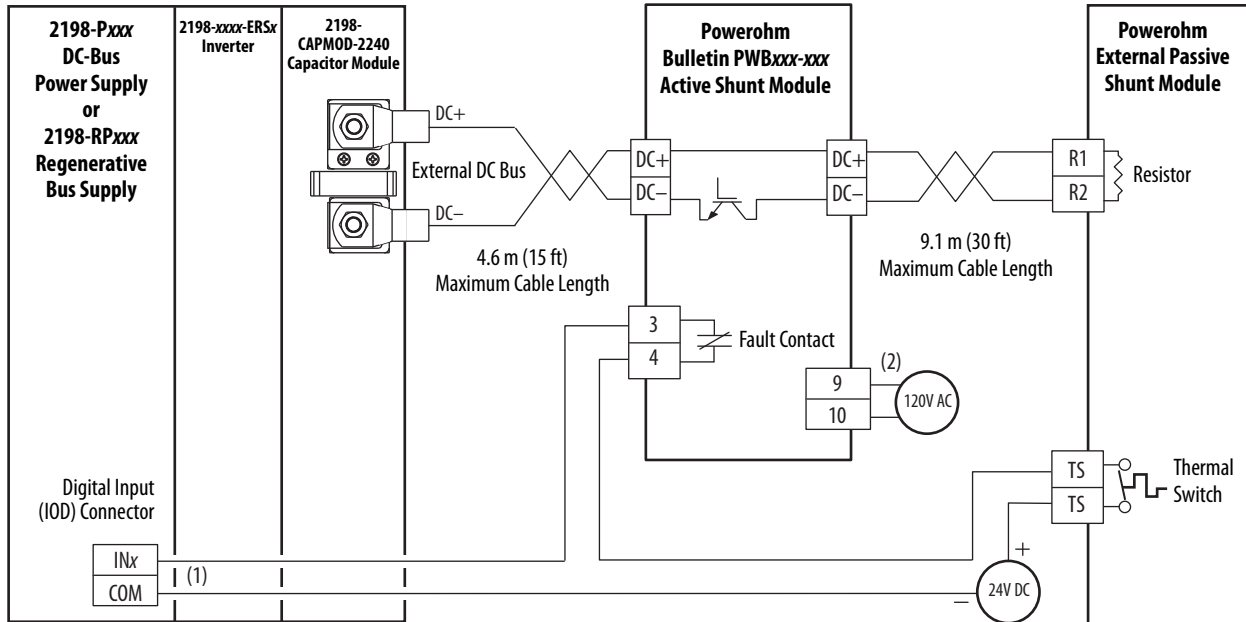


- (1) Configure any available digital input as Shunt Thermal Switch OK. See the [Digital Inputs Connector Pinouts](#) on [page 103](#).
- (2) Powerohm PKB050 and PKB050-800 shunts require 120V AC between pins 9 and 10 to supply power to the cooling fans.

See Knowledgebase document [1082776](#) for more information on wiring to these Powerohm Bulletin PKBxxx active shunts.

IMPORTANT Due to the 10 A connector current rating, connections to the Active Shunt (RC) connector on the regenerative bus supply are limited to Powerohm PKBxxx-xxx active shunts. PWBxxx-xxx active shunt connections must be made to the 2198-CAPMOD-2240 capacitor module.

Figure 186 - 2198 Power Supply with External Active Shunt (external brake resistor)



- (1) Configure any available digital input as Shunt Thermal Switch OK. See the [Digital Inputs Connector Pinouts](#) on [page 103](#).
- (2) Powerohm PWB050 and PWB050-800 shunts require 120V AC between pins 9 and 10 to supply power to the cooling fans.

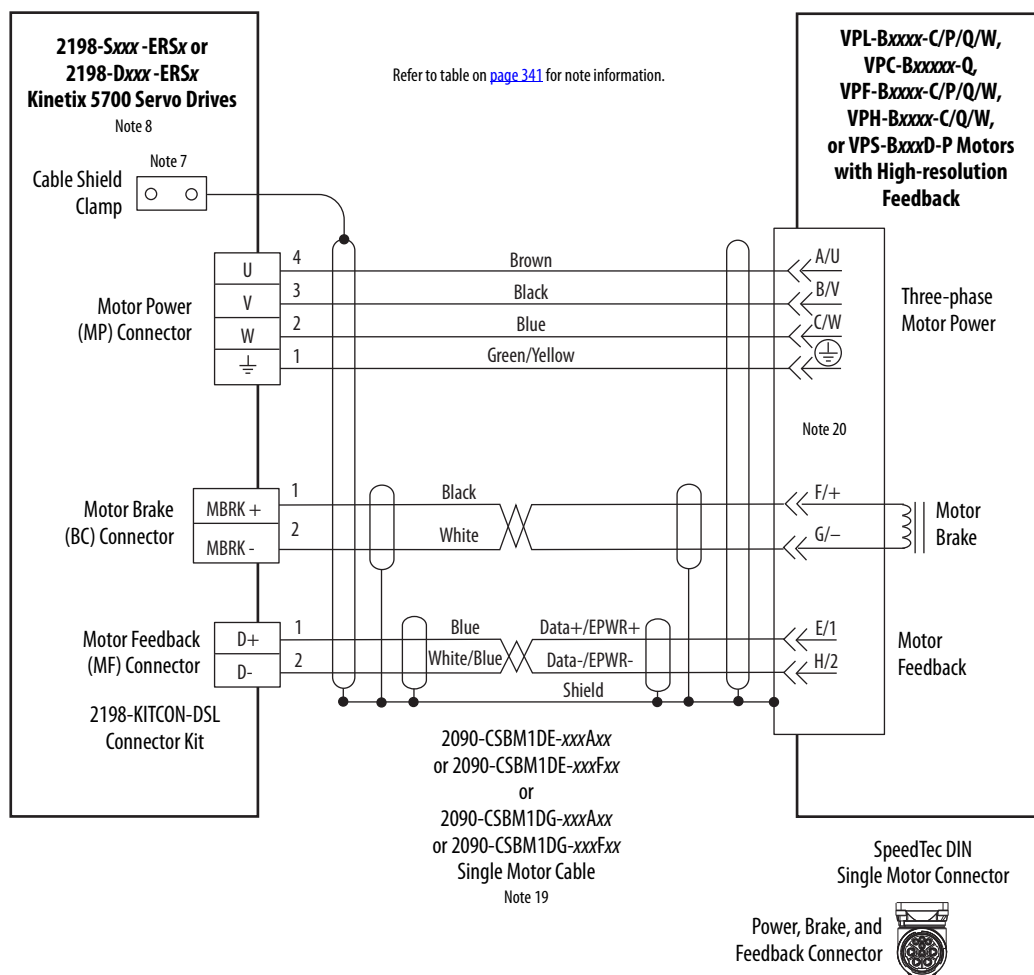
See Knowledgebase document [1082777](#) for more information on wiring to these Powerohm Bulletin PWBxxx active shunts.

For more information on Powerohm products, refer to the documentation included with those products or online at (<http://www.powerohm.com>).

Kinetix 5700 Servo Drive and Rotary Motor Wiring Examples

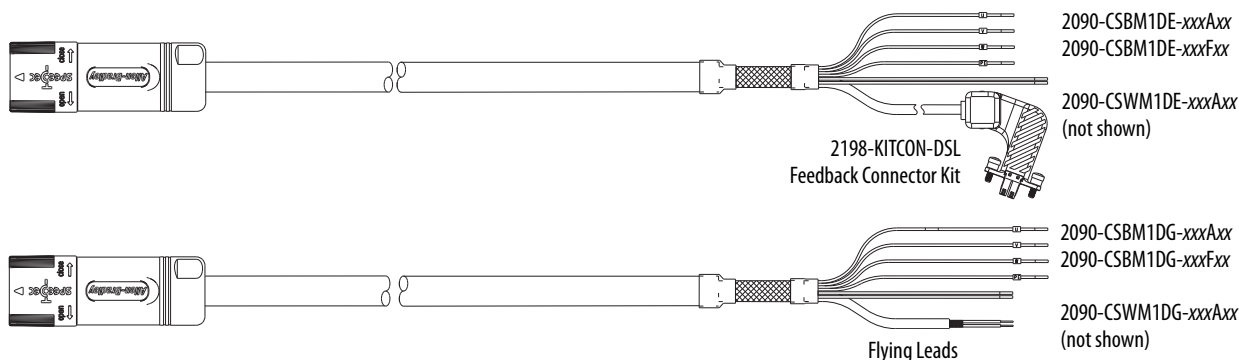
These Kinetix rotary motors use single cable technology. The motor power, brake, and feedback wires are all packaged in a single cable.

Figure 187 - Kinetix 5700 Drives with Kinetix VPL, VPC-Bxxxx-Q, VPF, VPH, and VPS Motors



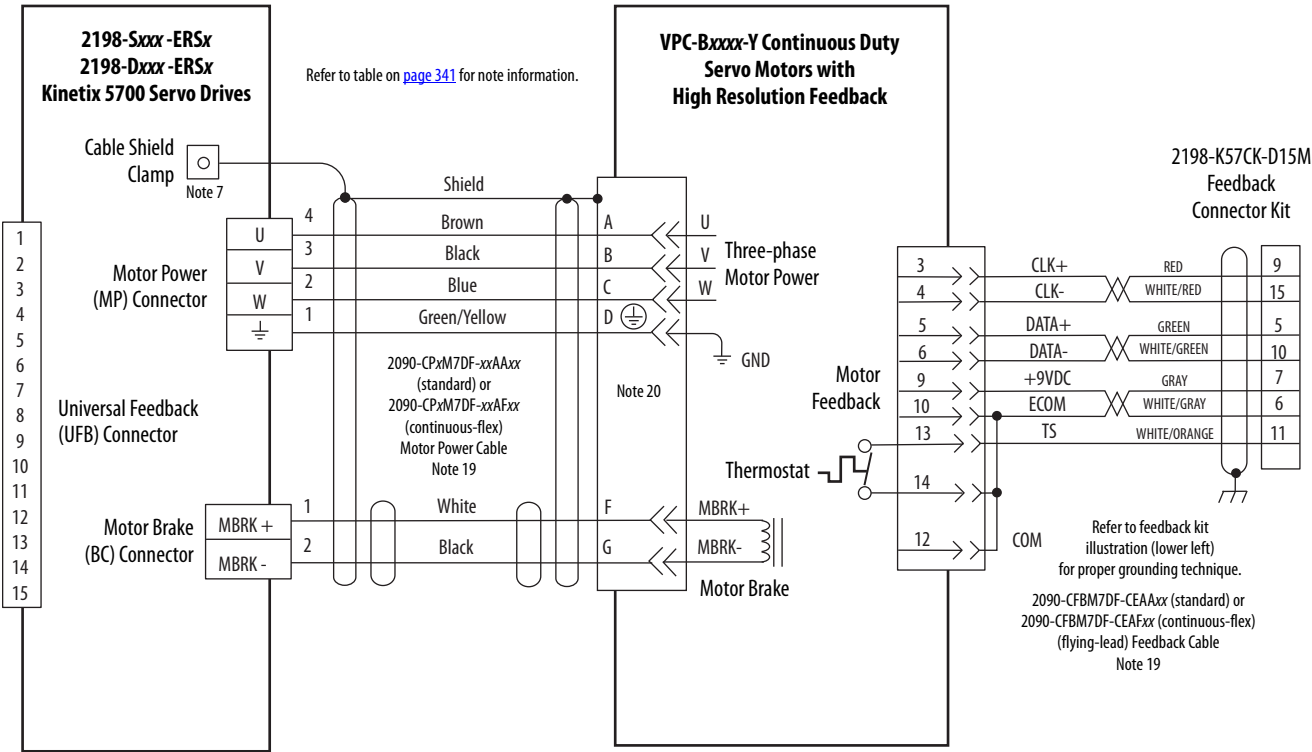
2090-CSxM1DE cables include the 2198-KITCON-DSL connector kit pre-assembled with the feedback conductors. 2090-CSxM1DG cables have flying leads and the 2198-KITCON-DSL kit is ordered separately.

Figure 188 - Single Motor Cables for Kinetix 5700 Servo Drives

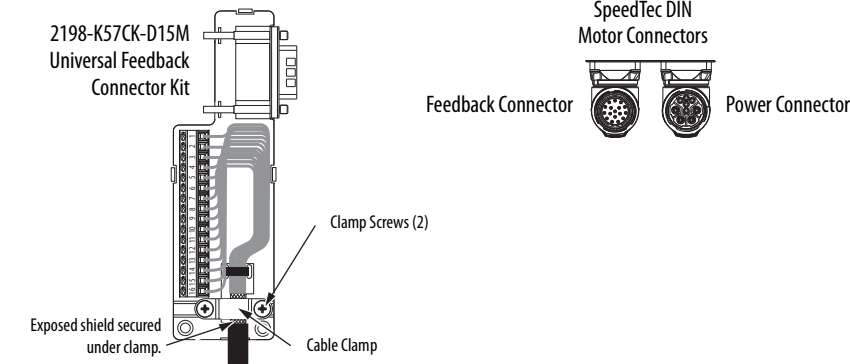


These Kinetix rotary motors have separate cables for motor power/brake and feedback connections.

Figure 189 - Kinetix 5700 Drives with Kinetix VPC-Y Continuous Duty Motors



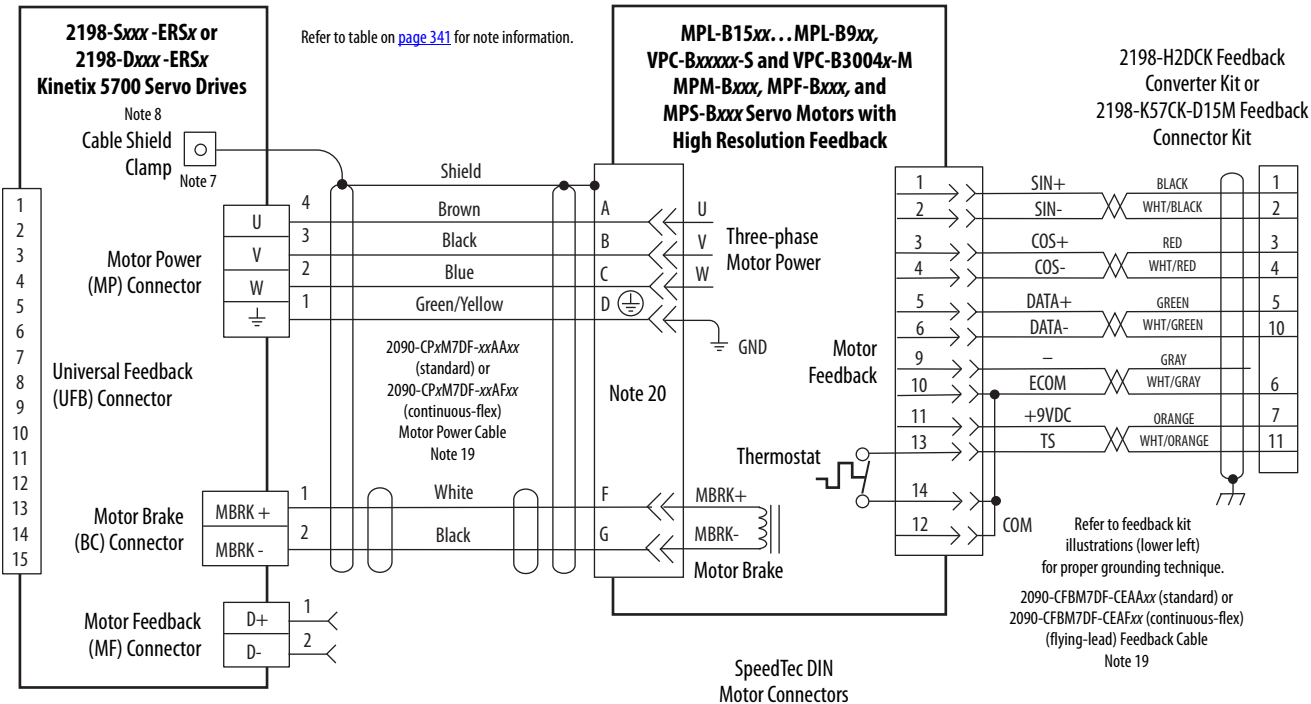
Grounding Techniques for Feedback Cable Shield



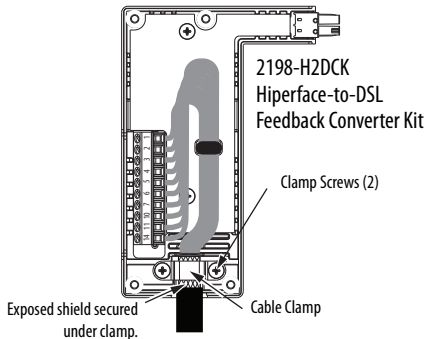
Refer to Universal Feedback Connector Kit Installation Instructions, publication [2198-IN010](#), for connector kit specifications.

These compatible Allen-Bradley rotary motors have separate cables for motor power/brake and feedback connections.

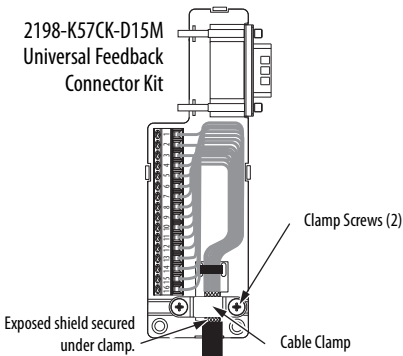
Figure 190 - Kinetix 5700 Drives with Kinetix MPL, MPM, MPF, MPS, and VPC Motors



Grounding Techniques for Feedback Cable Shield



Refer to Hiperface to DSL Feedback Converter Kit Installation Instructions, publication [2198-IN006](#), for converter kit specifications.



Refer to Universal Feedback Connector Kit Installation Instructions, publication [2198-IN010](#), for connector kit specifications.

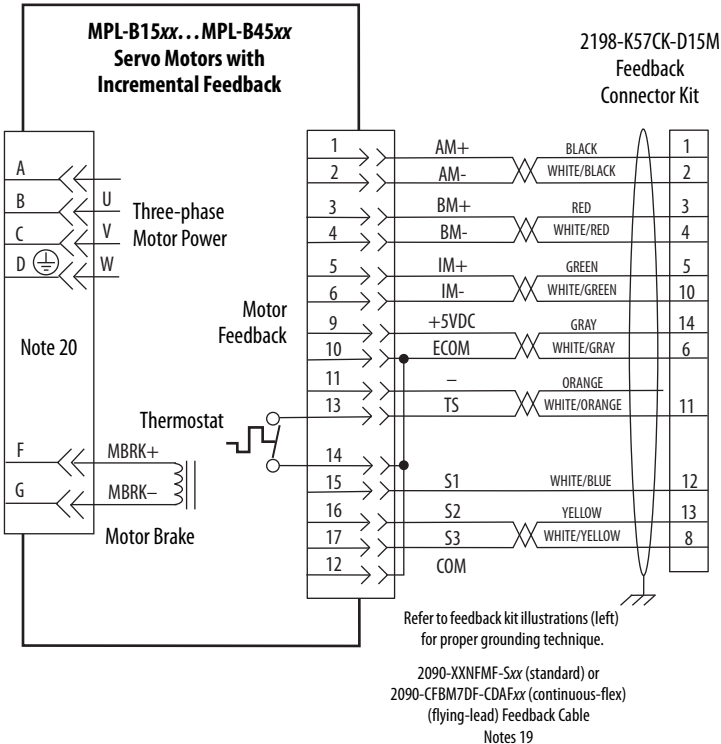
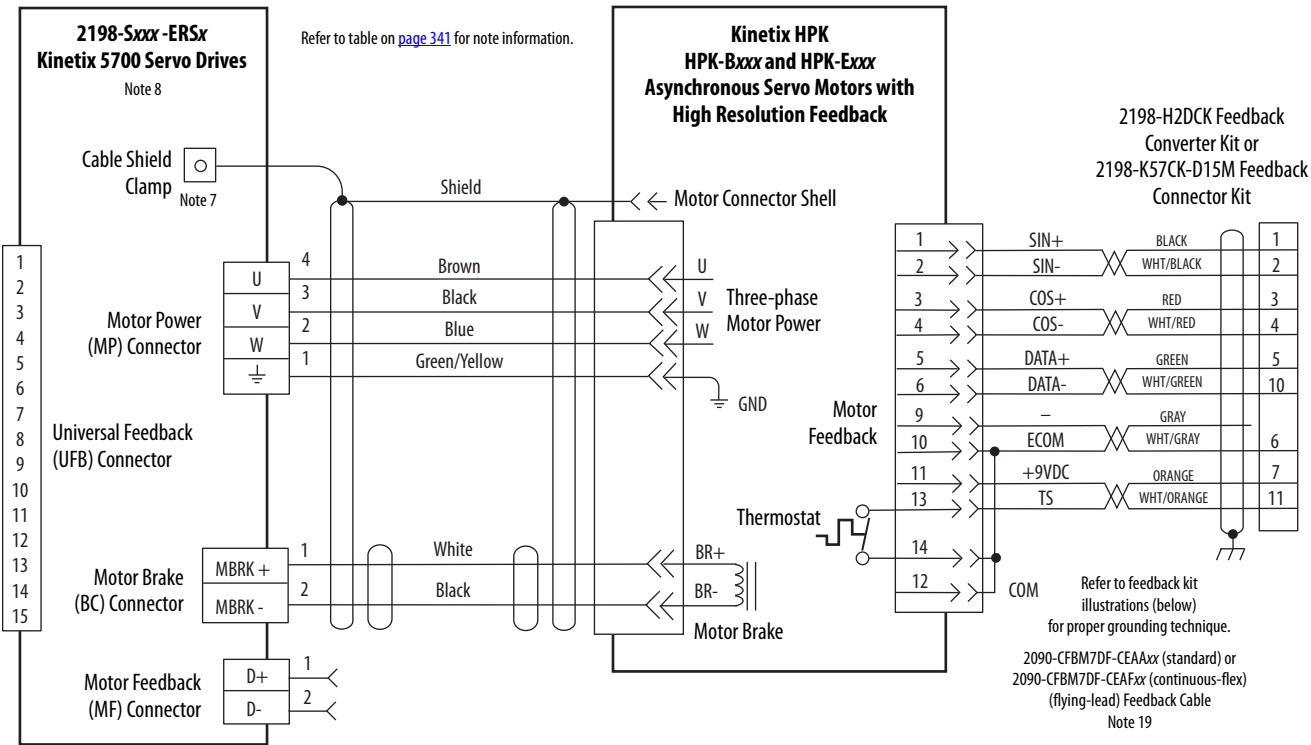
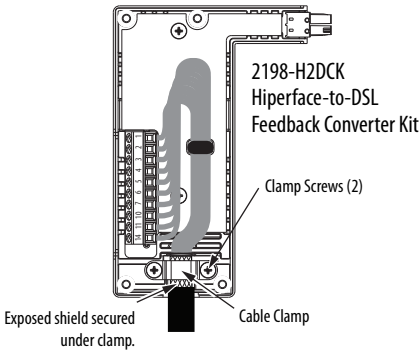


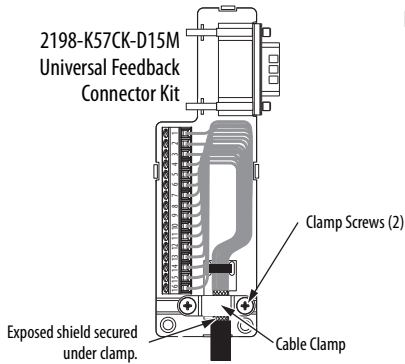
Figure 191 - Kinetix 5700 Drives with Kinetix HPK Servo Motors



Grounding Techniques for Feedback Cable Shield



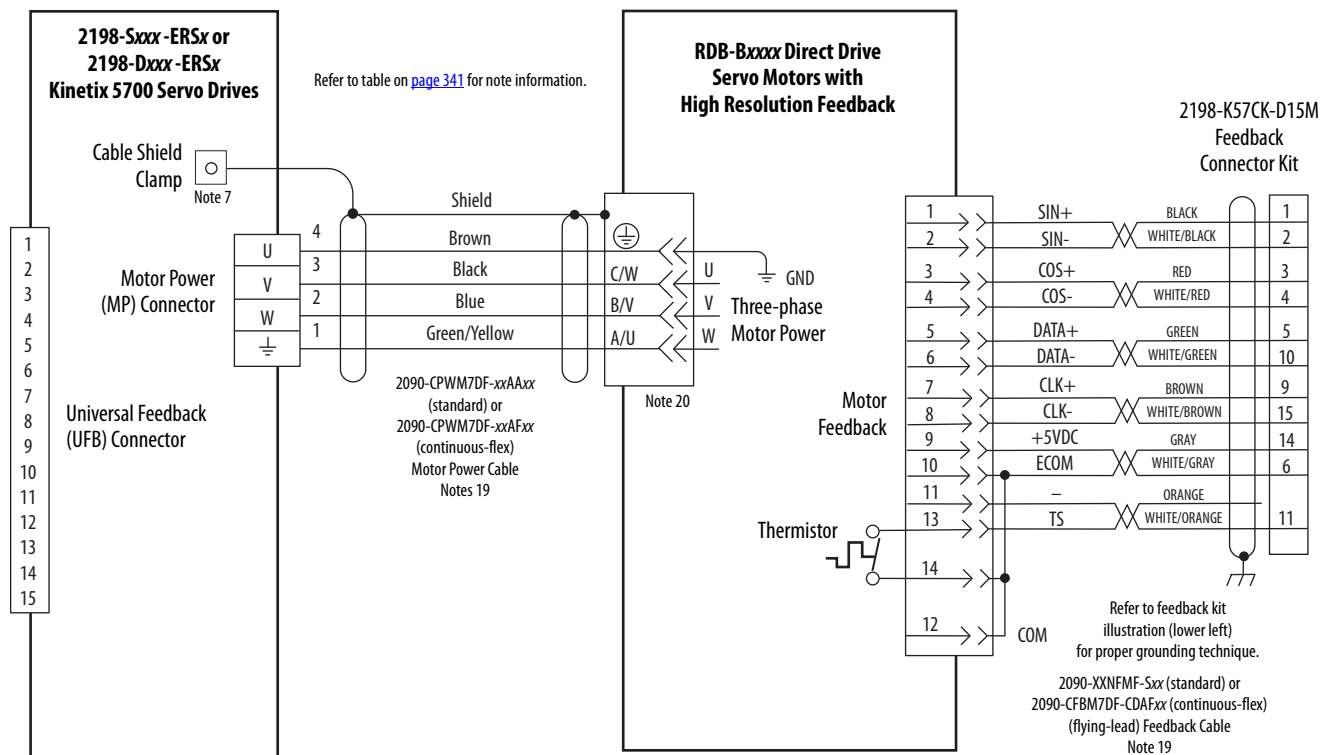
Refer to Hiperface to DSL Feedback Converter Kit Installation Instructions, publication [2198-IN006](#), for converter kit specifications.



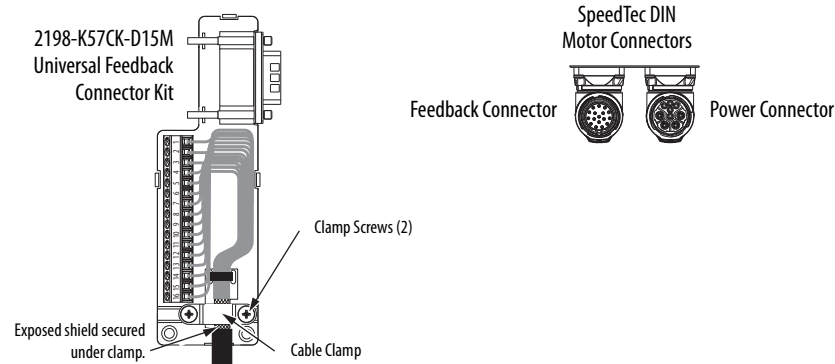
Refer to Universal Feedback Connector Kit Installation Instructions, publication [2198-IN010](#), for connector kit specifications.



Figure 192 - Kinetix 5700 Drives with Kinetix RDB Direct Drive Motors



Grounding Techniques for Feedback Cable Shield

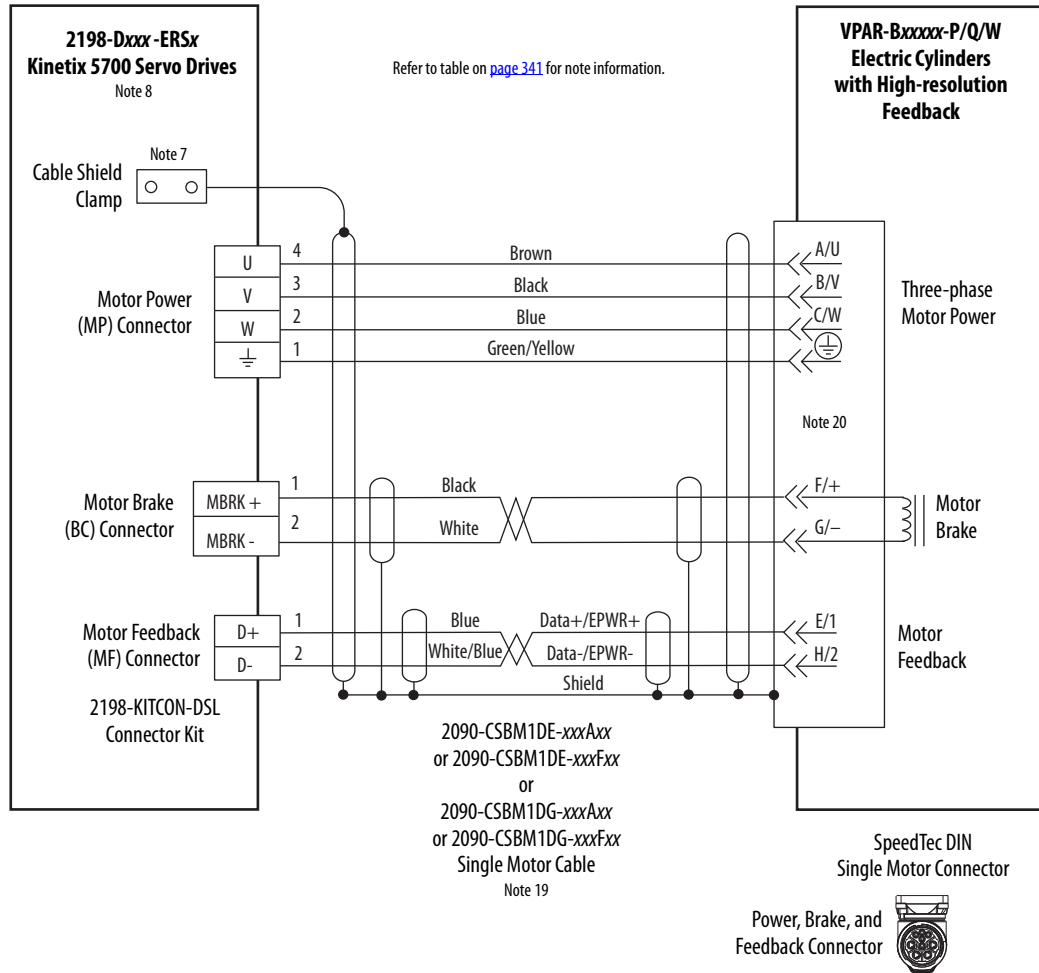


Refer to Universal Feedback Connector Kit Installation Instructions, publication [2198-IN010](#), for connector kit specifications.

Kinetix 5700 Servo Drive and Linear Actuator Wiring Examples

These Kinetix linear actuators use single cable technology. The motor power, brake, and feedback wires are all packaged in a single cable.

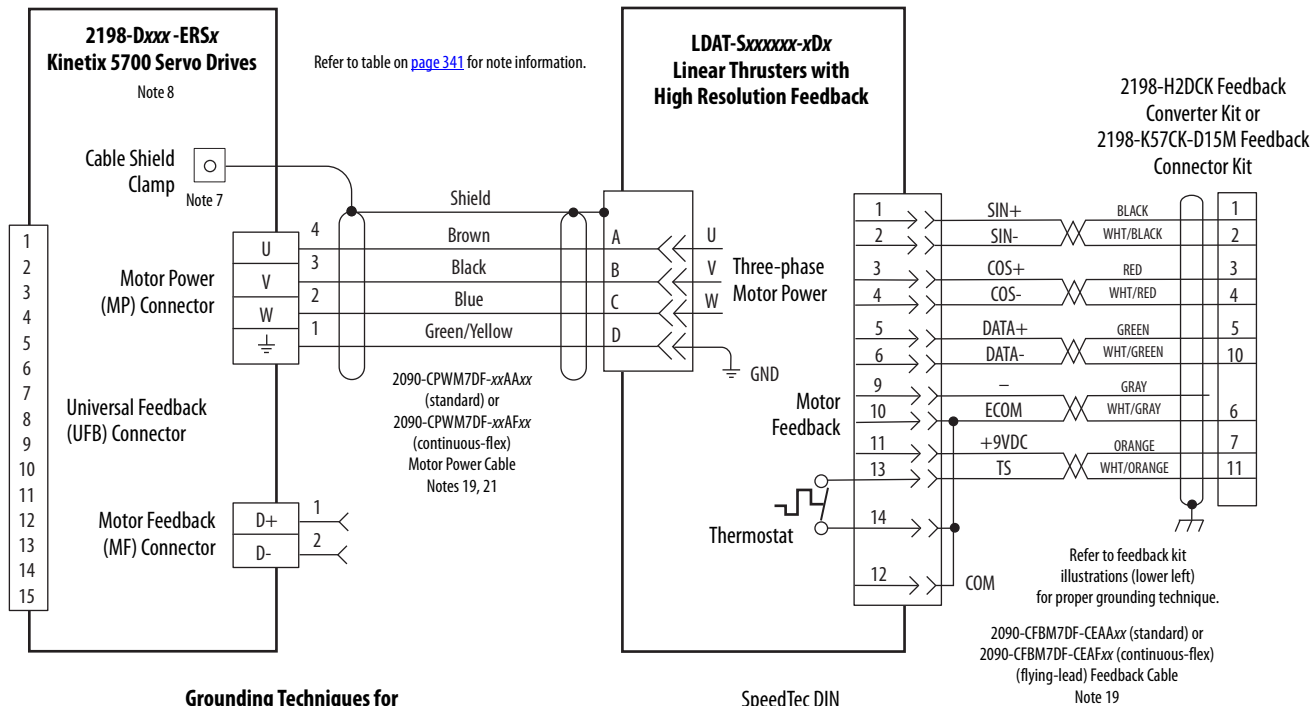
Figure 193 - Kinetix 5700 Drives with Kinetix VPAR Electric Cylinders



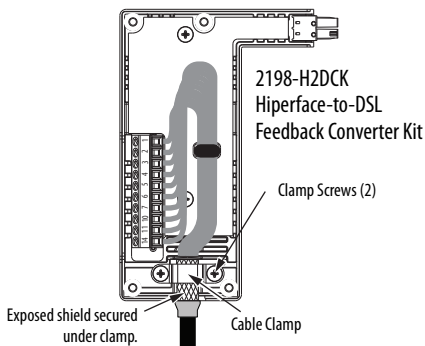
2090-CSxM1DE single cables include the 2198-KITCON-DSL connector kit pre-assembled with the feedback conductors. 2090-CSxM1DG cables have flying-leads and the 2198-KITCON-DSL kit is ordered separately. See the single cable examples on [page 362](#).

These compatible linear actuators have separate connectors and cables for power/brake and feedback connections.

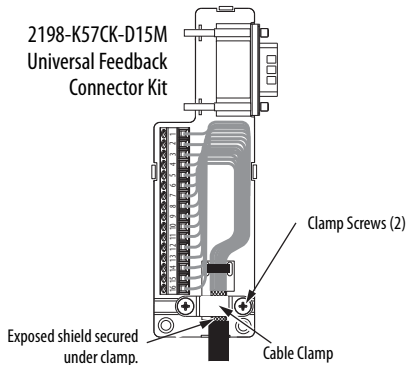
Figure 194 - Kinetix 5700 Drives with LDAT-Series Linear Thrusters



Grounding Techniques for
Feedback Cable Shield



Refer to Hiperface to DSL Feedback Converter Kit Installation Instructions,
publication [2198-IN006](#), for converter kit specifications.



Refer to Universal Feedback Connector Kit Installation Instructions,
publication [2198-IN010](#), for connector kit specifications.

SpeedTec DIN
Motor Connectors

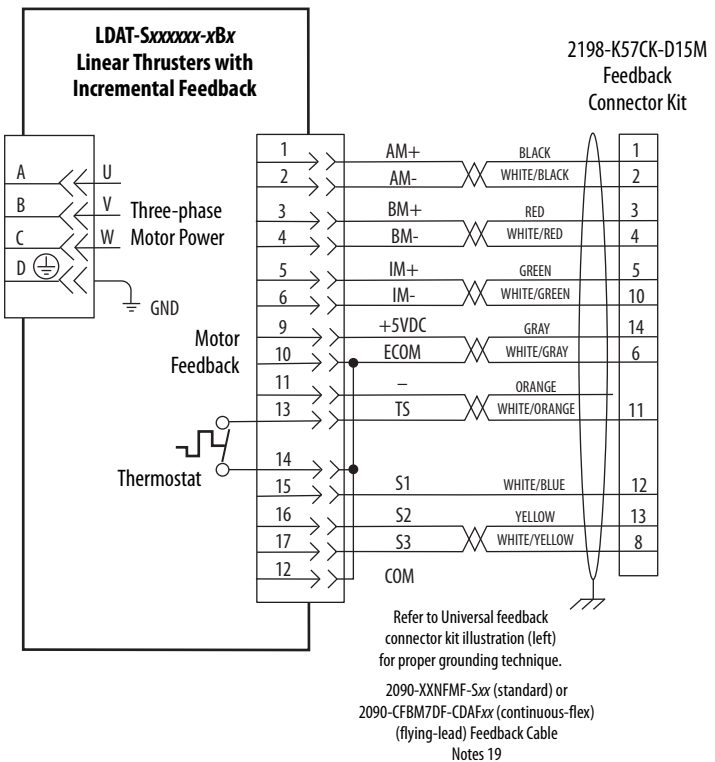
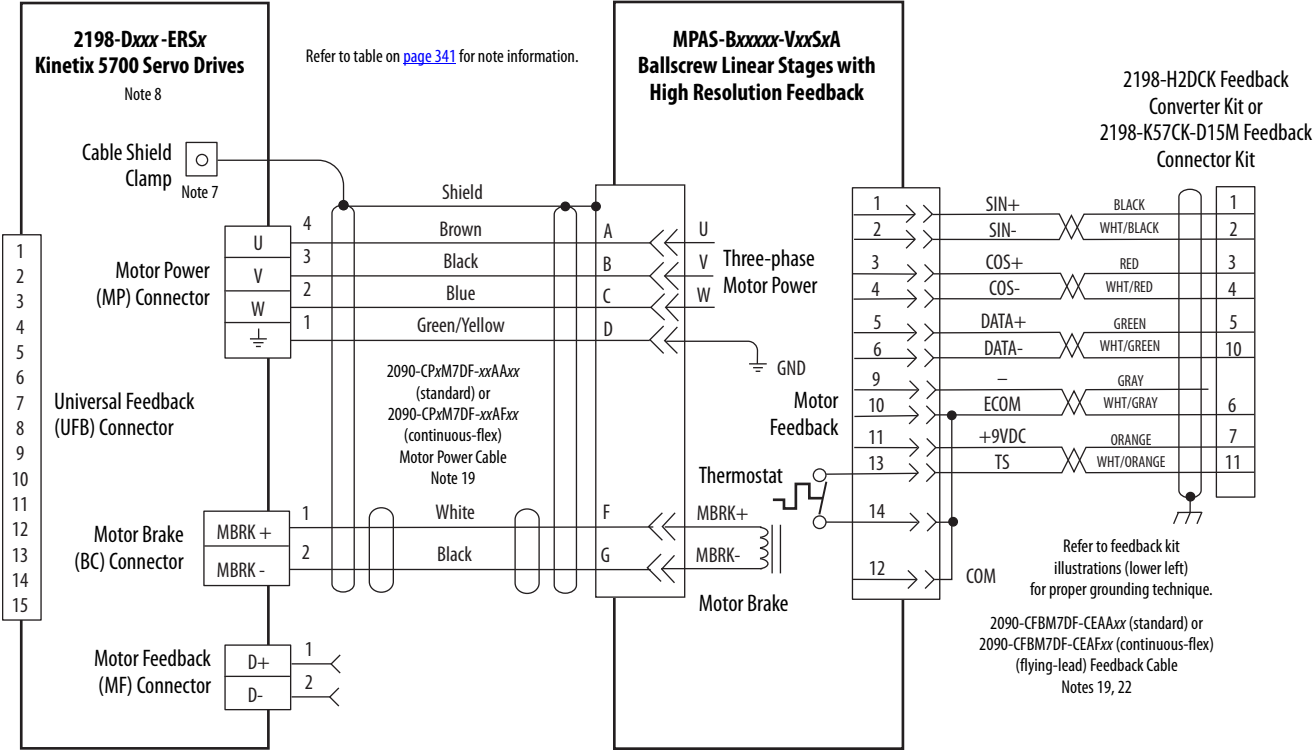
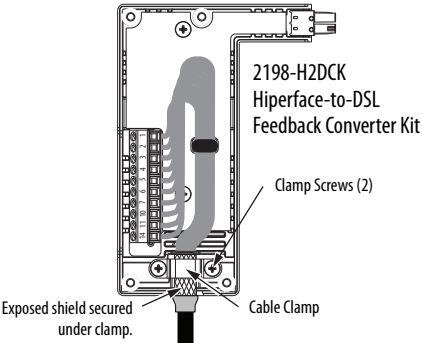


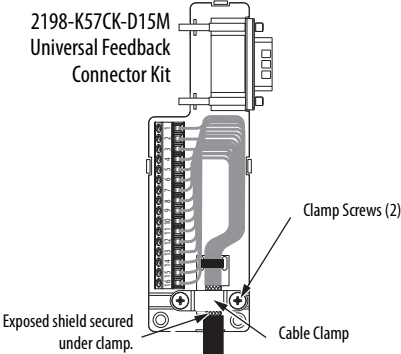
Figure 195 - Kinetix 5700 Drives with Kinetix MPAS Linear Stages



**Grounding Techniques for
Feedback Cable Shield**



Refer to HiPerface to DSL Feedback Converter Kit Installation Instructions, publication [2198-IN006](#), for converter kit specifications.



Refer to Universal Feedback Connector Kit Installation Instructions, publication [2198-IN010](#), for connector kit specifications.

**SpeedTec DIN
Motor Connectors**

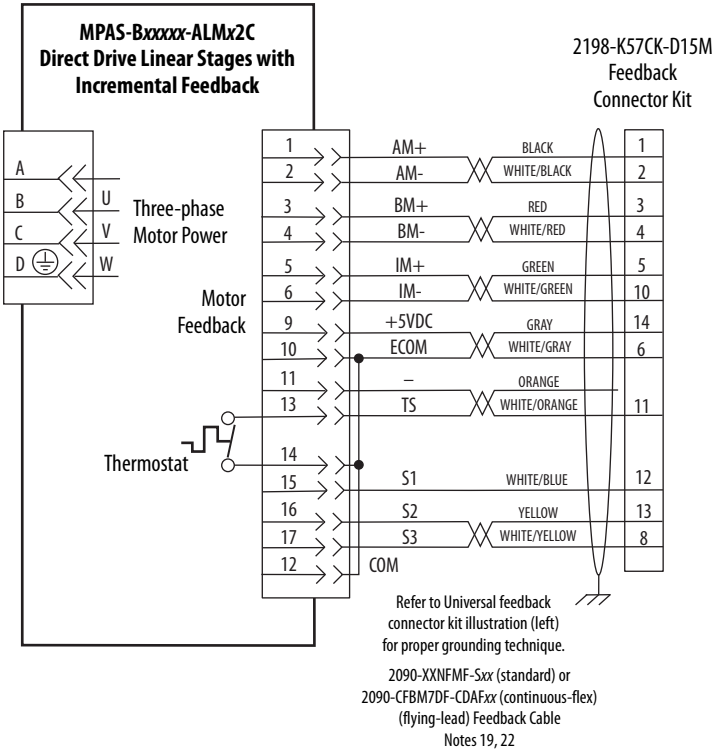
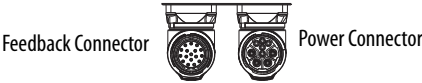
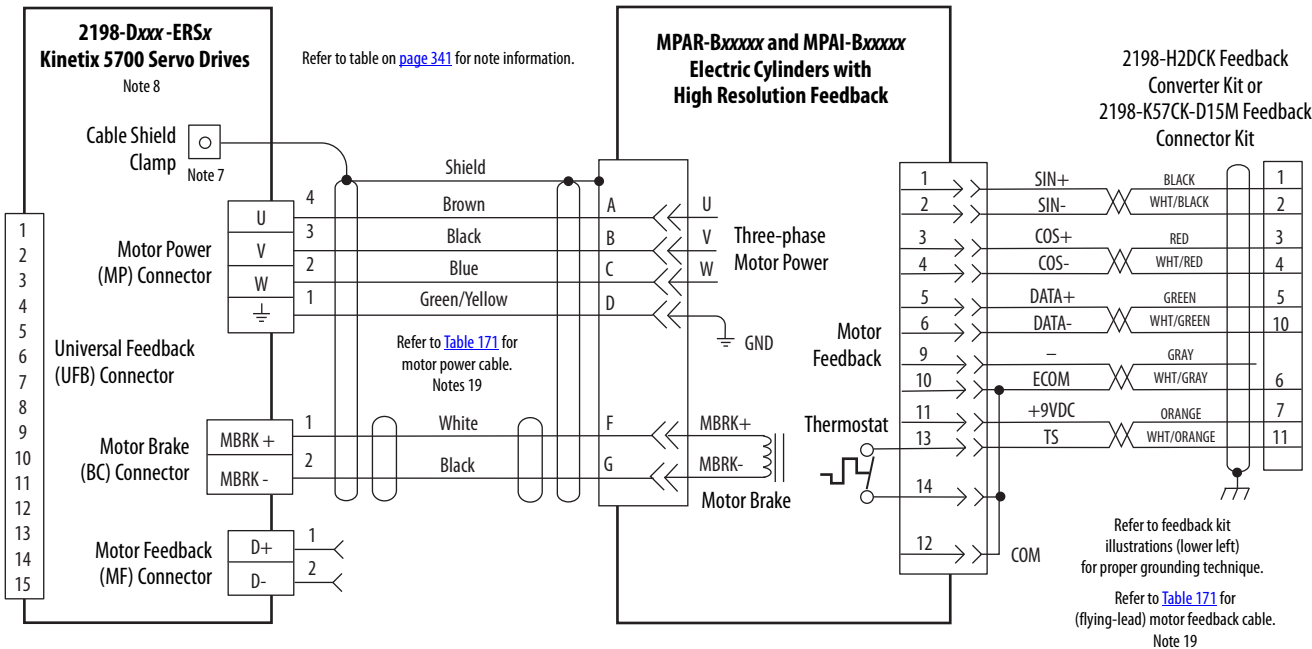


Figure 196 - Kinetix 5700 Drives with Kinetix MPAR and MPAI Electric Cylinders



Grounding Techniques for Feedback Cable Shield

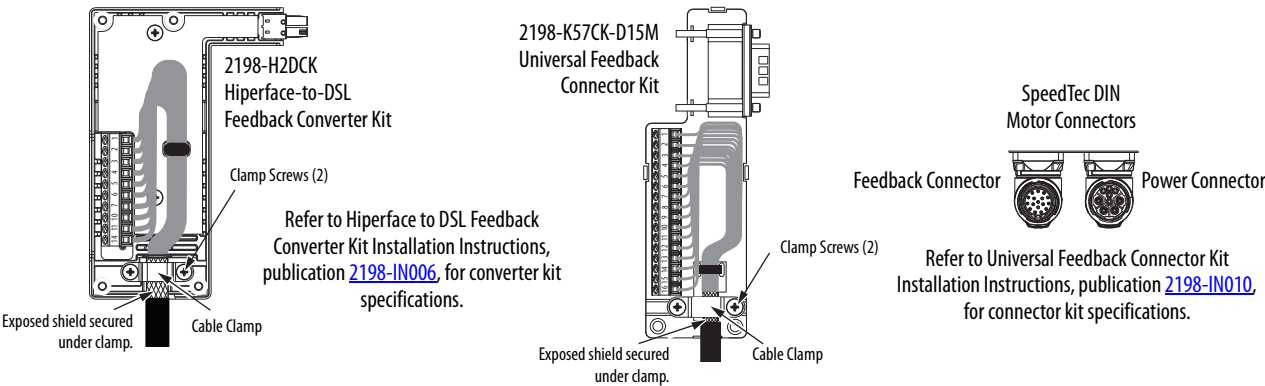
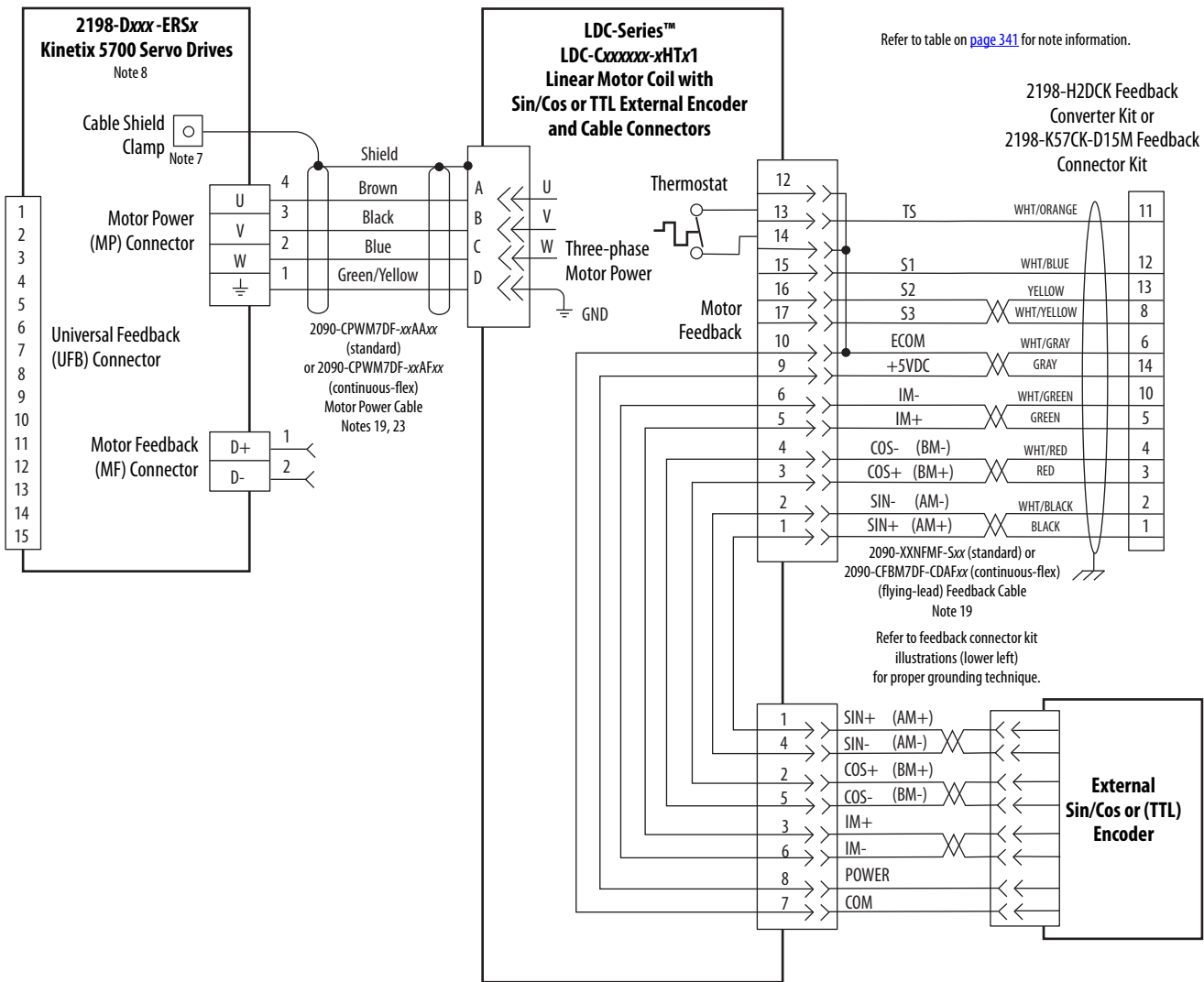


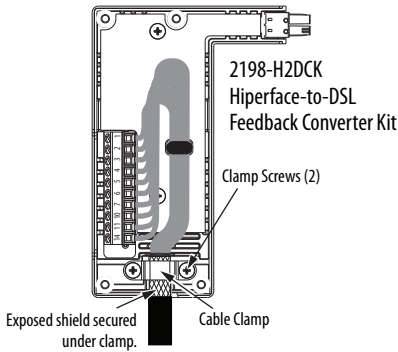
Table 171 - Kinetix MPAR and MPAI Electric Cylinders Power and Feedback Cables

| Kinetix MPAR and MPAI Electric Cylinders Cat. No. | Frame | Power Cable Cat. No. | Feedback Cable Cat. No. |
|--|-------|--|--|
| MPAR-B1xxx (series A and B) | 32 | 2090-XXNPMF-16Sxx (standard) or 2090-CPxM4DF-16AFxx (continuous-flex) | 2090-XXNFMF-Sxx (standard) or 2090-CFBM4DF-CEAFxx (continuous-flex) |
| MPAR-B2xxx (series A and B) | 40 | | |
| MPAR-B1xxx (series B and C) | 32 | | |
| MPAR-B2xxx (series B and C) | 40 | | |
| MPAR-B3xxx | 63 | | |
| MPAI-B2xxxx | 64 | 2090-CPxM7DF-16AAxx (standard) or 2090-CPxM7DF-16AFxx (continuous-flex) | 2090-CFBM7DF-CEAAxx (standard) or 2090-CFBM7DF-CEAFxx (continuous-flex) |
| MPAI-B3xxxx | 83 | | |
| MPAI-B4xxxx | 110 | | |
| MPAI-B5xxxx | 144 | | |

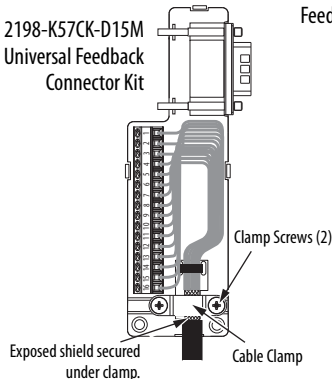
Figure 197 - Kinetix 5700 Drives with LDC-Series Linear Motors (cable connectors)



Grounding Techniques for Feedback Cable Shield



Refer to Hiperface to DSL Feedback Converter Kit Installation Instructions, publication [2198-IN006](#), for converter kit specifications.



Refer to Universal Feedback Connector Kit Installation Instructions, publication [2198-IN010](#), for connector kit specifications.

SpeedTec DIN Motor Connectors

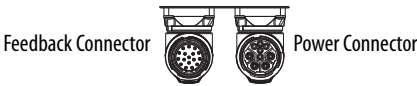
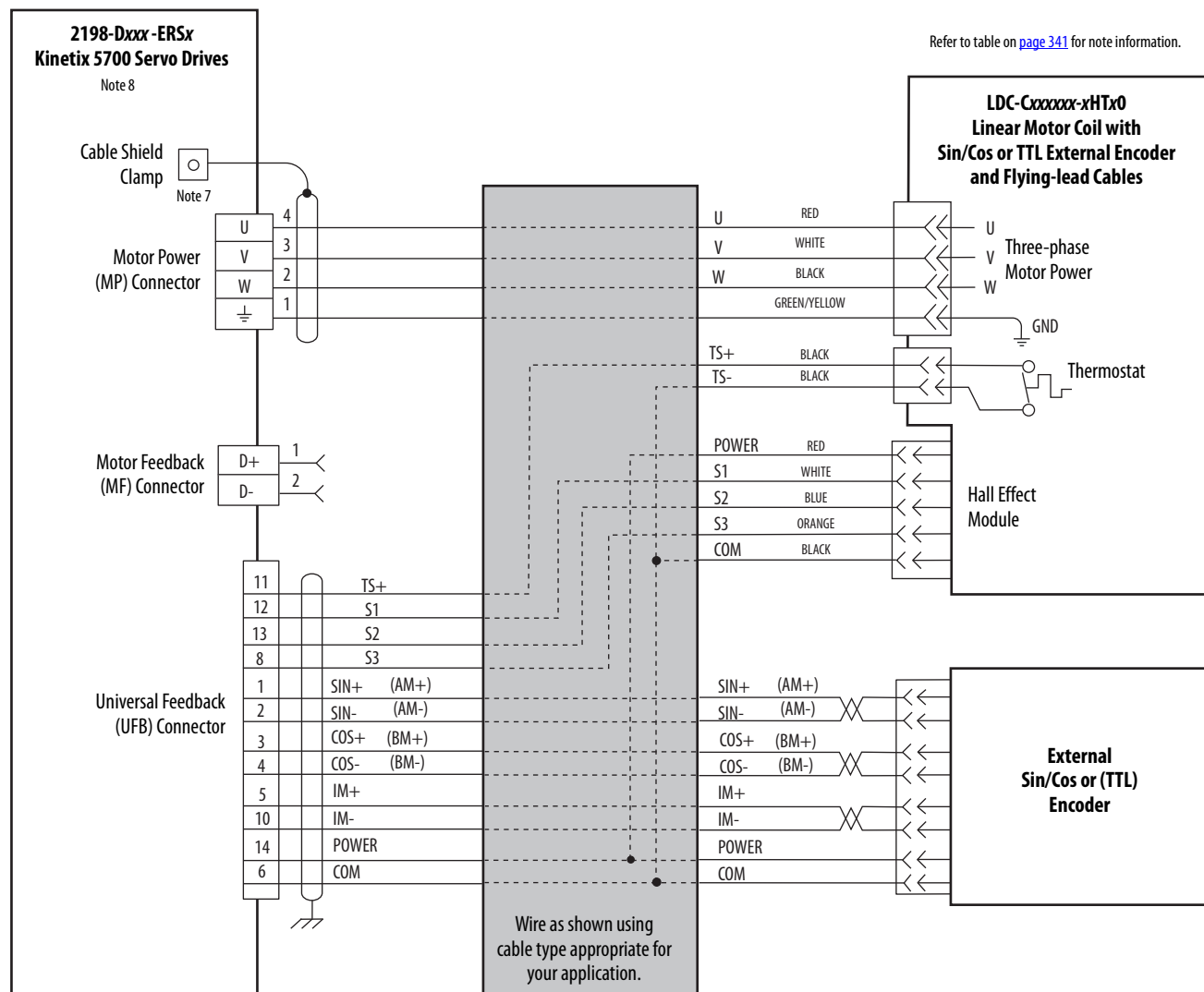
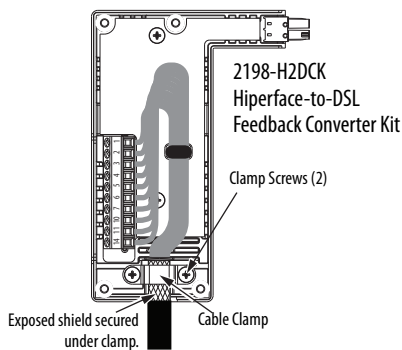


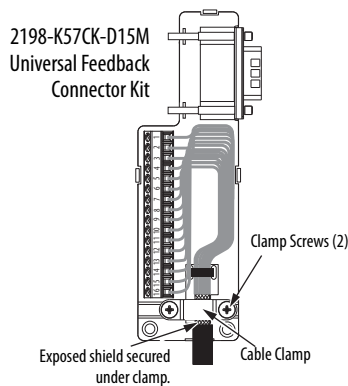
Figure 198 - Kinetix 5700 Drives with LDC-Series Linear Motors (flying-lead cables)



Grounding Techniques for Feedback Cable Shield



Refer to Hiperface to DSL Feedback
Converter Kit Installation Instructions,
publication [2198-IN006](#), for converter kit
specifications.

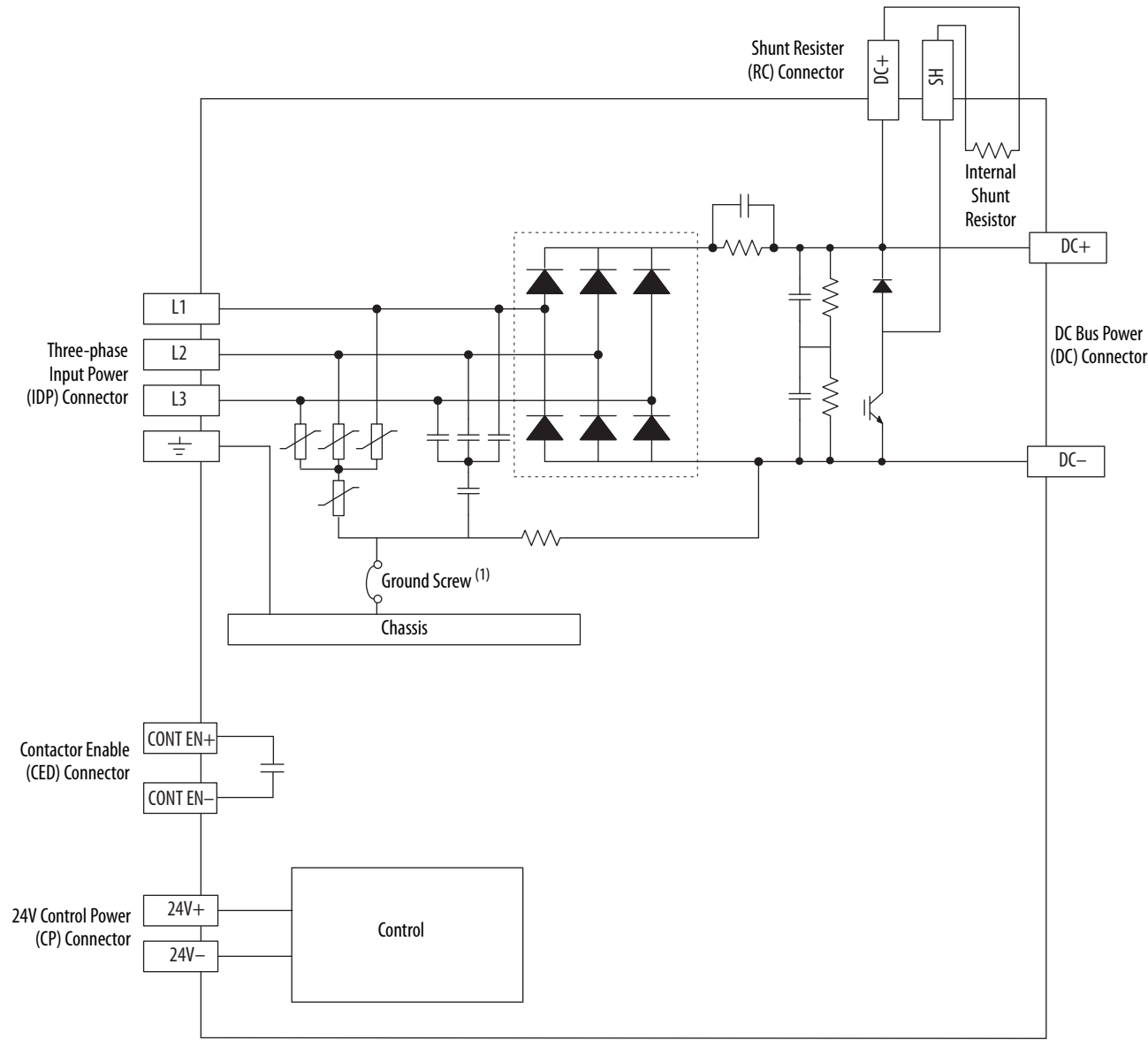


Refer to Universal Feedback Connector Kit
Installation Instructions, publication
[2198-IN010](#), for connector kit
specifications.

System Block Diagrams

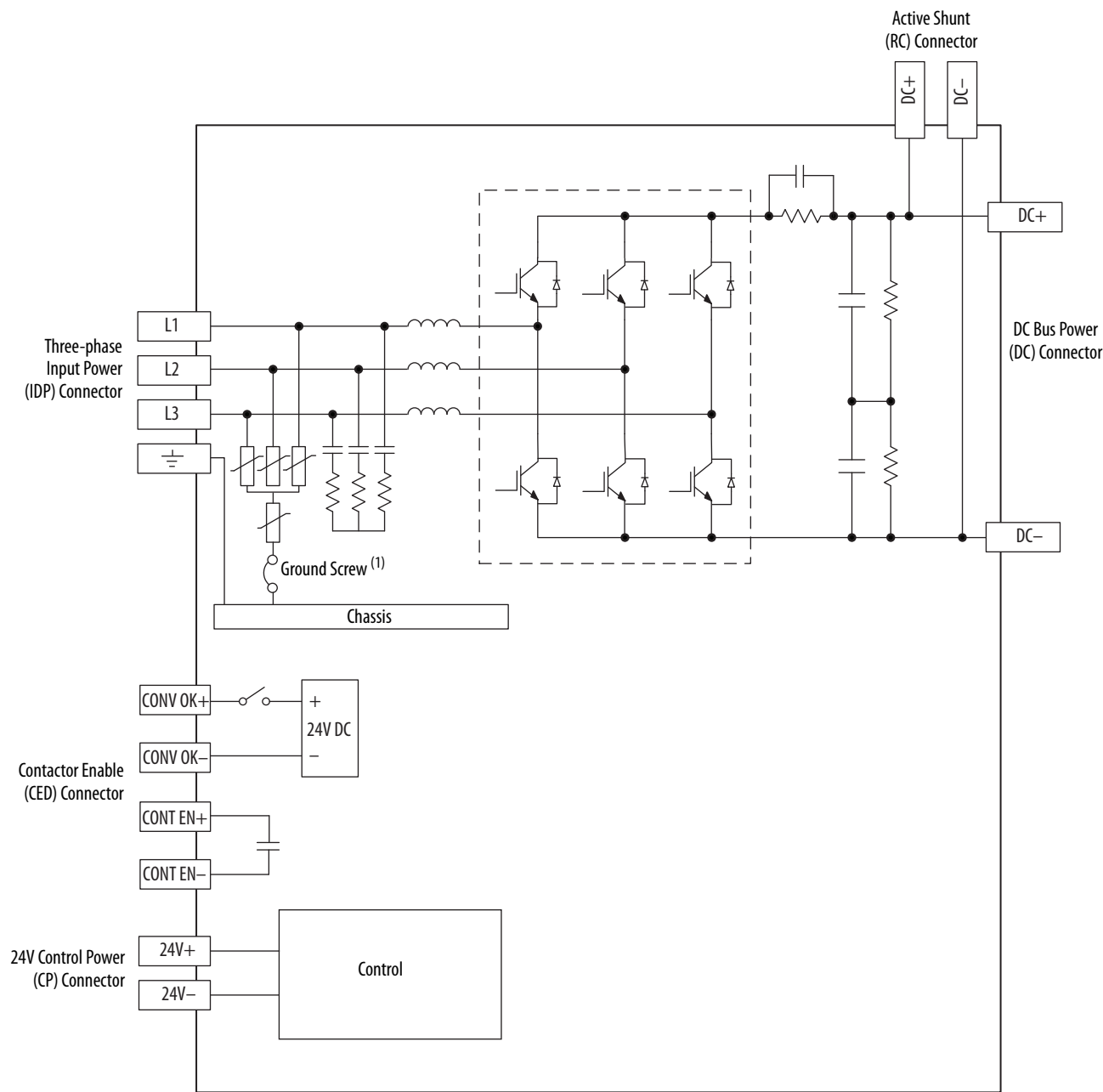
This section provides block diagrams of the Kinetix 5700 drive modules.

Figure 199 - DC-bus Power Supply Block Diagram



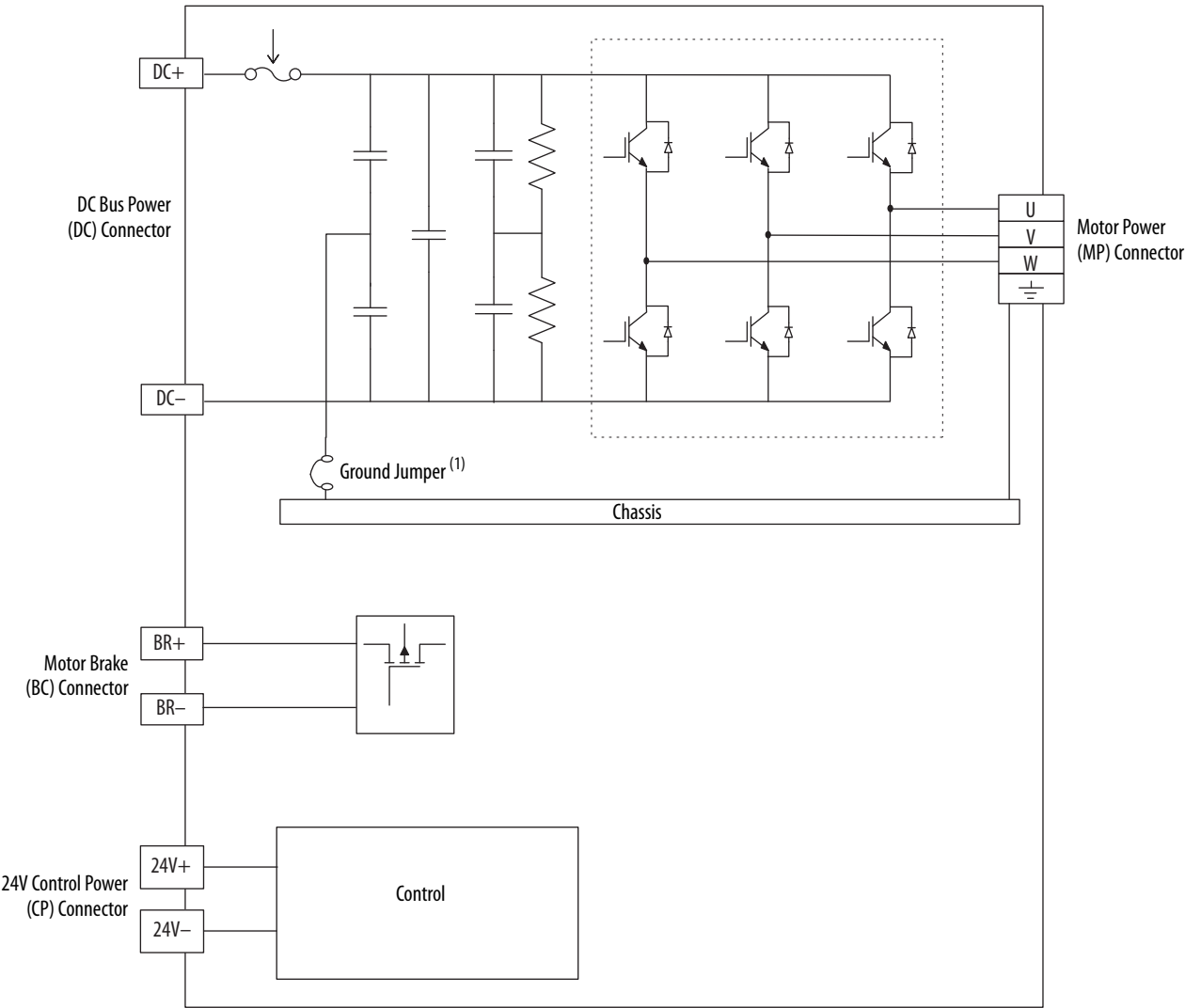
(1) Ground screw in the installed (default) configuration.

Figure 200 - Regenerative Bus Supply Block Diagram



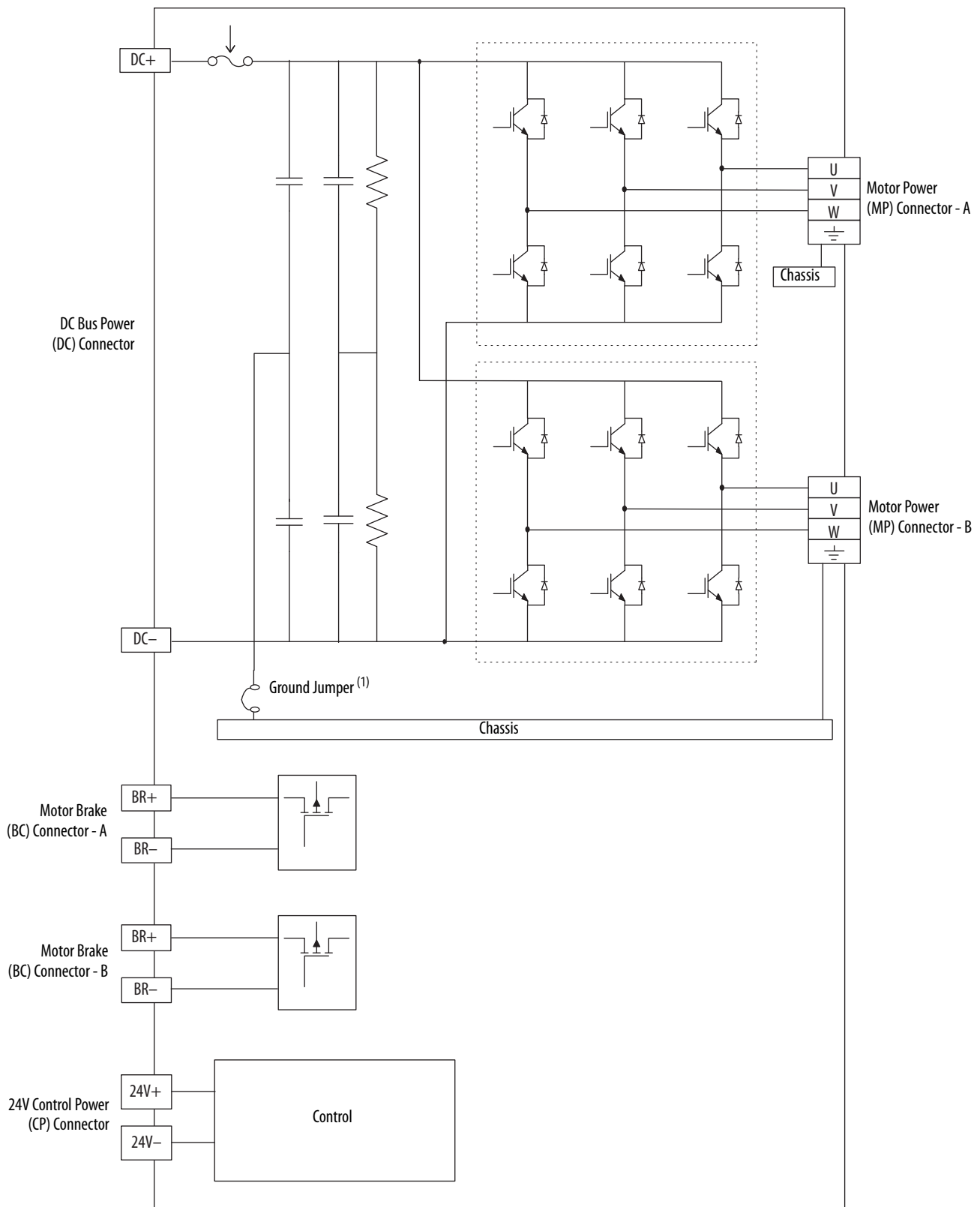
(1) Ground screw in the installed (default) configuration.

Figure 201 - Single-axis Inverter Block Diagram

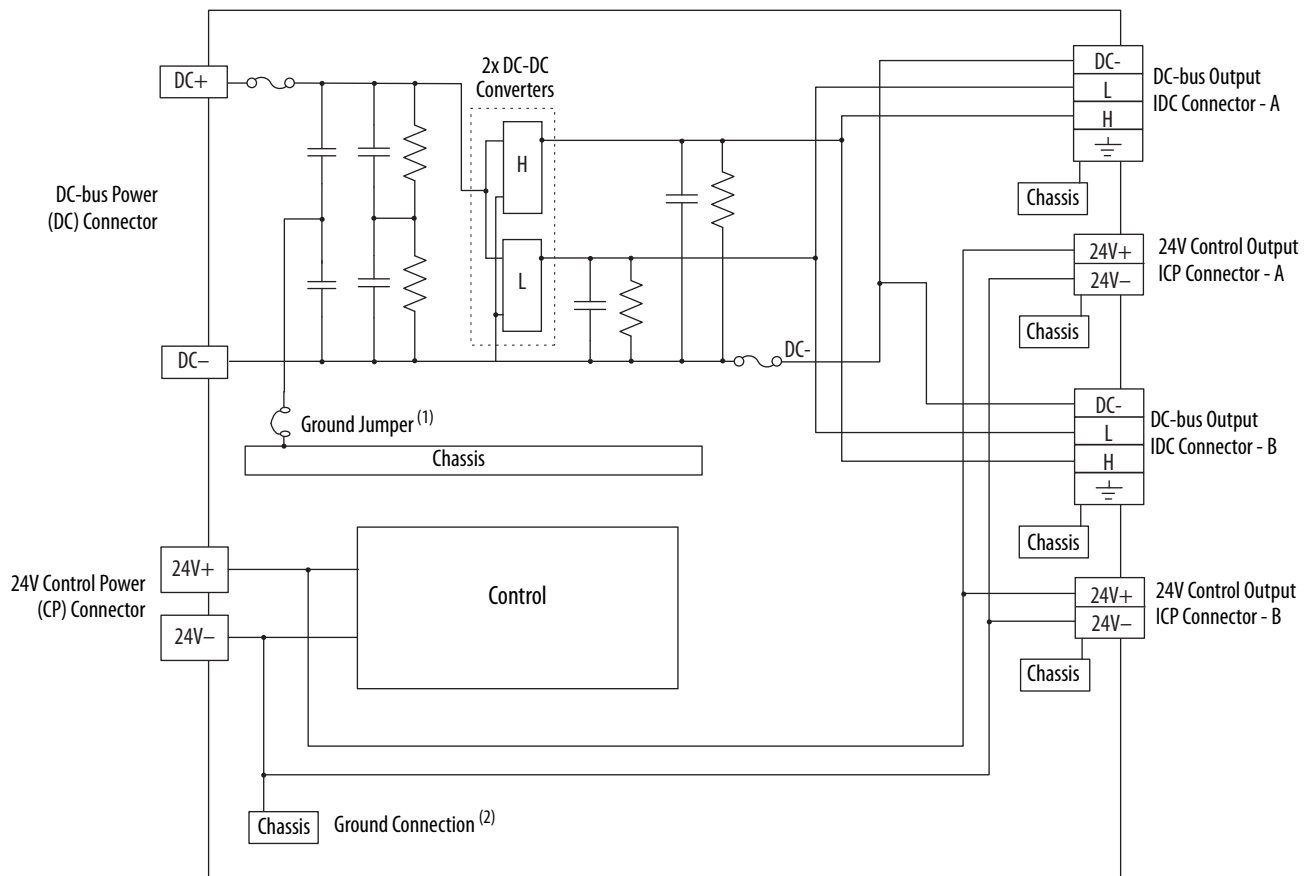


(1) Ground jumper installed on 2198-Sxxx-ERS3 (series A) drives.
Ground jumper removed on 2198-Sxxx-ERS4 and 2198-Sxxx-ERS3 (series B) drives.

Figure 202 - Dual-axis Inverter Block Diagram



(1) Ground jumper installed on 2198-Sxxx-ERS3 (series A) drives.
Ground jumper removed on 2198-Sxxx-ERS4 and 2198-Sxxx-ERS3 (series B) drives.

Figure 203 - iTRAK Power Supply Block Diagram

(1) Ground screw in the installed (default) configuration.

(2) Connection from 24V- to Chassis is made inside of the iTRAK power supply.

Figure 204 - Capacitor Module Block Diagram

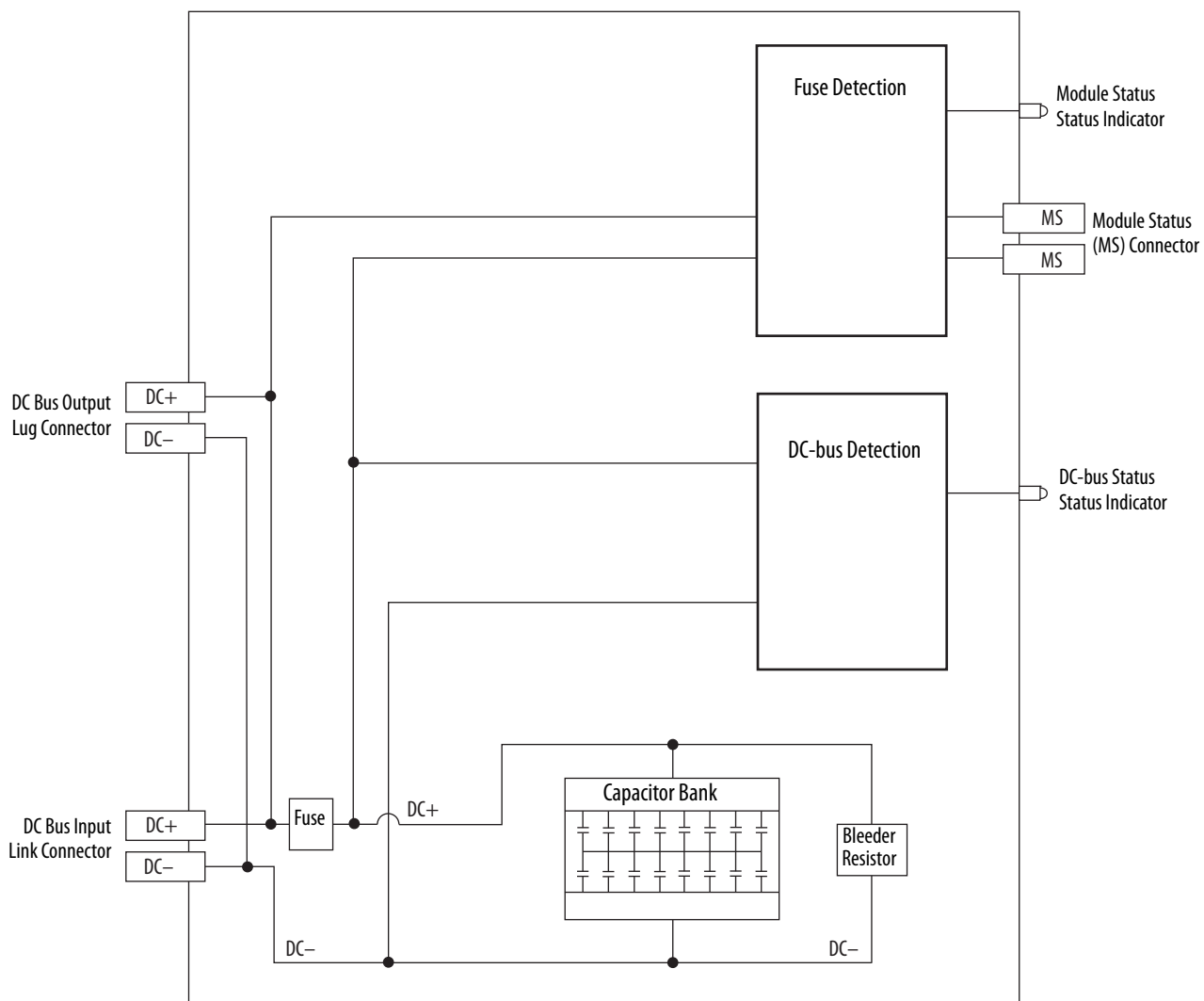
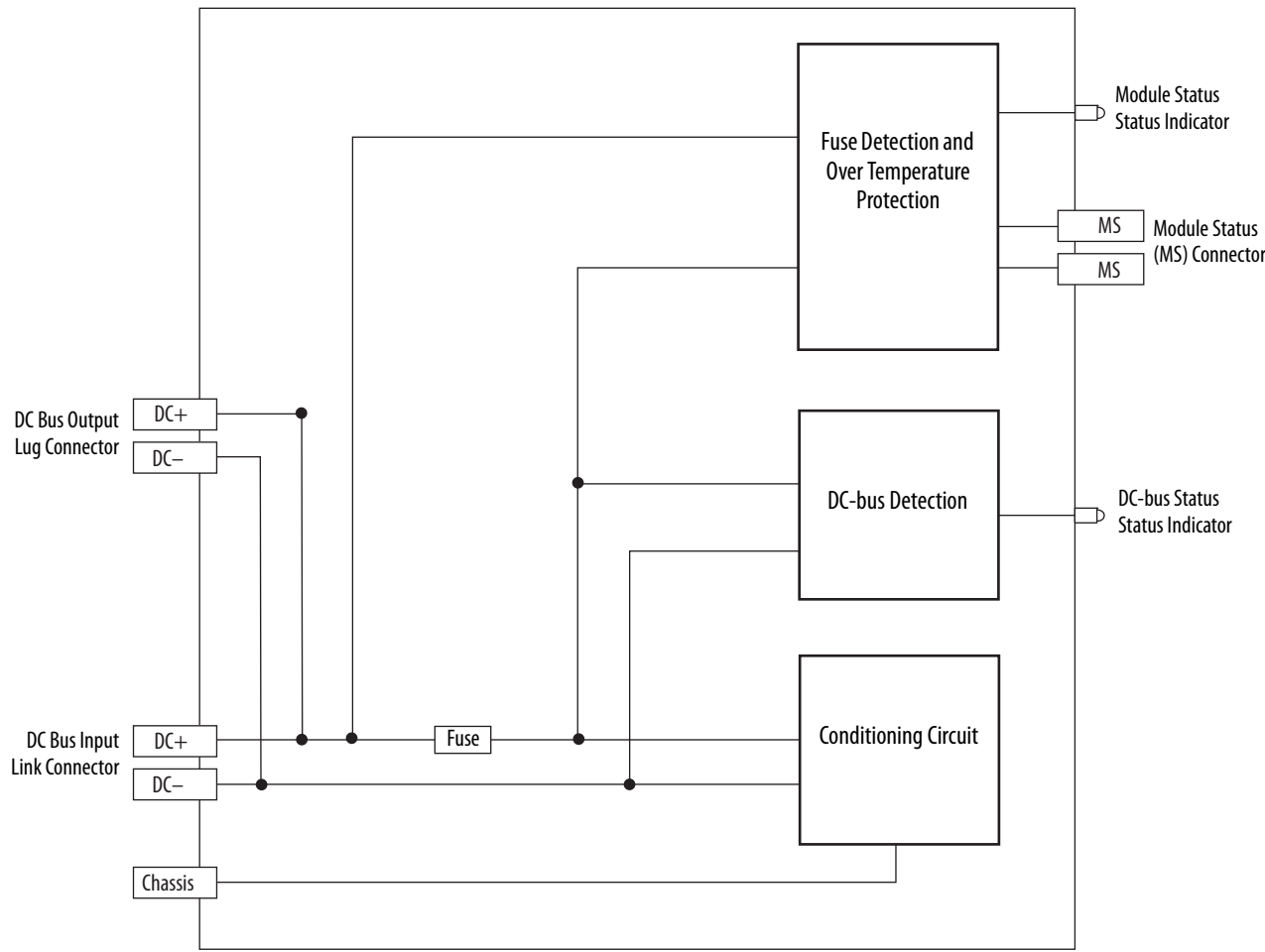


Figure 205 - DC-bus Conditioner Module Block Diagram



Notes:

Upgrade the Drive Firmware

This appendix provides procedures for upgrading your Kinetix® 5700 firmware by using ControlFLASH™ software.

| Topic | Page |
|-----------------------------|------|
| Before You Begin | 382 |
| Upgrade Firmware | 385 |
| Verify the Firmware Upgrade | 389 |

Upgrading drive firmware by using ControlFLASH software involves configuring your Logix 5000™ controller communication, selecting the drive to upgrade, and upgrading the firmware.

| | |
|------------------|--|
| IMPORTANT | If the drive firmware contains updated safety firmware, you must de-energize the safety inputs first or the upgrade fails. To update the drive firmware in Feedback Only mode, you must inhibit the axis first. Refer to Inhibit Feedback Only Axis on page 384 for more information. |
|------------------|--|

Before You Begin

The firmware revision for software must be as shown for EtherNet/IP™ networks.

Table 172 - Kinetix 5700 System Requirements

| Description | Firmware Revision |
|--|-------------------|
| Logix Designer application | 26.00.00 or later |
| RSLinx® software | 3.60.00 or later |
| ControlFLASH software kit ⁽¹⁾ | 12.01.00 or later |
| Catalog numbers of the targeted Kinetix 5700 drive module you want to upgrade. | |
| Network path to the targeted Kinetix 5700 drive module you want to upgrade. | |

(1) Download the ControlFLASH kit from <http://support.rockwellautomation.com/controlflash>. Contact Rockwell Automation® Technical Support at (440) 646-5800 for assistance.

For more ControlFLASH information (not drive specific), refer to the ControlFLASH Firmware Upgrade Kit User Manual, publication [1756-UM105](#).

IMPORTANT Control power must be present at CP-1 (24V+) and CP-2 (24V-) prior to upgrading your target module.

IMPORTANT For the DC-bus power supply and inverter modules, the axis state on the LCD display must be STANDBY, CONFIGURING, or PRECHARGE before beginning this procedure.

IMPORTANT The axis state on the LCD display must be STANDBY, when Protected mode is enabled. See [Table 105](#) on [page 193](#) for more information.

IMPORTANT For the iTRAK® power supply, the axis state on the LCD display must be in the START INHIBITED state. See the iTRAK System User Manual, publication [2198T-UM001](#) for information on upgrading firmware on other iTRAK system components.



ATTENTION: To avoid personal injury or damage to equipment during the firmware upgrade due to unpredictable motor activity, do not apply three-phase AC or common-bus DC input power to the drive.

Configure Logix 5000 Controller Communication

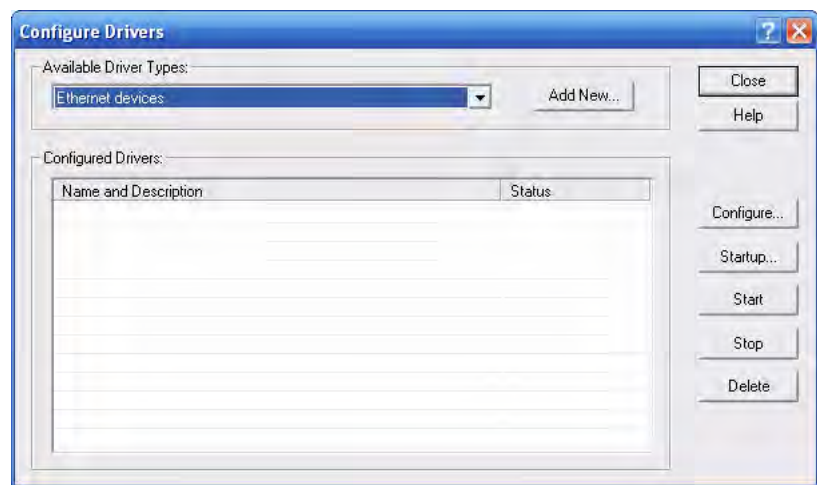
This procedure assumes that your communication method to the Logix 5000 controller is the Ethernet network. It also assumes that your Ethernet communication module or Logix 5000 controller has already been configured.

For more controller information, refer to [Additional Resources](#) on [page 13](#).

Follow these steps to configure Logix 5000 controller communication.

1. Open your RSLinx Classic software.
2. From the Communications menu, choose Configure Drivers.

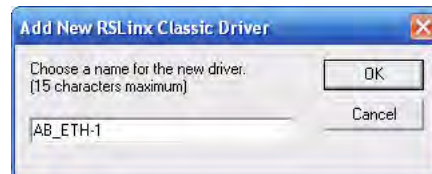
The Configure Drivers dialog box appears.



3. From the Available Driver Types pull-down menu, choose Ethernet devices.
4. Click Add New.

The Add New RSLinx Classic Driver dialog box appears.

5. Type the new driver name.



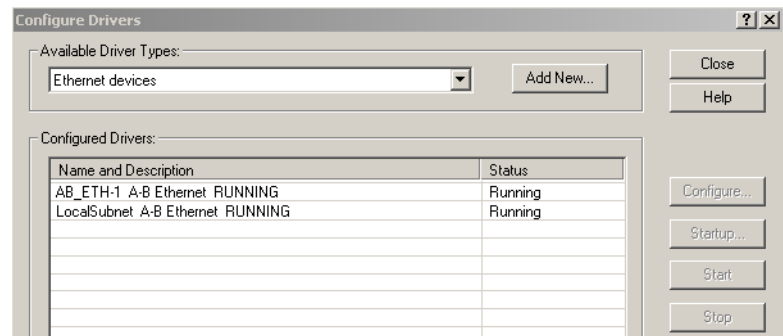
6. Click OK.

The Configure driver dialog box appears.



7. Type the IP address of your Kinetix 5700 servo drive.
8. Click OK.

The new Ethernet driver appears under Configured Drivers.



9. Click Close.
10. Minimize the RSLinx application dialog box.

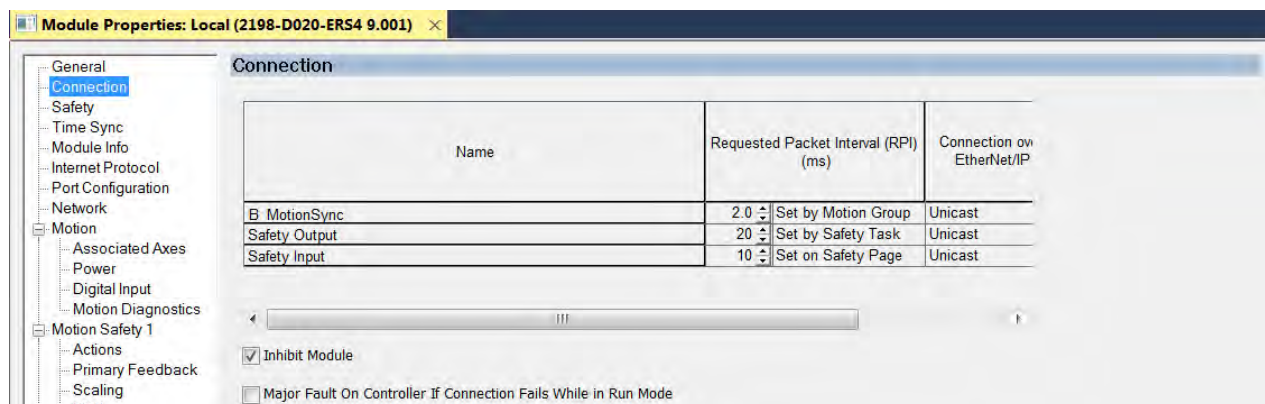
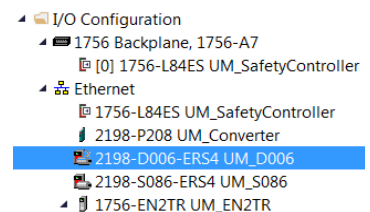
Inhibit Feedback Only Axis

If an axis is configured as Feedback Only, you must inhibit the axis prior to performing the firmware upgrade. Follow these steps to inhibit an axis.

1. Open your Logix Designer application.
2. Right-click the 2198-xxxx-ERSx servo drive you configured as Feedback Only and choose Properties.

The Module Properties dialog box appears.

3. Select the Connection category.



4. Check Inhibit Module.
5. Click OK.
6. Save your file and download the program to the controller.

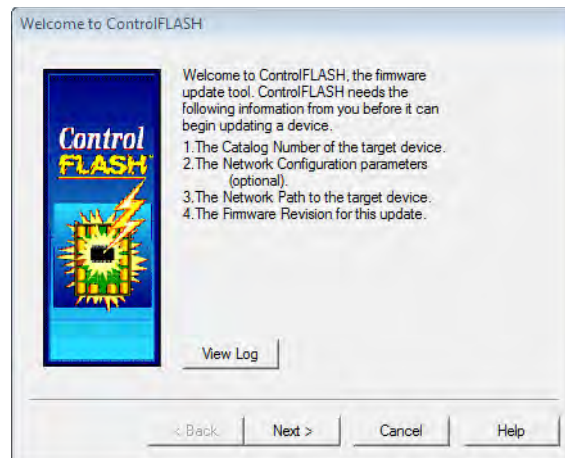
Upgrade Firmware

Follow these steps to select the drive module to upgrade.

1. In the Logix Designer application, from the Tools menu, choose ControlFLASH.

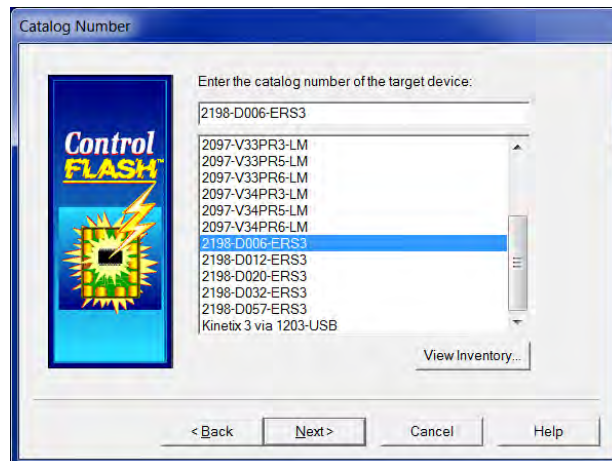
TIP You can also open ControlFLASH software by choosing Start>Programs>FLASH Programming Tools>ControlFLASH.

The Welcome to ControlFLASH dialog box appears.



2. Click Next.

The Catalog Number dialog box appears.

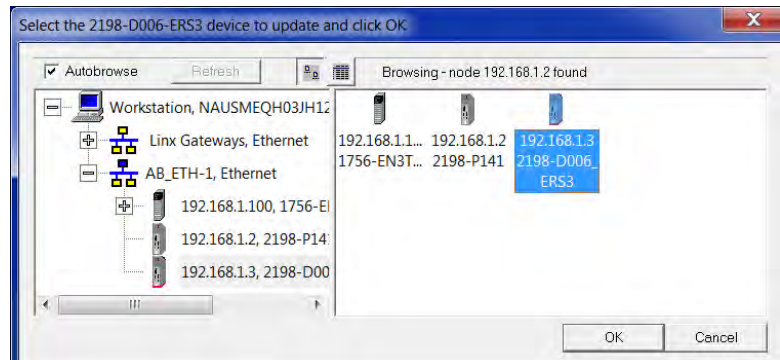


3. Select your drive module.

In this example, the 2198-D006-ERS3 servo drive is selected.

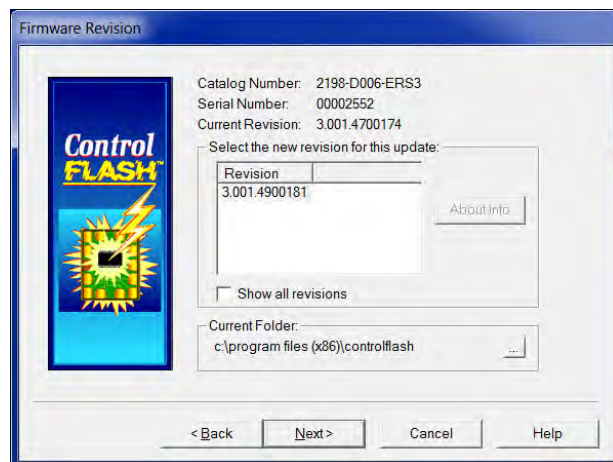
4. Click Next.

The Select Device to Update dialog box appears.



5. Expand your Ethernet node, Logix backplane, and EtherNet/IP network module.
6. Select the servo drive to upgrade.
7. Click OK.

The Firmware Revision dialog box appears.



8. Select the firmware revision to upgrade.
9. Click Next.

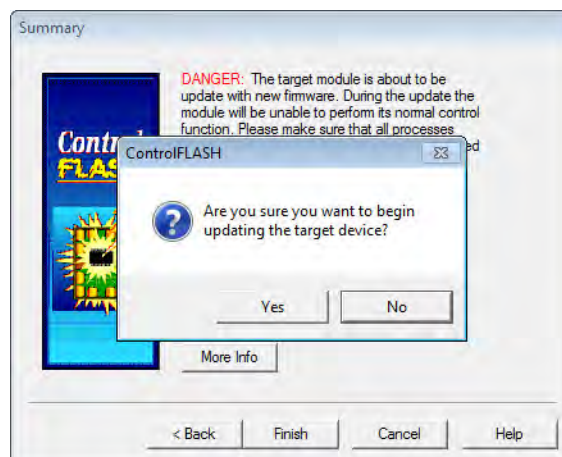
The Summary dialog box appears.



10. Confirm the drive catalog number and firmware revision.

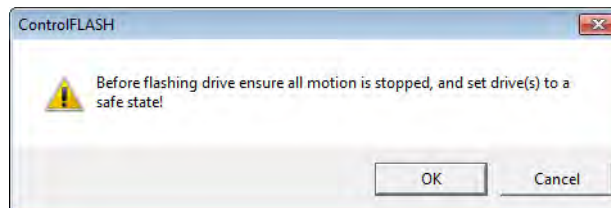
11. Click Finish.

This ControlFLASH warning dialog box appears.



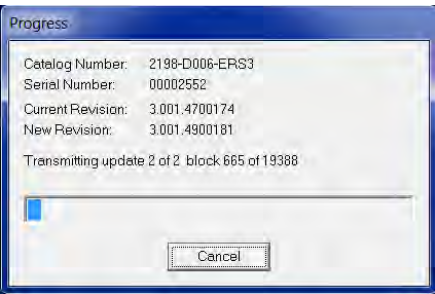
12. Click Yes (only if you are ready).

This ControlFLASH warning dialog box appears.



13. Acknowledge the warning and click OK.

The Progress dialog box appears and updating begins.

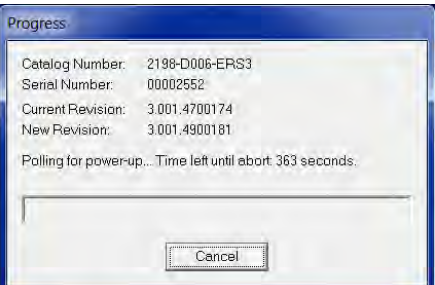


The axis state on the LCD display changes from CONFIGURING, STOPPED, or PRECHARGE to FIRMWARE UPDATE IN PROGRESS, which indicates that the upgrade is in progress.

After the upgrade information is sent to the drive, the drive resets and performs diagnostic checking.

14. Wait for the Progress dialog box to time out.

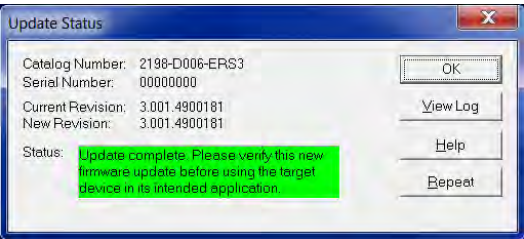
It is normal for this process to take several minutes.



IMPORTANT Do not cycle power to the drive during this process or the firmware upgrade does not complete successfully.

15. Verify that the Update Status dialog box appears and indicates success or failure as described below.

| Upgrading Status | If |
|------------------|---|
| Success | Update complete appears in a green Status dialog box, then go to step 16 . |
| Failure | Update failure appears in a red Status dialog box, then refer to the ControlFLASH Firmware Upgrade Kit User Manual, publication 1756-UM105 for troubleshooting information. |



16. Click OK.

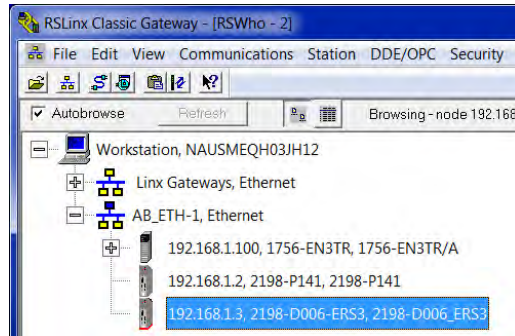
IMPORTANT If you are upgrading a feedback-only axis and you checked Inhibit Module on the Connection category in Module Properties, you must clear the Inhibit Module checkbox before resuming normal operation.

Verify the Firmware Upgrade

Follow these steps to verify your firmware upgrade was successful.

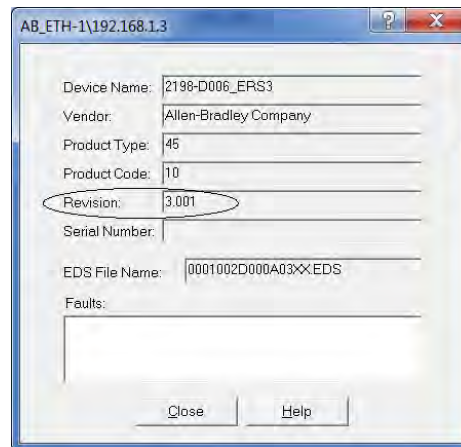
TIP Verifying the firmware upgrade is optional.

1. Open your RSLinx software.
2. From the Communications menu, choose RSWho.



3. Expand your Ethernet node, Logix backplane, and EtherNet/IP network module.
4. Right-click the drive module and choose Device Properties.

The Device Properties dialog box appears.



5. Verify the new firmware revision level.
6. Click Close.

Notes:

Size Multi-axis Shared-bus Configurations

This appendix provides information and examples for sizing your Kinetix® 5700 drive system power supplies and inverters in multi-axis shared-bus configurations.

| Topic | Page |
|-----------------------------------|------|
| Shared DC-bus Configurations | 391 |
| System Sizing Guidelines | 393 |
| System Sizing Example | 399 |
| System Sizing Application Example | 400 |

Shared DC-bus Configurations

You can supply power to your Kinetix 5700 shared DC-bus system configuration from following sources:

- Single 2198-Pxxx DC-bus power supply
- Multiple 2198-P208 DC-bus power supplies (up to three are possible)
- Single 2198-RPxxx regenerative bus supply
- Multiple 8720MC-RPS regenerative power supply

Shared DC-bus Definitions

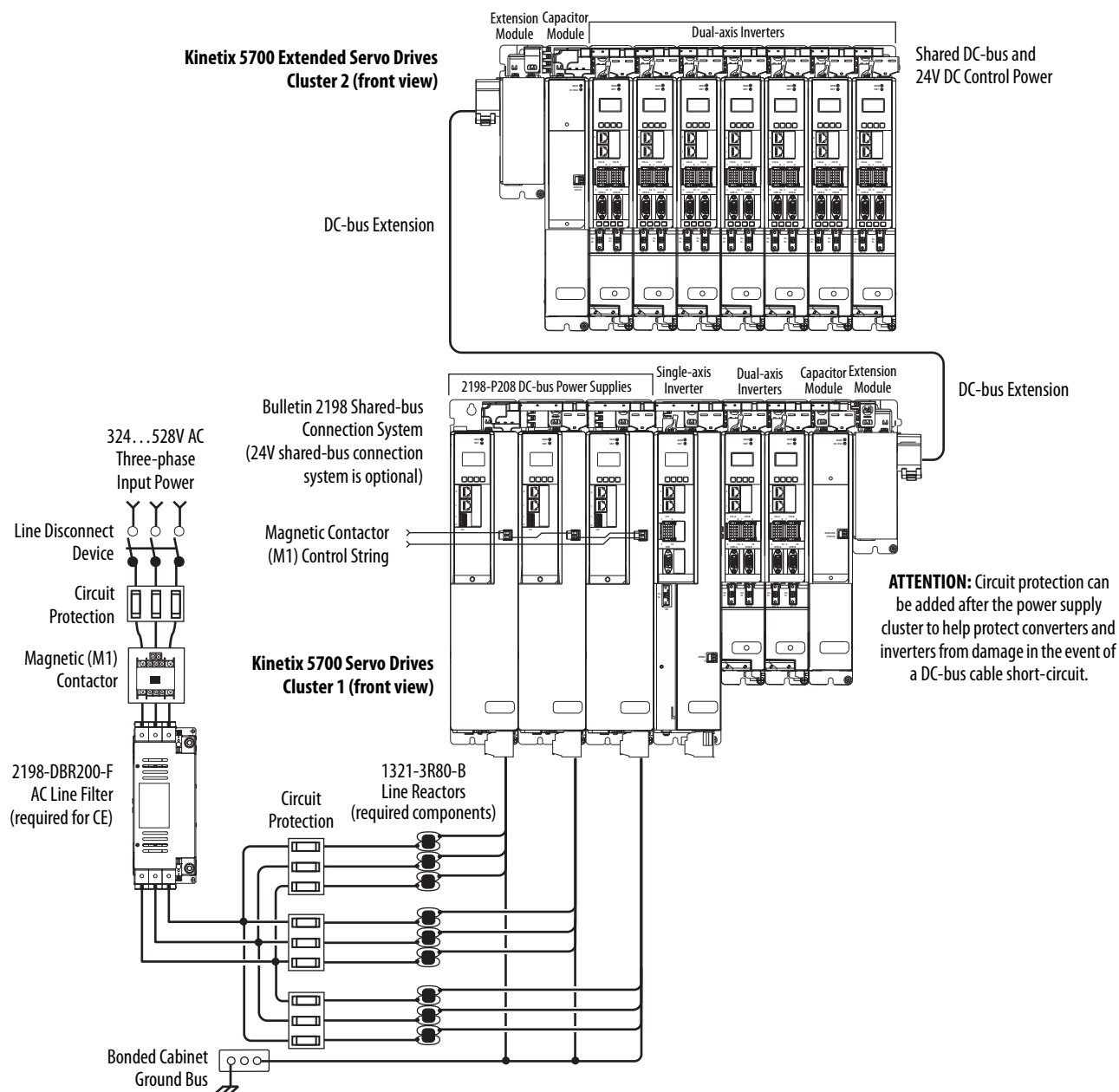
Throughout this manual, these terms are used to describe how drive modules are grouped together.

Table 173 - Shared-bus Terminology

| Term | Definition |
|----------------------|--|
| DC-bus group | Drive modules that are all connected to the same DC bus. |
| Cluster | Group of power supply and/or drive modules that are directly connected together via Kinetix 5700 DC bus-bars only. |
| Extended cluster | Group of drive modules that are directly connected together via Kinetix 5700 DC bus-bars and connected to the power supply cluster via customer-supplied DC-bus cable. |
| Power supply cluster | The cluster that contains the AC to DC converter (power supply). |
| Extended DC-bus | When 2 drive clusters are part of the same DC-bus group joined by the DC bus-bars and customer-supplied DC-bus cable. |

In this example, two drive clusters in the same cabinet are connected by the same 458...747V DC-bus voltage. Kinetix 5700 capacitor modules provide connection points for the DC bus. The extension module is needed only when the DC-bus system current exceeds 104 A, and can support up to 208 A maximum external DC-bus current.

Figure 206 - Extended DC-bus Installation



IMPORTANT When two or three DC-bus power supplies are wired together in the same drive cluster, they must all be catalog number 2198-P208.

General Sizing Guidelines

These limitations apply to Kinetix 5700 servo drive systems supplied by a single 2198-Pxxx or multiple 2198-P208 DC-bus power supplies, or 2198-RPxxx regenerative bus supplies:

- The sum of the inverter motor-power cable lengths for all inverters on the same DC bus-sharing group must not exceed 1200 m (3937 ft) to comply with CE requirements when used with 2198-DBRxx-F line filters. 2198-DBxx-F line filters have a total motor cable length limit of 400 m (1312 ft). See [Drive to Motor Cable Lengths](#) on [page 158](#) for additional motor power cable-length limitations.
- The total system capacitance limit is based on the power supply catalog number. DC-bus groups must not exceed the limits as defined in [Table 174](#).
- No more than three 2198-P208 DC-bus power supplies can be used to increase the converter power.
- If using the 24V DC shared-bus connection system to distribute control input power to a cluster of drive modules, current from the 24V power supply must not exceed 40 A.
- The Kinetix 5700 system can have multiple drive clusters in a single DC-bus group. See [DC Bus Cluster-to-Cluster Cable Lengths](#) on [page 155](#) for more information on extended clusters.

Refer the 8720MC Regenerative Power Supply Installation Manual, publication [8720MC-RM001](#), for additional system sizing limitations.

System Sizing Guidelines

You begin the process by selecting the motor for your application and sizing the drive and power supply combinations. Next, calculate whether the motor power cable length, total system capacitance, and 24V current demand are within specifications.

For systems with an iTRAK® power supply, the iTRAK system requirements must be calculated to determine the following:

- Kinetix 5700 DC-bus loading (DC-bus motoring and bus-regulation power requirements)
- 2198-Pxxx power supply or 2198-RPxxx regenerative power supply for providing DC-bus to the iTRAK power supplies
- 24V current demand
- Number of iTRAK power supplies required
- Resulting net converter power and bus-regulator capacity

See the iTRAK System User Manual, publication [2198T-UM001](#) for more information.

For iTRAK hardware and iTRAK power supplies, proceed to the [Calculate System and External-bus Capacitance](#) on [page 394](#).

Select Drive/Motor Combinations

The motor required for a particular application determines the servo drive required for full motor performance.

For best results, use the Motion Analyzer system sizing and selection tool, available at <https://motionanalyzer.rockwellautomation.com>. Drive/motor performance specifications and torque/speed curves are also available in the Kinetix 5700 Drive Systems Design Guide, publication [KNX-RM010](#).

Select the Power Supply and Define the DC-bus Groups

- Determine the converter DC-bus motoring and bus-regulation power requirements based on the load profile.
- Estimate the net converter and inverter power and bus-regulator capacity, based on the load profiles.
- Determine if 2198-CAPMOD-2240 capacitor modules are required.
- Determine if 2198-DCBUSCOND-RP312 DC-bus conditioner modules are required.

For best results, use the Motion Analyzer system sizing and selection tool, available at <https://motionanalyzer.rockwellautomation.com>.

Calculate System and External-bus Capacitance

Total system capacitance is the sum of all internal capacitance values from each of the drive modules (single-axis inverters, dual-axis inverters, power supplies, and capacitor modules) in the same DC-bus group.

The total system capacitance must be less than the maximum supported DC-bus capacitance value of the power supply.

| | |
|------------------|--|
| IMPORTANT | If your total system capacitance value exceeds the maximum supported capacitance value of the DC-bus power supply, perform one of the following: <ul style="list-style-type: none">• Increase the size of the 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply• Use multiple DC-bus power supplies (1...3 power supplies are possible) Decrease the total system capacitance by removing inverters or capacitor modules from the DC-bus group. |
|------------------|--|

External bus capacitance is the total system capacitance minus the power supply capacitance. The external bus capacitance must be entered into the Logix Designer application for a regenerative power supply to maintain proper control.

Table 174 - Power Supply Capacitance

| Power Supply | DC-bus Power Supply Cat. No. | Supported Capacitance, max μF | Internal Capacitance μF |
|--------------------------------|------------------------------|----------------------------------|----------------------------|
| Single DC-bus Power Supply | 2198-P031 | 8,000 | 585 |
| | 2198-P070 | | 780 |
| | 2198-P141 | 13,000 | 1640 |
| | 2198-P208 | | 2050 |
| Multiple DC-bus Power Supplies | 2198-P208 x 2 | 26,000 | 4100 |
| | 2198-P208 x 3 | 39,000 | 6150 |
| Regenerative Bus Supplies | 2198-RP088 | 9,000 | 940 |
| | 2198-RP200 | 15,000 | 2460 |
| | 2198-RP263 | 25,000 | 4510 |
| | 2198-RP312 | | 5740 |
| iTRAK Power Supply | 2198T-W25K-ER | 390 | 0 |

Table 175 - Internal Inverter and Accessory Module Capacitance

| Drive Module | Drive Module Cat. No. | Internal Capacitance μF |
|---------------------------|-----------------------|----------------------------|
| Dual-axis Inverters | 2198-D006-ERSx | 165 |
| | 2198-D012-ERSx | |
| | 2198-D020-ERSx | 330 |
| | 2198-D032-ERSx | 390 |
| | 2198-D057-ERSx | 705 |
| Single-axis Inverters | 2198-S086-ERSx | 560 |
| | 2198-S130-ERSx | 840 |
| | 2198-S160-ERSx | 1120 |
| | 2198-S263-ERSx | 2050 |
| | 2198-S312-ERSx | |
| Capacitor Module | 2198-CAPMOD-2240 | 2240 |
| Extension Module | 2198-CAPMOD-DCBUS-IO | 0 |
| DC-bus Conditioner Module | 2198-DCBUSCOND-RP312 | 0 |

Calculate the Total Motor Power Cable Length

To meet CE requirements, the sum of all motor power cable lengths from the same DC-bus group must not exceed 1200 m (3937 ft) when 2198-DBRxx-F line filters are used. See [Drive to Motor Cable Lengths](#) on [page 158](#) for additional motor power cable-length limitations.

Calculate 24V DC Control Power Current Demand

If using the 24V DC shared-bus connection system to distribute control input power to a drive cluster, output current from the 24V power supply must not exceed 40 A.

Table 176 - Control Power Current Specifications

| Drive Module | Drive Module Cat. No. | 24V Current Per Module (non-brake motor) A _{DC} | 24V Current, max (with maximum brake current) A _{DC} | 24V Inrush Current ⁽⁵⁾ A |
|-----------------------------------|--------------------------|--|---|--|
| DC-bus Power Supplies | 2198-P031 | 0.8 | — | 4.0 |
| | 2198-P070 | | | |
| | 2198-P141 | 1.9 | | |
| | 2198-P208 | | | |
| Regenerative Bus Supplies | 2198-RP088 | 4.3 | — | 4.0 |
| | 2198-RP200 | 5.4 | | |
| | 2198-RP263 | 9.1 | | |
| | 2198-RP312 | | | |
| Dual-axis Inverters | 2198-D006-ERSx | 1.4 ⁽²⁾ | 5.5 ⁽³⁾ | 4.0 |
| | 2198-D012-ERSx | | | |
| | 2198-D020-ERSx | | | |
| | 2198-D032-ERSx | 1.7 ⁽²⁾ | 7.7 ⁽³⁾ | |
| | 2198-D057-ERSx | 2.3 ⁽²⁾ | 8.3 ⁽³⁾ | |
| Single-axis Inverters | 2198-S086-ERSx | 4.6 | 9.6 ⁽⁴⁾ | 4.0 |
| | 2198-S130-ERSx | | | |
| | 2198-S160-ERSx | | | |
| | 2198-S263-ERSx | | | |
| | 2198-S312-ERSx | | | |
| iTRAK Power Supply ⁽¹⁾ | 2198T-W25K-ER | 1.3 | — | 2.2 |
| Capacitor Module | 2198-CAPMOD-2240 | 0.1 | — | 7.0 |
| Extension Module | 2198-CAPMOD-DCBUS-IO | — | | — |
| DC-bus Conditioner Module | 2198-DCBUSCOND-RP312 | 0.1 | | 7.0 |

(1) These values represent only the iTRAK power supply. They do not include the iTRAK motor modules that are connected to the iTRAK power supply and also draw current from this 24V control power input. For more information regarding 24V control power requirements, see the iTRAK System User Manual, publication [2198T-UM001](#).

(2) Values are base current per module.

(3) Values assume two brake motors, each drawing the maximum rating of 2 A, are attached to each module.

(4) Values assume the maximum rated brake current of 5 A.

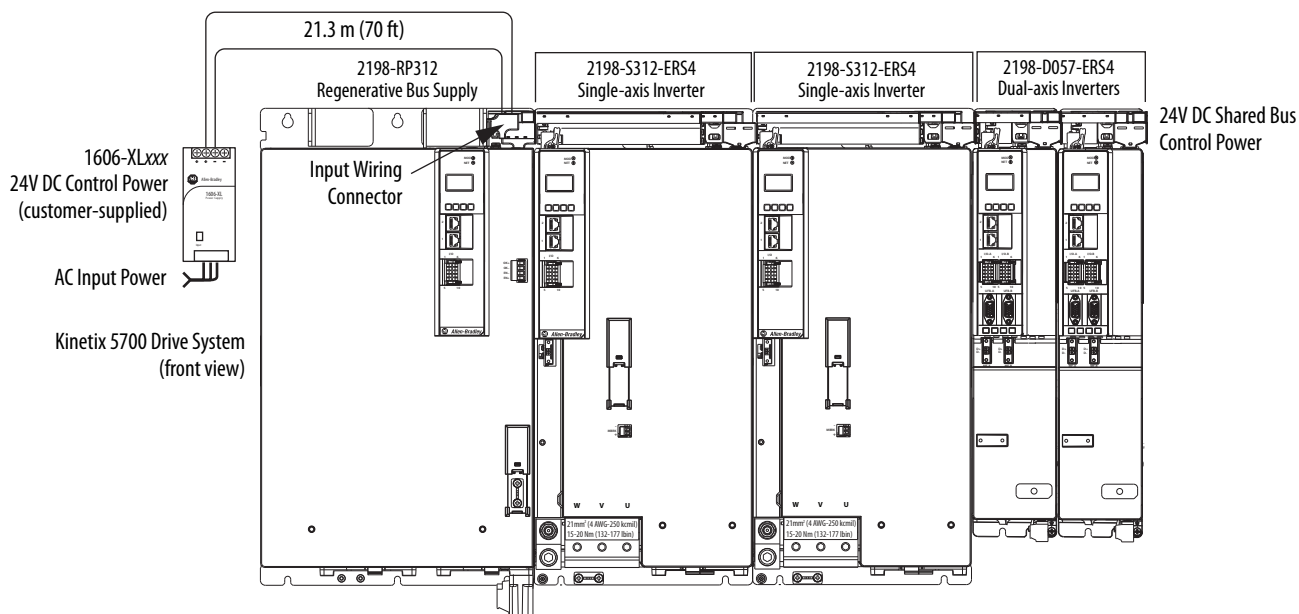
(5) Inrush current duration is less than 30 ms.

IMPORTANT If the 24V control-power output current (based on your system calculation) exceeds 40 A, you can insert another control-power input wiring connector at any point in your drive cluster. However, the input connector must always extend the 24V DC-bus from left to right.

24V DC Voltage Drop Calculation Example

In this example, the 24V DC power supply is 21.3 m (70 ft) away from the Kinetix 5700 drive system. The drive system includes one 2198-RP312 regenerative bus supply, two 2198-S312-ERS4 single-axis inverters, and two 2198-D057-ERS4 dual-axis inverters. The inverters supply power to six non-brake motors.

Figure 207 - 24V DC Voltage Drop Example System



Follow these steps to calculate the voltage drop for your drive system. The system conditions remain the same, but the wire gauge (AWG) is increased to reduce the voltage drop.

1. Determine the 24V DC control power current demand.

In this example, the total current demand is 22.9 A. See [Calculate 24V DC Control Power Current Demand](#) on [page 396](#) for current values.

| Module | Qty | Current Demand |
|----------------------|-----|-----------------------|
| 2198-RP312 | 1 | 9.1 A |
| 2198-S312-ERS4 | 2 | $4.6 \cdot 2 = 9.2$ A |
| 2198-D057-ERS4 | 2 | $2.3 \cdot 2 = 4.6$ A |
| Total current demand | | 22.9 A |

2. Determine the voltage drop across the wire that is used to supply 24V power to the drive system (voltage drop = current draw • resistance of the wire).

You must obtain the wire resistance value from the wire manufacturer. Resistance values used below are only examples.

| Wire Length | Wire Gauge mm ² (AWG) | Calculation | Voltage Drop |
|----------------|-------------------------------------|-------------------------------------|--------------|
| 21.3 m (70 ft) | 1.5 (16) | $22.9 \text{ A} \cdot 0.281 \Omega$ | 6.43V |
| | 4.0 (12) | $22.9 \text{ A} \cdot 0.111 \Omega$ | 2.54V |
| | 6.0 (10) | $22.9 \text{ A} \cdot 0.070 \Omega$ | 1.60V |

3. Determine if the voltage supplied to the drive system is within its required input-voltage range; $24\text{V} \pm 10\%$ (21.6...26.4V DC).

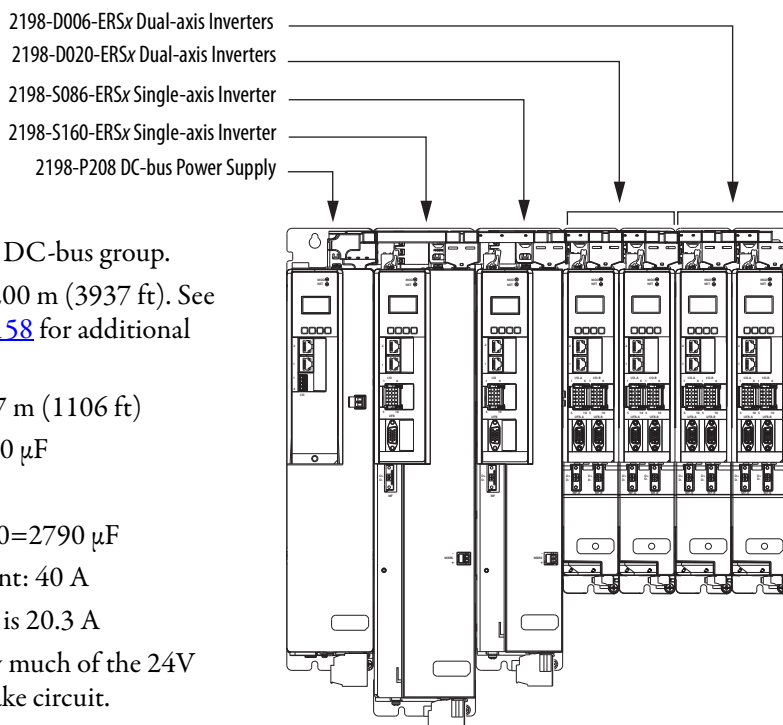
| Wire Length | Wire Gauge | Calculation | Applied Voltage |
|----------------|------------|-----------------------------|-----------------------|
| 21.3 m (70 ft) | 1.5 (16) | $24\text{V} - 6.43\text{V}$ | 17.57V (insufficient) |
| | 4.0 (12) | $24\text{V} - 2.54\text{V}$ | 21.46V (insufficient) |
| | 6.0 (10) | $24\text{V} - 1.60\text{V}$ | 22.40V (acceptable) |

In this example, increasing the wire gauge to 6 mm² (10 AWG) is one way to lower the voltage drop. See [24V Control Power Evaluation](#) on [page 49](#) for additional suggestions.

System Sizing Example

This example shows how a single Kinetix 5700 drive cluster meets the total bus capacitance, power cable length, and 24V DC current limitations.

Figure 208 - Example DC-bus Group (single drive cluster)



In this example, only 1 drive cluster defines the DC-bus group.

- Maximum motor power cable length: 1200 m (3937 ft). See [Drive to Motor Cable Lengths](#) on [page 158](#) for additional motor power cable-length limitations.
 - Total motor power cable length is 337 m (1106 ft)
- Maximum supported capacitance: 13,000 μF
 - Total system capacitance is 4840 μF
 - External bus capacitance is $4840 - 2050 = 2790$ μF
- Maximum 24V DC control power current: 40 A
 - Total 24V DC control power current is 20.3 A
 - The Coil Current column shows how much of the 24V current is consumed by the motor brake circuit.

All of the total system values are within the acceptable range.

Table 177 - System Sizing Example Data

| DC-bus Group Cat. No. | Axis | Internal Capacitance μF | Cable Length m (ft) | Servo Motor | | 24V DC Control Power Current Calculations | | |
|-----------------------|------|------------------------------------|---------------------|----------------------|---------------------|---|--|-----------------|
| | | | | Servo Motor Cat. No. | Brake Option Yes/No | Brake Current @ 24V DC A | 24V Current (non-brake motor) A_{DC} | Total Current A |
| 2198-P208 | | 2050 | — | — | — | — | 1.9 | 1.9 |
| 2198-S160-ERSx | | 1120 | 50 (164) | MPL-B980E | No | — | 4.6 | 4.6 |
| 2198-S086-ERSx | | 560 | 90 (295) | MPL-B660F | Yes | 2.1 | 4.6 | 6.7 |
| 2198-D020-ERSx | A | 390 | 20 (66) | VPL-B1152F | No | — | 1.4 | 1.4 |
| | B | | 15 (49) | VPL-B1152F | No | — | | |
| 2198-D020-ERSx | A | 390 | 9 (30) | VPL-B1003C | Yes | 0.50 | 1.4 | 2.4 |
| | B | | 90 (295) | VPL-B1003C | Yes | 0.50 | | |
| 2198-D006-ERSx | A | 165 | 9 (30) | MPL-B310P | Yes | 0.50 | 1.4 | 1.9 |
| | B | | 9 (30) | MPL-B310P | No | — | | |
| 2198-D006-ERSx | A | 165 | 15 (49) | MPL-B310P | No | — | 1.4 | 1.4 |
| | B | | 30 (98) | MPL-B310P | No | — | | |
| Totals | | 4840 | 337 (1106) | | | 3.6 | 16.7 | 20.3 |

For more information on motor and motor-brake specifications, refer to the Kinetix Rotary Motion Specifications Technical Data, publication [KNX-TD001](#).

System Sizing Application Example

This example shows how to size the DC-bus power supply for your multi-axis system by using the motor output power (kW). Sizing is based on the largest motor kW value in your drive system.

The Kinetix 5700 drive modules are zero-stacked and use the shared-bus connection system to extend power from the 2198-Pxxx DC-bus power supply or 2198-RPxxx regenerative bus supply to multiple drive modules. For best results, use the Motion Analyzer system sizing and selection tool, available at <https://motionanalyzer.rockwellautomation.com>.

Table 178 - Kinetix 5700 System Power Supply Continuous Output Power

| DC-Bus Power Supply Cat. No. | Continuous Output Power kW | Regenerative Bus Supply Cat. No. | Continuous Output Power kW |
|------------------------------|----------------------------|----------------------------------|----------------------------|
| 2198-P031 | 7 | 2198-RP088 | 24 |
| 2198-P070 | 17 | 2198-RP200 | 67 |
| 2198-P141 | 31 | 2198-RP263 | 119 |
| 2198-P208 | 46 | 2198-RP312 | 140 |

In this typical system, all axes are running in an asynchronous rapid acceleration/deceleration motion profile. Use this formula to calculate the minimum continuous output-power (kW) for your Kinetix 5700 drive system:

$$2198\text{-Pxxx} = \text{Largest motor-rated kW} \times (\text{axis-count} \times 0.6) + (\text{axis-count} \times 0.2)$$

Table 179 - Motor/Drive System Example

| Motor Quantity | Motor Cat. No. | Motor Rated Output ⁽¹⁾ kW | Drive Cat. No. |
|----------------|----------------|--------------------------------------|----------------|
| 1 | MPM-B2153F | 7.2 | 2198-S086-ERSx |
| 1 | | | 2198-S086-ERSx |
| 1 | MPL-B660F | 6.1 | 2198-S086-ERSx |
| 1 | | | 2198-S086-ERSx |
| 2 | VPL-B0753 | 0.82 | 2198-D020-ERSx |
| 2 | | | 2198-D020-ERSx |

8 = axis count

(1) For more motor specifications, see the Kinetix Rotary Motion Specifications Technical Data, publication [KNX-TD001](#).

$$\begin{aligned} \text{Continuous Output Power, min (kW)} &= 7.2 \times (8 \times 0.6) + (8 \times 0.2) \\ \text{kW} &= 7.2 \times 4.8 + 1.6 \\ \text{kW} &= 36.16 \end{aligned}$$

In this example, the MPM-B2153F motor has the largest motor-rated output. As a result, the minimum continuous output-power = 36.16 kW, and the 2198-P208 DC-bus power supply or 2198-RP200 regenerative bus supply is required for the 8-axis system example.

Maximum Motor Cable Lengths for Kinetix 5700 Power Supplies

This appendix provides information on maximum motor cable length limitations for Kinetix® 5700 drive systems.

| Topic | Page |
|--|------|
| DC-bus Power Supply Configurations | 402 |
| Regenerative Bus Supply Configurations | 404 |

Maximum motor cable lengths for the following configurations are dependent on these configuration variables:

- Kinetix 5700 power supply
 - 2198-Pxxx DC-bus power supply
 - 2198-RPxxx regenerative bus supply
- AC input power type
 - WYE grounded
 - WYE impedance grounded
 - WYE/Delta corner grounded or ungrounded
- AC input voltage
 - 480V AC
 - 400V AC
- Whether the regenerative bus supply is operating with DC bus regulation enabled or disabled
 - For more information on DC bus voltage regulation, refer to [DC-bus Voltage Regulation](#) on [page 42](#)
- Whether the drive cluster includes a DC-bus conditioner module
- Allen-Bradley® servo motor or actuator connected to the inverter

DC-bus Power Supply Configurations

2198-RPxxx regenerative power supplies have the same maximum drive-to-motor cable length limits as 2198-Pxxx DC-bus power supplies when they operate with DC-bus regulation disabled.

Table 180 - DC-bus Power Supply (480V AC input)

| AC Input Power Source Type | Motor/Actuator Cat. No. | Drive-to-Motor Cable Length, max m (ft) |
|---|--|--|
| WYE Grounded | <ul style="list-style-type: none"> LDAT-Sxxxxxx LDC-Cxxxxxx MPAS-B8xxxF-ALM MPAS-B9xxxL-ALM | 10 (32.8) |
| | <ul style="list-style-type: none"> VPx-B063xx, VPx-B075xx MPx-B15xx, MPx-B2xx MPAR-B1xxxx, MPAR-B2xxxx VPAR-B1xxxx, VPAR-B2xxxx MPAS-Bxxxx1, MPAS-Bxxxx2 MPAI-Bxxxxx | 90 (295) |
| | <ul style="list-style-type: none"> VPx-B100xx...VPx-B300xx MPAR-B3xxxx VPAR-B3xxxx MPx-B3xxx...MPx-B9xxx MPM-B115xx...MPM-B215xx HPK-xxxxxx RDB-Bxxxxx | 90 (295) |
| Delta Corner Grounded | <ul style="list-style-type: none"> VPx-B063xx, VPx-B075xx MPx-B15xx, MPx-B2xx MPAR-B1xxxx, MPAR-B2xxxx VPAR-B1xxxx, VPAR-B2xxxx MPAS-Bxxxx1, MPAS-Bxxxx2 MPAI-Bxxxxx | 15 (49.2) |
| | <ul style="list-style-type: none"> VPx-B100xx...VPx-B300xx MPAR-B3xxxx VPAR-B3xxxx MPx-B3xxx...MPx-B9xxx MPM-B115xx...MPM-B215xx HPK-xxxxxx RDB-Bxxxxx | 50 (164) |
| <ul style="list-style-type: none"> WYE Impedance Grounded ⁽¹⁾ WYE Ungrounded ⁽²⁾ Delta Ungrounded ⁽²⁾ | <ul style="list-style-type: none"> LDAT-Sxxxxxx LDC-Cxxxxxx MPAS-B8xxxF-ALM MPAS-B9xxxL-ALM | 10 (32.8) |
| | <ul style="list-style-type: none"> VPx-B063xx, VPx-B075xx MPx-B15xx, MPx-B2xx MPAR-B1xxxx, MPAR-B2xxxx VPAR-B1xxxx, VPAR-B2xxxx MPAS-Bxxxx1, MPAS-Bxxxx2 MPAI-Bxxxxx | 90 (295) |
| | <ul style="list-style-type: none"> VPx-B100xx...VPx-B300xx MPAR-B3xxxx VPAR-B3xxxx MPx-B3xxx...MPx-B9xxx MPM-B115xx...MPM-B215xx HPK-xxxxxx RDB-Bxxxxx | 90 (295) |

(1) Impedance grounded systems running in ground fault conditions, for prolonged periods of time, cause additional stress to the motor insulation and can cause premature motor failure.

(2) Unbalanced, floating, ungrounded systems can cause additional stress to the motor.

Table 181 - DC-bus Power Supply (400V AC input)

| AC Input Power Source Type | Motor/Actuator Cat. No. | Drive-to-Motor Cable Length, max m (ft) |
|---|---|--|
| WYE Grounded | <ul style="list-style-type: none"> • LDAT-Sxxxxxx • LDC-Cxxxxxx • MPAS-B8xxxF-ALM • MPAS-B9xxxL-ALM | 10 (32.8) |
| | <ul style="list-style-type: none"> • VPx-B063xx, VPx-B075xx • MPx-B15xx, MPx-B2xx • MPAR-B1xxxx, MPAR-B2xxxx • VPAR-B1xxxx, VPAR-B2xxxx • MPAS-Bxxxx1, MPAS-Bxxxx2 • MPAL-Bxxxx | 90 (295) |
| | <ul style="list-style-type: none"> • VPx-B100xx...VPx-B300xx • MPAR-B3xxxx • VPAR-B3xxxx • MPx-B3xxx...MPx-B9xxx • MPM-B115xx...MPM-B215xx • HPK-xxxxxx • RDB-Bxxxx | 90 (295) |
| Delta Corner Grounded | <ul style="list-style-type: none"> • VPx-B063xx, VPx-B075xx • MPx-B15xx, MPx-B2xx • MPAR-B1xxxx, MPAR-B2xxxx • VPAR-B1xxxx, VPAR-B2xxxx • MPAS-Bxxxx1, MPAS-Bxxxx2 • MPAL-Bxxxx | 50 (164) |
| | <ul style="list-style-type: none"> • VPx-B100xx...VPx-B300xx • MPAR-B3xxxx • VPAR-B3xxxx • MPx-B3xxx...MPx-B9xxx • MPM-B115xx...MPM-B215xx • HPK-xxxxxx • RDB-Bxxxx | 90 (295) |
| <ul style="list-style-type: none"> • WYE Impedance Grounded ⁽¹⁾ • WYE Ungrounded ⁽²⁾ • Delta Ungrounded ⁽²⁾ | <ul style="list-style-type: none"> • LDAT-Sxxxxxx • LDC-Cxxxxxx • MPAS-B8xxxF-ALM • MPAS-B9xxxL-ALM | 10 (32.8) |
| | <ul style="list-style-type: none"> • VPx-B063xx, VPx-B075xx • MPx-B15xx, MPx-B2xx • MPAR-B1xxxx, MPAR-B2xxxx • VPAR-B1xxxx, VPAR-B2xxxx • MPAS-Bxxxx1, MPAS-Bxxxx2 • MPAL-Bxxxx | 90 (295) |
| | <ul style="list-style-type: none"> • VPx-B100xx...VPx-B300xx • MPAR-B3xxxx • VPAR-B3xxxx • MPx-B3xxx...MPx-B9xxx • MPM-B115xx...MPM-B215xx • HPK-xxxxxx • RDB-Bxxxx | 90 (295) |

(1) Impedance grounded systems running in ground fault conditions, for prolonged periods of time, cause additional stress to the motor insulation and can cause premature motor failure.

(2) Unbalanced, floating, ungrounded systems can cause additional stress to the motor.

Regenerative Bus Supply Configurations

2198-RPxxx regenerative bus supplies have limited maximum drive-to-motor cable length when DC-bus regulation is enabled. However, the DC Bus can be extended up to 70 m (230 ft) to remote clusters of Kinetix 5700 inverters. The result is a shorter distance from the inverter to the motor and thus shorter individual motor cable lengths.

Table 182 - Regenerative Bus Supply (480V AC input)

| AC Input Power Source Type ⁽¹⁾ | Motor/Actuator Cat. No. | | Drive-to-Motor Cable Length, max m (ft) | |
|---|---|---|--|----------------------------|
| | | | With DC-bus Conditioner | Without DC-bus Conditioner |
| WYE Grounded | <ul style="list-style-type: none">LDAT-SxxxxxxLDC-Cxxxxxx | <ul style="list-style-type: none">MPAS-B8xxxF-ALMMPAS-B9xxxL-ALM | 10 (32.8) | 10 (32.8) |
| | <ul style="list-style-type: none">VPx-B063xx, VPx-B075xxMPx-B15xx, MPx-B2xxVPAR-B1xxxx, VPAR-B2xxxx | <ul style="list-style-type: none">MPAR-B1xxxx, MPAR-B2xxxxMPAS-Bxxxx1, MPAS-Bxxxx2MPAI-Bxxxxx | 20 (65.6) | 15 (49.2) |
| | <ul style="list-style-type: none">VPx-B100xx...VPx-B300xxVPAR-B3xxxxMPAR-B3xxxxRDB-Bxxxxxx | <ul style="list-style-type: none">MPx-B3xxx...MPx-B9xxxMPM-B115xx...MPM-B215xxHPK-xxxxxxx | 50 (164) | 30 (98.4) |
| WYE Impedance Grounded ⁽²⁾ | <ul style="list-style-type: none">LDAT-SxxxxxxLDC-Cxxxxxx | <ul style="list-style-type: none">MPAS-B8xxxF-ALMMPAS-B9xxxL-ALM | 10 (32.8) | 10 (32.8) |
| | <ul style="list-style-type: none">VPx-B063xx, VPx-B075xxMPx-B15xx, MPx-B2xxVPAR-B1xxxx, VPAR-B2xxxx | <ul style="list-style-type: none">MPAR-B1xxxx, MPAR-B2xxxxMPAS-Bxxxx1, MPAS-Bxxxx2MPAI-Bxxxxx | 20 (65.6) | 15 (49.2) |
| | <ul style="list-style-type: none">VPx-B100xx...VPx-B300xxVPAR-B3xxxxMPAR-B3xxxxRDB-Bxxxxxx | <ul style="list-style-type: none">MPx-B3xxx...MPx-B9xxxMPM-B115xx...MPM-B215xxHPK-xxxxxxx | 50 (164) | 30 (98.4) |

- (1) Corner-grounded and ungrounded input power can be used, but you must add an isolation transformer to the input power circuit to provide grounded-WYE power. Unbalanced, floating, or ungrounded systems can cause additional stress to the motor. For more information on these input power source types, see [Input Power Configurations for Kinetix 5700 Power Supplies](#) on [page 129](#).
- (2) Impedance grounded systems running in ground fault conditions, for prolonged periods of time, cause additional stress to the motor insulation and can cause premature motor failure.

Table 183 - Regenerative Bus Supply (400V AC input)

| AC Input Power Source Type ⁽¹⁾ | Motor/Actuator Cat. No. | | Drive-to-Motor Cable Length, max m (ft) | |
|---|---|--|--|----------------------------|
| | | | With DC-bus Conditioner | Without DC-bus Conditioner |
| WYE Grounded | <ul style="list-style-type: none">• LDAT-Sxxxxxx• LDC-Cxxxxxx | <ul style="list-style-type: none">• MPAS-B8xxxF-ALM• MPAS-B9xxxL-ALM | 10 (32.8) | 10 (32.8) |
| | <ul style="list-style-type: none">• VPx-B063xx, VPx-B075xx• MPx-B15xx, MPx-B2xx• VPAR-B1xxxx, VPAR-B2xxxx | <ul style="list-style-type: none">• MPAR-B1xxxx, MPAR-B2xxxx• MPAS-Bxxxx1, MPAS-Bxxxx2• MPAI-Bxxxxx | 50 (164) | 30 (98.4) |
| | <ul style="list-style-type: none">• VPx-B100xx . . . VPx-B300xx• VPAR-B3xxxx• MPAR-B3xxxx• RDB-Bxxxxxx | <ul style="list-style-type: none">• MPx-B3xxx . . . MPx-B9xxx• MPM-B115xx . . . MPM-B215xx• HPK-xxxxxx | 90 (295) | 90 (295) |
| WYE Impedance Grounded ⁽²⁾ | <ul style="list-style-type: none">• LDAT-Sxxxxxx• LDC-Cxxxxxx | <ul style="list-style-type: none">• MPAS-B8xxxF-ALM• MPAS-B9xxxL-ALM | 10 (32.8) | 10 (32.8) |
| | <ul style="list-style-type: none">• VPx-B063xx, VPx-B075xx• MPx-B15xx, MPx-B2xx• VPAR-B1xxxx, VPAR-B2xxxx | <ul style="list-style-type: none">• MPAR-B1xxxx, MPAR-B2xxxx• MPAS-Bxxxx1, MPAS-Bxxxx2• MPAI-Bxxxxx | 50 (164) | 30 (98.4) |
| | <ul style="list-style-type: none">• VPx-B100xx . . . VPx-B300xx• VPAR-B3xxxx• MPAR-B3xxxx• RDB-Bxxxxxx | <ul style="list-style-type: none">• MPx-B3xxx . . . MPx-B9xxx• MPM-B115xx . . . MPM-B215xx• HPK-xxxxxx | 90 (295) | 90 (295) |

- (1) Corner-grounded and ungrounded input power can be used, but you must add an isolation transformer to the input power circuit to provide grounded-WYE power. Unbalanced, floating, or ungrounded systems can cause additional stress to the motor. For more information on these input power source types, see [Input Power Configurations for Kinetix 5700 Power Supplies](#) on [page 129](#).
- (2) Impedance grounded systems running in ground fault conditions, for prolonged periods of time, cause additional stress to the motor insulation and can cause premature motor failure.

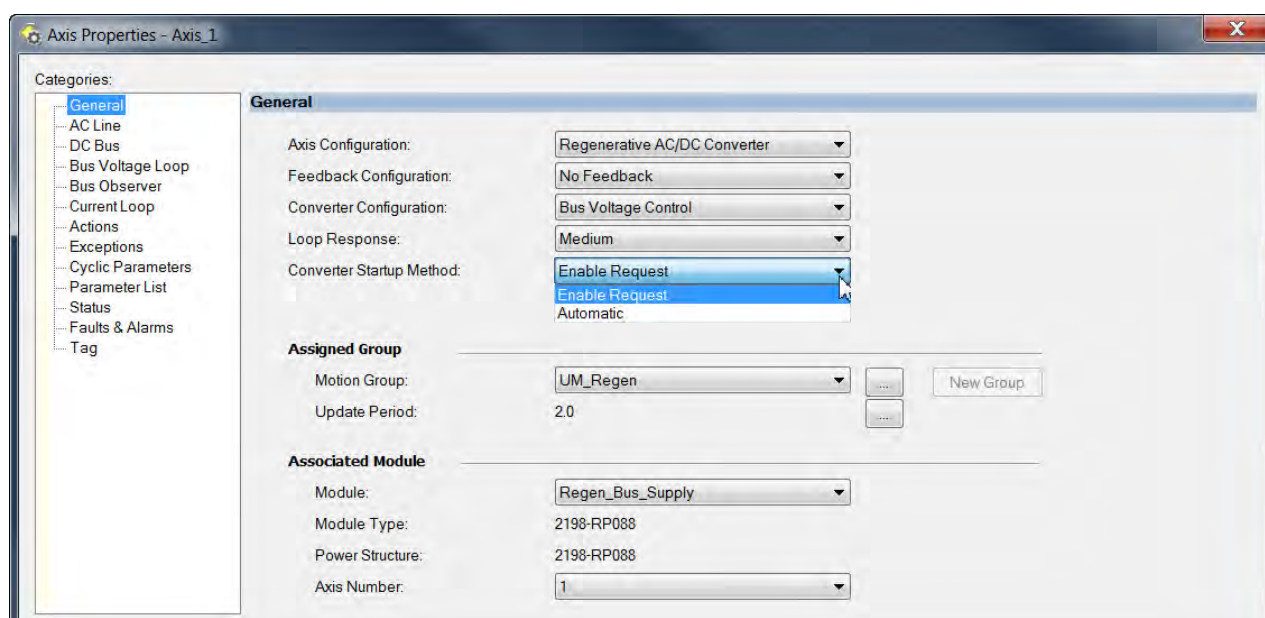
Regenerative Bus Supply Sequence Operation

In this appendix the sequencing of CIP™ axis states for Kinetix® 5700 regenerative bus supplies are explained. Timing diagrams illustrate when DC-bus voltage is applied and how the modules progress from PRECHARGE to RUNNING states. When in the RUNNING state, the regenerative bus supply is ready to provide full-line motoring and regenerative power to and from the Kinetix 5700 drive system.

| Topic | Page |
|---|------|
| Converter Startup Method - Enable Request | 406 |
| Converter Startup Method - Automatic | 409 |
| Sequence Operation of Discharging | 410 |

The Converter Startup Method is configured in the Studio 5000 Logix Designer® application. From the 2198-RPxxx module Axis Properties>General category, you can choose between Enable Request (default) and Automatic.

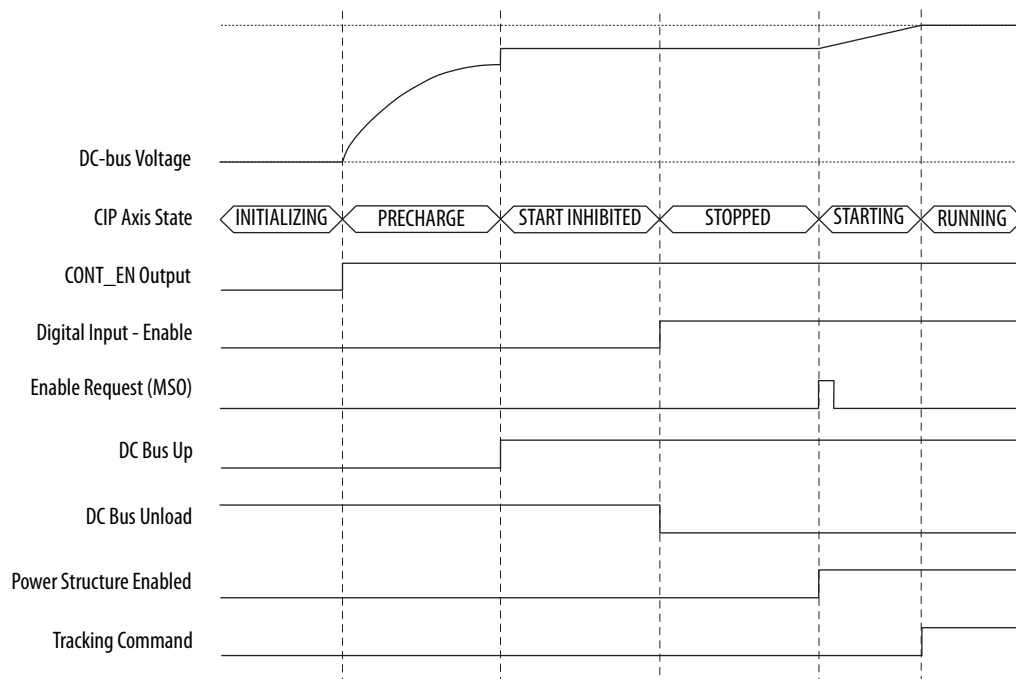
Figure 209 - Axis Properties>General Category



Converter Startup Method - Enable Request

When the Enable Request method is selected, a Motion Servo On (MSO) command is required for the regenerative bus supply to transition from the STOPPED state to the RUNNING state.

Figure 210 - Sequence Operation of Precharging - Enable Request Method



Initialization

The 2198-RPxxx regenerative bus supply uses the AB:MotionDevice_Diagnostics:S:0 tag data type.

Initialization consists of these four events:

- A connection is established between the controller and regenerative bus supply, through a forward open request from the controller
- The regenerative bus supply receives the configuration from the controller
- The Group Sync Service synchronizes with the regenerative bus supply
- The configuration and power are verified for the axes and associated modules in the Motion Group.

Following initialization, the regenerative bus supply transitions to the PRECHARGE state.

Precharge

When initialization is complete, the contactor enable relay closes, causing the M1 contactor to close, and precharge begins through the DC-bus resistor (see [Regenerative Bus Supply Configuration](#) on [page 348](#) for an example interconnect diagram).

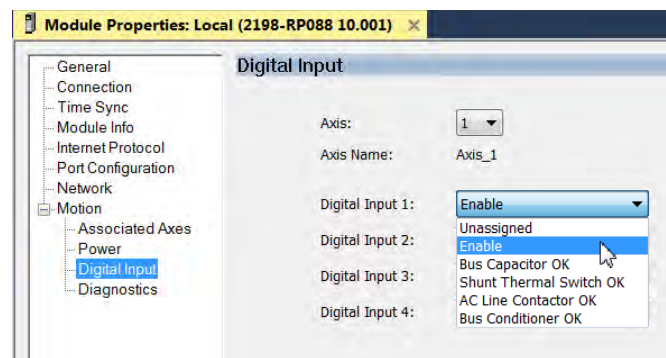
There is approximately 2.4 seconds of DC-bus precharge time plus 1.0 second relay-closing time for approximately 3.4 seconds total precharge time. This is consistent across all four 2198-RPxxx units.

The DC-bus resistor is not field replaceable nor can we measure the resistance externally. Once in the PRECHARGE state, the DC Bus Up status goes high and the regenerative bus supply transitions to the START INHIBITED state.

Start Inhibited

The digital inputs associated with the regenerative bus supply can be configured to cause the Converter Axis CIP Drive to go to a START INHIBITED state.

Figure 211 - Configure Digital Inputs



Enable is the default setting for Digital Input 1. When the Enable input is wired in the system it provides the ability to physically control the transition into the RUNNING state.

External 24V DC to IN1 on the IOD connector through the Enable permissive circuit (possibly a red top mushroom E-stop) with 24V DC common to COM on the Digital Inputs (IOD) connector is required to remove the START INHIBITED condition.

See [Contactor Wiring for Regenerative Bus Supply](#) on [page 358](#) for an example of how the digital input option is used.

If no Enable digital input is assigned or the correct inputs are seen, the regenerative bus supply moves to the STOPPED state.

Stopped

With DC-bus Up high and DC-bus Unload low, the regenerative bus supply is in a STOPPED state.

When configured for Enable Request, a Motion Servo On (MSO) command is required for the regenerative bus supply to transition from the STOPPED state to the RUNNING state.

- In the RUNNING state, the regenerative bus supply is ready to provide full-line motoring and regenerative power to and from the Kinetix 5700 drive system.
- While in the STOPPED state, the regenerative bus supply provides full-line motoring power, however, regeneration will not occur.

After issuing a Motion Servo On command, the regenerative bus supply transitions to the STARTING state.

Starting

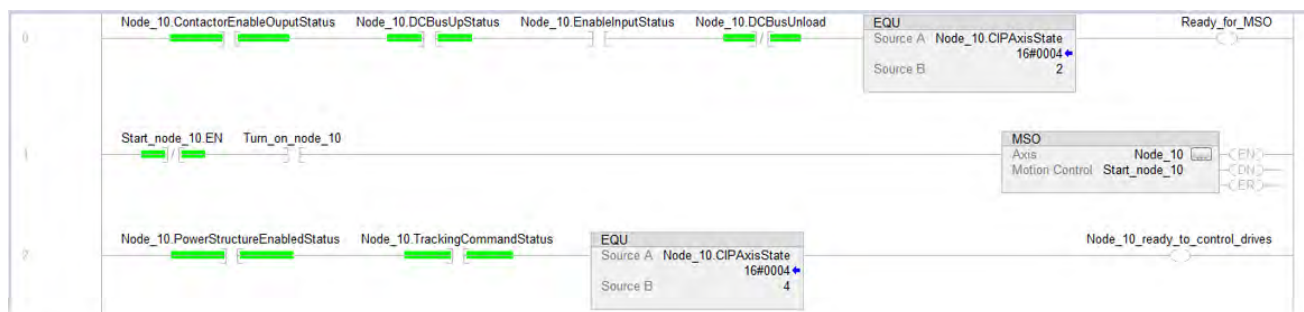
When the regenerative bus supply is in the STARTING state, the PowerStructureEnabledStatus tag equals 1, the IGBTs turn on, and the DC-bus increases by 5%. The regenerative bus supply then transitions to the RUNNING state.

Running

When the regenerative bus supply is in the RUNNING state, the TrackingCommandStatus tag equals 1 indicating that the regenerative bus supply is capable of both motoring and regenerating requirements.

The following code can be used to indicate that the regenerative bus supply is running and ready for both motoring and regeneration.

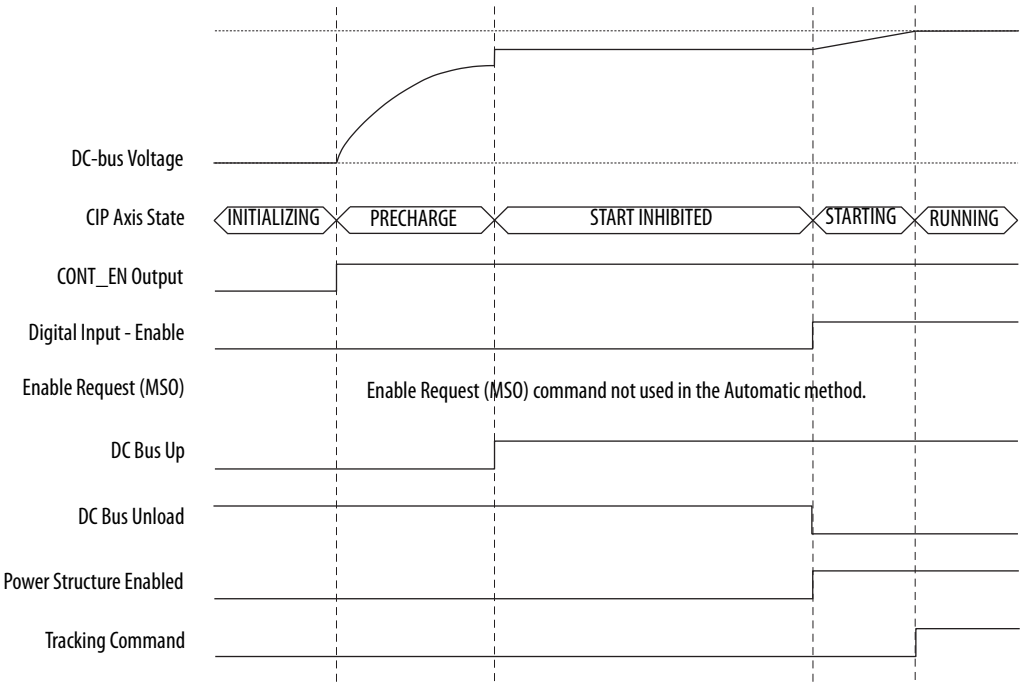
Figure 212 - Ready for Motoring and Regeneration



Converter Startup Method - Automatic

With the Automatic method, everything in the Enable Request sequence applies, except there is no STOPPED state or any need for the Motion Servo On (MSO) command. The regenerative bus supply automatically transitions to the RUNNING state.

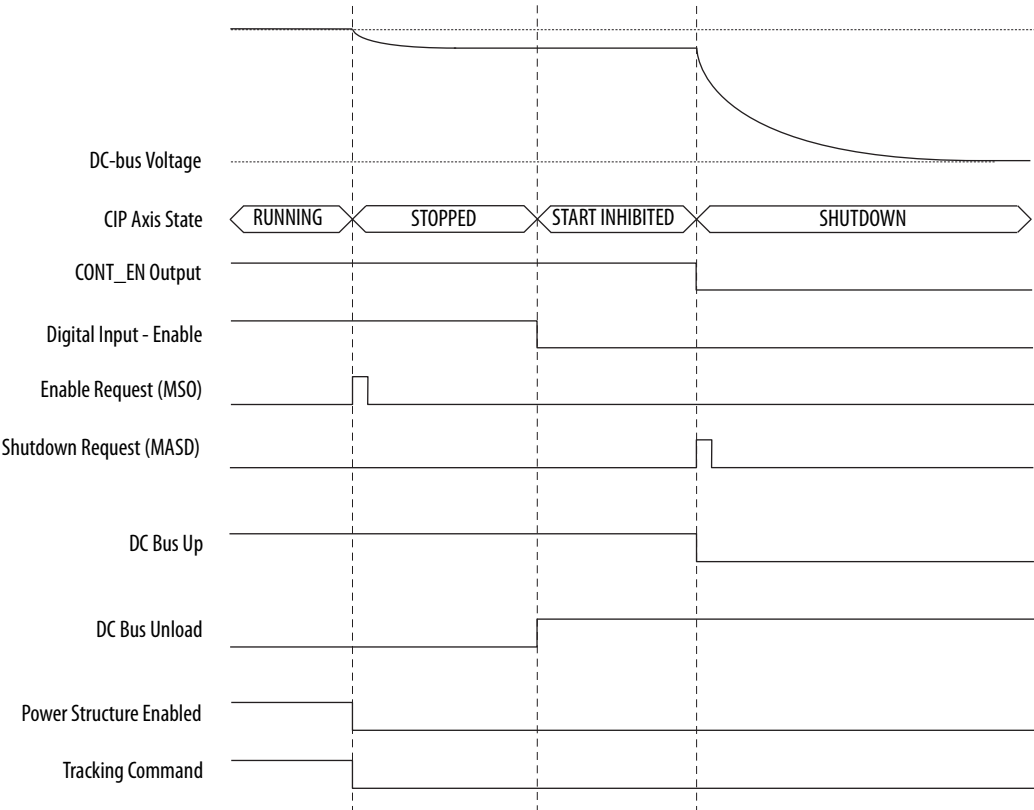
Figure 213 - Sequence Operation of Precharging - Automatic Method



Sequence Operation of Discharging

In the discharging sequence, the regenerative bus supply begins in the RUNNING state and transitions to the STOPPED state following a Motion Servo Off (MSF) command. If a Motion Axis Shutdown (MASD) command is executed, the regenerative bus supply transitions to the SHUTDOWN state, and a Motion Axis Shutdown Reset (MASR) command must be executed to transition out of the SHUTDOWN state.

Figure 214 - Sequence Operation of Discharging - Enable Request Method



Motor Control Feature Support

This appendix provides feature descriptions for the 400V-class induction motors and permanent-magnet motors that are supported by Kinetix® 5700 servo drives.

| Topic | Page |
|---|------|
| Frequency Control Methods | 412 |
| Current Limiting for Frequency Control | 416 |
| Stability Control for Frequency Control | 419 |
| Skip Speeds | 421 |
| Flux Up | 423 |
| Current Regulator Loop Settings | 426 |
| Motor Category | 426 |
| Selection of Motor Thermal Models | 432 |
| Speed Limited Adjustable Torque (SLAT) | 434 |
| Motor Overload Retention | 445 |
| Phase Loss Detection | 446 |
| Velocity Droop | 449 |
| Commutation Test | 451 |
| Adaptive Tuning | 451 |
| Field Weakening Mode | 452 |

Frequency Control Methods

The Kinetix 5700 servo drives support three open-loop frequency control methods. These are the choices:

- **Basic Volts/Hertz** - This method is used in single asynchronous-motor applications
- **Basic Volts/Hertz - Fan Pump** - This method is similar to Basic Volts/Hertz, but is specifically tailored for fan/pump applications
- **Sensorless Vector with Slip Compensation** - This method is used for most constant torque applications. Provides excellent starting, acceleration, and running torque

To configure your induction motor in the Logix Designer application, refer to [Configure Induction-motor Frequency-control Axis Properties](#) on [page 232](#).

Open-loop frequency control is suitable in applications such as conveyors, pumps, and fans. Features include the following:

- Start Boost and Run Boost
- Electronic motor thermal-overload protection per Class 10 requirements
- Two skip frequencies, in which the drive does not operate
- All three-phase induction motors, suitable for variable speed drive (VFD) operation, are supported

Table 184 - Motor Specifications

| Attribute | Value |
|-------------------------|------------------------------|
| Output frequency, max | 590 Hz |
| Pole pairs, max | 50 |
| Motor cable length, max | 90 m (295 ft) ⁽¹⁾ |

(1) Applies to all Kinetix 5700 drives and compatible motors/actuators with Hiperface and Hiperface DSL high-resolution absolute feedback. For compatible motors/actuators with incremental feedback, 30 m (98 ft) is the maximum cable length.

Basic Volts/Hertz

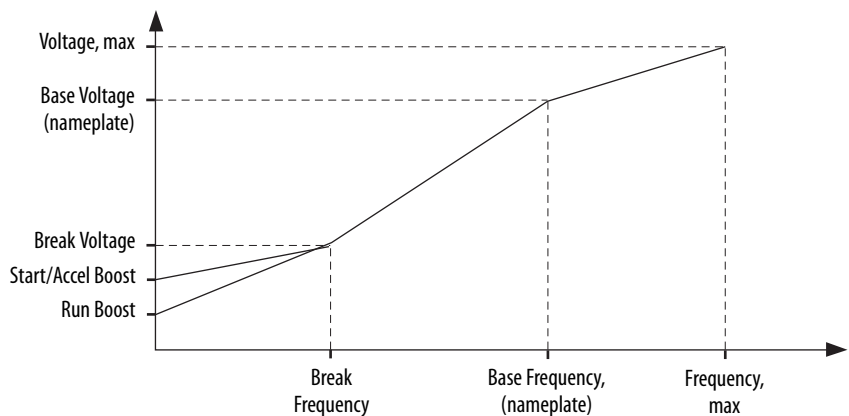
Volts/hertz operation creates a fixed relationship between output voltage and output frequency. Voltage is applied to the motor, which is based on the operating frequency command at a fixed volts/hertz ratio. The ratio is calculated from the motor nameplate data and entered into the Logix Designer application>Axis Properties>Frequency Control category.

The Basic Volts/Hertz method provides various patterns. The default configuration is a straight line from zero to rated voltage and frequency. As seen in [Figure 215](#), you can change the volts/hertz ratio to provide increased torque performance when required by programming five distinct points on the curve.

Table 185 - Basic Volts/Hertz Definitions

| Curve Feature | Definition |
|-----------------------------------|---|
| Start boost | Used to create additional torque for breakaway from zero speed and acceleration of heavy loads at lower speeds. |
| Run boost | Used to create additional running torque at low speeds. The value is typically less than the required acceleration torque. The drive lowers the boost voltage to this level when running at low speeds (not accelerating). This reduces excess motor heating that could result if the higher start/accel boost level were used. |
| Break voltage/frequency | Used to increase the slope of the lower portion of the Volts/Hertz curve, providing additional torque. |
| Motor nameplate voltage/frequency | Sets the upper portion of the curve to match the motor design. Marks the beginning of the constant power region. |
| Maximum voltage/frequency | Slopes the portion of the curve that is used above base speed. |

Figure 215 - Basic Volts/Hertz Method



Basic Volts/Hertz for Fan/Pump Applications

The Basic Volts/Hertz Fan/Pump (fan/pump) method is based on the Basic Volts/Hertz (V/Hz) method, but is specifically tailored for fan/pump applications.

Figure 216 - Output Voltage Equation

$$V_x = \left(\frac{f_x}{f_n} \right)^2 (V_n - V_{boost}) + V_{boost}$$

Where:

V_x = Output voltage

f_x = Output frequency

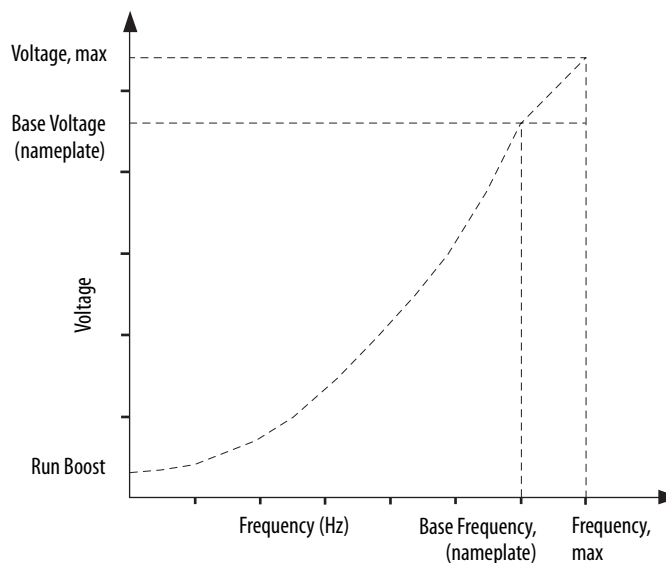
V_n = Rated voltage

f_n = Rated frequency

V_{boost} = Run boost voltage

For maximum system efficiency, fan/pump loads use variable frequency drives that are equipped with a specific V/Hz curve where voltage is proportional to square of the frequency.

Figure 217 - Basic Volts/Hertz Fan/Pump Method

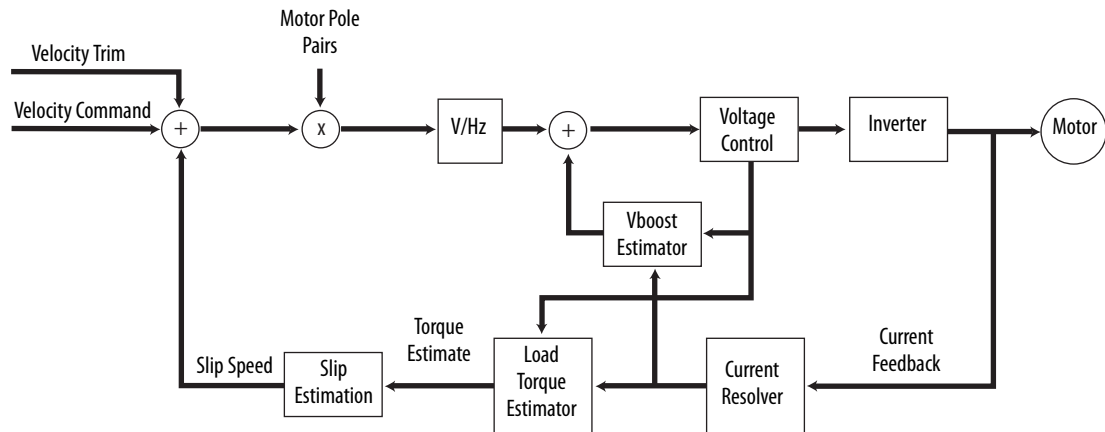


TIP The Fan/Pump control method supports the run-boost attribute, but does not support break-voltage, break-frequency, or start-boost.

Sensorless Vector

The Sensorless Vector method uses a volts/hertz core enhanced by a current resolver, slip estimator, and a voltage-boost compensator based on the operating conditions of the motor.

Figure 218 - Sensorless Vector Method

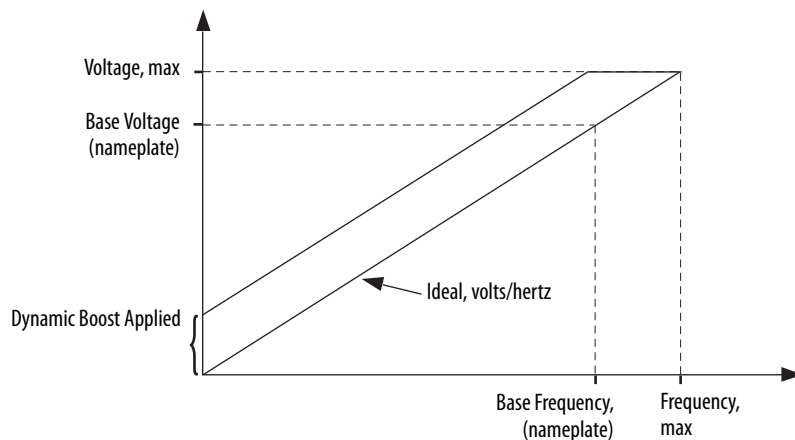


The algorithms operate on the knowledge of the relationship between the rated slip and torque of the motor. The drive uses applied voltages and measured currents to estimate operating slip-frequency. You can enter values to identify the motor resistance value or you can run a motor test to identify the motor resistance value (see [Motor Tests and Autotune Procedure](#) on [page 428](#)). Motor nameplate data and test results are ways to accurately estimate the required boost voltage.

The sensorless vector method offers better torque production and speed regulation over a wider speed range than basic volts/hertz.

Dynamic boost is applied internally to compensate voltage drop and improve starting torque.

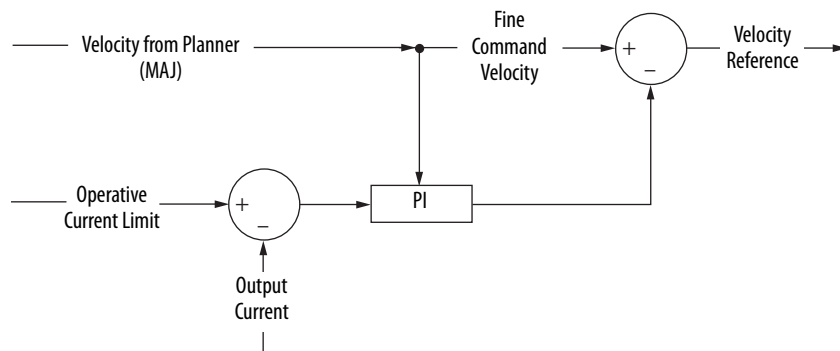
Figure 219 - Approximate Load Curve



Current Limiting for Frequency Control

The current limiting module prevents the OutputCurrent value from exceeding the OperativeCurrentLimit value when the drive is configured in Frequency Control mode.

Figure 220 - Current Limiting Module



In Frequency Control mode, OperativeCurrentLimit is the minimum value of the motor-thermal current limit, inverter-thermal current limit, motor-peak current limit, drive-peak current limit, and the CurrentVectorLimit value.

The Effects of Current Limiting

Indirect current limiting is available for induction motors configured for frequency control. You can use this feature to help prevent overcurrent faults due to aggressive acceleration/deceleration profiles or impact loads. The Current Limiting attribute uses a PI regulator to control the OutputCurrent by adjusting the velocity reference.

IMPORTANT When configured for Frequency Control (induction motors only), select the Decel and disable stopping action only when the Current Limiting feature is enabled.

Figure 221 - Effects of Current Limiting on an Aggressive Acceleration

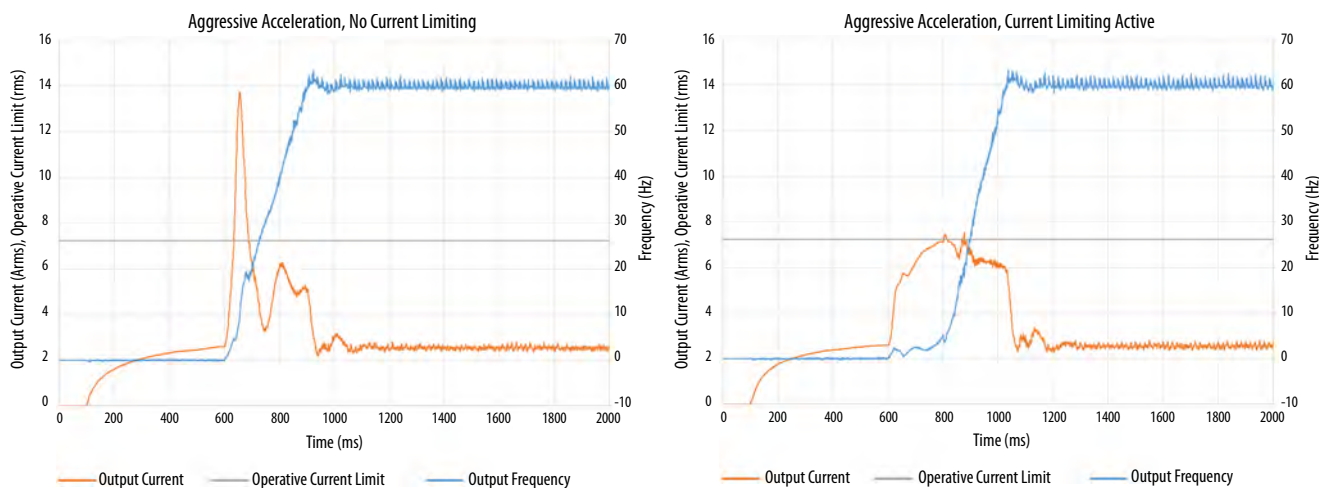
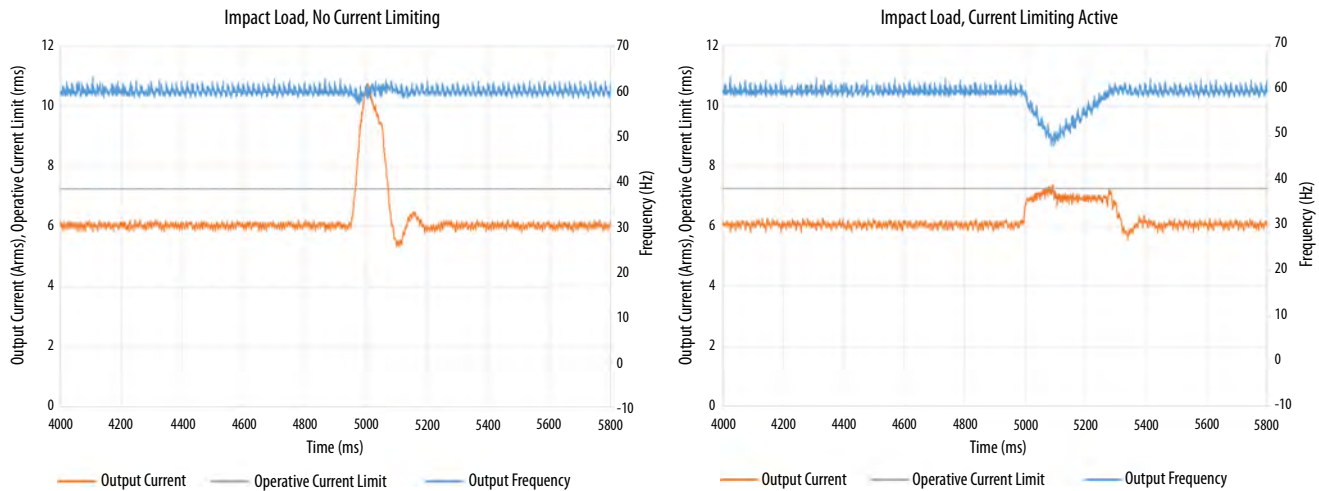


Figure 222 - Effects of Current Limiting on an Impact Load

Current limiting for frequency control is not enabled by default. You can enable via messaging by using the following device-specific attributes.

TIP We recommend you leave the Kp, Ki, Kd gains at the default values.

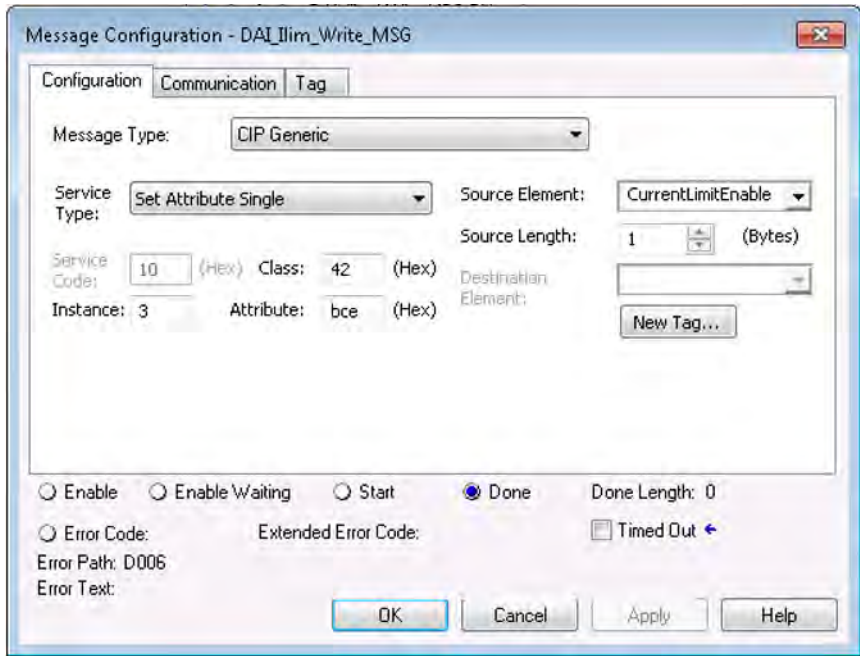
Table 186 - Enable Current Limiting via Messaging

| Attribute Offset | Type | Attribute Name | Conditional Implementation | Description |
|------------------|------|-------------------------|--|---|
| 3022 | SINT | Current Limiting Enable | Frequency Control Induction Motor only | When enabled, limits the rate of change to the velocity reference during high-current situations for improved current limiting. This feature is only active when executing an MDS command and when configured for Frequency Control. 0 = Current Limiting is disabled 1 = Current Limiting is enabled |
| 3023 | REAL | Current Limiting Kd | | Derivative gain for the current limiting function. Only functional when configured for Frequency Control and when executing an MDS command. Units of seconds. |
| 3024 | REAL | Current Limiting Ki | | Integral gain for the current limiting function. Only functional when configured for Frequency Control and when executing an MDS command. Units of feedback counts / (Amp, inst* Seconds). |
| 3025 | REAL | Current Limiting Kp | | Proportional gain for the current limiting function. Only functional when configured for Frequency Control and when executing an MDS command. Units of feedback counts / Amp, inst. |

IMPORTANT For induction motors greater than 5 Hp, it is recommended that the Stability Control feature also be enabled when Current Limiting is enabled.

Enable the Current Limiting Feature

In this example, a Message Configuration (MSG) instruction is configured to set the CurrentLimitingEnable attribute for axis 3 of a dual-axis inverter. The Instance field is used to direct the message to the proper axis. For single-axis inverters the value of 1 is used for Instance.



Set the CurrentVectorLimit Attribute Value

For current limiting, the CurrentVectorLimit attribute is used to help determine the OperativeCurrentLimit of the drive. Set the CurrentVectorLimit value to artificially lower OperativeCurrentLimit below the drive or motor peak current limits.

1. Select the Parameter List category and scroll to CurrentVectorLimit.

| | | |
|--------------------|-----------|------------------------------|
| CoastingTimeLimit | 0.0 s | |
| ConversionConstant | 1000000.0 | Motion Counts/Position Units |
| CurrentVectorLimit | 100.0 | % Motor Rated |
| FluxUpControl | No Delay | |
| FluxUpTime | 0.0 s | |

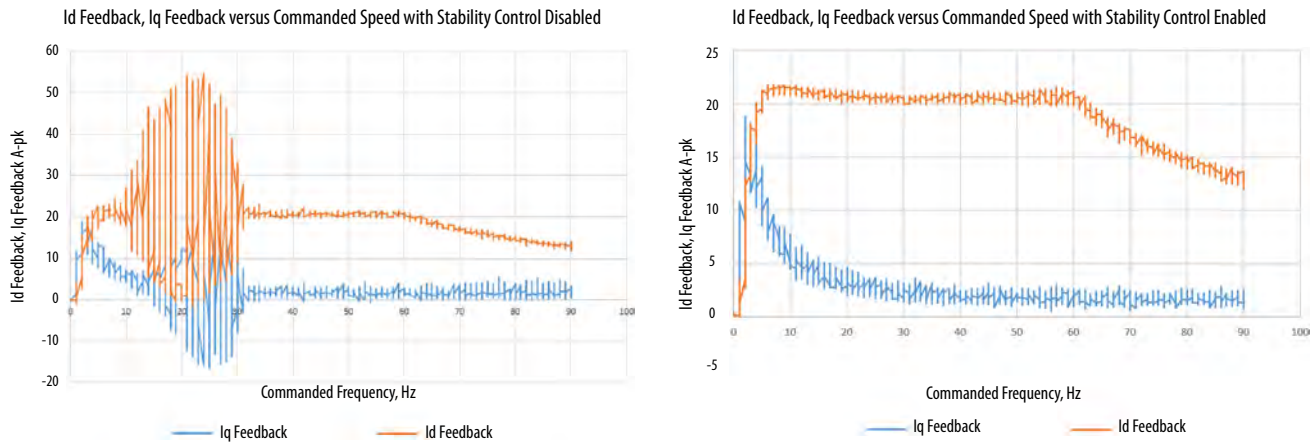
2. Set the CurrentVectorLimit value appropriate for your application.

IMPORTANT The CurrentVectorLimit attribute appears in the Parameter List of the Logix Designer application, version 29.00 and later. If you are using a previous version, the CurrentVectorLimit attribute must be set via a Message Configuration (MSG) instruction.

Stability Control for Frequency Control

Stability control is available for induction motors configured for frequency control. This feature can be used to help remove resonances that are sometimes seen on larger motors. The stability control feature adjusts the OutputFrequency and OutputVoltage commands to stabilize the OutputCurrent.

Figure 223 - Effects of Stability Control



Stability control for frequency control is not enabled by default. You can enable via messaging by using the following device-specific attributes.

TIP We recommend you leave the angle, voltage gains, and filter bandwidth at the default values.

Table 187 - Enable Current Limiting via Messaging

| Attribute Offset | Type | Attribute Name | Conditional Implementation | Description |
|------------------|------|----------------------------|--|---|
| 3026 | SINT | Stability Control Enable | Frequency Control Induction Motor only | Enables stability control when configured for frequency control. 0 = Stability Control is disabled 1 = Stability Control is enabled |
| 3027 | REAL | Stability Filter Bandwidth | | Sets the bandwidth of the low-pass filter applied to the current feedback signal. This bandwidth is common to both the angle and voltage stability control algorithms. Units of radians/second. |
| 3028 | REAL | Stability Voltage Gain | | The gain of the voltage stability control function. Only active when configured for frequency control. Units of Volt (inst,p-n)/Amp (inst). |
| 3029 | REAL | Stability Angle Gain | | The gain of the electrical angle stability control function. Only active when configured for frequency control. Units of radians/Amp (inst). |

IMPORTANT Because the stability control feature works by manipulating the OutputVoltage and OutputFrequency signals, these signals may appear 'noisy' when the feature is enabled.

Enable the Stability Control Feature

In this example, a Message Configuration (MSG) instruction is configured to enable the StabilityControl attribute for axis 3 of a dual-axis inverter. The Instance field is used to direct the message to the proper axis. For single-axis inverters the value of 1 is used for Instance.

The screenshot shows the 'Message Configuration - DAI_Stab_Write_MSG' dialog box. It has three tabs: 'Configuration', 'Communication', and 'Tag'. The 'Configuration' tab is active. The 'Message Type' is set to 'CIP Generic'. The 'Service Type' is 'Set Attribute Single'. The 'Source Element' is 'StabilityControlEnab'. The 'Source Length' is '1 (Bytes)'. The 'Service Code' is '10 (Hex)', 'Class' is '42 (Hex)', 'Instance' is '3', and 'Attribute' is 'bd2 (Hex)'. The 'Destination Element' is empty, with a 'New Tag...' button below it. At the bottom, there are radio buttons for 'Enable', 'Enable Waiting', 'Start', and 'Done' (which is selected). There are also fields for 'Done Length: 0', 'Error Code', 'Extended Error Code', 'Error Path: D006', and 'Error Text'. A 'Timed Out' checkbox is also present. The bottom right has 'OK', 'Cancel', 'Apply', and 'Help' buttons.

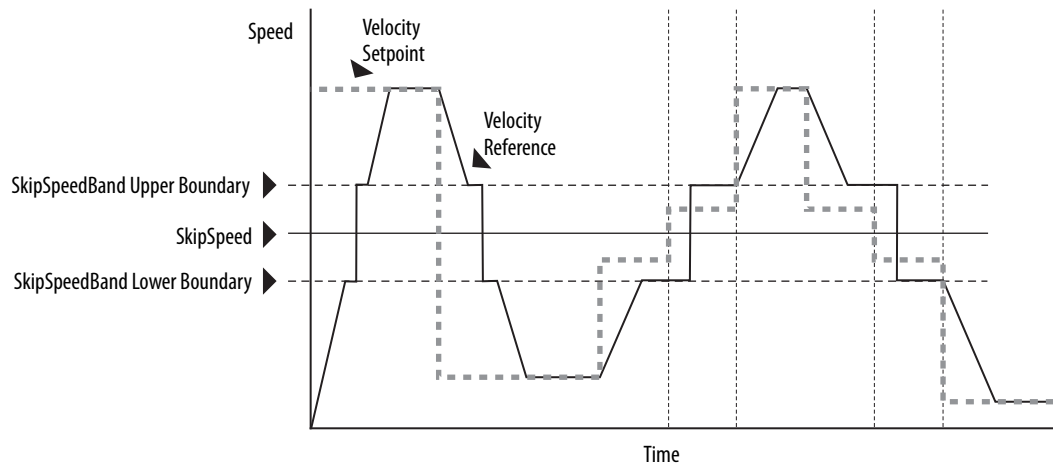
| Field | Value |
|---------------------|----------------------|
| Message Type | CIP Generic |
| Service Type | Set Attribute Single |
| Source Element | StabilityControlEnab |
| Source Length | 1 (Bytes) |
| Service Code | 10 (Hex) |
| Class | 42 (Hex) |
| Instance | 3 |
| Attribute | bd2 (Hex) |
| Destination Element | |
| Done Length | 0 |
| Error Code | |
| Extended Error Code | |
| Error Path | D006 |
| Error Text | |

Skip Speeds

Some machines have a resonant operating frequency (vibration speed) that is undesirable or could cause equipment damage. To guard against continuous operation at one or more resonant points, you can configure the skip-speed attributes in the Logix Designer application>Axis Properties>Parameter List category.

The value that is programmed into the SkipSpeed1 or SkipSpeed2 attribute sets the central speed of a skip-speed band within which the drive does not operate. The width of the band is determined by the SkipSpeedBand attribute. The range is split, half above and half below the SkipSpeed x attribute. Any command set-point within this band is adjusted by the skip-speed feature to fall at either the upper or lower skip-speed band boundary value. The skip-speed feature contains hysteresis (25% of the SkipSpeedBand value) to prevent frequent switching of VelocityReference.

Figure 224 - Single Skip Speed Example



A SkipSpeedBand value of 0 disables the skip-speed feature.

IMPORTANT When a single SkipSpeed value is desired, the SkipSpeed1 and SkipSpeed2 settings must be the same.

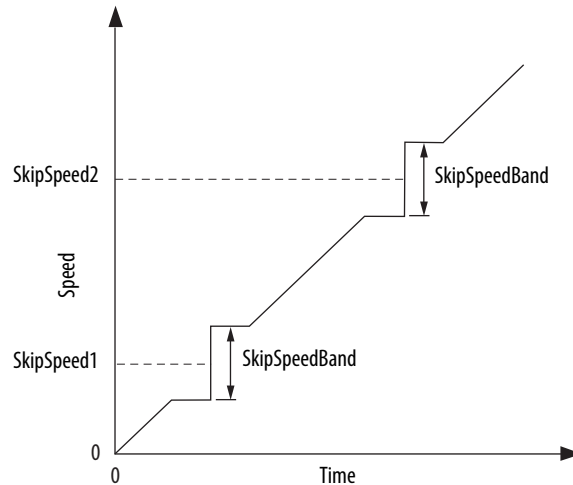
IMPORTANT Acceleration and deceleration are affected by the skip-speed feature. Too large of a SkipSpeedBand value can result in an overcurrent drive fault.

IMPORTANT The MaximumFrequency attribute is always enforced. Skip-speed band boundary values beyond the MaximumFrequency value do not apply.

Multiple Skip Speeds

The Kinetix 5700 drives feature two independent skip-speed attributes (SkipSpeed1 and SkipSpeed2) that use the same SkipSpeedBand.

Figure 225 - Multiple Skip Speed Example

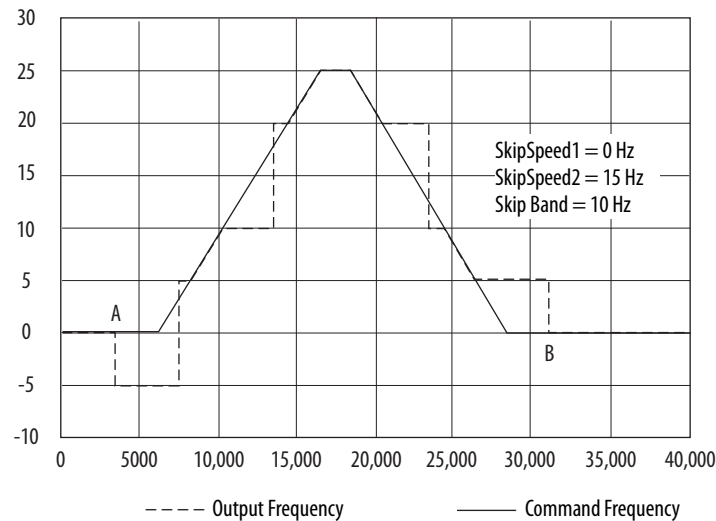


When skip-speed band boundaries of SkipSpeed1 and SkipSpeed2 overlap, the skip-speed hysteresis is calculated using the effective skip band.

In [Figure 226](#), SkipSpeed1 is set to 0 and SkipSpeed2 is set to 15 hz. The skip band is 10 Hz wide.

At point A the axis is enabled, and the motor begins to rotate at -5 Hz even though the command is 0 Hz. As the command reaches hysteresis point the output frequency begins to follow the command. During deceleration, when the command decreases to 0 Hz, the output frequency continues at 5 Hz until the axis is disabled (point B), or the command is changed outside of the skip band.

Figure 226 - Zero-speed Skip Frequency

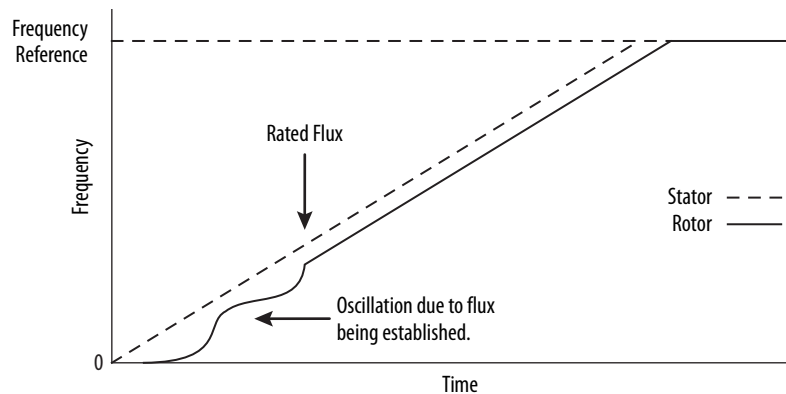


Flux Up

AC induction motors require that flux builds in the motor stator before controlled torque can develop. To build flux, voltage is applied. There are two methods to flux the motor and three configurable FluxUpControl settings.

With the No Delay setting (normal start), flux is established when the output voltage and frequency are applied to the motor. While flux is building, the unpredictable nature of the developed torque can cause the rotor to oscillate even though acceleration of the load can occur. In the motor, the acceleration profile does not follow the commanded acceleration profile due to the lack of developed torque.

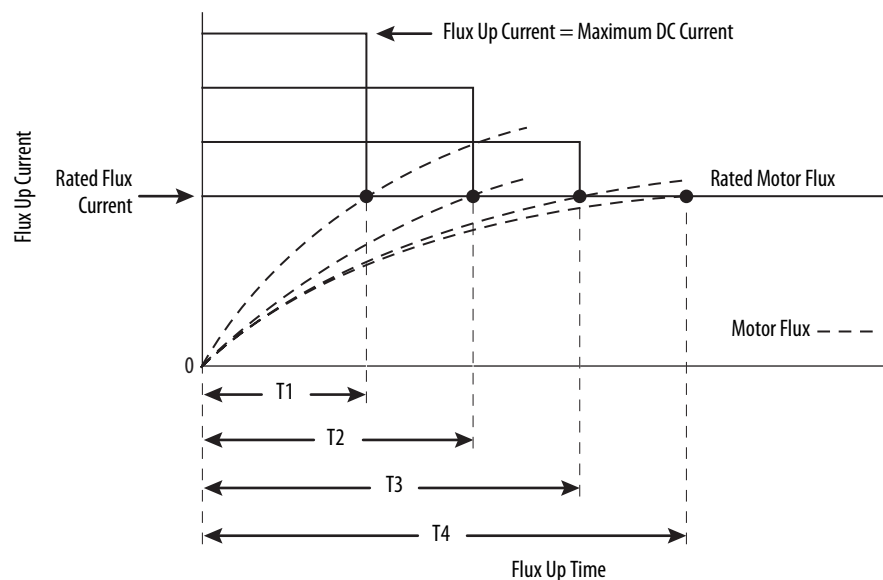
Figure 227 - Acceleration Profile during Normal Start - No Flux Up



With the Automatic setting (default) DC current is applied to the motor so that flux builds before rotation. The flux-up time period is based on the level of flux-up current and the rotor time constant of the motor. The flux-up current is not adjustable.

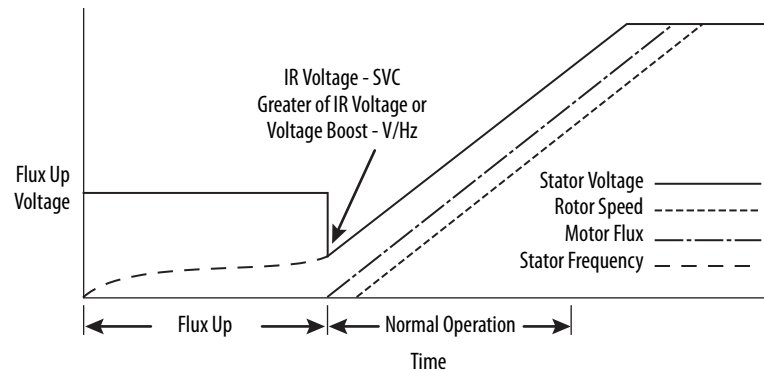
In the Manual setting, DC current is applied to the motor so that flux builds before rotation. The flux-up time period is determined by the FluxUpTime attribute. The flux-up current is not adjustable.

Figure 228 - Flux Up Current versus Flux Up Time



Once rated flux is reached in the motor, normal operation can begin and the desired acceleration profile achieved.

Figure 229 - Rated Flux Reached



Flux Up Attributes

| ID | Access | Attribute | Conditional Implementation |
|-----|--------|-----------------------------|--|
| 558 | Set | Flux Up Control | Ind Motor only 0 = No Delay 1 = Manual Delay 2 = Automatic Delay |
| 559 | Set | Flux Up Time ⁽¹⁾ | Ind Motor only Units: Seconds Default: 0.0000 Min/Max: 0.0000 / 1000.00 |

(1) This is the time designated for the Manual Delay setting. This attribute is not supported by the Automatic delay method. The flux-up feature is disabled if FluxUpControl is set to Manual Delay and FluxUpTime is set to 0.

FluxUpControl Attribute

When the motion axis is enabled, DC current is applied to an induction motor to build stator flux before transitioning to the Running state. This attribute controls how an induction motor is to be fluxed in the Starting state prior to transitioning to the Running state.

Table 188 - FluxUp Control Delay Methods

| Delay Method | Description |
|-----------------|--|
| No delay | The axis transitions immediately to the Running state while the motor flux is building. |
| Manual delay | The axis remains in the Starting state while the motor stator flux is building according to the Flux Up Time attribute. |
| Automatic delay | The drive determines the amount of delay time to fully flux the motor based on the motor configuration attribute data or measurements. |

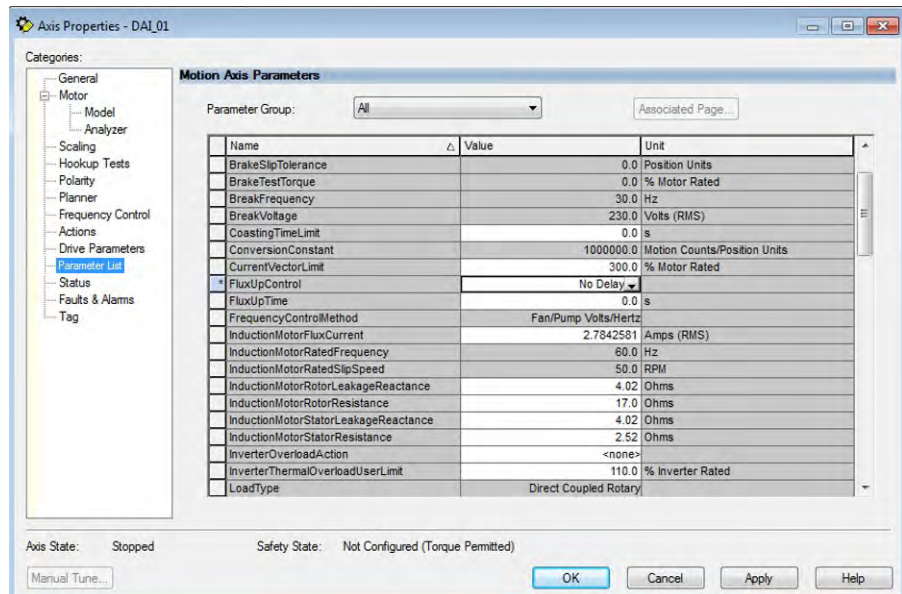
FluxUpTime Attribute

When FluxUpControl is configured for Manual Delay, this attribute sets the length of delay time to fully flux the motor before transitioning to the Running state.

Configure the Flux Up Attributes

Follow these steps to configure the flux-up attributes.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the Parameter List category and scroll to FluxUpControl.



3. From the FluxUpControl pull-down menu, choose the proper delay value appropriate for your application.

| | |
|---------------------------|-----------------|
| CurrentVectorLimit | 300.0 |
| FluxUpControl | No Delay |
| FluxUpTime | No Delay |
| FrequencyControlMethod | Manual Delay |
| InductionMotorFluxCurrent | Automatic Delay |

4. If you chose Manual Delay in [step 3](#), enter a value in the FluxUpTime attribute appropriate for your application.

If you chose No Delay or Automatic Delay in [step 3](#), the FluxUpTime attribute does not apply.

Current Regulator Loop Settings

Current loop bandwidth is set differently based on the selected motor type.

Table 189 - Current Regulator Loop Settings

| Motor Type | Default Torque/Current Loop Bandwidth Hz |
|----------------------------------|---|
| Rotary permanent magnet | 1000 |
| Rotary interior permanent magnet | |
| Linear permanent magnet | |
| Rotary induction | 400 |

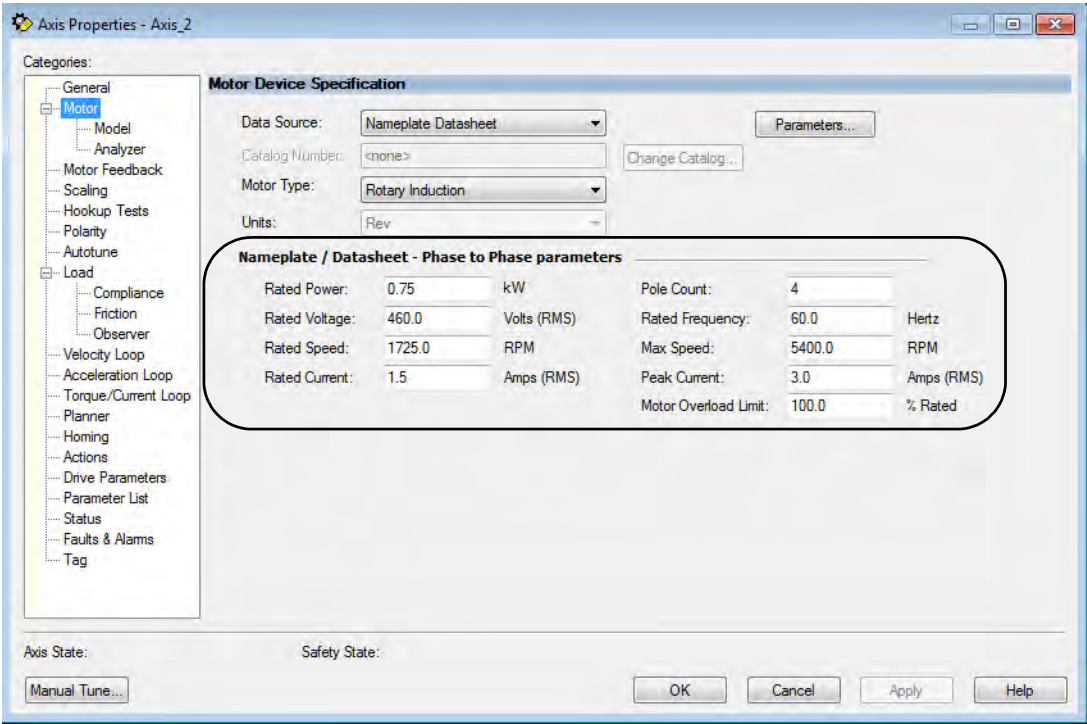
IMPORTANT The Logix Designer application does not perform calculations when the Torque/Current Loop Bandwidth attribute is updated. This bandwidth affects many other gains and limits. Changing, (lowering) the torque loop bandwidth without updating all the dependent attributes can result in drive/motor instability.

Motor Category

From the Motor category you can enter motor nameplate or datasheet values (phase-to-phase parameters) for rotary induction motors.

In this example, the Motor category>Nameplate / Datasheet parameters, were taken from a typical motor performance datasheet. Max Speed and Peak Current values are typically application dependent.

Figure 230 - Motor Nameplate / Datasheet Example



See [Figure 231](#) for motor manufacturer performance data sheet example.

Figure 231 - Motor Manufacturer Performance Data Sheet

CERTIFICATION DATA SHEET

TYPICAL MOTOR PERFORMANCE DATA

| | | | | | | | | | |
|---|-----|--------------------|----------|--------------------|------------|---------------|------------------|-----------------|-------------------|
| HP | kW | SYNC. RPM | F.L. RPM | FRAME | ENCLOSURE | KVA CODE | | DESIGN | |
| 1 | .75 | 1800 | 1725 | 56C | TENV | P | | A | |
| PH | Hz | VOLTS | FL AMPS | START TYPE | DUTY | INSL | S.F. | AMB°C | ELEVATION |
| 3 | 60 | 460 | 1.5 | INVERTER ONLY | CONTINUOUS | F3 | 1.0 | 40 | 3300 |
| FULL LOAD EFF: 84 | | 3/4 LOAD EFF: 82.5 | | 1/2 LOAD EFF: 78.5 | | GTD. EFF | ELEC. TYPE | | NO LOAD AMPS |
| FULL LOAD PF: 75 | | 3/4 LOAD PF: 65.5 | | 1/2 LOAD PF: 51 | | 81.5 | SQ CAGE INV DUTY | | 1 |
| F.L. TORQUE | | LOCKED ROTOR AMPS | | L.R. TORQUE | | B.D. TORQUE | | F.L. RISE°C | |
| 3 LB-FT | | 30 / 15 | | 10.8 LB-FT 360% | | 15 LB-FT 500% | | 65 | |
| SOUND PRESSURE @ 3 FT. | | SOUND POWER | | ROTOR WK ^2 | | MAX. WK ^2 | | SAFE STALL TIME | APPROX. MOTOR WGT |
| 62 dBA | | 72 dBA | | 0.11 LB-FT ^2 | | 0 LB-FT ^2 | | 0 SEC. | 42 LBS. |
| EQUIVALENT WYE CKT. PARAMETERS (OHMS PER PHASE) | | | | | | | | | |
| R1 | | R2 | | X1 | | X2 | | XM | |
| 8.378 | | 5.6232 | | 10.7068 | | 9.9116 | | 278.036 | |
| RM | | ZREF | | XR | | TD | | TD0 | |
| 11132.8 | | 284 | | 1.7 | | 0.0071 | | 0.136 | |

Motor>Model Category

From the Motor>Model category you can enter additional motor nameplate or datasheet values (phase-to-neutral parameters) for induction motors.

The Motor>Model parameters are used in closed-loop induction-motor control mode, sensorless vector control mode, and when FluxUp is enabled, and are estimated automatically by the Logix Designer application based on the motor nameplate data. You can also enter these parameter values directly from the motor nameplate/datasheet or indirectly by running a Motor>Analyzer test.

Figure 232 - Phase-to-Neutral Parameters

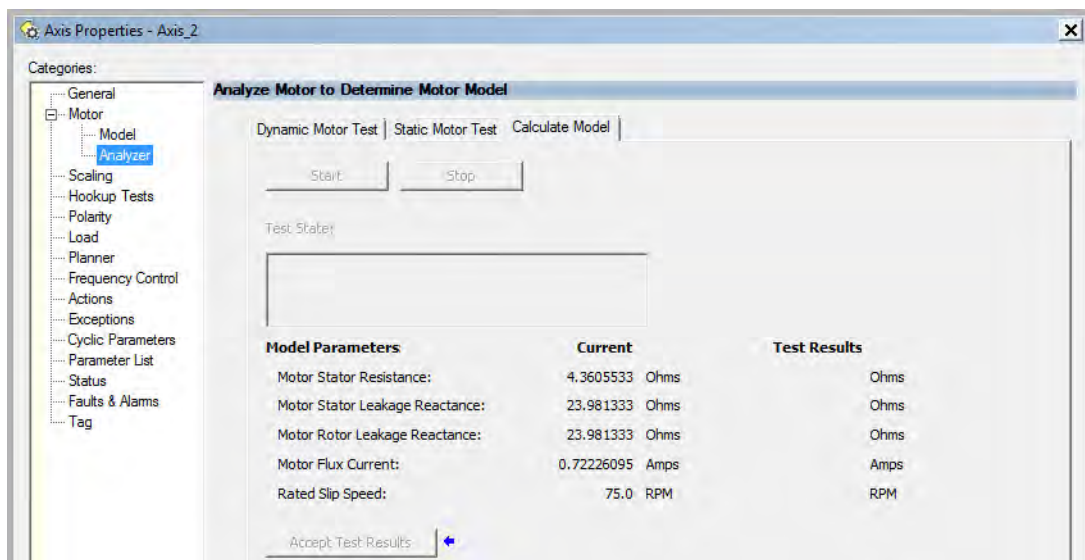
IMPORTANT If you do not know the Stator Leakage, Rotor Leakage, Stator Resistance, Rated Flux Current, and system inertia, you can run the static motor test and Autotune procedure to determine the parameter values.

Motor>Analyzer Category

From the Motor>Analyzer category you can perform three types of tests to identify motor parameters.

In this example, the Calculate Model test was run. If the Motor>Analyzer test executes successfully, and you accept the test values, they populate the Model Parameter attributes.

Figure 233 - Motor Analyzer Category



Motor Tests and Autotune Procedure

You can perform three types of tests to identify motor parameters and one test for motor/system inertia. These parameters are used by sensorless-vector frequency-control and induction motor closed-loop modes. [Table 190](#) recommends which test to use based on the control mode and application.

Table 190 - Motor Tests and Autotune Matrix

| Control Mode | Description | Calculate | Static | Dynamic | Autotune (inertia test) |
|---------------------------------------|--------------------------------|-------------------------|--------------------------|--------------|-----------------------------|
| Induction motor - Frequency control | Basic volts/hertz | Not required | Not required | Not required | Not required |
| | Basic volts/hertz for Fan/Pump | Not required | Not required | Not required | Not required |
| | Sensorless vector | Required ⁽¹⁾ | Preferred | Not required | Not required |
| Induction motor - Closed-loop control | | Required ⁽¹⁾ | Preferred ⁽²⁾ | Preferred | Required ^{(1) (3)} |

(1) Not required for the Logix Designer application, version 29.00 and later.

(2) If it is not desired to rotate the motor (due to coupled load) you can perform this test for induction motor closed-loop mode and skip the Dynamic test. The dynamic test provides the best results for induction motor closed-loop mode.

(3) The motor inertia value must be non-zero prior to running a dynamic test. The motor inertia value is estimated automatically based upon the Motor Nameplate data in the Logix Designer application, version 29.00 and later. For previous versions, an Autotune test must be run or the motor inertia value entered directly.

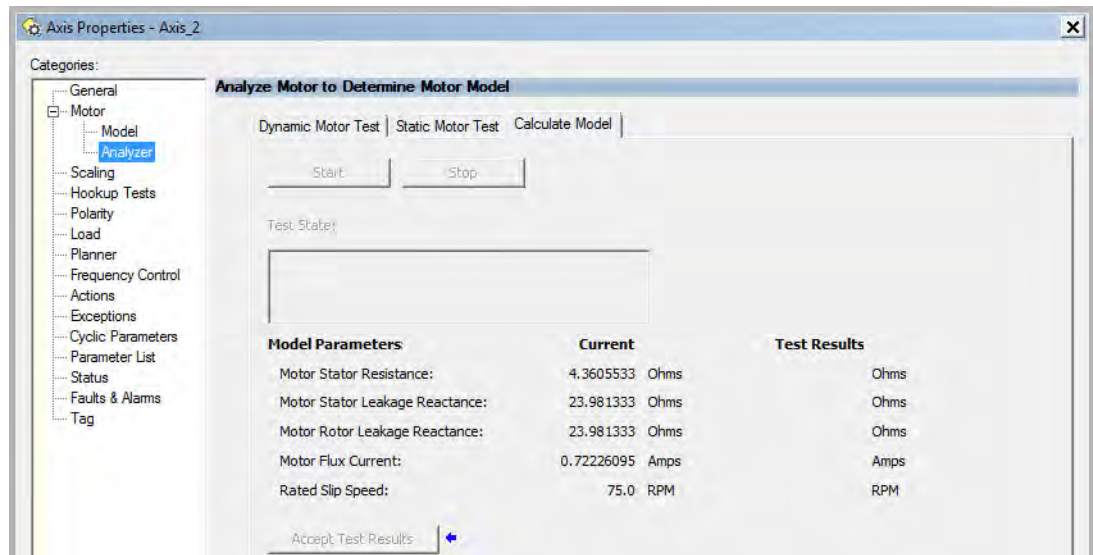
For motor/system autotune procedure, see [Tune Induction Motors](#) on [page 273](#) for more information.

The Motor>Analyzer category offers three choices for calculating or measuring electrical motor data.

Follow these steps to run motor tests and identify motor parameters.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the Motor>Analyzer category.

Nameplate data was entered on [page 426](#). The nameplate data must be entered before running the Calculate test.



3. Click Start to run the test.
4. Click Accept Test Results to save the values.
5. Click OK.

Motor Analyzer Category Troubleshooting

Calculate Model

When a Calculate test is run, the drive uses motor nameplate data to estimate the motor's Rated Flux Current, Stator Resistance (R_s), Stator Leakage Reactance (X_1) and Rotor Leakage Reactance (X_2). The drive also calculates the rated slip speed based on rated speed and rated frequency. No measurements are taken when using the Calculate test.

Static Motor Test

Use the Static test if the motor shaft cannot rotate or if it is already coupled to the load. Only tests that do not create motor movement are run. During this test, the Stator Resistance (R_s), Stator Leakage Reactance (X_1), and Rotor Leakage Reactance (X_2) values are measured during a series of static tests. The Rated Flux Current is estimated, since measurement of this value requires

motor movement. The drive also calculates the rated slip speed based on rated speed and rated frequency.

The Static test requires that you enter initial estimates for Rated Flux Current, Rated Slip Speed, Stator Resistance (Rs), Stator Leakage Reactance (X1), and Rotor Leakage Reactance (X2) into the Motor Model fields.

- For the Logix Designer application, version 29.00 or later, initial estimates are populated by the controller.
- For the Logix Designer application, version 28.00 or earlier, this can be done by running and accepting the results of a Calculate test, or by entering the values directly into the Logix Designer application.

Dynamic Motor Test

Dynamic tests are run with the motor disconnected from the load because the motor shaft turns and there are no travel limits. This is often the most accurate test method. During this test, the Stator Resistance (Rs), Stator Leakage Reactance (X1) and Rotor Leakage Reactance (X2) values are measured in a series of static tests. The Rated Flux Current is measured during a rotational test, in which the drive commands 75% of the motor rated speed.

The rated slip speed is measured during a second rotational test, in which the drive commands a speed (default of 100% of the motor rated speed) and set a torque limit (default of 50% of the motor rated torque). This quickly accelerates the motor to rated speed and then decelerates back to zero speed.

IMPORTANT The Dynamic test does not support travel limits.

The Dynamic test also requires that you enter initial estimates for Rated Flux Current, Rated Slip Speed, Stator Resistance (Rs), Stator Leakage Reactance (X1), and Rotor Leakage Reactance (X2) into the Motor Model fields.

- For the Logix Designer application, version 29.00 or later, initial estimates are automatically populated by the controller.
- For the Logix Designer application, version 28.00 or earlier, this can be done by running and accepting the results of a Calculate test, or by entering the values directly into the Logix Designer application.

The Dynamic test uses the Ramp Acceleration and Ramp Deceleration attributes to set the rotational test ramp-up and ramp-down times. If the resulting acceleration/deceleration times are less than 10 seconds, 10 seconds is used. If these attributes are not supported, 10 seconds is also used.

The Dynamic test also uses the IM Slip Test Velocity Command (percent of rated speed) and IM Slip Test Torque Limit (percent of rated torque) attributes to define the motion profile for the slip measurement. The default values are 100.0 and 50.0 respectively. The speed command dictates the speed that the motor spins up to and the torque dictates how quickly the motor reaches that speed. In general, A higher speed and lower torque results in a longer acceleration and a more accurate rated slip speed.

However, be aware that the dynamic test will not return expected results if the torque limit is set below 30.0.

Table 191 - Slip Test via Messaging

| Attribute Offset | Type | Attribute Name | Conditional Implementation | Description |
|------------------|------|-------------------------------|----------------------------------|--|
| 3095 | REAL | IM Slip Test Torque Limit | Closed loop induction motor only | Sets positive and negative torque limits for the slip test within the Dynamic motor test (similar to the torque limits in the inertia test). Units are in percent of rated torque. |
| 3096 | REAL | IM Slip Test Velocity Command | | Sets the velocity command for the slip test within the Dynamic motor test, (similar to the velocity command in the inertia test). Units are in percent of motor rated speed. |

The Dynamic test requires the Positive and Negative Torque Limits for said axis are not over-written while the test is in progress. This can be satisfied by making sure that (1) these cyclic attributes are not checked as writable within the Drive Parameters tab of the axis properties and (2) these parameters are not being messaged via an MSG instruction.

When configured for closed-loop control, the Dynamic test requires that an accurate system inertia is set in the Logix Designer application.

- For the Logix Designer application, version 29.00 or later, a default value is automatically populated by the controller.
- For the Logix Designer application, version 28.00 or earlier, this can be done by running and accepting the results of an Autotune test, or by entering the motor inertia value directly into the Logix Designer application.

When configured for closed-loop control, the Dynamic test uses the velocity regulator tuning as entered into the Logix Designer application. If the motor is coupled to a load, the velocity regulator tuning may need to be adjusted to make sure the velocity response is well controlled. The Dynamic test fails if the steady-state velocity feedback is not within a $\pm 30\%$ tolerance of the commanded velocity.

IMPORTANT The Dynamic test is not supported in closed-loop Torque Control.

If using the Dynamic test in Frequency Control mode, uncouple the motor from any load or results may not be valid. In closed-loop control, either a coupled or uncoupled load produces valid results.

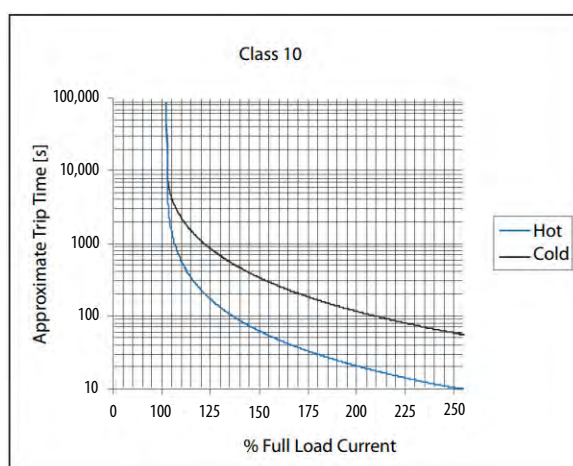
Selection of Motor Thermal Models

The Kinetix 5700 drives contain two motor thermal-overload protection algorithms that you can use to prevent the motor from overheating.

Generic Motors

The default thermal model is a generic I^2T Class 10 overload protection algorithm. This model is active if the MotorWindingToAmbientResistance or the MotorWindingToAmbientCapacitance values are 0.0. The purpose of this algorithm is to limit the time a motor is operating with excessive levels of current. The relationship between Motor Overload Factory Limit trip-time and motor output current is shown in [Figure 234](#).

Figure 234 - Motor Overload Curve



You can use the MotorOverloadLimit attribute (default of 100%, max of 200%) to increase the motor overload trip-time by artificially increasing the motor rated current (for thermal protection only). MotorOverloadLimit should only be increased above 100% if cooling options are applied. Increasing MotorOverloadLimit causes MotorCapacity to increase more slowly.

The generic motor thermal model also derates the motor rated current (for thermal protection only) when operating at low speeds. The derating factor is 30% at 0 Hz and 0% at 20 Hz, with linear interpolation between. Operating at output frequencies less than 20 Hz causes MotorCapacity to increase more quickly.

When the generic motor thermal-model is active, the MotorCapacity attribute increases only if the motor output current is greater than the effective motor rated current (taking into account the MotorOverloadLimit and low speed derating factor). The default MotorThermalOverloadFactoryLimit and MotorThermalOverloadUserLimit values for this thermal model are both 100%.

IMPORTANT The generic motor-thermal model does not support Current Foldback as a Motor Overload Action.

Thermally Characterized Motors

If the `MotorWindingToAmbientResistance` and `MotorWindingToAmbientCapacitance` attribute values are both non-zero, the motor is considered thermally characterized and an alternate motor thermal model is run. The purpose of this algorithm is to limit the time a motor is operating with excessive levels of current. This thermal model uses the first-order time constant determined from the `MotorWindingToAmbientResistance` and `MotorWindingToAmbientCapacitance` values to estimate the motor thermal capacity based on the motor output current.

The `MotorOverloadLimit` attribute (default of 100%, max of 200%) can be used to increase the motor overload trip-time by increasing the `MotorThermalOverloadFactoryLimit` value. The `MotorOverloadLimit` should be increased above 100% only if cooling options are applied. Increasing `MotorOverloadLimit` does not change the behavior of `MotorCapacity`.

This thermal model supports setting the `MotorOverloadAction` attribute as `Current Foldback`. Selecting the `Current Foldback` action results in a reduction in the current reference via the `MotorThermalCurrentLimit` attribute value that is reduced in proportion the percentage difference between the `MotorCapacity` and the `MotorOverloadLimit` values.

When this thermal model is active, the `MotorCapacity` attribute is non-zero if the motor output current is non-zero. The default `MotorThermalOverloadFactoryLimit` and `MotorThermalOverloadUserLimit` values for this thermal model are both 110%.

| | |
|------------------|--|
| IMPORTANT | This thermal model does not derate the motor-rated current when operating at low speeds. Operating at low output frequencies does not cause the <code>MotorCapacity</code> behavior to change. |
|------------------|--|

Speed Limited Adjustable Torque (SLAT)

Speed limited adjustable torque (SLAT) is a special mode of operation used primarily in web handling applications. While configured for SLAT, the drive typically operates as a torque regulator. The drive can automatically enter velocity regulation based on conditions within the velocity regulator and the magnitude of the velocity regulator's output, relative to the applied TorqueTrim attribute.

A torque regulated application can be described as any process requiring tension control. For example, a winder or unwinder with material being drawn or pulled with a specific tension required. The process also requires that another element set the speed.

When operating as a torque regulator, the motor current is adjusted to achieve the desired torque. If the material being wound or unwound breaks, the load decreases dramatically and the motor can potentially go into a runaway condition.

The SLAT feature is used to support applications that require a robust transition from torque regulation to velocity regulation (and vice versa). The SLAT feature can be configured via the SLATConfiguration attribute as:

Table 192 - SLAT Configuration Descriptions

| Name | Description |
|-----------------------|---|
| SLAT Disable | SLAT function is disabled. Normal Velocity Loop operation. |
| SLAT Min Speed/Torque | Drive automatically switches from Torque regulation to Velocity regulation if VelocityError < 0 and switches back to Torque regulation if VelocityError > SLATSetPoint for SLATTimeDelay. |
| SLAT Max Speed/Torque | Drive automatically switches from Torque regulation to Velocity regulation if VelocityError > 0 and switches back to Torque regulation if VelocityError < SLATSetPoint for SLATTimeDelay. |

Direction of the applied torque and direction of the material movement determine whether SLAT minimum or SLAT maximum mode should be used.

Motion Polarity Setting

The Motion Polarity setting in the Logix Designer application > Axis Properties > Polarity does not affect SLAT behavior, however, you may require clarification on whether to use the SLAT Min Speed/Torque or SLAT Max Speed/Torque configuration when Motion Polarity is set to Inverted. In this case, the velocity error displayed in the Logix Designer application is inverted compared to what is actually used by the axis to control the SLAT function. So, if the SLAT configuration is set to Min and then Motion Polarity is switched to Inverted, change the SLAT configuration to Max.

Table 193 - SLAT Operation When Motion Polarity Is Inverted

| Velocity Command | Motion Polarity | SLAT Configuration |
|----------------------|-----------------|--------------------|
| Positive (clockwise) | Normal | Min |
| | Inverted | Max |
| Negative (CCW) | Normal | Min |
| | Inverted | Max |

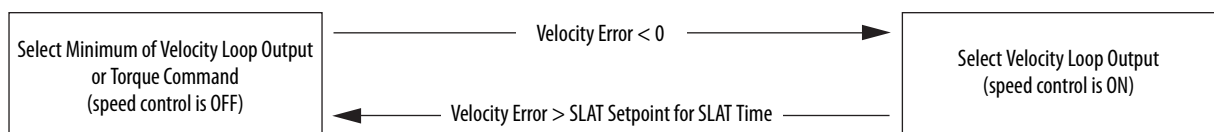
SLAT Min Speed/Torque

SLAT Min Speed/Torque is a special mode of operation primarily used in web handling applications. The drive typically operates as a torque regulator, provided that the TorqueTrim attribute is less than the torque output due to the velocity regulator's control effort. The drive can automatically enter velocity regulation based on conditions within the velocity regulator and the magnitude of the velocity regulator's output relative to the torque reference.

When used for SLAT control, an application dependent VelocityCommand value is applied to the drive via an MAJ instruction or MDS instruction (2198-xxxx-ERS4 and 2198-xxxx-ERS3 series B drives, firmware 9.001 or later). An application dependent TorqueTrim value is also applied via cyclic write. Under normal operation, VelocityCommand is set to a level that results in the velocity regulator's control effort becoming saturated when the motor's speed is mechanically limited. The TorqueReference value equals the TorqueTrim value, resulting in a positive VelocityError value.

Should the mechanical speed limitation be removed (example: web break), the motor accelerates and VelocityError becomes negative. At this time, a forced transition to velocity regulation occurs, and the motor's speed is regulated to the VelocityCommand attribute.

The axis remains in velocity regulation until VelocityError exceeds SLATSetPoint for a time specified by SLATTimeDelay. At this point, the axis returns to operating as a torque regulator.

Figure 235 - SLAT Min Speed/Torque

See the Integrated Motion on the EtherNet/IP™ Network Reference Manual, publication [MOTION-RM003](#), for more information on SLAT attributes.

SLAT Max Speed/Torque

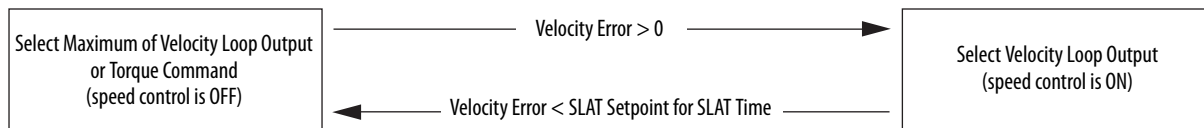
SLAT Max Speed/Torque is a special mode of operation primarily used in web handling applications. The drive typically operates as a torque regulator, provided that the TorqueTrim attribute is greater than the torque output due to the velocity regulator's control effort. The drive can automatically enter velocity regulation based on conditions within the velocity regulator and the magnitude of the velocity regulator's output relative to the torque reference.

When used for SLAT control, an application dependent VelocityCommand value is applied to the drive via an MAJ instruction or MDS instruction (2198-xxxx-ERS4 and 2198-xxxx-ERS3 series B drives, firmware 9.001 or later). An application dependent TorqueTrim value is also applied via cyclic write. Under normal operation, VelocityCommand is set to a level that results in the velocity regulator's control effort becoming saturated when the motor's speed is mechanically limited. The TorqueReference value equals the TorqueTrim value, resulting in a negative VelocityError value.

Should the mechanical speed limitation be removed (example: web break), the motor accelerates and VelocityError becomes positive. At this time, a forced transition to velocity regulation occurs, and the motor's speed is regulated to the VelocityCommand attribute.

The axis remains in velocity regulation until VelocityError is less than SLATSetPoint for a time specified by SLATTimeDelay. At this point, the axis returns to operating as a torque regulator.

Figure 236 - SLAT Max Speed/Torque



See the Integrated Motion on the EtherNet/IP Network Reference Manual, publication [MOTION-RM003](#), for more information on SLAT attributes.

SLAT Attributes

| ID | Access | Attribute | Conditional Implementation |
|-----|--------|--------------------|---|
| 833 | Set | SLAT Configuration | 0 = SLAT Disable ⁽¹⁾ 1 = SLAT Min Speed/Torque 2 = SLAT Max Speed/Torque |
| 834 | Set | SLAT Set Point | Velocity Units |
| 835 | Set | SLAT Time Delay | Seconds |

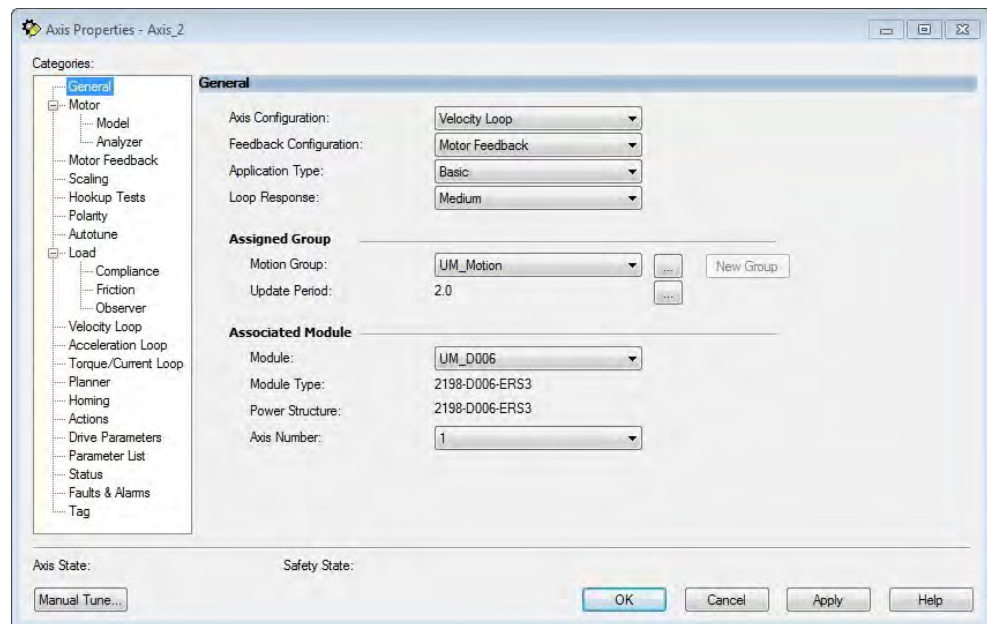
(1) SLAT Disable, when viewed in version 28.00 (and earlier) of the Logix Designer application, reads Torque Only.

Configure the Axis for SLAT

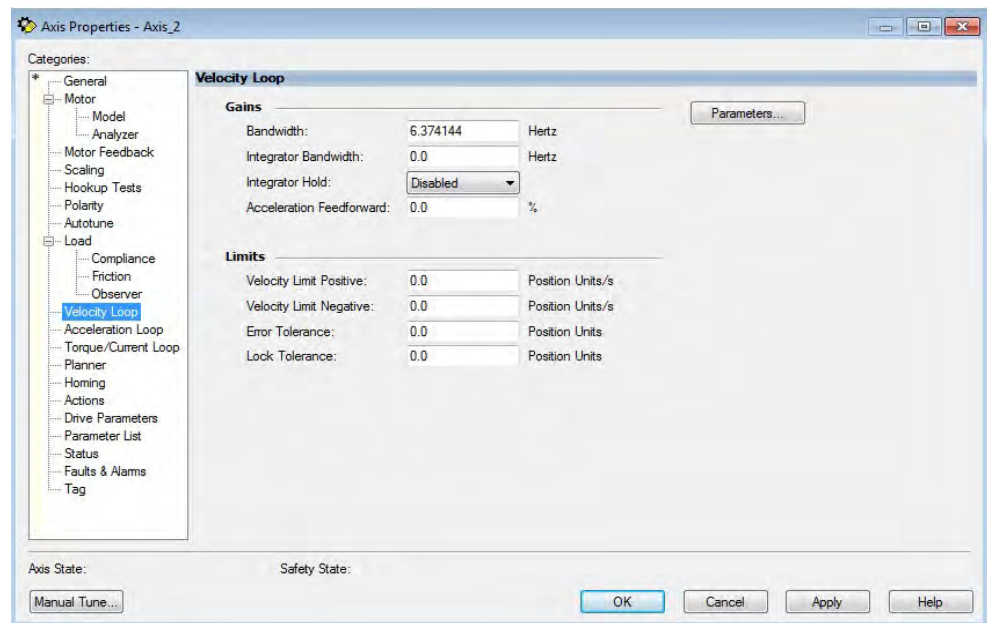
Follow these steps to configure the SLAT attributes.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the General category.

The General dialog box appears.



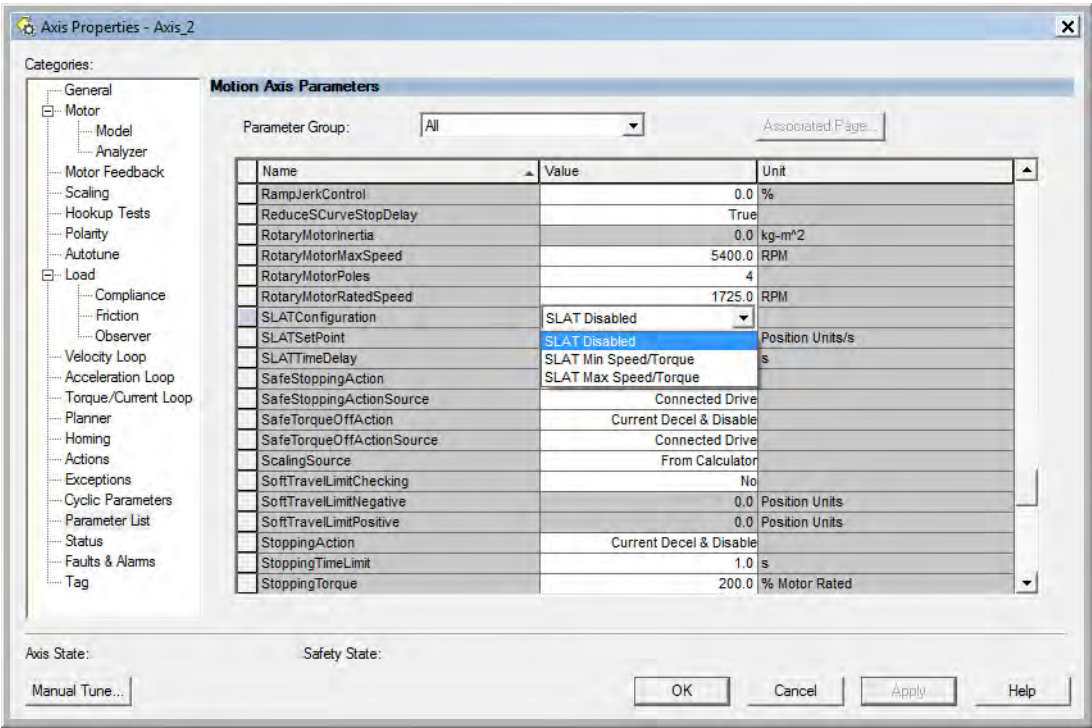
3. From the Axis Configuration pull-down menu, choose Velocity Loop.
- The Velocity Loop dialog box appears.



4. Enter values for the Velocity Loop attributes appropriate for your application.

- 5. Click Apply.
- 6. Select the Parameters List category.

The Motion Axis Parameters dialog box appears.



- 7. From the SLATConfiguration pull-down menu, choose the SLAT configuration appropriate for your application.

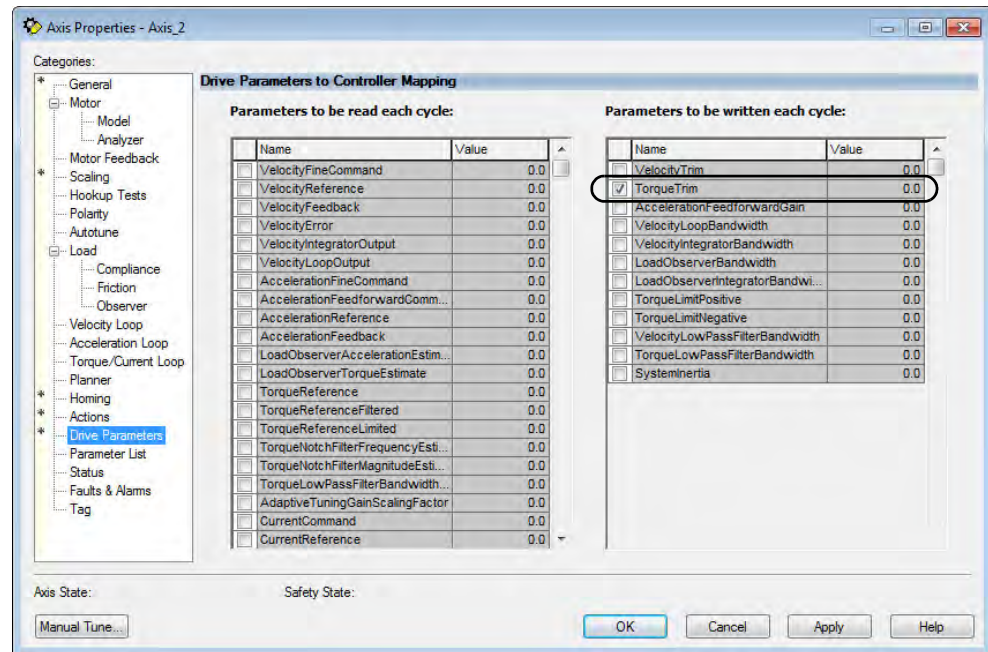
IMPORTANT SLAT parameters are configurable only when Velocity Loop is chosen from the General category, Axis Configuration pull-down menu.

- 8. Click Apply.
- 9. Enter values for SLATSetPoint and SLATTimeDelay attributes appropriate for your application.

| | | |
|-------------------|-----------------------|------------------|
| SLATConfiguration | SLAT Max Speed/Torque | |
| SLATSetPoint | 0.0 | Position Units/s |
| SLATTimeDelay | 0.0 | s |

- 10. Click OK.
- 11. Select the Drive Parameters category.

The Drive Parameters to Controller Mapping dialog box appears.



When using SLAT with Kinetix 5700 drives, the velocity command is sent to the drive via an MAJ instruction or MDS instruction (2198-xxxx-ERS4 and 2198-xxxx-ERS3 series B drives, firmware 9.001 or later). The torque command is sent via the cyclic write TorqueTrim attribute. See the Integrated Motion on the EtherNet/IP Network Reference Manual, publication [MOTION-RM003](#), for more information on cyclic read and cyclic write.

For MAJ instructions:

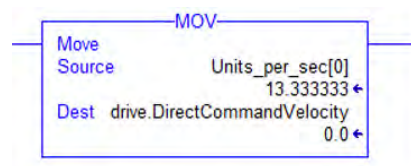
- When using SLAT, start the axis with the MSO instruction.
- The VelocityCommand is sent via the MAJ instruction.
- The TorqueCommand is sent to AxisTag.TorqueTrim.
- To make changes to the VelocityCommand, you must re-trigger the MAJ with the Speed value or use a MCD (motion change dynamics) instruction.
- To stop the axis use a MAS instruction.
- The axis accelerates and decelerates at the MAJ instruction programmed Acceleration and Deceleration rates.
- You can also change the rates using the MCD instruction.

For MDS instruction (2198-xxxx-ERS4 and 2198-xxxx-ERS3 series B drives, firmware 9.001 or later):

- When using SLAT, start the axis with an MDS instruction.
- The MDS instruction turns on the power structure enable and tracking command status and also executes the velocity command.

See sample code in [Motion Drive Start \(MDS\) Instruction](#).

- The acceleration and deceleration rate is controlled by Ramped Acceleration and Ramped Deceleration by using the SSV instruction.
- The Torque Command is set to Axis Tag.Torque Trim. Make sure the Torque Trim Write is checked in the drive parameter (see Drive Parameters dialog box above). The value can be changed.
 - Alternatively, you can use the Axis Tag.DirectCommandVelocity to alter the Velocity Command when the existing MDS instruction is being executed.



- To stop the axis, use MAS instructions, keeping the Change Decel to NO and by using an SSV instruction to change Ramped Deceleration for the desired rate.

Motion Drive Start (MDS) Instruction

Kinetix 5700 inverters, catalog numbers 2198-xxxx-ERS4 and 2198-xxxx-ERS3 (series B) with firmware revision 9.001 or later, provide access to the Motion Drive Start (MDS) instruction. Use the MDS instruction to activate the drive control loops for the specified axis and run the motor at the specified speed.

For information regarding the MDS instruction, refer to the Logix 5000™ Controllers Motion Instructions Reference Manual, publication [MOTION-RM002](#).

For the Kinetix 5700 drive, the MDS instruction is valid only when the axis configuration is set to one of these control modes:

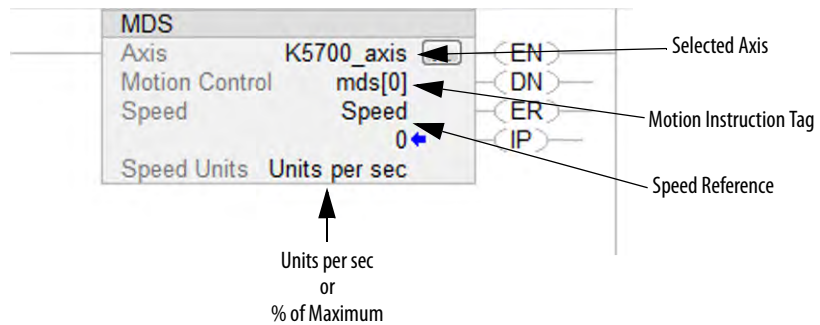
- Frequency Control
- Velocity Loop
- Torque Loop

IMPORTANT The MDS instruction is not valid when the axis configuration is set to Position Loop.

Motion Drive Start Instruction Configuration

The MDS instruction is configured in a similar fashion to most motion instructions, as seen in this example.

Figure 237 - Typical MDS Instruction

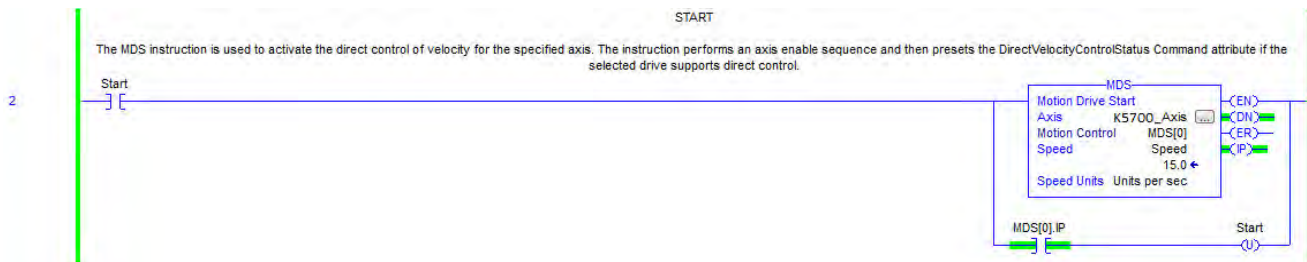


The MDS instruction is similar to a Motion Axis Jog (MAJ) instruction, however, the MDS instruction does not set the acceleration/deceleration rates. The acceleration rate is dynamically set by the ramp attributes configured in a Set System Value (SSV) instruction. See Ramp Attributes on [page 443](#).

TIP The K5700_Axis was configured for revolutions. Therefore, the Speed Units are revolutions per second (rev/s).

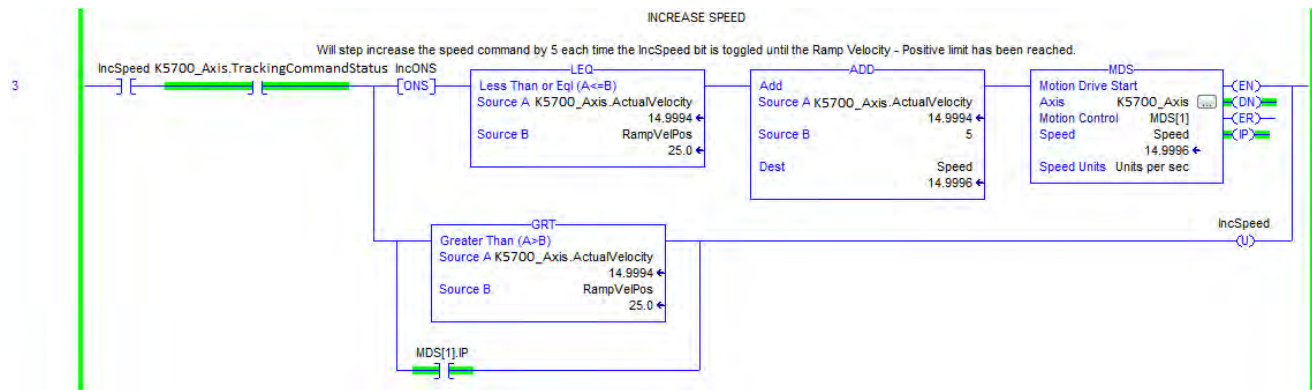
Motion Drive Start (MDS) Sample Code

Figure 238 - Start



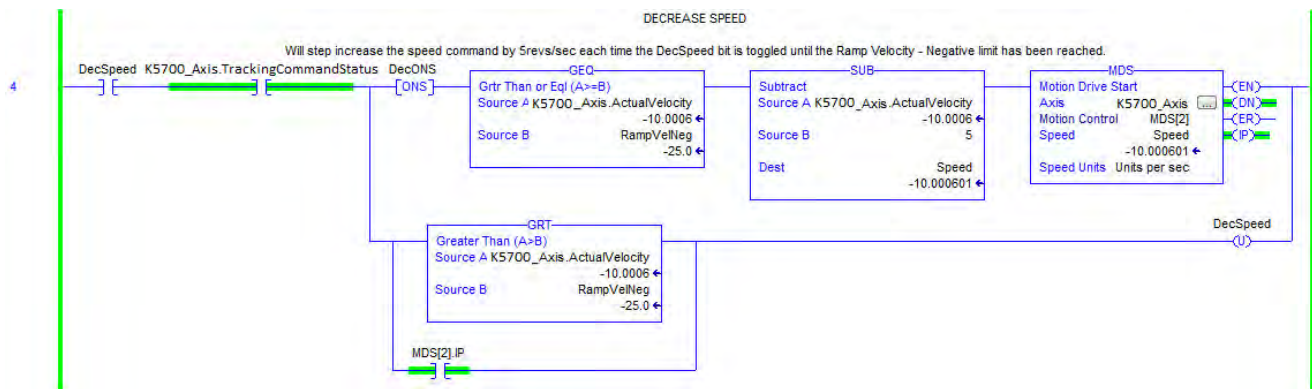
The speed is increased by updating the speed reference and then re-executing the MDS instruction.

Figure 239 - Increase Speed



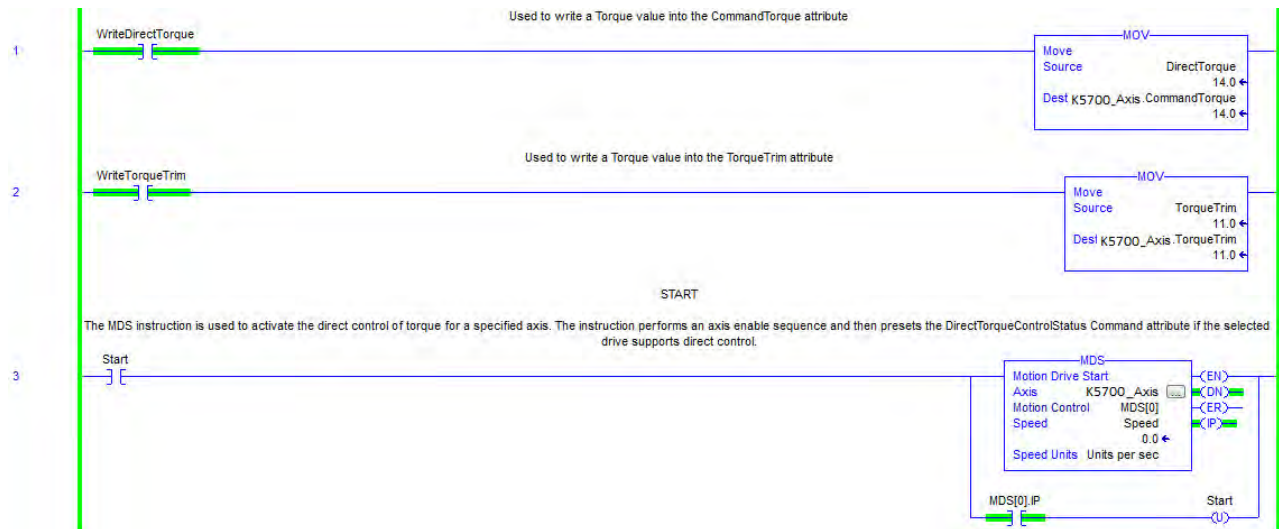
The speed is decreased by updating the speed reference and then re-executing the MDS instruction.

Figure 240 - Decrease Speed



When the axis configuration is in Torque Loop, the Speed attribute within the MDS instruction is not used to command the speed of the drive. The speed is determined by the amount of torque specified in the CommandTorque and/or TorqueTrim attributes.

Figure 241 - Torque Mode



IMPORTANT You must command zero torque in the CommandTorque and TorqueTrim attributes before you can use the Motion Axis Stop (MAS) instruction to stop a specific motion process on an axis or to stop the axis completely. To use the MAS instruction, you must set Change Decel to No. Otherwise, an instruction error can occur. The deceleration rate is set based on the Ramp Deceleration attribute. The Motion Servo Off (MSF) instruction is used to deactivate the drive output for the specified axis and to deactivate the axis' servo loop. If you execute an MSF instruction while the axis is moving, the axis coasts to an uncontrolled stop.

Ramp Attributes

The MDS instruction is validated if the Integrated Motion on EtherNet/IP drive device supports the following five ramp attributes:

- RampAcceleration
- RampDeceleration
- RampVelocity - Positive
- RampVelocity - Negative
- RampJerk - Control

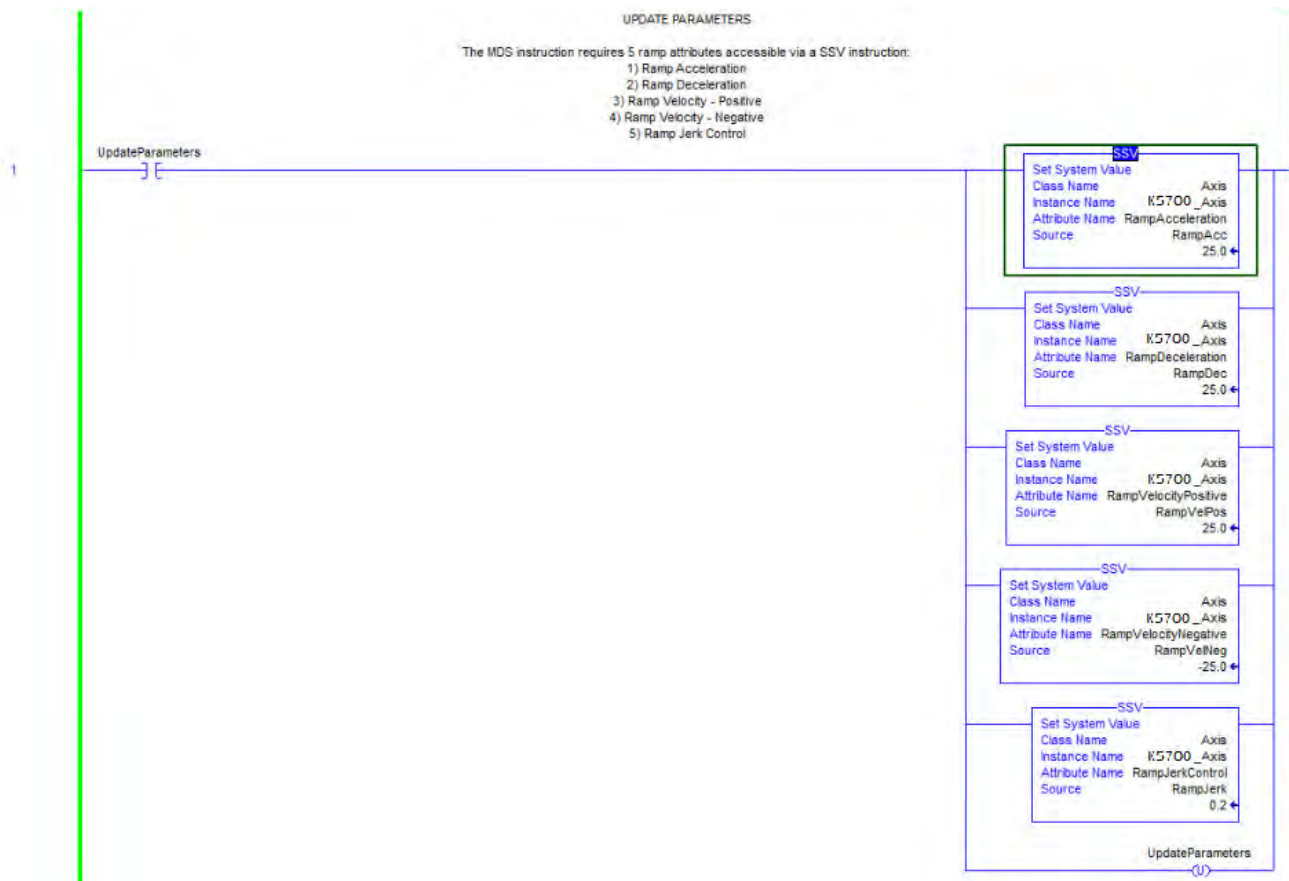
IMPORTANT Ramp attributes are available only when the Kinetix 5700 drive axis configuration is set to Frequency Control or Velocity Loop. Ramp attributes are not available when the axis configuration is set to Torque Loop or Position Loop.

Table 194 - Ramp Attributes

| Ramp Attribute | Access | ID | Description |
|-------------------------|--------|-----|---|
| RampVelocity - Positive | Set | 374 | Ramp Velocity - Positive attribute is a positive value that defines the maximum positive velocity command output of the Ramp Generator. |
| RampVelocity - Negative | Set | 375 | Ramp Velocity - Negative attribute is a negative value that defines the maximum negative velocity command output of the Ramp Generator. |
| RampAcceleration | Set | 376 | The Ramp Acceleration attribute is a positive value that defines the maximum acceleration (increasing speed) of the velocity command output by the Ramp Generator. |
| RampDeceleration | Set | 377 | The Ramp Deceleration attribute is a positive value that defines the maximum deceleration (decreasing speed) of the velocity command output by the Ramp Generator. |
| RampJerk - Control | Set | 379 | The Ramp Jerk Control attribute sets the percentage of acceleration or deceleration time that is applied to the speed ramp as jerk limited S-Curve based on a step change in velocity. The S-Curve time is added half at the beginning and half at the end of the ramp. A value of 0 results in no S-Curve, for example, a linear acceleration or deceleration ramp. A value of 100% results in a triangular acceleration profile with the peak being the configured ramp acceleration or deceleration. As the Jerk Control value increases, the derived accelerating jerk value decreases based on the following: $0.5 \cdot 0.01 \cdot \text{Jerk Control} \cdot \text{Ramp Vel Positive/Ramp Accel}$. The decelerating Jerk limit value also decreases according to the following: $0.5 \cdot 0.01 \cdot \text{Jerk Control} \cdot \text{Ramp Vel Negative/Ramp Decel}$. |

IMPORTANT The Ramp attributes can be viewed and set with only an SSV or GSV instruction.

Figure 242 - Ramp Attribute Sample Code



Motor Overload Retention

The motor overload retention feature protects the motor in the event of a drive power-cycle, in which the motor thermal state is lost.

With motor overload retention, upon drive power-up the MotorCapacity attribute initially reads:

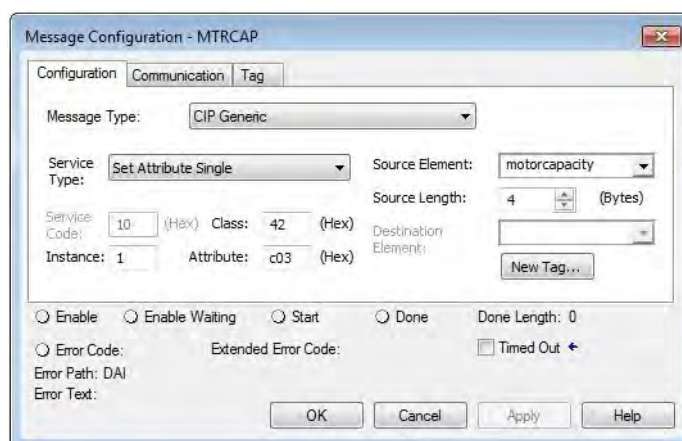
- 20% if the motor is configured to use an integral thermal switch or an integral motor winding temperature is available
- 50% if the motor is not configured to use an integral thermal switch or an integral motor winding temperature is not available

If you have a separate monitoring algorithm within your Logix 5000 controller, you can use the InitialMotorCapacity attribute $(3075)_{10}$ or $(C03)_{16}$ to change the initial MotorCapacity value that the motor overload retention feature populates.

- You can write to the InitialMotorCapacity attribute only in the Stopped state after power-up
- You cannot write to the InitialMotorCapacity attribute after the first time the axis is enabled following a power cycle.

Use a message instruction to write to the InitialMotorCapacity value.

In this example, the source element tag motorcapacity is a REAL Data type.



Phase Loss Detection

The phase-loss detection feature is designed to determine if motor power wiring is electrically connected to a motor and that reasonable current control exists. This attribute enables the operation of the drive's torque proving functions that work in conjunction with mechanical brake control.

When the ProvingConfiguration attribute is enabled, the drive performs a torque prove test of the motor current while in the Starting state to prove that current is properly flowing through each of the motor phases before releasing the brake. If the torque prove test fails, the motor brake stays engaged and a FLT-S09 Motor Phase Loss exception (fault) is generated.

IMPORTANT The mechanical brake must be set as soon as the drive is disabled. When the brake is under the control of the axis state machine, this is automatic. But, when controlled externally, failure to set the brake when the drive is disabled can cause a free-fall condition on a vertical application.

Table 195 - Phase-loss Detection Startup Sequence

| Startup Phase | Description |
|---------------|---|
| Phase 1 | When the drive receives an enable request, the Starting state begins execution and torque proving starts. |
| Phase 2 | The torque proving feature ramps current to the motor-phase output connector and verifies that the current feedback circuitry detects current on each of the phases. |
| Phase 3 | Once motor-current feedback has been verified in each motor phase, the drive attempts to enable the current control loop at a user-specified current level, and verifies that the current-loop error tolerance is within range. |

Torque proving is available for all motoring configurations including closed-loop servo control and induction motors.

For permanent magnet (PM) motors, the drive attempts to apply current to the motor phases such that all current through the motor is flux current. However, due to the electrical angle of the motor at the time of the MSO instruction, it may not be possible to verify the motor phase wiring with only flux current. Therefore, with a PM motor it is possible that the motor shaft can move slightly during torque proving if no motor brake exists to hold the load.

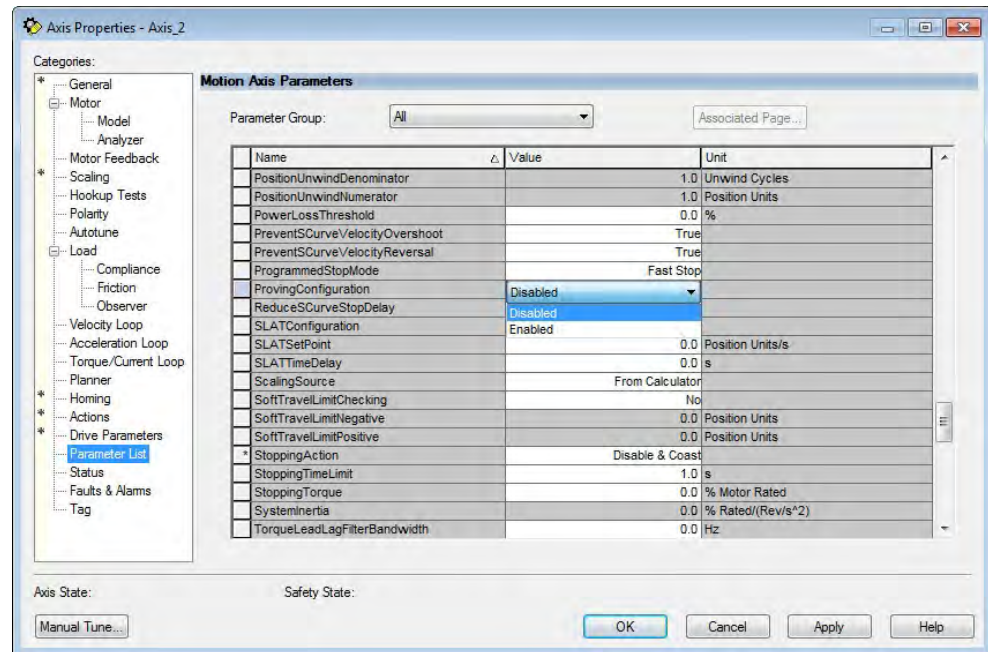
Phase-loss Detection Attributes

| ID | Access | Attribute | Conditional Implementation |
|-----|--------|----------------------|---|
| 590 | SSV | ProvingConfiguration | 0 = Disabled 1 = Enabled |
| 591 | SSV | TorqueProveCurrent | % Motor Rated Units: Amps Default: 0.000 Min/Max: 0/10,000 |

Phase-loss Detection Configuration

Follow these steps to configure the phase-loss detection attributes.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the Parameter List category and scroll to ProvingConfiguration.



3. From the ProvingConfiguration pull-down menu, choose Enabled to enable the torque proving feature.

| | | |
|--|-----------|-----------------|
| <input type="checkbox"/> TorqueOffset | 0.0 | % Motor Rated |
| <input checked="" type="checkbox"/> TorqueProveCurrent | 0.0 | % Motor Rated |
| <input type="checkbox"/> TorqueRateLimit | 1000000.0 | % Motor Rated/s |

4. Enter a value in the TorqueProveCurrent attribute appropriate for your application.
5. Click OK.

The TorqueProveCurrent attribute is active only if ProvingConfiguration is set to Enabled. TorqueProveCurrent lets you specify the amount of current that is used during the torque proving test and calculated as a percentage of motor rating. The higher the TorqueProveCurrent value the more current the drive delivers to the motor to verify that the motor phase wiring is available and capable of that current level. High current levels conversely cause more thermal stress and (potentially) can cause more torque to be driven against the motor brake during the test. If the TorqueProveCurrent level selected is too small, the drive cannot distinguish the proving current from noise, and in this case the drive posts an INHIBIT M04 torque-proving configuration fault code. The minimum amount of torque proving current depends on catalog number of the drive.

Phase Loss Detection Current Example

In this example, a 2198-D020-ERS3 dual-axis inverter is paired with a VPL-B1003T-C motor with 6.77 A rms rated current. Use the phase-loss detection equation and table to calculate the initial minimum torque-proving current as a percentage of motor rated current. Depending on the unique characteristics of your application, the required torque-proving current value can be larger than the initial recommended value.

Figure 243 - Phase-loss Detection Equation

$$\left(\frac{\text{Rating From Table}}{\text{Motor Rated Current}} \right) \times 100\% = \frac{0.5746 \text{ A}}{6.77 \text{ A}} \times 100\% = 8.49\%$$

Table 196 - Recommended Phase-loss Detection Current

| Drive Cat. No. | Phase-loss Detection Current, min A, rms |
|----------------|---|
| 2198-S086-ERSx | 7.183 |
| 2198-S130-ERSx | 9.337 |
| 2198-S160-ERSx | 12.21 |
| 2198-S263-ERSx | 21.492 |
| 2198-S312-ERSx | 27.436 |
| 2198-D006-ERSx | 0.1796 |
| 2198-D012-ERSx | 0.3591 |
| 2198-D020-ERSx | 0.5746 |
| 2198-D032-ERSx | 0.9337 |
| 2198-D057-ERSx | 1.6520 |

Velocity Droop

The velocity droop function can be useful when some level of compliance is required due to rigid mechanical coupling between two motors. The feature is supported when the axis is configured for Frequency Control, Velocity Control, or Position Control.

Closed Loop Control

The closed-loop velocity droop function is supported when configured for either Velocity or Position control. The velocity error input to the integral term is reduced by a fraction of the velocity regulator's output, as controlled by the VelocityDroop attribute. Therefore, as torque loading on the motor increases, actual motor speed is reduced in proportion to the droop gain. This is helpful when some level of compliance is required due to rigid mechanical coupling between two motors.

IMPORTANT The closed-loop velocity droop function acts to reduce the velocity error input to the integral term, but never changes the polarity of the velocity error.

IMPORTANT When configured for closed-loop control, the units of the VelocityDroop attribute are Velocity Control Units / Sec / % Rated Torque.

Frequency Control

The velocity droop function is also supported when configured for Frequency Control. As the estimated I_q current within the motor increases, the velocity reference is reduced in proportion to the VelocityDroop attribute. Therefore, as torque loading on the motor increases, actual motor speed is reduced in proportion to the droop gain. This is helpful when some level of compliance is required due to rigid mechanical coupling between two motors.

IMPORTANT The frequency-control velocity droop function acts to reduce the velocity reference, but never changes the direction of the velocity reference.

IMPORTANT When configured for frequency control, the units of the VelocityDroop attribute are Velocity Control Units / Sec / % Rated I_q Current.

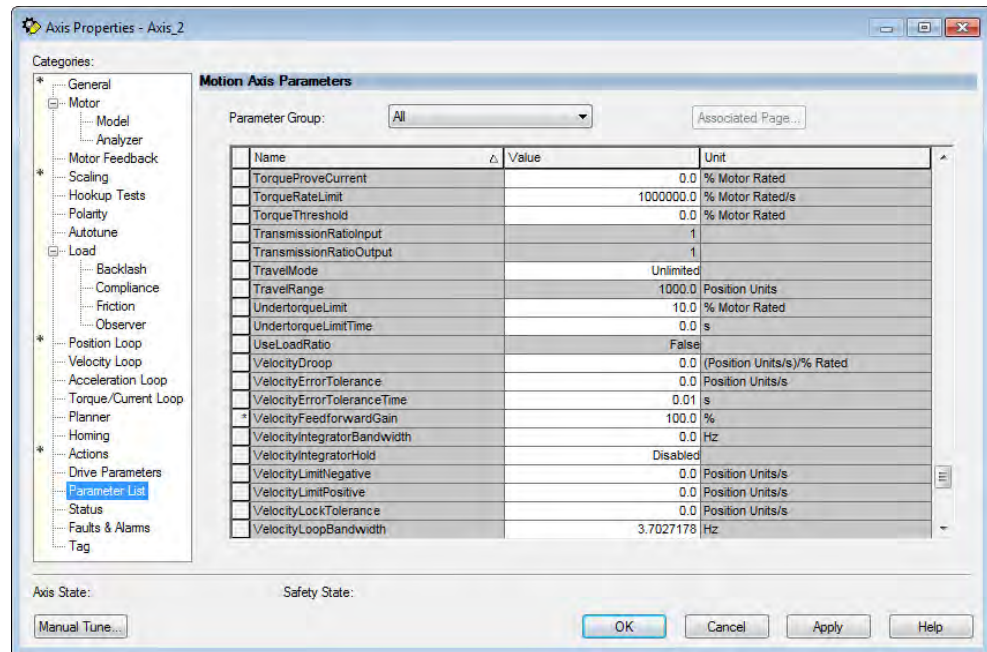
Velocity Droop Attribute

| ID | Access | Attribute | Conditional Implementation |
|---------|--------|----------------|--------------------------------|
| 464/321 | SSV | Velocity Droop | Velocity Units / Sec / % Rated |

Velocity Droop Configuration

Follow these steps to configure the velocity droop attribute.

1. In the Controller Organizer, right-click an axis and choose Properties.
2. Select the Parameter List category and scroll to VelocityDroop.



3. Enter a value in the Velocity Droop attribute appropriate for your application.
4. Click OK.

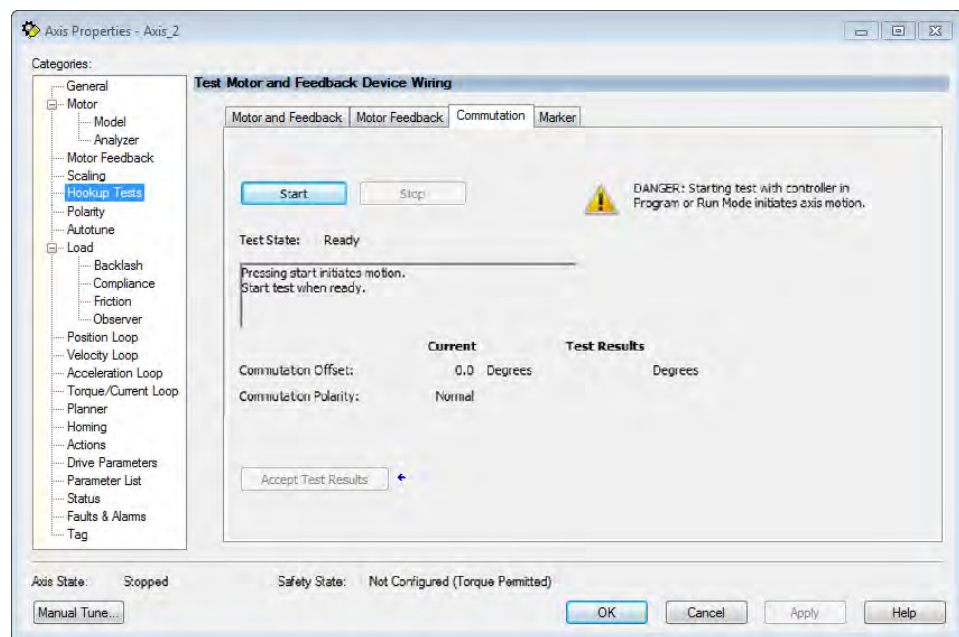
Commutation Test

The commutation test determines an unknown commutation offset and can also be used to determine the unknown polarity of the start-up commutation wiring. You can also use the commutation test to verify a known commutation offset and the polarity start-up commutation wiring.

IMPORTANT This test applies to third-party or custom permanent-magnet motors equipped with (TTL with Hall and Sine/Cosine with Hall) incremental encoders that are not available as a catalog number in the Motion Database.

IMPORTANT When motors have an unknown commutation offset and are not listed in the Motion Database by catalog number, you cannot enable the axis.

Figure 244 - Hookup Tests - Commutation Tab



To run the commutation test, see [Test the Axes](#) on [page 268](#).

Adaptive Tuning

The adaptive tuning feature is an algorithm inside the Kinetix 5700 servo drives. The algorithm continuously monitors and, if necessary, adjusts or adapts various filter parameters and, in some cases, control-loop gains to compensate for unknown and changing load conditions while the drive is running. Its primary function is to:

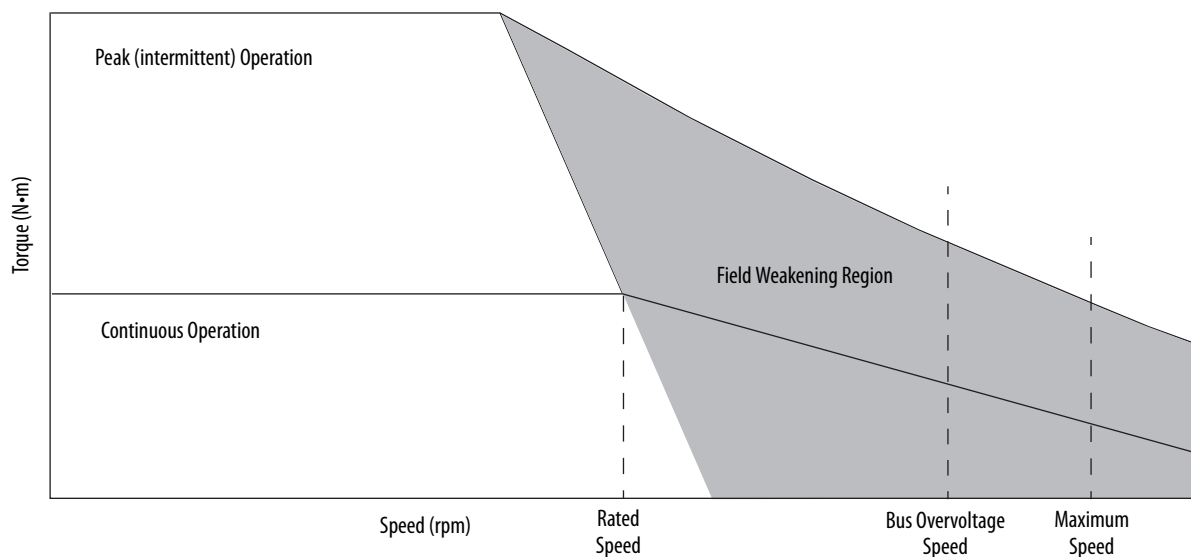
- Automatically adjust torque-loop notch and low-pass filter parameters to suppress resonances
- Automatically adjust control-loop gains to avoid instability when detected

See Motion System Tuning Application Techniques, publication [MOTION-AT005](#), for more information on the AdaptiveTuningConfiguration attribute.

Field Weakening Mode

Kinetix VPC interior permanent-magnet (IPM) motors are designed to operate in Field Weakening mode to widen the speed range. Operation in Field Weakening mode can result in Back EMF voltage increasing to a level that exceeds the DC-bus voltage if a loss of control occurs. When this loss of control occurs, the Back EMF voltage can charge the DC-bus to a level that can overvoltage the DC-bus caps and result in a failure of the common DC-bus.

Figure 245 - Field Weakening Region



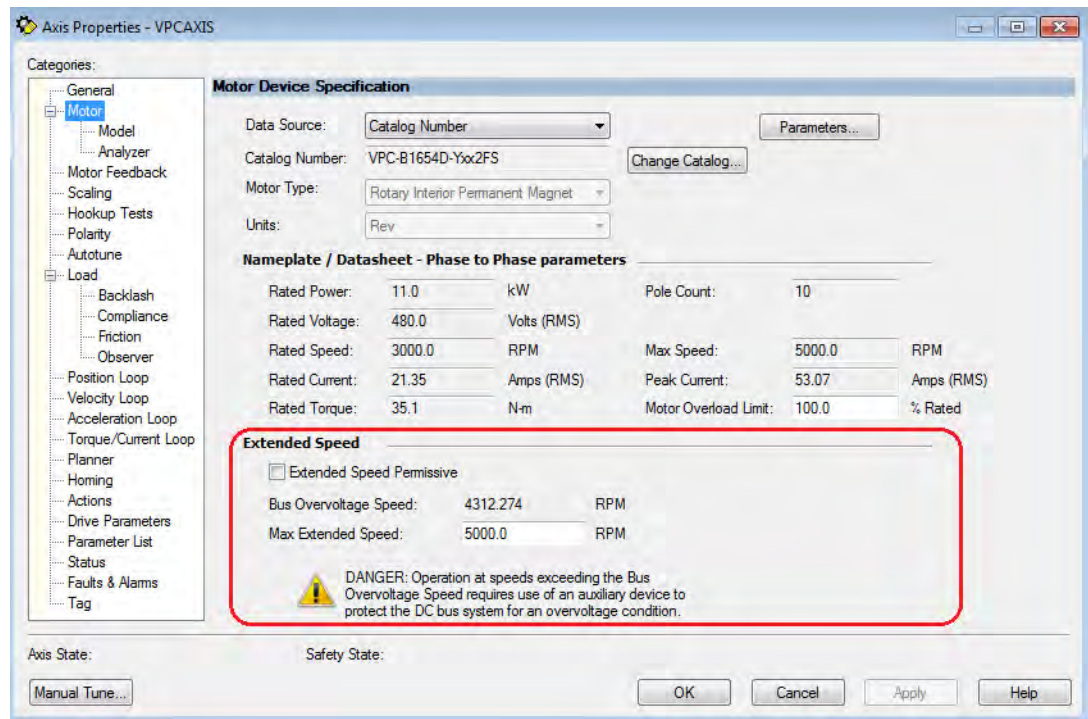
ATTENTION: DC-bus failure can cause damage to all drive modules in the bus group, not just the inverter connected to the Kinetix VPC motor.

Extended Speed Feature

The Extended Speed feature is implemented in the Logix Designer application to help prevent accidental operation at unsafe speeds. With this feature, the controller calculates a Bus Overvoltage Speed based upon the drive's maximum allowable bus-voltage and the Back EMF of the motor. This is the maximum speed that does not risk damaging the drive modules in the bus group. By default, the Extended Speed feature limits motor velocity to the Bus Overvoltage Speed.

Configure Extended Speed Operation

The extended speed feature is only configurable with Kinetix 5700 drives and Kinetix VPC continuous-duty IPM motors. You can configure the Extended Speed feature in Axis Properties>Motor category of the Logix Designer application (version 29.00 or later).



Follow these steps to enable operating at speeds greater than the Bus Overvoltage Speed.

1. In the Extended Speed field, check Extended Speed Permissive.
2. Set the Max Extended Speed attribute as required by your application.



WARNING: Operation at speeds exceeding the Bus Overvoltage Speed requires use of an auxiliary device to protect the DC bus system from an overvoltage condition.

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