



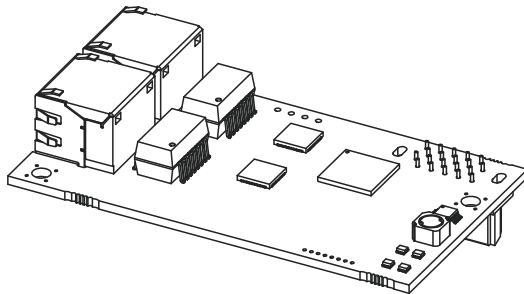
# YASKAWA AC Drive A1000 Option

# EtherCAT<sup>®</sup>

## Installation Manual

**Type:** SI-ES3 for A1000 Series

To properly use the product, read this manual thoroughly and retain for easy reference, inspection, and maintenance. Ensure the end user receives this manual.



### ATTENTION!

This product can only be used on A1000 drives with firmware version VSA901017 to VSA901099 installed.

---

Copyright © 2011 YASKAWA EUROPE GMBH

All rights reserved. No part of this publication may be reproduced, stored in a retrieval system, or transmitted, in any form or by any means, mechanical, electronic, photocopying, recording, or otherwise, without the prior written permission of YASKAWA. No patent liability is assumed with respect to the use of the information contained herein. Moreover, because YASKAWA is constantly striving to improve its high-quality products, the information contained in this manual is subject to change without notice. Every precaution has been taken in the preparation of this manual. YASKAWA assumes no responsibility for errors or omissions. Neither is any liability assumed for damages resulting from the use of the information contained in this publication.

# A1000 Option EtherCAT

## Installation Manual

---

### Table of Contents

<b>1 Preface and Safety</b> .....	<b>4</b>
<b>2 Product Overview</b> .....	<b>8</b>
<b>3 Software Parts</b> .....	<b>9</b>
<b>4 Receiving</b> .....	<b>10</b>
<b>5 EtherCAT® Option Components</b> .....	<b>11</b>
<b>6 Installation Procedure</b> .....	<b>16</b>
<b>7 EtherCAT® Option Related Drive Parameters</b> .....	<b>22</b>
<b>8 Object Dictionary</b> .....	<b>24</b>
<b>9 Process Data Objects (PDO)</b> .....	<b>27</b>
<b>10 Fault Diagnosis and Possible Solutions</b> .....	<b>29</b>
<b>11 Specifications</b> .....	<b>38</b>

## 1 Preface and Safety

YASKAWA manufactures products used as components in a wide variety of industrial systems and equipment. The selection and application of YASKAWA products remain the responsibility of the equipment manufacturer or end user. YASKAWA accepts no responsibility for the way its products are incorporated into the final system design. Under no circumstances should any YASKAWA product be incorporated into any product or design as the exclusive or sole safety control. Without exception, all controls should be designed to detect faults dynamically and fail safely under all circumstances. All systems or equipment designed to incorporate a product manufactured by YASKAWA must be supplied to the end user with appropriate warnings and instructions as to the safe use and operation of that part. Any warnings provided by YASKAWA must be promptly provided to the end user. YASKAWA offers an express warranty only as to the quality of its products in conforming to standards and specifications published in the YASKAWA manual. **NO OTHER WARRANTY, EXPRESS OR IMPLIED, IS OFFERED.** YASKAWA assumes no liability for any personal injury, property damage, losses, or claims arising from misapplication of its products.

### ◆ Applicable Documentation

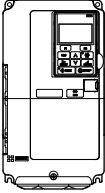
The following manuals are available for SI-ES3 EtherCAT® Option card:

#### Option Card

	<b>YASKAWA AC Drive A1000 Option EtherCAT® Installation Manual (this book)</b> <b>Manual No.: YEU TOEP C710616 99A</b>
	Read this manual first. The installation manual is packaged with the EtherCAT® Option and contains a basic overview of wiring, settings, functions, and fault diagnoses.
	<b>YASKAWA AC Drive A1000 Option EtherCAT® Technical Manual</b> <b>Manual No.: YEU SIEP C710616 99A</b>
	The technical manual contains detailed information. To obtain the technical manual access these sites: Europe: <a href="http://www.yaskawa.eu.com">http://www.yaskawa.eu.com</a> Japan: <a href="http://www.e-mechatronics.com">http://www.e-mechatronics.com</a> USA: <a href="http://www.yaskawa.com">http://www.yaskawa.com</a> Other areas: contact a YASKAWA representative.

For the drive setup, refer to one of the documentation listed below.

## YASKAWA Drive

	<p>Refer to the manual of the drive this option card is being used with. The instruction manual for the drive covers basic installation, wiring, operation procedures, functions, troubleshooting, and maintenance information. It also includes important information on parameter settings and how to tune the drive. A Quick Start Guide is included with the drive. For the more detailed technical manual, visit YASKAWA's homepage. Europe: <a href="http://www.yaskawa.eu.com">http://www.yaskawa.eu.com</a> Japan: <a href="http://www.e-mechatronics.com">http://www.e-mechatronics.com</a> USA: <a href="http://www.yaskawa.com">http://www.yaskawa.com</a> Other areas: contact a YASKAWA representative</p>
---	---

## ◆ Terms

**Note:** Indicates supplemental information that YASKAWA highly recommends be followed. Content identified by Note: is not related to personnel safety or equipment damage safety messages.

EtherCAT® Option:	YASKAWA AC Drive SI-ES3 EtherCAT® option card
EtherCAT®:	Ethernet for Control Automation Technology, an open Ethernet-based network
NOID:	Network Option Interface Driver (YASKAWA Interface driver)
Online-DRV:	NOID processing mode, process (ctrl/resp) data is active
Online-DRVMB:	NOID processing mode, process resp data is active, ctrl data is on hold (Until MEMOBUS process is complete)
Online-PRG:	NOID processing mode, NO process (ctrl/resp) data is active
Host:	YASKAWA drive 1000 series
JTAG:	Joint Test Action Group, an IEEE standard interface test port for test and programming purposes
LED:	Light Emitting Diode
OPT, Option:	The unit described in this document
INV, Inverter:	Host application to OPT
PCB:	Printed Circuit Board
SPI:	Serial Peripheral Interface Bus
FCS:	Frame Check Sequence
INVR:	Drive register number
ESI:	EtherCAT Slave Information

## ◆ Registered Trademarks

- EtherCAT® is registered trademark and patented technology, licensed by Beckhoff Automation GmbH, Germany.

# 1 Preface and Safety

---

- Other company names and product names listed in this manual are registered trademarks of those companies.

## ◆ Supplemental Safety Information

---

Read and understand this manual before installing, operating, or servicing this option card. The option card must be installed according to this manual and local codes.

The following conventions are used to indicate safety messages in this manual. Failure to heed these messages could result in serious or possibly even fatal injury or damage to the products or to related equipment and systems.

### **DANGER**

Indicates a hazardous situation, which, if not avoided, will result in death or serious injury.

### **WARNING**

Indicates a hazardous situation, which, if not avoided, could result in death or serious injury.

### **CAUTION**

Indicates a hazardous situation, which, if not avoided, could result in minor or moderate injury.

### **NOTICE**

Indicates an equipment damage message.

## ■ General Safety

### **General Precautions**

- The diagrams in this section may include drives without covers or safety shields to illustrate details. Be sure to re-install covers or shields before operating any devices. The option board should be used according to the instructions described in this manual.
- Any illustrations, photographs, or examples used in this manual are provided as examples only and may not apply to all products to which this manual is applicable.
- The products and specifications described in this manual or the content and presentation of the manual may be changed without notice to improve the product and/or the manual.
- When ordering a new copy of the manual due to damage or loss, contact your YASKAWA representative or the nearest YASKAWA sales office and provide the manual number shown on the front cover.

## DANGER

### **Heed the safety messages in this manual.**

Failure to comply will result in death or serious injury.

The operating company is responsible for any injuries or equipment damage resulting from failure to heed the warnings in this manual.

## NOTICE

### **Do not expose the drive to halogen group disinfectants.**

Failure to comply may cause damage to the electrical components in the option card.

Do not pack the drive in wooden materials that have been fumigated or sterilized.

Do not sterilize the entire package after the product is packed.

### **Do not modify the drive circuitry.**

Failure to comply could result in damage to the drive and will void warranty.

YASKAWA is not responsible for any modification of the product made by the user. This product must not be modified.

## 2 Product Overview

### ◆ About This Product

---

The EtherCAT® Option (Model: SI-ES3) is an option card designed to connect the YASKAWA AC drive to an EtherCAT® network. Using this option card and an EtherCAT® master can;

- operate the drive
- monitor the drive operation status
- read or modify drive parameters.

The SI-ES3 option provides instant connectivity to an EtherCAT® network for the YASKAWA A1000 drive. The option contains support for the Velocity mode according the CANopen Device Profile and Motion Control (DSP402) profile. It also contains YASKAWA vendor specific CANopen objects based on the present CANopen option board specification.

The EtherCAT® Option supports the following communication profiles;

- DS 301 Ver. 4.02
- DSP 402 Ver. 3.0 Velocity Mode



**EtherCAT Conformance tested**

### ◆ Applicable Models

---

The option can be used with the drive models in [Table E.1](#).

**Table E.1 Applicable Models**

Drive Series	Drive Model Number	Software Version <1>
A1000	CIMR-A□2A□□□□	VSA901017 to VSA901099
	CIMR-A□4A□□□□	

<1> See “PRG” on the drive nameplate for the software version number.



## 3 Software Parts

### ◆ NOID - Network Option Interface Driver

This section explains communication sequences provided by the SI-ES3 option to startup and control the drive.

Functionality provided:

- Startup/initialization of option with the drive.
- Option and drive compatibility/acceptance management.
- Process data parameter (register) mapping.
- Drive <--> Option re-initialization management (remap of process data).
- MEMOBUS channel.
- Error management.
- Drive <- -> Option basic control response data in Online-DRV mode.
- Drive <- -> Option operation mode.

### ■ Drive/Option Identification Information

This section specifies the option/drive specific identification information exchanged during power-up state of the application driver.

**Table E.2 Drive/Option Identification Information**

Setting	Value	Description
Option model code	0x53455333	Option mode code, 4-digot ASCII string. Value: SES3=0x53455333 Used by drive to identify what kind of option that is mounted.
Option software version	DEC: 24201	Last 5 decimal digits of decimal option firmware revision. Def: VST9242zz VST9 = A1000 option card 2 = European product 42 = Product code zz = Minor revision
Drive model codes	ALL	Drive model codes accepted by option NOID driver. If the provided drive model code does not match the list the option will raise the OFx31 drive error. Option will accept any drive model code.

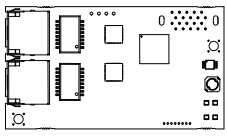


# 4 Receiving

Please perform the following tasks after receiving the EtherCAT® Option:


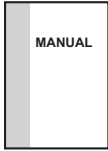
- Inspect the EtherCAT® Option for damage.  
If the EtherCAT® Option appears damaged upon receipt, contact the shipper immediately.
- Verify receipt of the correct model by checking the information on the PCB (see [Figure E.2](#)).
- If you have received the wrong model or the EtherCAT® Option does not function properly, contact your supplier.

### ◆ Contents and Packaging

**Table E.3 Option Package Contents**

Description:	Option Card	Ground Cable	Screws (M3)
			
<b>Quantity:</b>	1	1	3

**Table E.4 Option Package Contents (cont'd)**

Description:	LED Label	Installation Manual
		
<b>Quantity:</b>	1	1

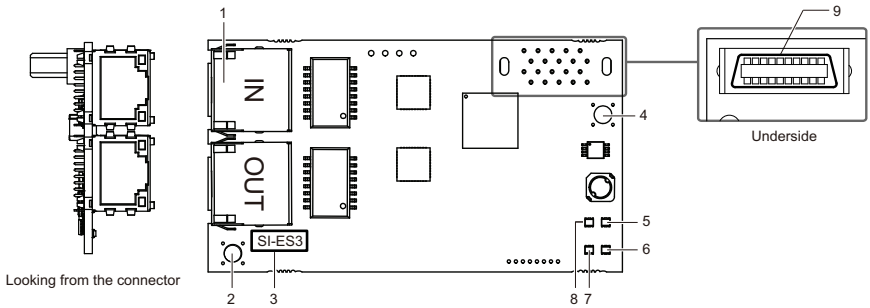
### ◆ Tool Requirements

A Phillips screwdriver PH1(#1) or PH2(#2) is required to install the EtherCAT® option.

**Note:** Tools required to prepare EtherCAT® cables for wiring are not listed in this manual.

## 5 EtherCAT® Option Components

### ◆ EtherCAT® Option



- |  |                     |
|--|---------------------|
| 1 – Communication cable connector (RJ45) | 5 – LED (RUN)       |
| 2 – Ground terminal (installation hole)  | 6 – LED (ERR)       |
| 3 – Model number                         | 7 – LED (L/A OUT)   |
| 4 – Installation hole                    | 8 – LED (L/A IN)    |
|  | 9 – Connector (CN5) |

#### Option Card

*Refer to EtherCAT® Option Status LEDs on page 12 for details on the LEDs.*

## 5 EtherCAT® Option Components

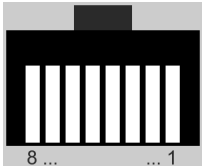
---

### ◆ Communication connector

---

The EtherCAT® Option is connected to the network using a RJ45 connector. The pin assignment is explained in [Table E.5](#).

**Table E.5 Communication connector (RJ45)**

EtherCAT® Connector	Pin	Signal	Description
	1	TD+	Send data
	2	TD-	
	3	RD+	Receive data
	4	–	N.C. (Pins denoted as N.C. do not connect to any signal)
	5	–	N.C. (Pins denoted as N.C. do not connect to any signal)
	6	RD-	Receive data
	7	–	N.C. (Pins denoted as N.C. do not connect to any signal)
	8	–	N.C. (Pins denoted as N.C. do not connect to any signal)
Housing	–	Shield	

### ◆ EtherCAT® Option Status LEDs

---

The EtherCAT® Option has four LEDs that indicate the communication status. The indications conform with DS303, Part 3: Indicator Specification.

#### ■ LEDs L/A OUT and L/A IN: Ethernet Link/Activity 1 and 2

The Link/Activity indicators show the status of the physical link and show activity on the link period

#### ■ RUN LED

A green lit EtherCAT® RUN LED indicates the status of the EtherCAT® network state machine.

A red lit EtherCAT® RUN LED is only used by the NOID firmware loader, refer to [Table E.6](#).

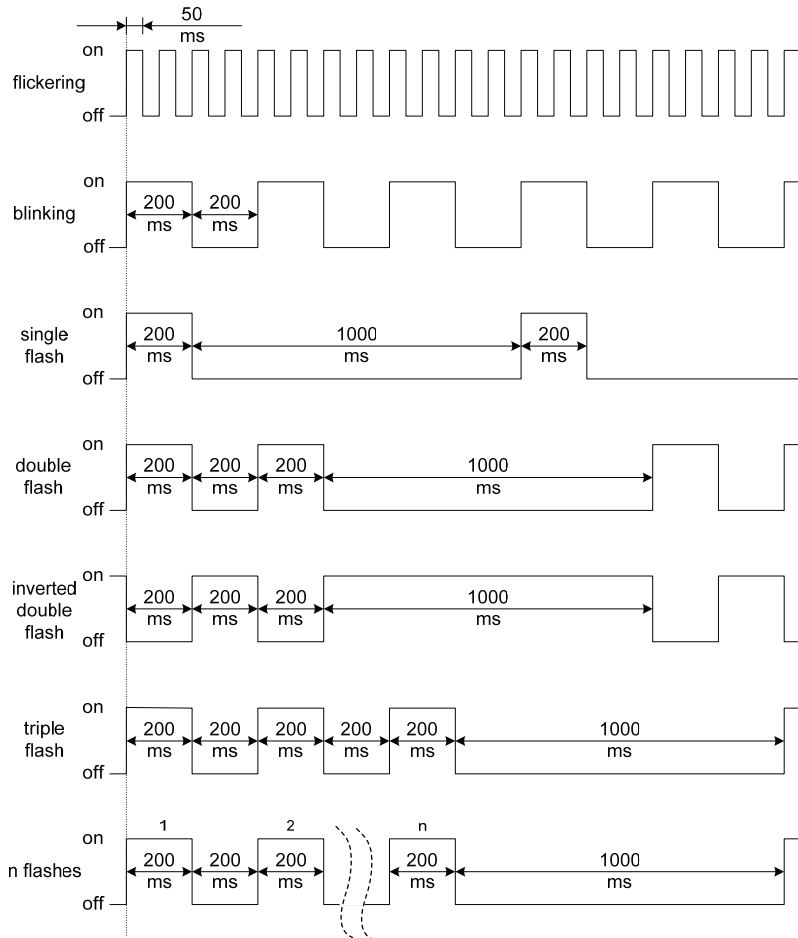
#### ■ EtherCAT® ERROR indicator

The red EtherCAT® error LED indicates the presence of any errors.

**Table E.6 UNDERSTANDING THE STATUS LEDS**

LED	Color	Display	Meaning
Link Activity 1/2	-	Continuously Off	No link. The communication cable is not physically connected. The EtherCAT® controller is not started up.
	Green	Continuously On	The module is connected to Ethernet. A communication cable is physically connected, but no data are being exchanged.
		Flickering	There is traffic on Ethernet, data are being exchanged
RUN	-	Continuously Off	The device is in Init state
	Green	Blinking	The device is in Pre-Operational State (flashing rate about 2.5 Hz)
		Single flash	The device is in Safe-Operational State (one short flash (approximately 200 ms) followed by a long off condition (approximately 1000 ms))
		Continuously On	The device is in Operational State
	Red	Blinking (1 Hz or 6 Hz)	The Option BOOT or APP firmware is executing the NOID firmware loader. 1 Hz: Firmware loader protocol in IDLE state (waiting for commands from the drive) 6 Hz: Firmware loader protocol is processing commands.
ERR	Red	Continuously Off	No link. The EtherCAT® communication is in working condition.
		Blinking	General configuration error
		Single flash	The slave device application has changed the EtherCAT® state autonomously: The parameter "Change" in the AL status register is set to 0x01: change/error. Single flash is one short flash (approximately 200 ms) followed by a long off phase (approximately 1000 ms).
		Double flash	The sync manager watchdog timeout has occurred. Double flash is two short flashes (approximately 200 ms each), separated by an off condition (approximately 200 ms), and then a long off phase (approximately 1000 ms)
		Continuously On	Possible causes: 1. An EtherCAT® PDI (Process Data Interface) error has occurred, the NOID application interface has failed. 2. An option card FATAL event has occurred (system has stalled execution, see EtherCAT® vendor object 0x4000 for the cause).
		Blinking (1 Hz or 6 Hz)	The option BOOT or APP firmware is executing the NOID firmware loader. 1Hz: Firmware loader protocol in IDLE state (waiting for commands from drive) 6Hz: Firmware loader protocol is processing commands.

Figure E.3 explains the indicator flash rates.



### LED Flash Rates and Meaning

### ◆ DSP402 functionality

---

This part manages the DSP402 drive profile functionality in the option and converts the control/status data into drive specific control/status data.

### ◆ Vendor specific CANopen objects

---

This part integrates the vendor specific CANopen object model into EtherCAT®.

### ◆ Error management

---

This part processes drive and EtherCAT® specific errors and assures that all faults process and propagate properly to the drive/EtherCAT® network.

### ◆ EtherCAT® processing stack

---

The "EtherCAT® Slave example code" from the EtherCAT® technology group (ETG) is used as a main base in this project. It is internally adopted to fit the product.

# 6 Installation Procedure

### ◆ Section Safety

#### DANGER

##### Electric Shock Hazard

**Power to the drive must be shut off when installing this option card.**

Even though the power has been shut off, voltage still remains in the drive's DC bus. Wait before removing the front cover once the drive has been turned off.

The CHARGE light on the drive will go out after voltage in the DC bus drops below 50 V, at which point it is safe to remove the front cover.

Due to the risk of electric shock, be sure that all LEDs have gone out and that the DC bus voltage has reached a safe level prior to performing any work on the drive.

#### WARNING

##### Electrical Shock Hazard

**Do not remove the front cover of the drive while the power is on.**

Failure to comply could result in death or serious injury.

The diagrams in this section may include drives without covers or safety shields to show details. Be sure to reinstall covers or shields before operating any devices. The option board should be used according to the instructions described in this manual.

**Do not allow unqualified personnel to use equipment.**

Failure to comply could result in death or serious injury.

Maintenance, inspection, and replacement of parts must be performed only by authorized personnel familiar with installation, adjustment, and maintenance of this product.

**Do not touch the option card while the power supply to the drive is switched on.**

Failure to comply could result in death or serious injury.

**Do not use damaged wires, place excessive stress on wiring, or damage the wire insulation.**

Failure to comply could result in death or serious injury.

#### NOTICE

##### Damage to Equipment

**Observe proper electrostatic discharge procedures (ESD) when handling the option card, drive, and circuit boards.**

Failure to comply may result in ESD damage to circuitry.

**Never shut the power off while the drive is outputting voltage.**

Failure to comply may cause the application to operate incorrectly or damage the drive.



### NOTICE

**Do not operate damaged equipment.**

Failure to comply may cause further damage to the equipment.

Do not connect or operate any equipment with visible damage or missing parts.

**Tighten all terminal screws to the specified tightening torque.**

Loose electrical connections could result in death or serious injury by fire due to overheating of electrical connections.

**Do not use unshielded cable for control wiring.**

Failure to comply may cause electrical interference resulting in poor system performance.

Use shielded twisted-pair wires and ground the shield to the ground terminal of the drive.

**Properly connect all pins and connectors.**

Failure to comply may prevent proper operation and possibly damage equipment.

**Check wiring to ensure that all connections are correct after installing the option card and connecting any other devices.**

Failure to comply may result in damage to the option card.

## 6 Installation Procedure

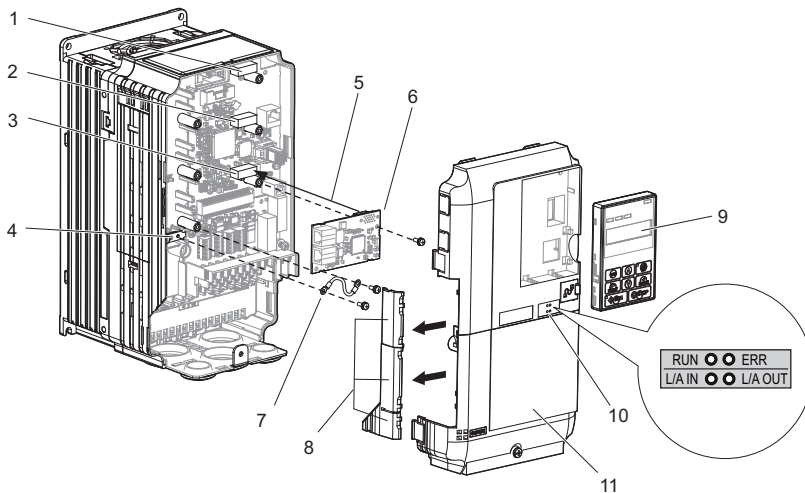
### ◆ Prior to Installing the Option Card

Prior to installing the EtherCAT® Option, wire the drive and make necessary connections to the drive terminals. For more information on wiring and connecting the drive, refer to the manual packaged with the drive. Verify that the drive runs normally without the option installed.

### ◆ Installing the Option

1. Shut off power to the drive, wait the appropriate amount of time for voltage to dissipate, then remove the operator (I) and front cover (K). Refer to the drive manual for direction on removing the front cover.
2. Insert the CN5 connector on the option (E) into the CN5-A connector on the drive (C), then fasten it into place using one of the screws included with the option. Connect the ground wire (G) to the ground terminal (D) using one of the screws provided with the option.

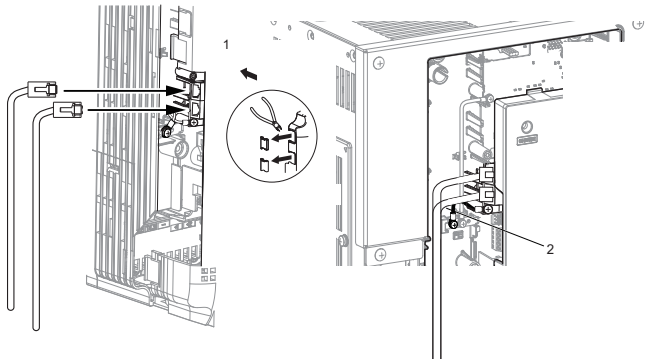
**Note:** There are only two screw holes on the drive for ground terminals. If three option cards are connected, two of the ground wires will need to share the same ground terminal.



- |                                   |   |
|-----------------------------------|---|
| 1 – Connector CN5-C               | 7 – Ground wire   |
| 2 – Connector CN5-B               | 8 – Use with cutters to create an opening for cable lines |
| 3 – Connector CN5-A               | 9 – Operator  |
| 4 – Drive grounding terminal (FE) | 10 – LED label  |
| 5 – Insert connector CN5 here     | 11 – Front cover  |
| 6 – Option card                   |   |

### Installing the Option Card

- Prepare RJ45 network cable connectors.  
In the drives CIMR-A□2A0004 to 0040 and 4A0002 to 0023 the network cable must be routed to the outside through the drive top cover. Use a pair of diagonal cutters to cut out the perforated openings at the left side of the top cover. Make sure no sharp edges that can damage the cable remain. Drives 2A0056 to 0211, and 4A0031 to 0165 have enough space to keep all wiring inside the unit.



- |  |  |
|--|--|
| 1 – Opening for network cables<br>(CIMR-A□2A0004 to 0040,<br>4A0002 to 0023) | 2 – Space for wiring<br>(CIMR-A□2A0056 to 0211,<br>4A0031 to 0165) |
|--|--|

### Wiring Routing

- Plug in the RJ45 network cable connector into the option.
  - Reinstall the front cover back onto the drive as it was before.
- Note:**
- Take care when wiring the option card so that the front cover easily fits back onto the drive.
  - Install Cable Cover option to maintain the drive Enclosure Type integrity.

## 6 Installation Procedure

---

6. Attach the LED label (J) packaged with the option as shown in *Figure E.4*.
7. Switch on the drive power supply.  
An “Aer” Alarm message indicating that the node address is set to 0 will appear on the drive display. Set the node address in parameter F6-35. Set the communication speed in parameter F6-36.
8. Cycle the power supply to activate the changed settings. Installation complete.

### ◆ Communication Cable Specifications

---

To ensure proper performance, YASKAWA recommends using EtherCAT® dedicated Cat5e communication cables.

### ◆ Network Termination

---

The EtherCAT® network does not require a termination resistor if the drive is the last node in the network. Network termination is realized by the ASIC of the EtherCAT® option card.

### ◆ ESI File

---

For easy network implementation of drives equipped with an EtherCAT® Option, the ESI file can be obtained from:

Europe: <http://www.yaskawa.eu.com>

Japan: <http://www.e-mechatronics.com>

USA: <http://www.yaskawa.com>

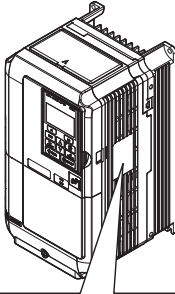
Other areas: contact a YASKAWA representative








### ◆ Identification of Drive Firmware Version

1. Read out firmware version from drive digital operator.

Check monitor parameter U1-25 when the drive is switched ON. The display shows the last four digits of the firmware version and the value should be in the range of 1017 ~ 1099.

2. Verifying firmware version on drive nameplate



		Normal Duty Amps / Heavy Duty Amps	
AC drive model	MODEL : CIMR-AC2A0021FAA		
Input specifications	MAX APPLI. MOTOR : 5.5kW / 3.7kW REV : A		
Output specifications	INPUT : AC3PH 200-240V 50/60Hz 24A/18.9A	IND. CONT.EQ. 7J48 B	Firmware version
	OUTPUT : AC3PH 0-240V 0-400Hz 21A/17.5A		
Lot number	MASS : 3.5 kg		
Serial number	O / N :		
	S / N :		
			
	FILE NO : E131457 IP20		
	TYPE 1 ENCLOSURE		Enclosure type
			

### Verifying firmware version on drive nameplate

# 7 EtherCAT® Option Related Drive Parameters

The drive parameters listed in [Table E.7](#) have influence on some functions of the SI-ES3 option card. Check these parameters before starting network communications.

**Table E.7 Parameter Settings**

No.	Name	Description	Default
b1-01 <1>	Frequency Reference Selection	Selects the frequency reference input source 0: Operator - Digital preset speed d1-01 to d1-17 1: Terminals - Analog input terminals 2: MEMOBUS/Modbus communications 3: Option card 4: Pulse Input (Terminal RP)	<6>
b1-02 <1>	Run Command Selection	Selects the run command input source 0: Digital Operator - RUN and STOP keys 1: Digital input terminals S□ 2: MEMOBUS/Modbus communications 3: Option card	1
E2-04 <2>	Motor 1 Motor Poles	Set the number of motor poles described on the motor nameplate. 2 to 48	4
F6-01	Operation Selection after Communications Error	Determines drive response when a bUS error is detected during communications with the EtherCAT® Option 0: Ramp to Stop 1: Coast to Stop 2: Fast-Stop 3: Alarm Only <3>	1
F6-02	External Fault Detection Conditions (EF0)	Sets the condition for external fault detection (EF0) 0: Always detected 1: Detected only during operation	0
F6-03	Stopping Method for External Fault from Communication Option Board	Determines drive response for external fault input (EF0) detection during EtherCAT® communication 0: Ramp to Stop 1: Coast to Stop 2: Fast-Stop 3: Alarm Only <3>	1
F6-06 <4>	Torque Reference/Torque Limit selection from Communications Option	0: Torque reference/torque limit via network communications are disabled. 1: Torque reference/torque limit via network communications are enabled. <5>	0
F6-07	NetRef/ComRef Selection Function	0: Multi-step speed reference disabled (F7 mode) 1: Multi-step speed reference allowed (V7 mode)	0

## 7 EtherCAT® Option Related Drive Parameters

No.	Name	Description	Default
F6-08	Reset Communication Related Parameters	<p>Determines if communication-related parameters are set back to their original default values when the drive is initialized.</p> <p>0: Do not reset F6-□□ and F7-□□ parameters when the drive is initialized using parameter A1-03.</p> <p>1: Rest F6-□□ and F7-□□ parameters when the drive is initialized using parameter A1-03.</p> <p><b>Note:</b> Setting this parameter does not affect communication-related parameters. Setting this parameter only determines if communication-related parameters (F6-□□ and F7-□□) are also reset when A1-03 is used to initialize the drive.</p>	0
o1-03 <7>	Digital Operator Display Selection	<p>Sets the units to display the frequency reference and output frequency.</p> <p>0: 0.01 Hz</p> <p>1: 0.01% (100% = E1-04)</p> <p>2: r/min (enter the number of motor poles to E2-04/E4-04/E5-04)</p> <p>3: User defined by parameters o1-10 and o1-11</p>	<6>

- <1> To start and stop the drive from an EtherCAT® master device using serial communications, set b1-02 to 3. To control the frequency reference of the drive via the master device, set b1-01 to 3.
- <2> E2-04 is necessary to set up when the Drive Profile DSP402 objects are used.
- <3> If set to 3, then the drive will continue to operate when an EF0 fault is detected. Take proper safety measures, such as installing an emergency stop switch.
- <4> This parameter might not appear in certain drives. Furthermore its availability is limited to depending on the control mode selection. For details refer to the technical manual for the drive the option card is used with.
- <5> If the drive is set to receive the torque reference/limit from the network (F6-06 = 1) make sure the value is set appropriately by the controller. If no torque reference/limit value is entered the motor will not produce torque.
- <6> The default value depends on the drive used and/or the drive software version. For details refer to the technical manual for the drive.
- <7> Changing o1-03 changes the units for input object 2010 (Hex) (frequency reference), output object 2110 (Hex) (output frequency) and 2200 (Hex) (motor speed). Furthermore o1-03 must be set to 2 and E2-04 must be set to the correct value in order to use the Drive Profile DSP402.

# 8 Object Dictionary

## ◆ Object Dictionary Overview

---

The Object Dictionary consists of three sections:

- Communication Profile Objects
- Manufacturer Specific Profile Objects
- Drive and Motion Profile Objects

The tables below give an overview of the communication objects available in the SI-ES3 option. Refer to the page references given for further details on each object.

## ■ Communication Profile Objects (DSP 301)

Index (Hex)	Name
1000	Device Type
1001	Error Register
1003	Pre-defined Error Field
1008	Manufacturer Device Name
1009	Manufacturer Hardware Version
100A	Manufacturer Software Version
1010	Store Parameters
1011	Restore Default Parameters
1018	Identity Object
1600 - 1628	Receive PDO Mapping
1A00 - 1A28	Tranmit PDO mapping
1C00	Sync Manager Communication Type
1C12	Sync Manager RxPDO assign
1C13	Sync Manager TxPDO assign



## ■ Manufacturer Specific Profile Objects (DS 301)

Index (Hex)		Content
Input	2000	Operation Command
	2010	Speed Command
	2020	Torque Limit
	2030	Torque Compensation
	2040	MEMOBUS/Modbus Read Command
	2050	MEMOBUS/Modbus Write Command
	2060	MEMOBUS/Modbus Unlimited Enter Command
	2070	MEMOBUS/Modbus Limited Enter Command
	2080	Selectable (default: none)
	2090	Selectable (default: none)
	20A0	Selectable (default: none)
	20B0	Selectable (default: none)
	20C0	Selectable (default: none)
	20D0	FM analog output 1
	20E0	AM analog output 2
	20F0	Multi-function DO output
	3000	Selectable (default: none)
3100	Selectable (default: none)	
Output	2100	Drive Status
	2110	Output Frequency
	2120	Output Current
	2130	Output Torque
	2140	MEMOBUS/Modbus Read Command Response
	2150	MEMOBUS/Modbus Write Command Response
	2155	PDO Parameter Write Response
	2160	MEMOBUS/Modbus Not Limited Enter Command Response
	2180	Selectable (default: Input terminal status)
	2190	Selectable (default: Analog input 1 monitor)
	21A0	Selectable (default: none)
	21B0	Selectable (default: none)
	21C0	Selectable (default: none)
	21E0	Selectable (default: none)
	21D0	Selectable (default: none)
	21F0	Selectable (default: none)
	2200	Motor Speed
	2210	DC Bus Voltage
	2220	Analog input monitor A1
	2240	Analog input monitor A2
	2260	Analog input monitor A3
	2270	Inverter DI Input
	4000	Option NVS FATAL Record
4001	Option Info + Status Record	

## 8 Object Dictionary

---

### ■ Drives and Motion Profile Objects (DSP 402)

Object Type	Index (Hex)	Name
Common Entries	60FD	Digital Inputs
	60FE	Digital Outputs
Device Control	6040	Controlword
	6041	Statusword
	6060	Modes of operation
	6061	Modes of operation display
Velocity Mode	6042	v1 target velocity
	6043	v1 velocity demand
	6044	v1 control effort
	6046	v1 velocity min max amount
	6048	v1 velocity acceleration
	6049	v1 velocity deceleration
	604A	v1 velocity quick stop
	604C	v1 dimension factor
604D	v1 pole number	

# 9 Process Data Objects (PDO)

PDOs (Process Data Object) will be used for I/O exchange. PDOs are mapped to objects during configuration (PRE-OPERATIONAL state).

TxPDOs are used to transfer data from the option card and RxPDOs are used to transfer data to the option card.

The module supports at least 8 parameters mapped to RxPDO and 8 parameters mapped to TxPDO.

### ◆ PDOs and Default PDO Setup

The drive supports 15 Receive and 16 Transmit PDOs. The tables below show available PDOs, their default settings and the objects required to set up when changing the PDO configuration or the PDO mapping.

#### ■ Transmit PDOs (TxPDO)

The Transmit PDOs have a default mapping according to the table below. The transmit PDOs can be re-mapped by the end user by writing to map objects 0x1A00-0x1A28, please see [page 24](#).

PDO number	Transmit PDO Mapping	
	Mapped objects (Hex)	Index (Hex)
1	Sub-index 1: 0x6041#0, 2-bytes (DSP402 status word)	0x1A00
2	Sub-index 1: 0x6041#0, 2-bytes (DSP402 status word)	0x1A01
	Sub-index 2: 0x6061#0, 2-bytes, (DSP402 Modes of operation display)	
6	Sub-index 1: 0x6041#0, 2-bytes (DSP402 status word)	0x1A05
	Sub-index 2: 0x6044#0, 2-bytes, (v1 control effort)	
7	Sub-index 1: 0x6041#0, 2-bytes (DSP402 status word)	0x1A06
	Sub-index 2: 0x60FD#0, 4-bytes, (Digital inputs)	
21	Sub-index 1: 0x6042#0, 2-bytes (v1 target velocity)	0x1A14
22	Sub-index 1: 0x6043#0, 2-bytes (v1 velocity demand)	0x1A15
23	Sub-index 1: 0x6048#1, 4-bytes (v1 Accel delta speed)	0x1A16
	Sub-index 2: 0x6048#2, 2-bytes, (v1 Accel delta time)	
24	Sub-index 1: 0x6049#1, 4-bytes (v1 Decel delta speed)	0x1A17
	Sub-index 2: 0x6049#2, 2-bytes, (v1 Decel delta time)	
25	Sub-index 1: 0x604A#1, 4-bytes (v1 quick-stop delta speed)	0x1A18
	Sub-index 2: 0x604A#2, 2-bytes, (v1 quick-stop delta time)	
26	Sub-index 1: 0x604C#1, 4-bytes (v1 Dimension factor)	0x1A19
	Sub-index 2: 0x604C#2, 4-bytes, (v1 Dimension factor)	
36	Sub-index 1: 0x2100#1, 2-bytes (Drive status)	0x1A23
37	Sub-index 1: 0x2110#1, 2-bytes (Output frequency)	0x1A24
38	Sub-index 1: 0x2120#1, 2-bytes (Output current)	0x1A25
39	Sub-index 1: 0x2130#1, 2-bytes (Output torque reference)	0x1A26
40	Sub-index 1: 0x2140#1, 2-bytes (MEMOBUS/Modbus read response)	0x1A27
41	Sub-index 1: 0x2150#1, 2-bytes (MEMOBUS/Modbus write response)	0x1A28

## 9 Process Data Objects (PDO)

### ■ Receive PDOs (RxPDO)

The Receive PDOs have a default mapping according to the table below. The end user can re-map Receive PDOs by writing to the map objects 0x1600-1628, refer to n Communication Profile Objects (DSP 301).

PDO number	Receive PDO Mapping	
	Mapped objects (Hex)	Index (Hex)
1	Sub-index 1: 0x6040#0, 2-bytes (DSP402 control word)	0x1600
2	Sub-index 1: 0x6040#0, 2-bytes (DSP402 control word) Sub-index 2: 0x6060#0, 1-bytes, (DSP402 Modes of operation)	0x1601
6	Sub-index 1: 0x6040#0, 2-bytes (DSP402 control word) Sub-index 2: 0x6042#0, 2-bytes, (v1 target velocity)	0x1605
7	Sub-index 1: 0x6040#0, 2-bytes (DSP402 control word) Sub-index 2: 0x60FE#1, 4-bytes, (Physical digital outputs)	0x1606
8	Sub-index 1: 0x6040#0, 2-bytes (DSP402 control word) Sub-index 2: 0x6060#0, 1-bytes, (DSP402 Modes of operation)	0x1607
21	Sub-index 1: 0x6048#1, 4-bytes (v1 Accel delta speed) Sub-index 2: 0x6048#2, 2-bytes, (v1 Accel delta time)	0x1614
22	Sub-index 1: 0x6049#1, 4-bytes (v1 Decel delta speed) Sub-index 2: 0x6049#2, 2-bytes, (v1 Decel delta time)	0x1615
23	Sub-index 1: 0x604A#1, 4-bytes (v1 quick-stop delta speed) Sub-index 2: 0x604A#2, 2-bytes, (v1 quick-stop delta time)	0x1616
24	Sub-index 1: 0x604C#1, 4-bytes (v1 Dimension factor) Sub-index 2: 0x604C#2, 4-bytes, (v1 Dimension factor)	0x1617
36	Sub-index 1: 0x2000#1, 2-bytes (Operation command)	0x1623
37	Sub-index 1: 0x2010#1, 2-bytes (Speed reference/limit)	0x1624
38	Sub-index 1: 0x2020#1, 2-bytes (Torque reference/limit)	0x1625
39	Sub-index 1: 0x2030#1, 2-bytes (Torque compensation)	0x1626
40	Sub-index 1: 0x2040#1, 4-bytes (MEMOBUS/Modbus read request)	0x1627
41	Sub-index 1: 0x2050#1, 4-bytes (MEMOBUS/Modbus write request)	0x1628

## 10 Fault Diagnosis and Possible Solutions

### ◆ EtherCAT® Option Card Error Codes

The following error codes will be shown in object 1003, subindex 01 if the correspondent error occurred on the drive.

#### ■ Inverter and CANopen/EtherCAT® Faults

##### ■ Emergency Object (EMCY)

The emergency object is used for sending fault information from the communication module to the CANopen/EtherCAT® network.

The emergency object is triggered by a fault event from the host or the option card itself. An emergency object is transmitted only once per 'error event'.

Emergency error codes are specified for a number of events. Emergency word specification:

**Table E.8 Emergency Word Specification**

Byte	0	1	2	3	4	5	6	7
Content	Emergency error code	Error register object 0x1001	Manufacturer specific error info. Not used. Set to zero.					

##### ■ Emergency Messages, DSP301 & DSP402

The error codes specified in the list below can be read from CANopen object 0x1003 (Pre-defined error field)

**Table E.9 Error Codes**

Error Code (Hex)	Meaning	Drive Display	INVR:0x0080 Enum Value
0000	No error	No error	0x00
3220	DC bus undervoltage	Uv1	0x02
5200	Control power supply undervoltage	Uv2	0x03
3221	DC bus charging circuit fault	Uv3	0x04
2330	Ground fault	GF	0x06
2220	Over current	oC	0x07
3210	DC bus overvoltage	ov	0x08
4280	Heatsink overheat	oH	0x09
4210	Heatsink overheat	oH1	0x0A

## 10 Fault Diagnosis and Possible Solutions

Error Code (Hex)	Meaning	Drive Display	INVR:0x0080 Enum Value
2310	Motor overload	oL1	0x0B
2221	Drive overload	oL2	0x0C
2311	Overtorque detection 1	oL3	0x0D
2312	Overtorque detection 2	oL4	0x0E
5420	Braking transistor fault	rr	0x0F
4410	Internal braking resistor overheat	rHI	0x10
5441	External fault 3	EF3	0x11
5442	External fault 4	EF4	0x12
5443	External fault 5	EF5	0x13
5444	External fault 6	EF6	0x14
5445	External fault 7	EF7	0x15
5480	External fault 8	EF8	0x16
FF17	Cooling FAN fault	FAn	0x17
7180	Motor over speed (control mode using PG)	oS	0x18
8321	Speed deviation (control mode using PG)	dEv	0x19
7305	PG fault (control mode using PG)	PGo	0x1A
3130	Input phase loss	PF	0x1B
3300	Output phase loss	LF	0x1C
FF01	Motor overheat alarm	oH3	0x1D
5300	Digital operator disconnected	oPr	0x1E
5530	EEPROM error	Err	0x1F
4310	Motor overheat (PTC input)	oH4	0x20
FF08	MEMOBUS/Modbus Error	CE	0x21
FF07	BUS error	bUS	0x22
FF06	Control fault	CF	0x25
8313	Zero servo fault	SvE	0x26
5481	Fault input from option card	EF0	0x27
FF02	PID feedback lost	FbL	0x28
FF03	Undertorque detected 1	UL3	0x29
FF04	Undertorque detected 2	UL4	0x2A
FF05	High slip braking OL	oL7	0x2B
6000	Hardware fault DPRAM	CPSDPRAM	0x30
FF31	Intermediary voltage fault	VCF	0x31
FF32	Z-phase pulse fall detection (Closed Loop Vector for PM motors)	dv1	0x32

## 10 Fault Diagnosis and Possible Solutions

Error Code (Hex)	Meaning	Drive Display	INVR:0x0080 Enum Value
FF33	Z-phase noise fault detection (Closed Loop Vector for PM motors)	dv2	0x33
FF34	Inversion detection (Closed Loop Vector for PM motors)	dv3	0x34
FF35	Inversion prevention detection (Closed Loop Vector for PM motors)	dv4	0x35
FF36	Output current imbalance	LF2	0x36
FF37	Pullout detection 2	STo	0x37
FF38	PG Disconnect	PGo	0x38
FF3B	Too many speed search restarts	SEr	0x3B
FF41	PID feedback loss	FbH	0x41
FF0D	External fault at input terminal S1	EF1	0x42
FF0E	External fault at input terminal S2	EF2	0x43
FF44	Mechanical weakening detection 1	oL5	0x44
FF45	Mechanical weakening detection 2	UL5	0x45
FF46	Current offset fault	CoF	0x46
FF47	Programming Error 1	PE1	0x47
FF49	Current offset fault	dWFL	0x49
6301	Error during object content selection	-	-

### ◆ SDO Abort Codes

SDO abort codes are supported as specified in DS301. Additionally the abort codes listed below are implemented.

**Table E.10 SDO Abort Codes**

SDO Abort Code	Description
0602 0010 (Hex)	Consecutive MEMOBUS/Modbus Read/Write/Enter commands are sent but the wait time between messages is too short.
	A MEMOBUS/Modbus Read or Write Response (2140 (Hex) and 2150 (Hex)) was attempted but no or an incorrect MEMOBUS/Modbus address has been written to object 2040 (Hex) or 2050 (Hex) before.
	A MEMOBUS/Modbus write request has been sent during DC bus under voltage.
0602 0022 (Hex)	Drive Profile DSP402 is used and a value is written to object 6042 (Hex) (v1 Target Velocity) while the drive status is not "Operation Enable".
	Object 2155 (Hex) is tried to be read while the SI-ES3 option is not in "Operational" state.
	A MEMOBUS/Modbus Read or Write command (2040 (Hex) and 2050 (Hex)) was performed with an invalid MEMOBUS/Modbus address.

## 10 Fault Diagnosis and Possible Solutions

---

### ◆ Drive-Side Error Codes

---

Drive-side error codes appear on the drive's digital operator. Causes of the errors and corrective actions are listed in [Table E.11](#) and [Table E.9](#). For additional error codes, refer to the technical manual for the drive.

The bUS (EtherCAT® Option Communication Error) and EF0 (External Fault Input from the EtherCAT® Option) may appear as an alarm or a fault. If they occur as an alarm, the "ALM" LED on the drive digital operator will blink and the alarm code will flash in the display. When these occur as a fault, the "ALM" LED will light and the display will show the fault code.

If communication stops while the drive is running, check the following items:

- Is the EtherCAT® Option properly installed?
- Is the communication line properly connected to the EtherCAT® Option? Is it loose?
- Is the controller program working? Has the controller CPU stopped?
- Did a momentary power loss interrupt communications?



## ■ Faults

**Table E.11** lists possible faults when using a communication option. The drive's fault contact will close if one of these faults occur.

**Table E.11 Fault Display and Possible Solutions**

Digital Operator Display		Fault Name
<i>bUS</i>	bUS	EtherCAT® Option Communication Error
		After establishing initial communication, the connection was lost. Only detected when the run command or frequency reference is assigned to the option (b1-01=3 or b1-02=3).
Cause		Possible Solution
Master controller (PLC) has stopped communicating.		Check for faulty wiring. ⇒ Correct any wiring problems.
Communication cable is not connected properly.		
A data error occurred due to noise.		Check the various options available to minimize the effects of noise. ⇒ Take steps to counteract noise in the control circuit wiring, main circuit lines, and ground wiring. ⇒ If a magnetic contactor is identified as a source of noise, install a surge absorber to the contactor coil. ⇒ Make sure the cable used fulfills the EtherCAT® requirements. Ground the shield on the controller side and on the EtherCAT® Option side.
EtherCAT® Option is damaged.		⇒ If there are no problems with the wiring and the error continues to occur, replace the EtherCAT® Option.

Digital Operator Display		Fault Name
<i>EFO</i>	EFO	External Fault Input from EtherCAT Option
		The alarm function for an external device has been triggered.
Cause		Possible Solution
An external fault is being sent from the upper controller (PLC).		⇒ Remove the cause of the external fault. ⇒ Reset the external fault input from the upper controller (PLC) device.
Problem with the upper controller (PLC) program.		⇒ Check the program used by the upper controller (PLC) and make the appropriate corrections.

Digital Operator Display		Fault Name
<i>oFR00</i>	oFA00	EtherCAT Option Card Fault
		The drive does not support the option board plugged in.
Cause		Possible Solution
Non-compatible option connected to the drive.		⇒ Check the drive option board compatibility. Replace the option card if the fault persists even though the drive should support it.

## 10 Fault Diagnosis and Possible Solutions

Digital Operator Display		Fault Name
oFA01	oFA01	EtherCAT Option Card Fault
		Option card is not properly connected.
Cause		Possible Solution
Problem with the connectors between the drive and EtherCAT® Option.		⇒ Turn the power off and check the connectors between the drive and EtherCAT® Option.

Digital Operator Display		Fault Name
oFA30 to oFA43	oFA30 to oFA43	EtherCAT Option Card Fault
		Communication ID error
Cause		Possible Solution
Option card hardware fault		⇒ Replace the EtherCAT® Option. Contact YASKAWA for assistance.

Digital Operator Display		Fault Name
oFb00	oFb00	Option Card Fault at Connector CN5-B
		Non-compatible option card is connected.
Cause		Possible Solution
The EtherCAT® option card has been plugged into option port CN5-B.		⇒ Always use option port CN5-A for communication option cards.

Digital Operator Display		Fault Name
oFb02	oFb02	Option Card Fault at Connector CN5-B
		Two of the same option cards are connected at the same time.
Cause		Possible Solution
Two or more input option cards (analog, digital or communication) have been connected to the drive at the same time.		⇒ Use either an analog input option AI-A3 or a digital input option DI-A3 or a communication option card. Never use two of these cards at the same time.

Digital Operator Display		Fault Name
oFc00	oFc00	Option Card Fault at Connector CN5-C
		Non-compatible option card is connected.
Cause		Possible Solution
The EtherCAT® option card has been plugged into option port CN5-C.		⇒ Always use option port CN5-A for communication option cards.

Digital Operator Display		Fault Name
oFc02	oFc02	Option Card Fault at Connector CN5-C
		Two of the same option cards are connected at the same time.
Cause		Possible Solution
Two or more input option cards (analog, digital or communication) have been connected to the drive at the same time.		⇒ Use either an analog input option AI-A3 or a digital input option DI-A3 or a communication option card. Never use two of these cards at the same time.

## ■ Option board error management

This section describes the errors managed by the option board and the linked actions taken.

**Table E.12 Option Board Error Management**

Option Error	Description	Error Indication	Possible Solution
OP→SAFEOP/PREOP when Drive running	When an EtherCAT state transition from OP → SAFEOP/PREOP was made when the drive was in OPERATION enabled.	BUS error is triggered in drive.  Note: Error against drive will be cleared when the next lower to higher EtherCAT state transition is made.	<ul style="list-style-type: none"> <li>• Check and correct state machine transitions in control word.</li> </ul>
OP→SAFEOP 1. EtherCAT WD timeout	If the EtherCAT watchdog timeout is enabled (Default in native XML description file) and output data from PLC to the drive isn't updated in time an error will be triggered	BUS error is triggered in drive.  Note: Error against drive will be cleared when the next lower to higher EtherCAT state transition is made.	<ul style="list-style-type: none"> <li>• Check network connection (e.g. if cables plugged in at each node)</li> <li>• Check telegram timing. Are telegrams sent to the slave the error occurred on?</li> </ul>
OP→SAFEOP 1. Drive FCS error 2. Drive COMID error	1. Drive has detected a Sum check error 2. Drive has detected a Communication Option ID error Possible cause: 1. Option card is overloaded. 2. Option is not properly processing the state.	1. Drive fault: OFx32 2. Drive fault: OFx30	1+2 Actions: a. Disable process data OUT sync manager channel b. Force EtherCAT state change to SAFE_OP
OP→SAFEOP 1. Option card FCS error 2. Option card COMID error	1. Option card has detected a Sum check error 2. Option card has detected a Communication Option card ID error Possible cause: 1. Drive system is overloaded. 2. Drive is not properly processing the state.	1. Drive fault: OFx32 2. Drive fault: OFx30	1+2 Actions: a. Disable process data IN sync manager channel b. Force EtherCAT state change to SAFE_OP

## 10 Fault Diagnosis and Possible Solutions

Option Error	Description	Error Indication	Possible Solution
Initial power-up sequence not completed within 10 seconds	<p>Possible cause:</p> <p>Drive is not processing the internal interface protocol.</p> <p>Drive does not support EtherCAT option card</p>	<p>Drive fault: OFx00</p> <p>Option will log FATAL event record in NVS memory and set ERR LED: solid RED, see <a href="#">Table E.6</a></p>	<p>Actions:</p> <ol style="list-style-type: none"> <li>1. Check drive firmware version as described on <a href="#">page 21</a>.</li> <li>2. If drive firmware version is correct, replace option card.</li> <li>3. Replace the drive.</li> </ol>
I/F proc timeout	<p>Option card has not processed any drive system frames in 1000 ms.</p> <p>Possible cause:</p> <p>Drive has stopped serving the internal interface to option card or HW failure.</p>	<p>Option will log FATAL event record in NVS memory, and set ERR LED: solid RED, see <a href="#">Table E.6</a></p>	<ul style="list-style-type: none"> <li>• Force EtherCAT state to INIT</li> </ul>
Option ID Error: Power-up sequence copyright string mismatch.	<p>Drive reported invalid copyright string in power-up process</p>	<p>Option will log FATAL event record in NVS memory, and set ERR LED: solid RED, see <a href="#">Table E.6</a></p>	<ul style="list-style-type: none"> <li>• Replace option card</li> </ul>

### ■ Minor Faults and Alarms

Table 6 lists up alarms that might occur during operation using a communication option board. If a multi function digital output of the drive is programmed for H2-□□ = 10, the output will close if these alarms occur.

Digital Operator Display		Minor Fault Name
<i>CALL</i>	CALL	Serial Communication Transmission Error
		Communication has not yet been established.
Cause		Possible Solution
Communication wiring is faulty, there is a short circuit, or something is not connected properly.		Check for wiring errors. ⇒ Correct the wiring. ⇒ Remove and ground shorts and reconnect loose wires.
Programming error on the master side		⇒ Check communications at start-up and correct programming errors.
Communication circuitry is damaged.		⇒ Replace the drive if the fault continues to occur.

Digital Operator Display		Minor Fault Name
<i>EEP</i>	EEP	EEPROM Error
		EEPROM checksum error
Cause		Possible Solution
Communication wiring is faulty, there is a short circuit, or something is not connected properly.		Check for wiring errors. ⇒ Correct the wiring. ⇒ Remove and ground shorts and reconnect loose wires.
EEPROM checksum error		If these errors occur, the object dictionary will be reset to its default values. ⇒ After the object dictionary has been changed and object dictionary contents are then changed, execute a Store Parameter command (Index = 1010 (Hex)). ⇒ If the object dictionary has not been changed, execute a Restore Parameter command (Index = 1011 (Hex)).

## 11 Specifications

### ◆ Specifications

**Table E.13 Option Card Specifications**

Items	Specifications
Model	SI-ES3
Communication Profile	DS 301 Ver. 4.02 DSP 402 Ver. 1.1 Velocity Mode
Connector	RJ45 connector
Communications Speed	10/100 MBbps
Ambient Temperature	-10 °C to +50 °C
Humidity	up to 95% RH (no condensation)
Storage Temperature	-20 °C to +60 °C (allowed for short-term transport of the product)
Area of Use	Indoor (free of corrosive gas, airborne particles, etc.)
Altitude	up to 1000 m

### ◆ Internal Scan Cycle

A1000: 1 ms

### ◆ Revision History

The revision dates and the numbers of the revised manuals appear on the bottom of the back cover.

MANUAL NO. YEU TOEP C710616 99A

Published in Germany

July 2011

11-7

Date of  
publication

Date of original  
publication

Date of Publication	Revision Number	Section	Revised Content
July 2011	-	-	First Edition



# YASKAWA AC Drive A1000 Option

## EtherCAT® Installation Manual

### DRIVE CENTER (INVERTER PLANT)

2-13-1, Nishimiyaichi, Yukuhashi, Fukuoka, 824-8511, Japan  
Phone: 81-930-25-3844 Fax: 81-930-25-4369  
<http://www.yaskawa.co.jp>

### YASKAWA ELECTRIC CORPORATION

New Pier Takeshiba South Tower, 1-16-1, Kaigan, Minatoku, Tokyo, 105-6891, Japan  
Phone: 81-3-5402-4502 Fax: 81-3-5402-4580  
<http://www.yaskawa.co.jp>

### YASKAWA AMERICA, INC.

2121 Norman Drive South, Waukegan, IL 60085, U.S.A.  
Phone: (800) YASKAWA (927-5292) or 1-847-887-7000 Fax: 1-847-887-7310  
<http://www.yaskawa.com>

### YASKAWA ELÉTRICO DO BRASIL LTDA.

Avenda Fagundes Filho, 620 Bairro Saude, São Paulo, SP04304-000, Brasil  
Phone: 55-11-3585-1100 Fax: 55-11-5581-8795  
<http://www.yaskawa.com.br>

### YASKAWA EUROPE GmbH

Hauptstrasse 185, 65760 Eschborn, Germany  
Phone: 49-6196-569-300 Fax: 49-6196-569-398  
<http://www.yaskawa.eu.com>

### YASKAWA ELECTRIC UK LTD.

1 Hunt Hill Orchardton Woods, Cumbernauld, G68 9LF, United Kingdom  
Phone: 44-1236-735000 Fax: 44-1236-458182  
<http://www.yaskawa.co.uk>

### YASKAWA ELECTRIC KOREA CORPORATION

7F, Doore Bldg. 24, Yeoido-dong, Yeoungdongpo-gu, Seoul, 150-877, Korea  
Phone: 82-2-784-7844 Fax: 82-2-784-8495  
<http://www.yaskawa.co.kr>

### YASKAWA ELECTRIC (SINGAPORE) PTE. LTD.

151 Lorong Chuan, #04-01, New Tech Park, 556741, Singapore  
Phone: 65-6282-3003 Fax: 65-6289-3003  
<http://www.yaskawa.com.sg>

### YASKAWA ELECTRIC (SHANGHAI) CO., LTD.

No. 18 Xizang Zhong Road, 17F, Harbour Ring Plaza, Shanghai, 200001, China  
Phone: 86-21-5385-2200 Fax: 86-21-5385-3299  
<http://www.yaskawa.com.cn>

### YASKAWA ELECTRIC (SHANGHAI) CO., LTD. BEIJING OFFICE

Room 1011, Tower W3 Oriental Plaza, No. 1 East Chang An Ave.,  
Dong Cheng District, Beijing, 100738, China  
Phone: 86-10-8518-4086 Fax: 86-10-8518-4082

### YASKAWA ELECTRIC TAIWAN CORPORATION

9F, 16, Nanking E. Rd., Sec. 3, Taipei, 104, Taiwan  
Phone: 886-2-2502-5003 Fax: 886-2-2505-1280



YASKAWA Europe GmbH

In the event that the end user of this product is to be the military and said product is to be employed in any weapons systems or the manufacture thereof, the export will fall under the relevant regulations as stipulated in the Foreign Exchange and Foreign Trade Regulations. Therefore, be sure to follow all procedures and submit all relevant documentation according to any and all rules, regulations and laws that may apply. Specifications are subject to change without notice for ongoing product modifications and improvements.

© 2011 YASKAWA Europe GmbH. All rights reserved.

MANUAL NO. YEU TOEP C710616 99A

Published in Germany July 2011 11-7