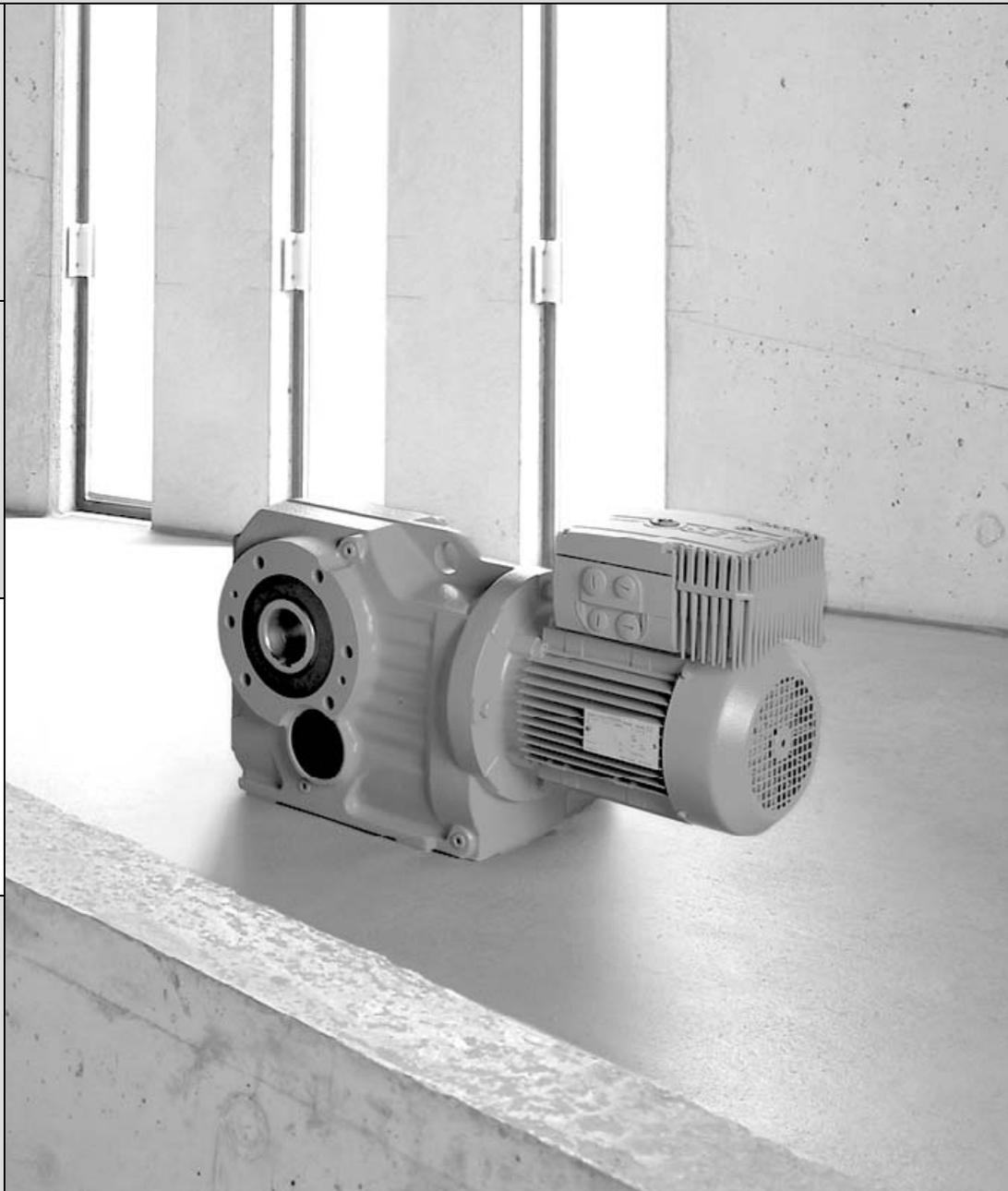
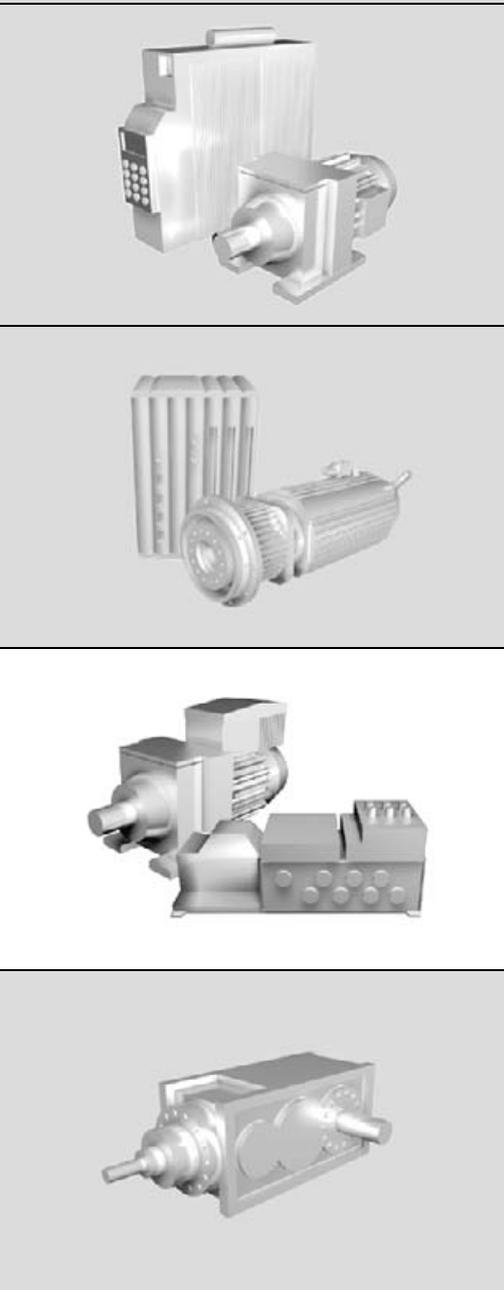




SEW
EURODRIVE

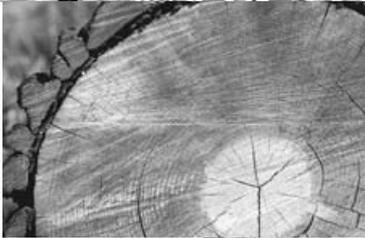


MOVIMOT[®] Table Positioning

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Manual





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1 Important Notes



- **This manual does not replace the detailed operating instructions!**
- **Only electrical specialists are allowed to perform installation and startup observing applicable accident prevention regulations and the MOVIMOT® operating instructions!**

Documentation

- Read through this manual carefully before you commence installation and startup of MOVIMOT® with this application module.
- This manual assumes that the user has access to and is familiar with the following MOVIMOT® documentation:
 - Drive System for Decentralized Installation system manual
 - MOVIMOT® operating instructions
 - "PROFIBUS Interfaces and Field Distributors", "InterBus Interfaces and Field Distributors" or "DeviceNet/CANopen Interfaces and Field Distributors" manual (depending on the bus system used).
- A requirement of fault-free operation and fulfillment of any rights to claim under guarantee is that you observe the information in the documentation.

Safety and warning notes

Always observe the safety and warning instructions contained in this publication!



Electrical hazard

Possible consequences: Severe or fatal injuries.



Hazard

Possible consequences: Severe or fatal injuries.



Hazardous situation

Possible consequences: Slight or minor injuries.



Harmful situation

Possible consequences: Damage to the unit and the environment.



Tips and useful information.



2 System Description

2.1 Application areas

Table positioning for the MQ.. fieldbus interfaces is particularly suited to the materials handling and logistics industries:

Application examples:

- Carriages
- Transverse carriages
- Gantries

Table positioning for MQ.. fieldbus interfaces offers the following advantages:

- User-friendly operator interface
- You only have to set the parameters required for table positioning and bus operation (ratios, speeds, diameters, bus parameters)
- You are guided through the process of setting the parameters which removes the need for complicated programming
- Monitor mode for optimum diagnosis
- You do not need any programming experience
- Rapid familiarization with the system
- 32 table positions can be defined and selected via a fieldbus



3 Project Planning

3.1 Prerequisites

PC and software Table positioning for MQ.. fieldbus interfaces has been implemented as an IPOS^{plus} program and forms part of the SEW MOVITOOLS software package. To use MOVITOOLS, you must have a PC with one of the following operating systems: Windows[®] 95, Windows[®] 98, Windows[®] 2000, Windows NT[®] 4.0 or Windows[®] XP.

**MOVIMOT[®],
fieldbus interface
and encoder**

Table positioning is performed with MOVIMOT[®] and an MQ.. fieldbus interface. You must select the MQ.. module depending on the bus type you want to use.

The system needs a corresponding position detection system for positioning. This is provided by the NV26 proximity sensor. The corresponding evaluation circuitry is contained in the MQ.. module. In this case, the two proximity switches of the NV26 proximity sensor system are connected to binary inputs DI0 and DI1. The evaluation electronics in the MQ.. module provide a position value that can be read from the H511 variable. The proximity switches must be connected so the value in H511 increases when the motor turns clockwise.

Variable H511 can be read as follows:

- Start MOVITOOLS
- Choose "MQx" as the device type
- Choose "Shell" from the [Execute Program] section
- Then choose [Display] / [IPOS Information] from the menu



3.2 Functional description

The "Table Positioning for MQ.." application offers the following functional characteristics:

- 32 table positions can be defined and selected.
- The travel speed can be selected as required for each positioning movement.

Operating modes

The functions are implemented with four operating modes:

- **Jog mode**
 - CW or CCW direction of rotation via two virtual binary inputs
 - Choice of two speeds (rapid speed and slow speed for fine positioning) via a virtual binary input
- **Teach mode**
 - Movement can be performed to every single position in jog mode and then stored in teach mode
- **Reference mode**
 - Reference travel is started with a start command at a virtual binary input. Reference travel establishes the reference point (**machine zero**) for absolute positioning operations
- **Automatic mode**
 - Selecting the target position using five virtual binary inputs (binary coded)
 - Checkback of the selected target position at the start of movement using five virtual binary outputs (binary coded)
 - Confirmation that the selected position has been reached via virtual binary output "Target position reached"



3.3 Scaling of the drive

Calculating conversion factors for user units

You can have the scaling factors calculated automatically as part of the startup procedure of table positioning for MQ... To do this, you have to enter the following data:

- Diameter of the drive wheel or the spindle pitch.
- Gear unit ratio (i gear unit)
- Additional gear ratio (i additional gear)

The pulses/distance scaling factor [inc/mm] is then calculated using the following formula:

$$\text{Pulses} = 24 \times i_{\text{gear unit}} \times i_{\text{additional gear}}$$

$$\text{Distance} = \pi \times d_{\text{drive wheel}} \text{ OR } s_{\text{spindle pitch}}$$

You can also enter the pulses/distance directly. If you enter a unit other than millimeters [mm] as the travel unit, this user travel unit is also used for the reference offset and the table positions.

3.4 Reference cam and machine zero

Note the following points during project planning:

- You can enter a reference offset during startup of the table positioning if you do not want the machine zero (= reference point for table positioning) to be located on the reference position.
- The following formula applies: Machine zero = Reference position + Reference offset
This way, you can alter the machine zero without having to move the reference cam.

3.5 Special features of reference travel

Note the following points during project planning of the reference travel:

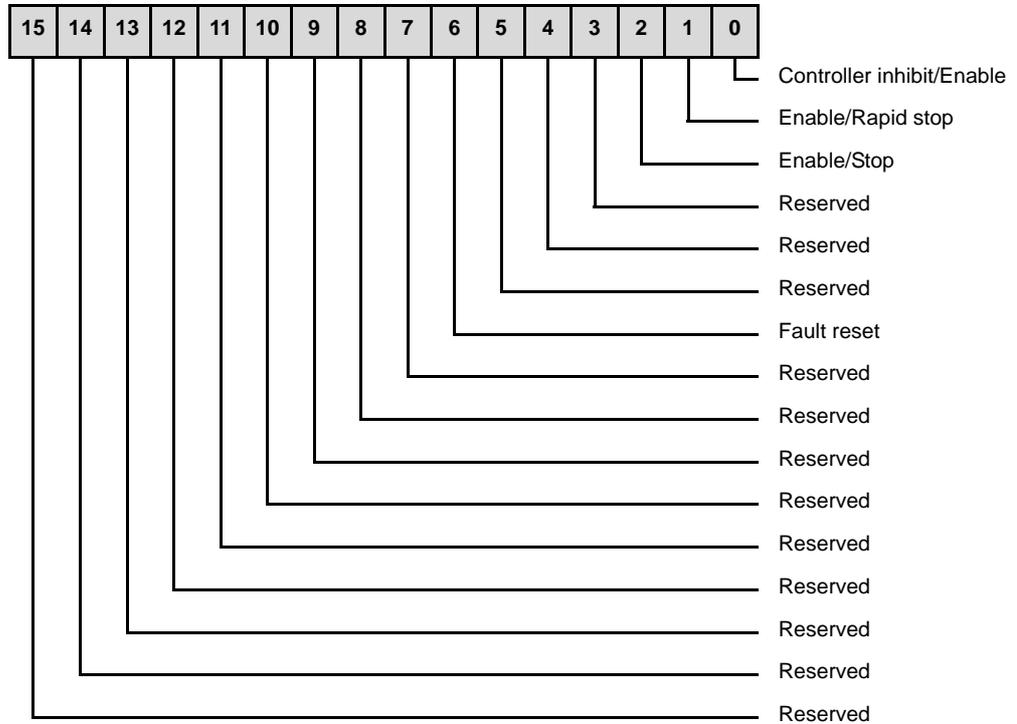
Reference travel to reference cam

Reference travel takes place to the falling edge of the reference cam. This means the accuracy of the reference position depends on the switching accuracy of the reference cam.

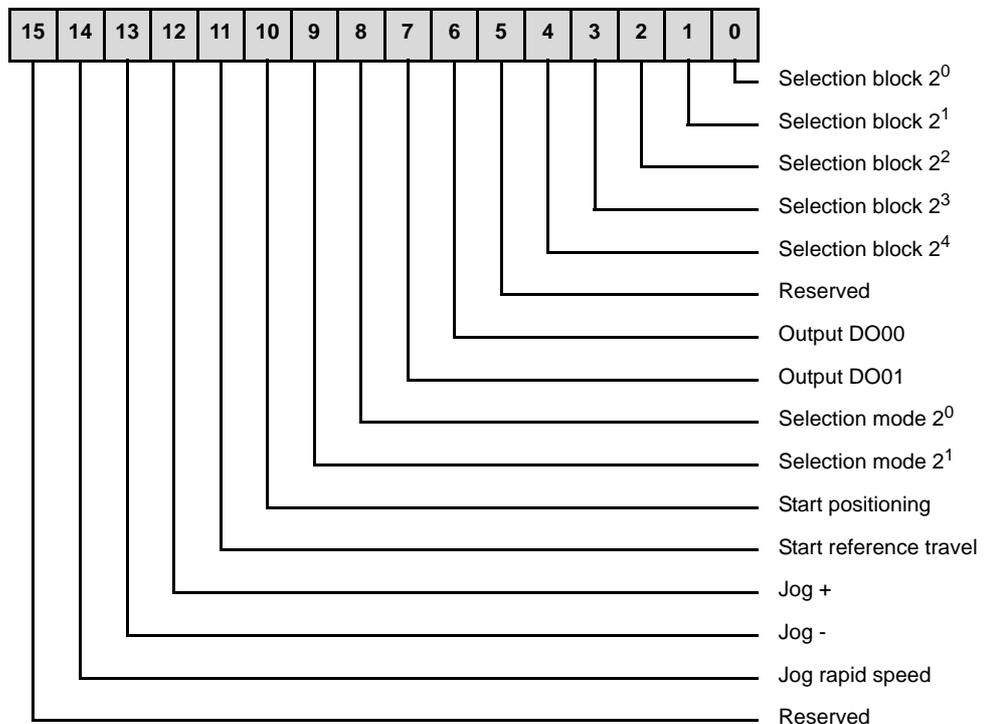


3.6 Assignment of process data

Process output data PO1



Process output data PO2

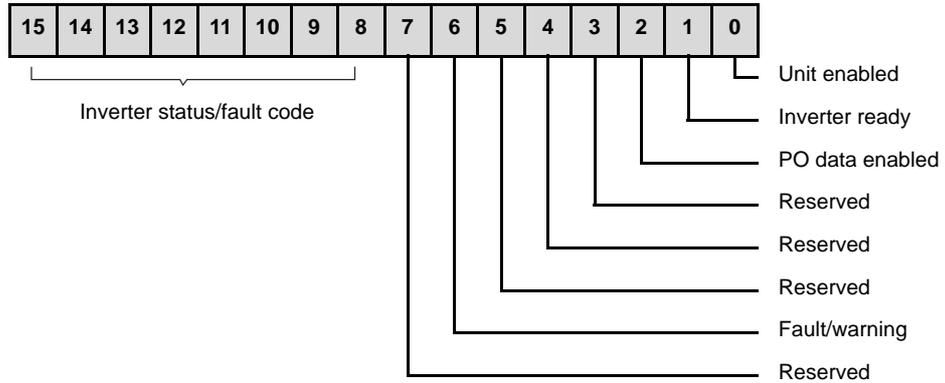




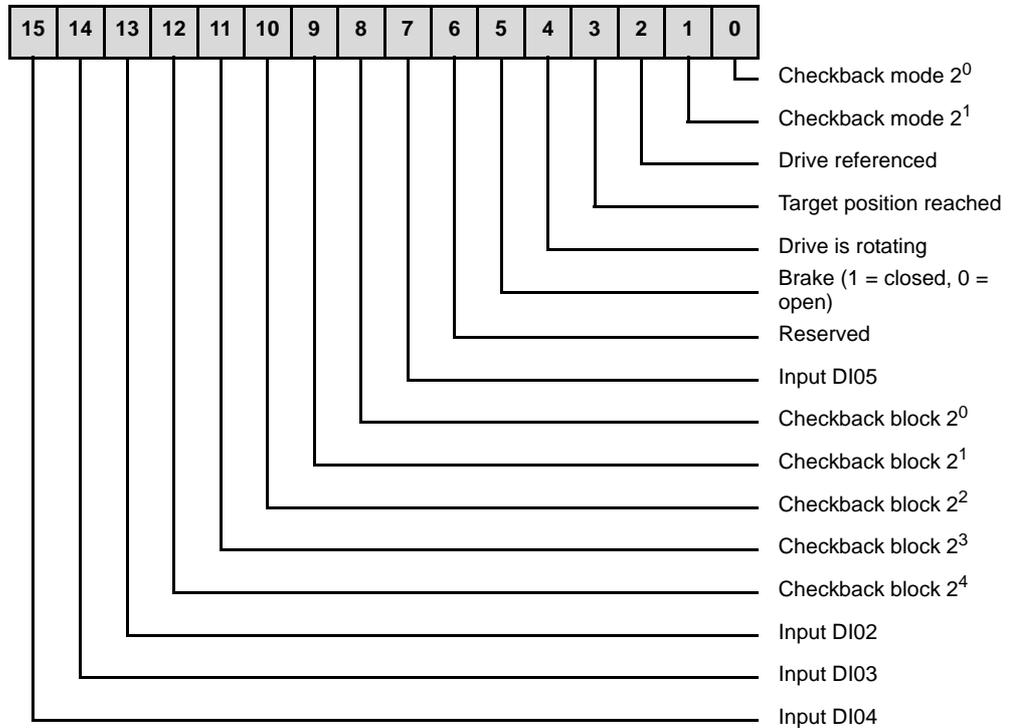
Project Planning

Assignment of process data

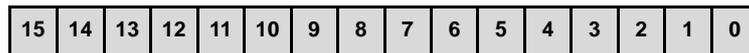
Process input data PI1



Process input data PI2



Process input data PI3



As required:
 Actual position [increments]
 Output current [% I_N]



4 Installation

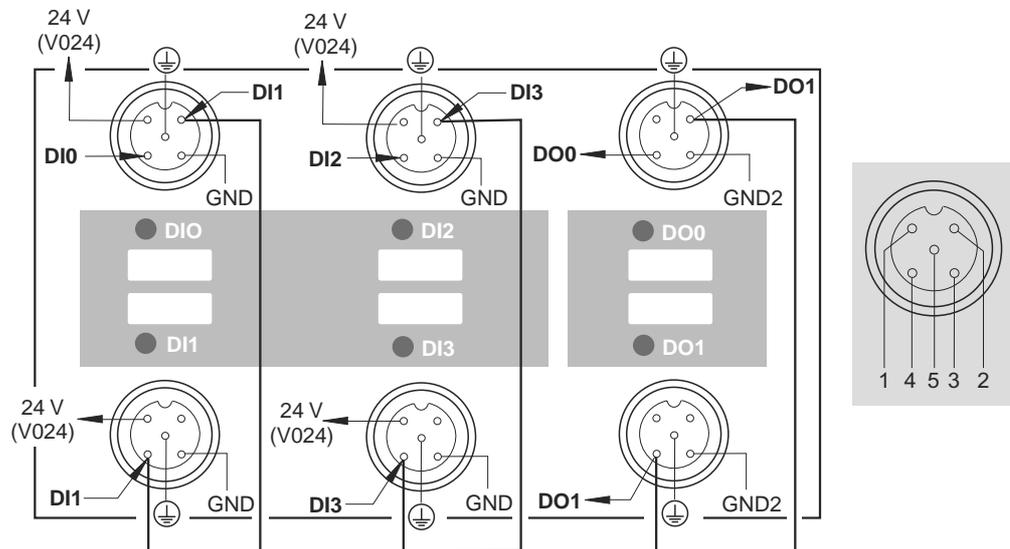
4.1 Connecting MOVIMOT® and the fieldbus interface/fieldbus distributor

Install the MOVIMOT® drive and selected fieldbus interface/field distributor as described in the relevant documentation.

- "Drive System for Decentralized Installation" system manual
- MOVIMOT® operating instructions
- PROFIBUS Interfaces, Field Distributors manual
- InterBus Interfaces, Field Distributors manual
- DeviceNet/CANopen Interfaces, Field Distributors manual

4.2 Connecting inputs/outputs of the fieldbus interfaces

**MQP22, MQI22,
MQD22**



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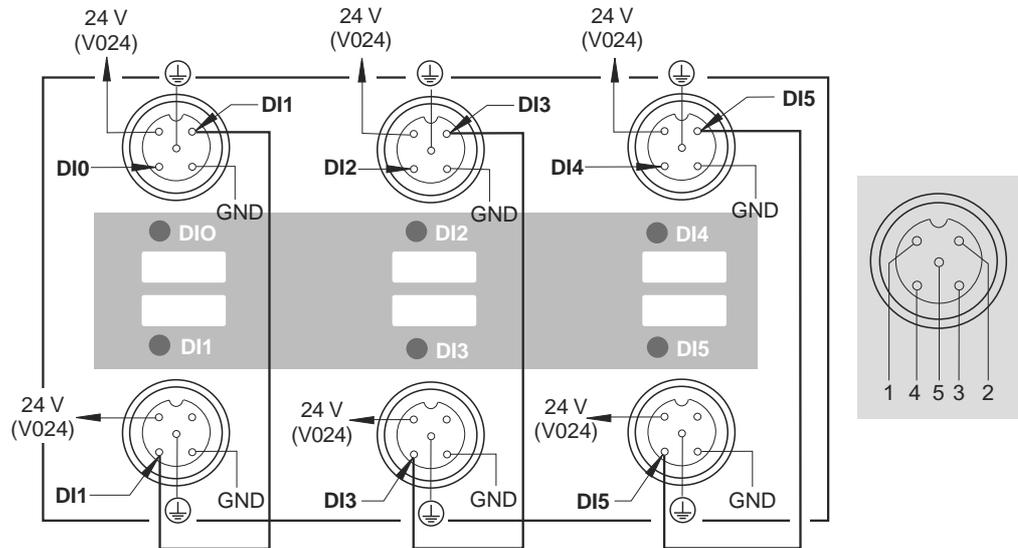
Input/output		Assignment
Input	DI0	Proximity sensor 1
	DI1	Proximity sensor 2
	DI2	Reference cam (if reference type 3 or 4 has been selected)
	DI3	Unassigned
Output	DO0	Unassigned
	DO1	Unassigned



Installation

Connecting inputs/outputs of the fieldbus interfaces

**MQP32, MQI32,
MQD32**



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Input	Assignment
DI0	Proximity sensor 1
DI1	Proximity sensor 2
DI2	Reference cam (if reference type 3 or 4 has been selected)
DI3	Unassigned
DI4	Unassigned
DI5	Unassigned

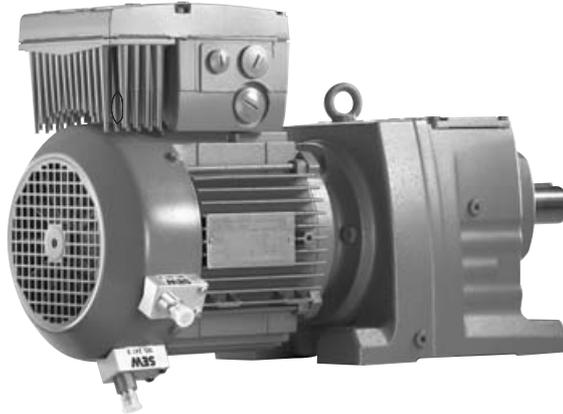


4.3 Connecting the NV26 proximity sensor

Features

The NV26 proximity sensor offers the following features:

- 2 sensors with 6 pulses/revolution
- 24 increments/revolution with 4-fold evaluation
- Encoder monitoring and evaluation is possible with MQ..



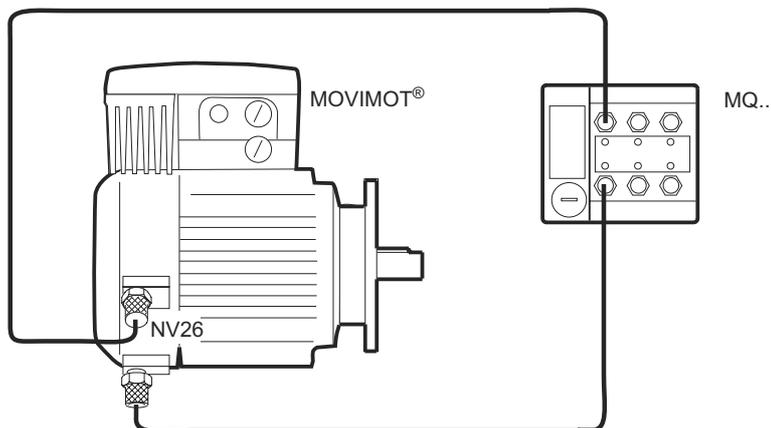
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There must be a 45° angle between the sensors.

Connection

- Use a shielded M12 cable to connect the NV26 proximity sensor to the DI0 and DI1 inputs of the MQ.. fieldbus interface



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- The current position can be checked by reading variable H511 (ActPosMot).
- SEW-EURODRIVE recommends activating the encoder monitoring function using parameter P504 "Encoder monitoring motor".



5 Startup

5.1 General information

Correct project planning and installation are the prerequisites for successful startup. For detailed project planning information, refer to the "Drive Systems for Decentralized Installation" system manual.

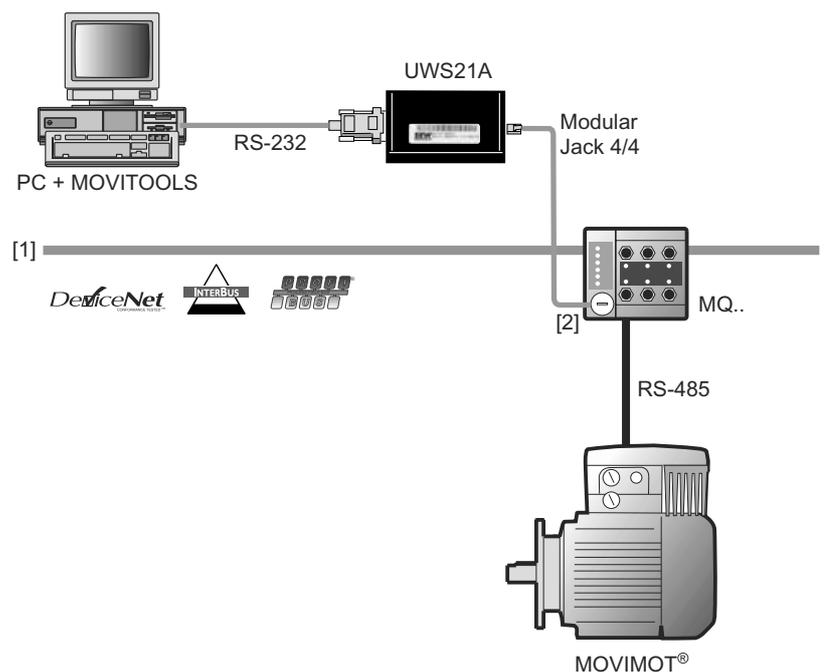
Check the installation and the connection of the proximity sensor on the basis of the installation notes in this manual and the following documentation:

- "Drive System for Decentralized Installation" system manual
- MOVIMOT® operating instructions
- PROFIBUS Interfaces, Field Distributors manual
- InterBus Interfaces, Field Distributors manual
- DeviceNet/CANopen Interfaces, Field Distributors manual

5.2 Preliminary work

Perform the following steps before startup:

- Connect the MQ.. fieldbus interface to the PC via the serial interface (see the following illustration)



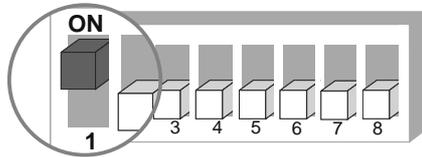
- [1] Fieldbus
[2] Diagnostic interface

- Install the SEW MOVITOOLS software®
- Start "MOVITOOLS/Shell"



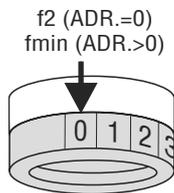
5.3 Settings on MOVIMOT®

1. Check that MOVIMOT® has been connected correctly (see the section "Installation").
2. Set DIP switch S1/1 (on MOVIMOT®) to ON (= Address 1):



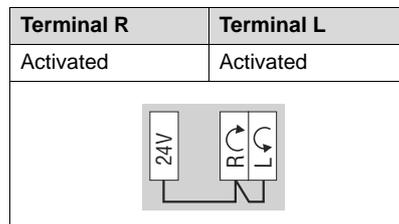
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3. Set switch f2 to "0":

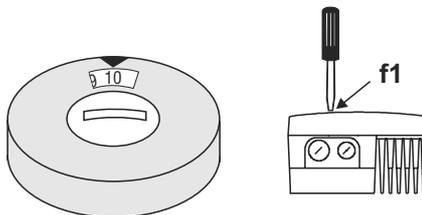


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4. Enable both directions of rotation on MOVIMOT®:



5. Put on the connection box cover and screw it into place.
6. Set the setpoint potentiometer f1 to "10":



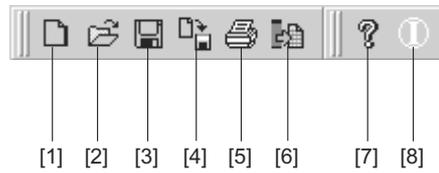
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7. Make sure the retaining screw of the cover has a seal and reinstall it.



5.4 The menu bar

The following figure displays the menu bar in the startup window of the bus positioning:



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Symbol	Meaning	
[1]	New file	All parameters are set to the default values
[2]	Open file	All parameters are read out from the selected file
[3]	Save file	All parameters are stored in the current file
[4]	Save file as	All parameters are stored in a file. You have a free choice of filename.
[5]	Print file	Print the parameter list
[6]	Upload	All parameters are read from the inverter
[7]	Help	Calls up the help function
[8]	Info	Displays the version information

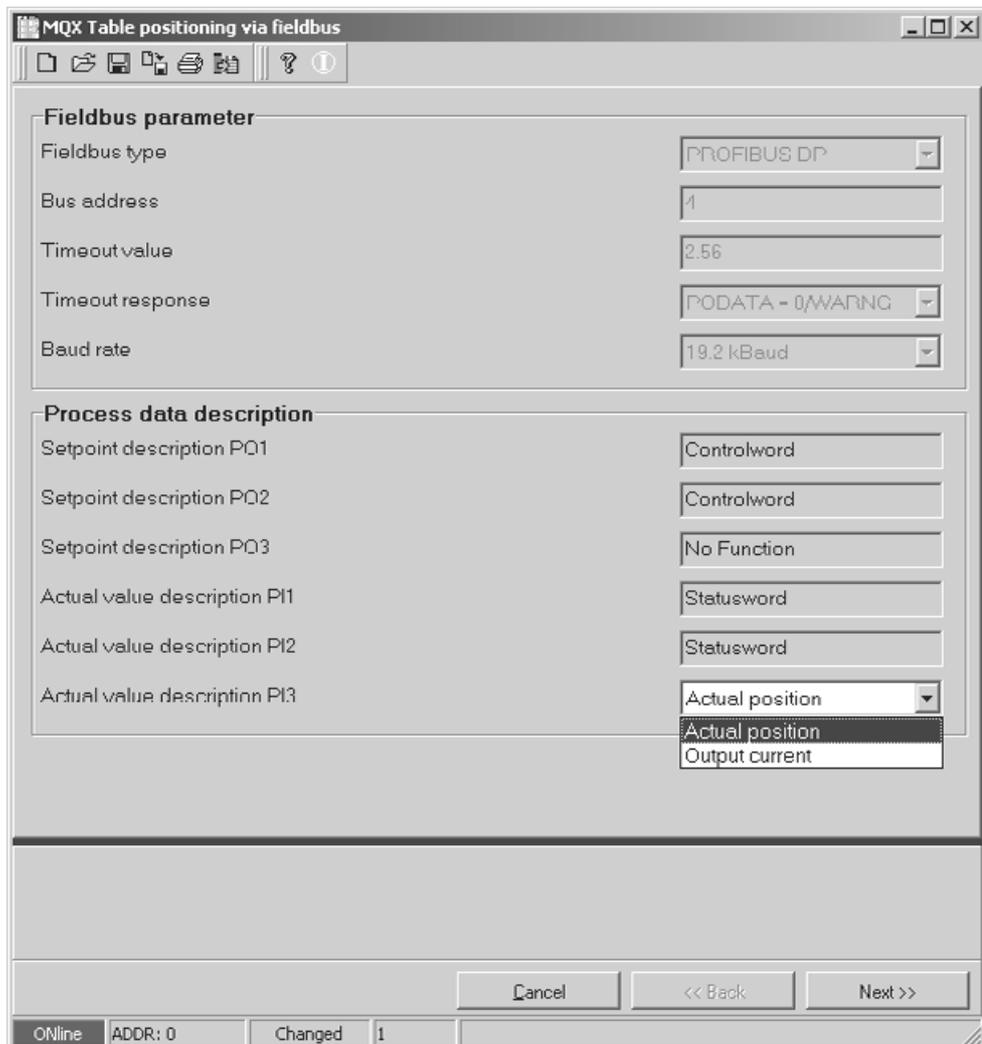


5.5 Setting the fieldbus parameters

The window for setting the fieldbus parameters appears if the table positioning for the MQ.. program is started for the first time.

You have to make the following settings in this window:

- Define the process data description for PI 3
 - You can choose from: "Actual position" or "Output current"



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5.6 Entering the default settings

In this window you have to set the scaling factors for the distance.

Calculating the scaling factors

In this input screen, the numerator/denominator factor is calculated for the conversion to user travel units.. The following entries have to be made for this:

- Diameter of the drive wheel in the unit "mm"
- Gear unit ratio
- Additional gear ratio

The numerator/denominator factor is calculated automatically when you press the [Calculation] button.

You can also calculate the numerator/denominator factor using the following formula:

$$\text{Pulses} = 24 \times i_{\text{gear unit}} \times i_{\text{additional gear}}$$

$$\text{Distance} = \pi \times d_{\text{drive wheel}} \text{ or } s_{\text{spindle pitch}}$$



Entering the reference travel parameters

- Enter the reference offset
- Enter the reference travel type

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Reference travel type		
Type 3		<ul style="list-style-type: none"> • Search direction is CW • Reference point is the left negative edge of the reference cam • The reference cam must be located at the CW end of the travel range • Machine zero is reference position + reference offset.
Type 4		<ul style="list-style-type: none"> • Search direction is CCW • Reference point is the right negative edge of the reference cam • The reference cam must be located at the CCW end of the travel range • Machine zero is reference position + reference offset.
Type 5		<ul style="list-style-type: none"> • No reference travel • Current position is the reference point • Machine zero is current position + reference offset.



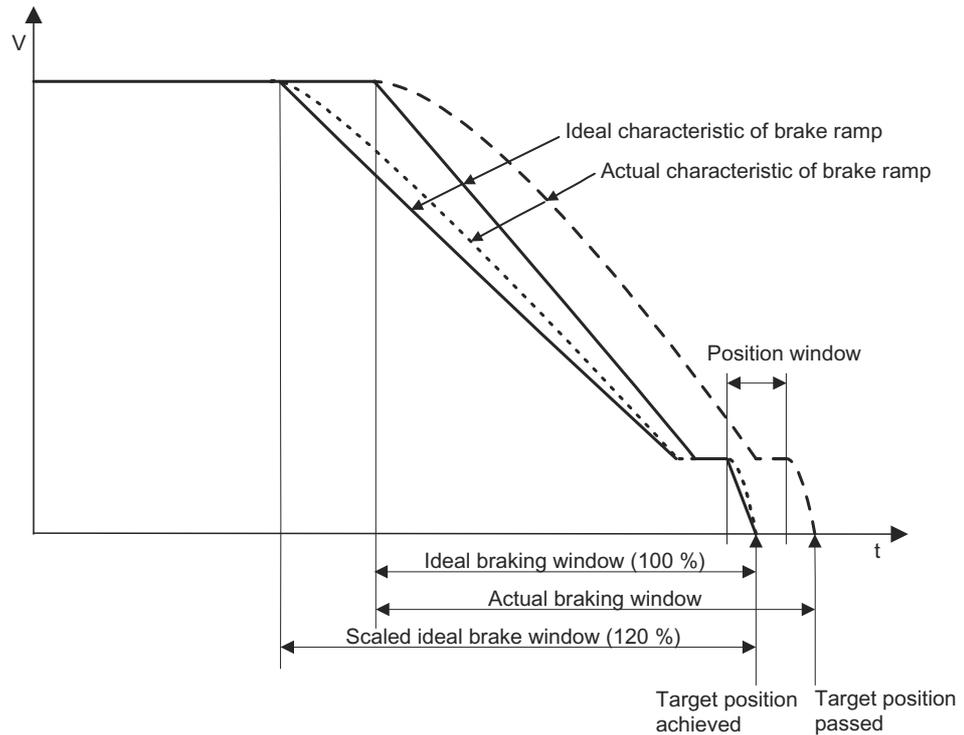
Startup

Entering the default settings

Entering the parameters for the automatic mode

- "Automatic ramp" (enter in seconds)
- "Position window" (enter in increments)
- "Change counting direction"
- "Optimize braking response"

Here, you can optimize the braking response if the drive overshoots the target position e.g. due to unfavorable load conditions. Default setting is 100 %. Increasing the parameter causes the braking process to be extended depending on the speed (see the diagram below).



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5.7 Entering table positions

You have to make the following settings in this window:

Jog mode

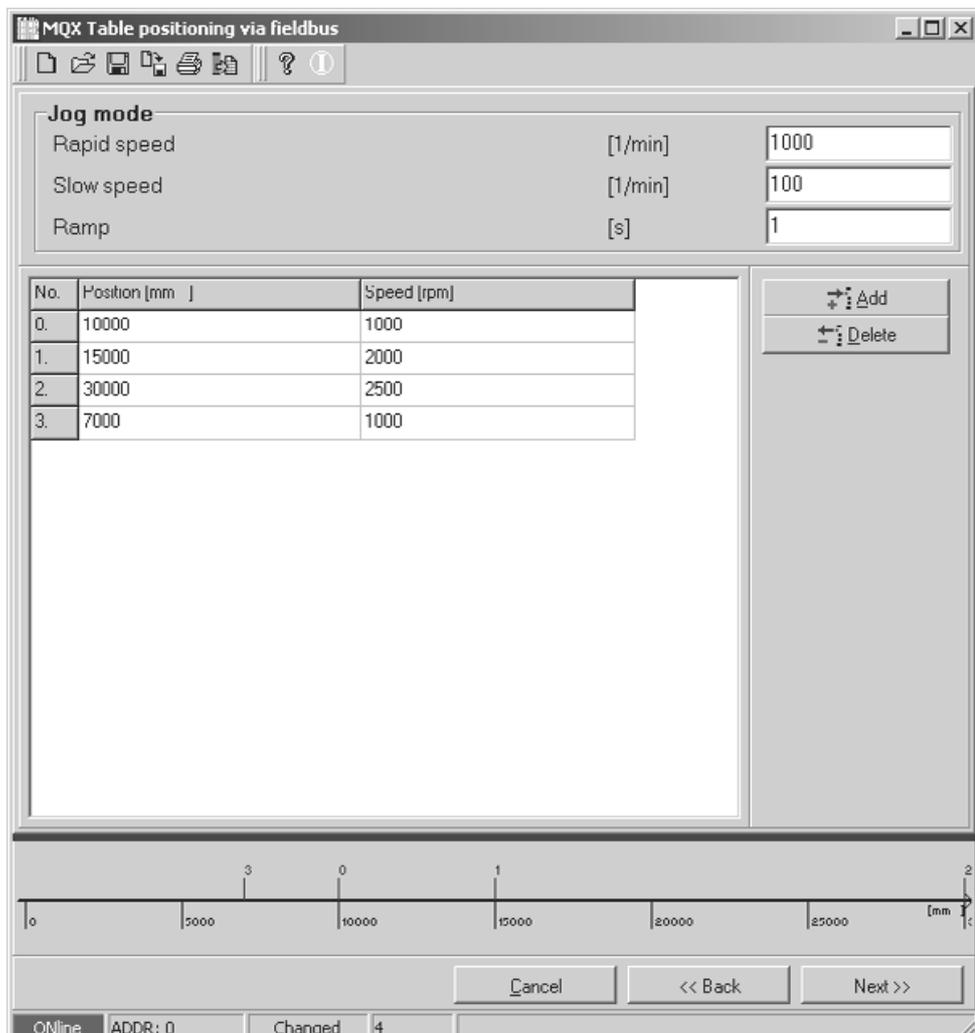
- Enter the valid speeds and the ramp for jog mode

Enter positions

- You can define up to 32 table positions in this window.
- The table positions are entered in increments or the specified user travel unit.
- You always have to enter absolute position values in relation to the machine zero established by the reference position and reference offset.

Table entry	Drive reaction
500 [mm]	The drive moves 500 mm CW
-1500 [mm]	The drive moves 1500 mm CCW

- In addition, you have to enter the speed [1/min] for every table position. This speed is used for moving to the table position.

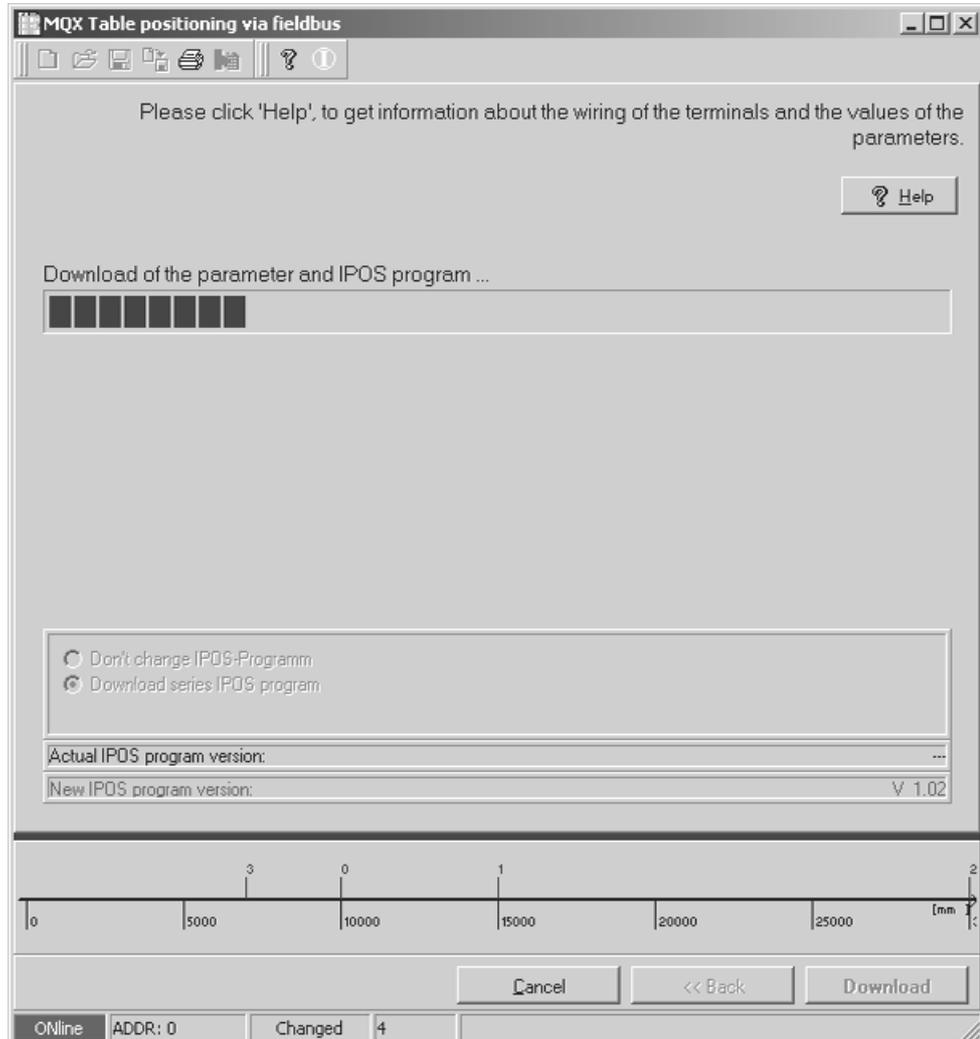


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5.8 Downloading parameters and the IPOS^{plus}® program

Start the download by pressing the <Download> button:



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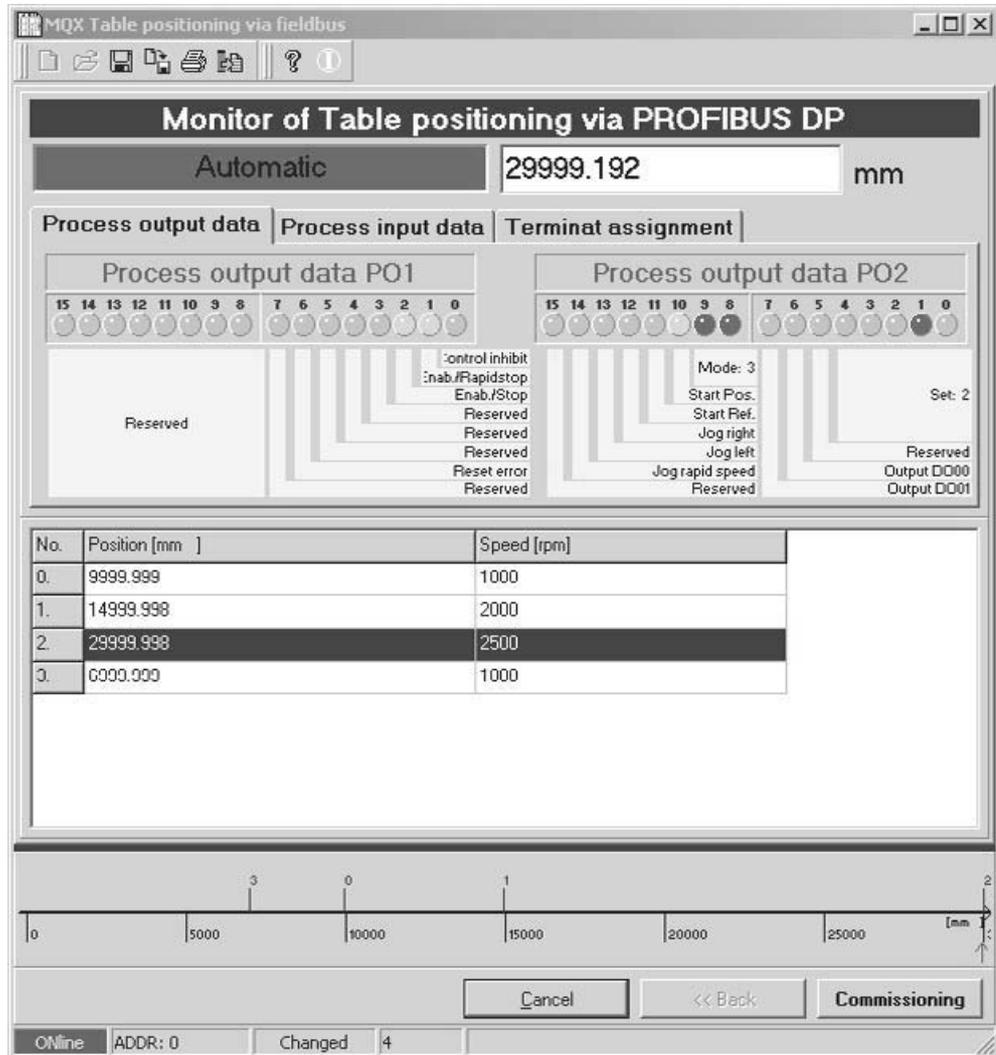
The following functions are performed during the download:

- Removing the parameter lock
- Stopping any IPOS^{plus}® programs that may have been started
- Downloading the IPOS^{plus}® program for MQ.. table positioning
- Setting the fieldbus parameters
- Setting the scaling parameters
- Setting the ramps and speeds
- Starting the IPOS^{plus}® program
- Re-establishing the status of the parameter lock



5.9 Repeated startup

The table positioning monitor appears immediately if MQ.. table positioning is started once startup has been performed.



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If you want to change any settings, click <Startup> to call up the screen for setting the fieldbus parameters. You can now repeat the startup procedure.

5.10 Setting parameters

The following parameters are set automatically for the application:

Parameter number	Parameter name	Parameter value
600	Binary input DI00	MQ.. Encoder In
601	Binary input DI01	MQ.. Encoder In



5.11 Starting the drive

Operating modes

- **Jog mode**
 - CW or CCW via virtual binary inputs PO2:12 and PO2:13
 - Choice of two speeds (rapid speed and slow speed for fine positioning) via virtual binary input PO2:14

- **Teach mode**
 - Movement can be performed to every single position in jog mode and then stored in teach mode. The table cell is selected using virtual binary inputs PO2:0 ... 4. The position is adopted using the positive edge at PO2:10.

- **Reference mode**
 - Reference travel is started with a start command at virtual input PO2:11. Reference travel establishes the reference position (machine zero) for absolute positioning operations. The end of reference travel is confirmed via PI2:8.

- **Automatic mode**
 - Selecting the target position using five virtual binary inputs PO2:0 to PO2:4 (binary coded)
 - Checkback of the selected target position at the start of movement using five virtual binary outputs PI2:8 to PI2:12 (binary coded)
 - Confirmation that the selected position has been reached via virtual binary output PI2:3



No function is executed in teach mode or automatic mode unless reference travel has been performed.

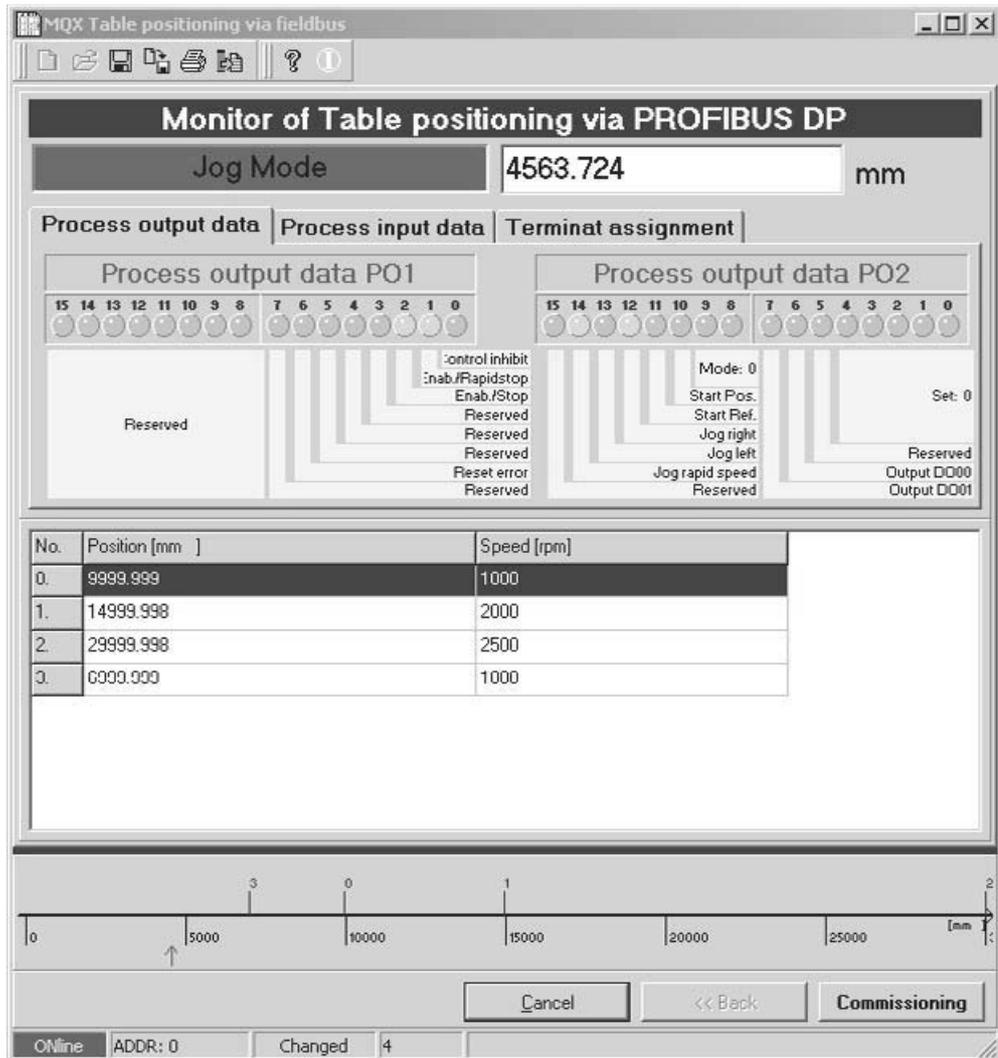


Jog mode (PO2:8 = "0" and PO2:9 = "0")

In jog mode, you can move the drive clockwise or counterclockwise manually using "1" signals at binary inputs PO2:12 "Jog +" or PO2:13 "Jog -". The drive can travel at creep speed (PO2:12 = "0") or rapid speed (PO2:13 = "1").

Jog mode is required for:

- Moving to new table positions that are to be saved in teach mode
- For service purposes when the drive should be moved independently of the automatic functions of the system



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Startup Starting the drive

Reference mode (PO2:8 = "0" and PO2:9 = "1")

The reference position is defined by reference travel to the reference cam. The reference offset is set during startup and you can use it to alter the machine zero without having to move the reference cam.

The following formula applies: Machine zero = reference position + reference offset

No.	Position [mm]	Speed [rpm]
0.	9999.999	1000
1.	14999.998	2000
2.	29999.998	2500
3.	6000.000	1000

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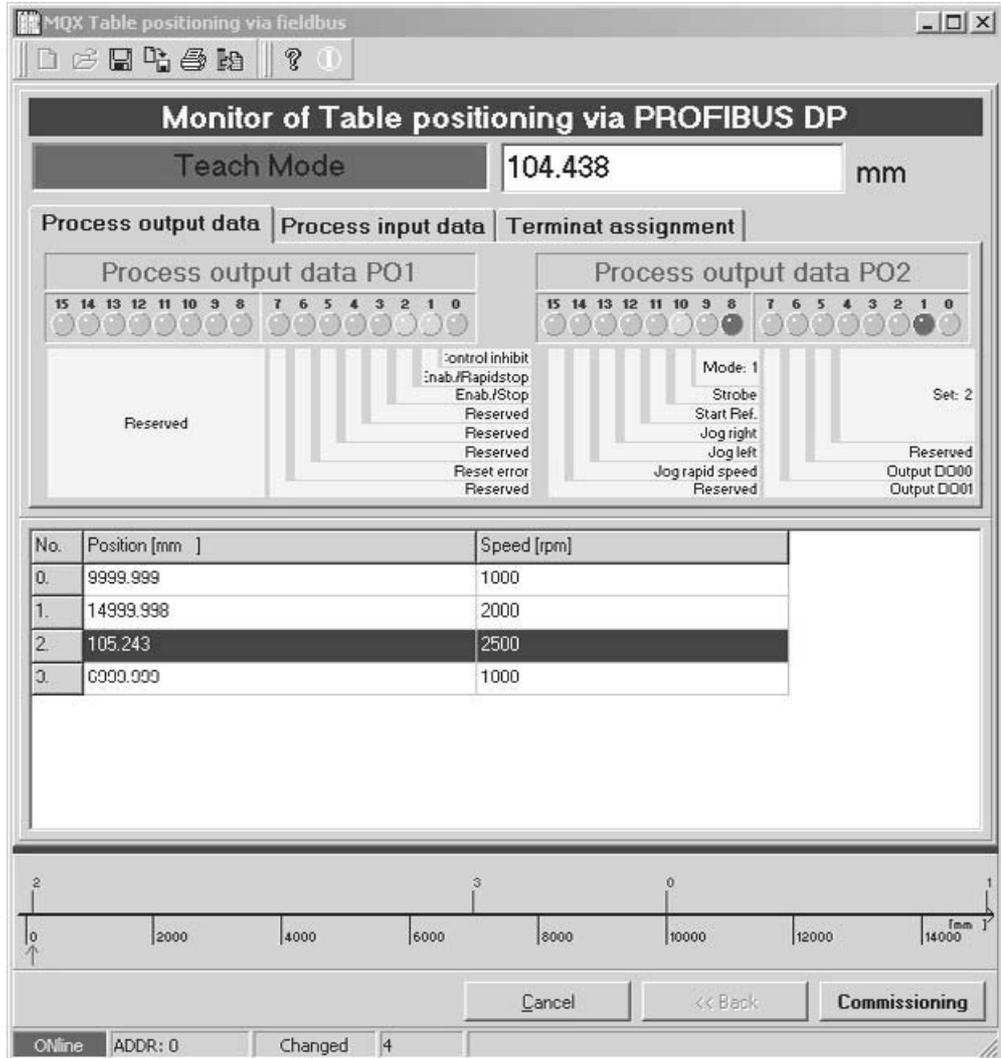
- The correct type of reference travel must be set. If it is not, repeat the table positioning startup and set the type of reference travel you want.
- Enable the inverter via PO1:1 and PO1:2 ("1" signals to "Enable/Rapid stop" and "Enable/Stop").
- Start reference travel with a "1" signal on PO2:11 "Start reference travel". The "1" signal on PO2:11 must be present for the entire duration of the reference travel.
- If the drive reaches the reference position (DI02 "Reference cam" = "1"), the drive changes direction at reference speed 2 and stops when it leaves the reference position (DI03 "1" → "0"). The brake is applied when this happens. Binary output PI2:2 "IPOS reference" is set (= "1" signal). The "1" signal at PO2:11 can now be revoked.

The drive is now referenced. It is now possible to set the required operating mode.



Teach In (PO2:8 = "1" and PO2:9 = "0")

In teach mode, you can save the current position of the drive as a new table position. You must first move to the position you want to save as a new table position. This movement must take place in jog mode.



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Enter the new position as follows:

- Move to the position in jog mode
- Switch to teach mode
- Use PO2:0 to PO2:4 to select the table cell (no.) into which the new position should be written. The positions are in binary coded format:

Table position	PO2:4	PO2:3	PO2:2	PO2:1	PO2:0
0	0	0	0	0	0
1	0	0	0	0	1
...
31	1	1	1	1	1

- Apply the signal sequence "0"- "1"- "0" to binary input PO2:10 ("Strobe") to write the new position to the selected table cell. The position is now saved in the non-volatile memory.



Startup Starting the drive

Automatic mode (PO2:8 = "1" and PO2:9 = "1")

In automatic mode, you can select a table position using binary inputs PO2:0 to PO2:4. The positions are in binary coded format:

Table position	PO2:4	PO2:3	PO2:2	PO2:1	PO2:0
0	0	0	0	0	0
1	0	0	0	0	1
...
31	1	1	1	1	1

It is only possible to select table cells that contain position entries. If an undefined table cell is selected, the table cell that was last defined is activated.

- Positioning travel is started with a "1" signal on binary input PO2:10 (Start positioning).
- The "1" signal must be active on PO2:10 throughout the entire positioning travel otherwise the drive stops.

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The mechanical holding brake is applied when the selected position is reached. The drive is inhibited.

The blue bar shows the selected table cell. The current position of the drive is displayed as a numerical value in the "Current position" window and is indicated graphically by a green arrow on the line of numbers.

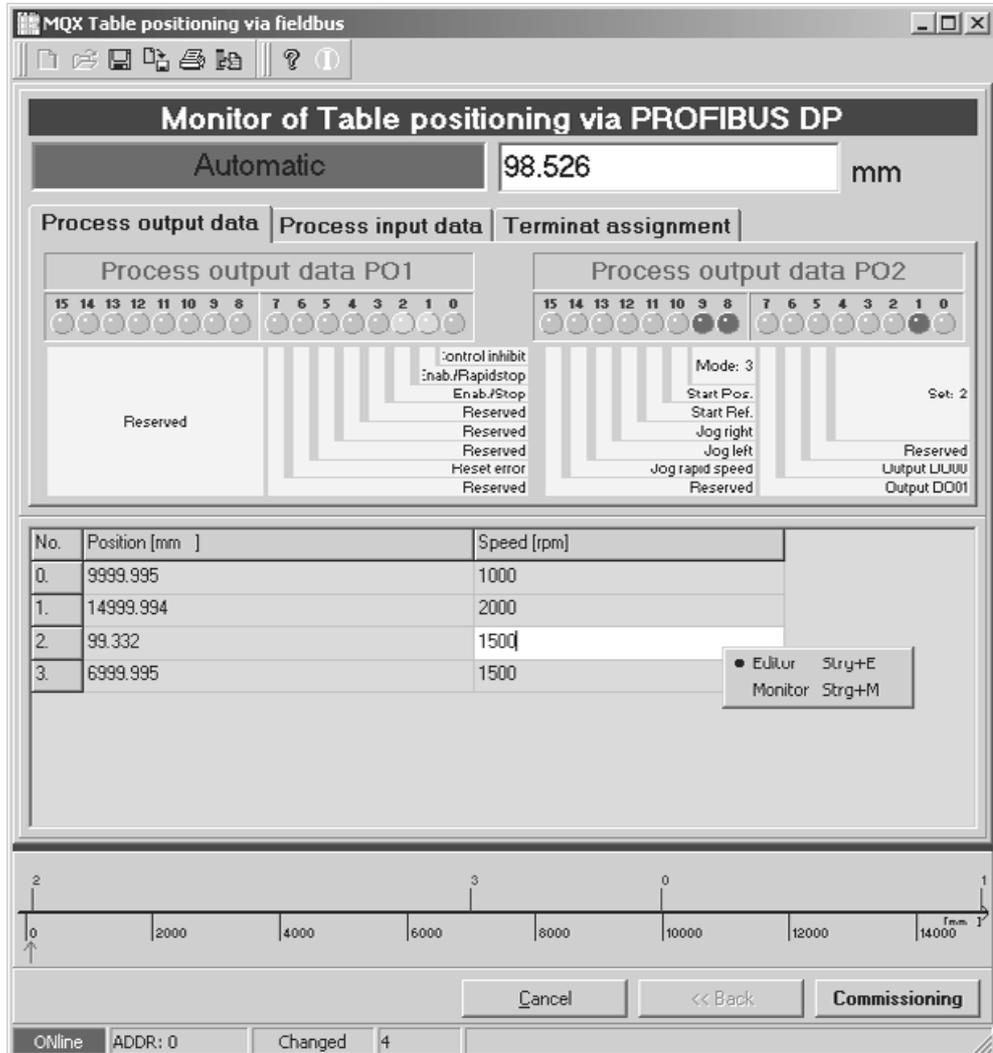


Edit mode

Changing the positioning speed in the monitor:

Click with the right mouse button in the display area of the table to switch between monitor and editor mode for the table.

In the editor mode, select the positioning speed you want to change by clicking it with the left mouse button.



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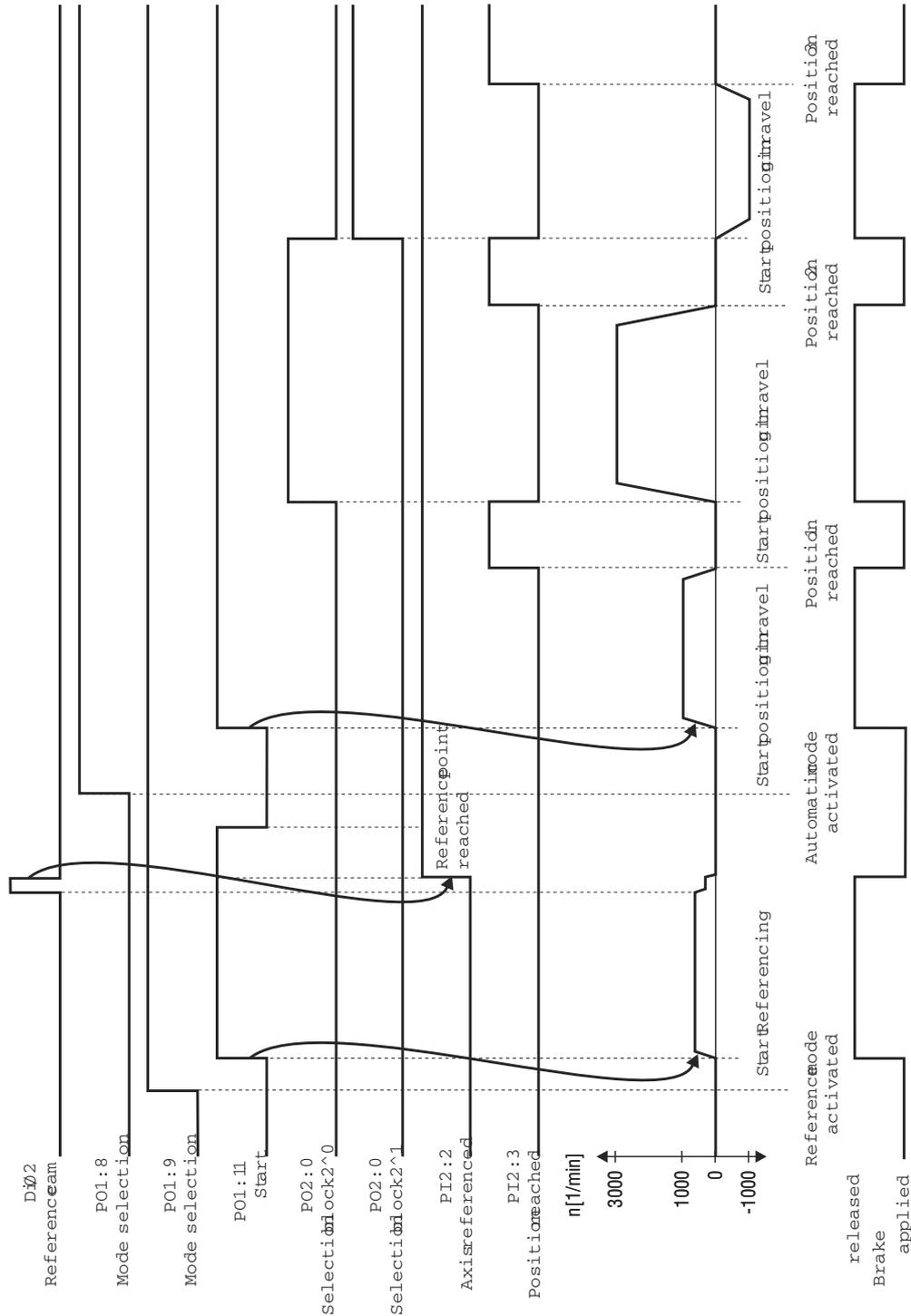
6 Operation and Service

6.1 Timing diagrams

The following preconditions apply to timing diagrams:

- PO1:1 "Enable/rapid stop" = "1" and
- PO1:2 "Enable/Stop" = "1" signals

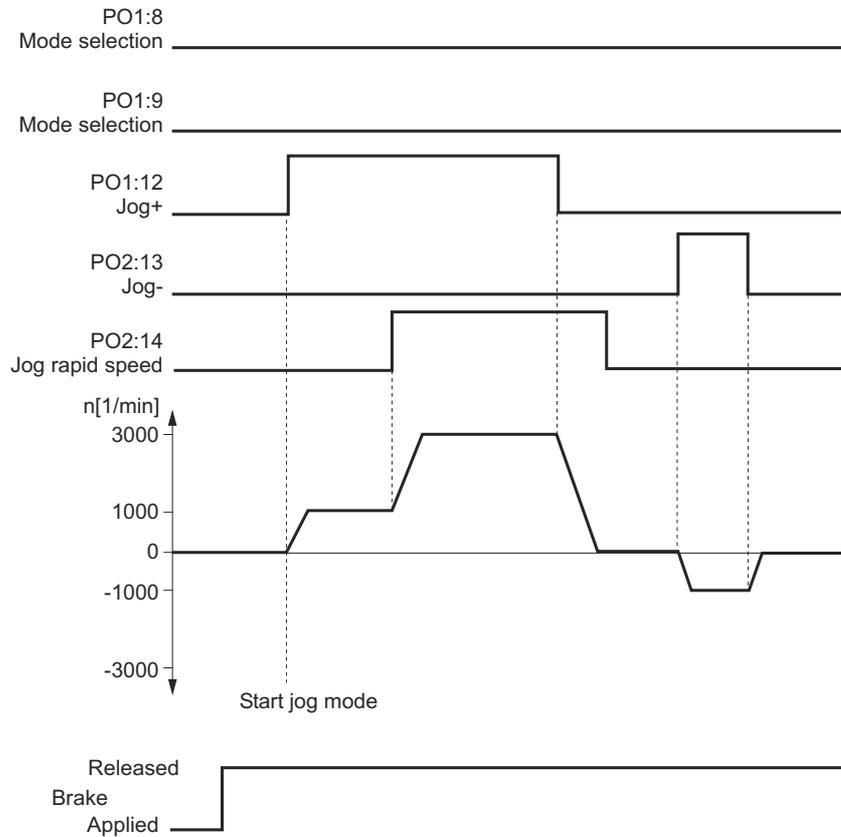
Referencing mode and automatic mode



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Jog mode



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6.2 Unit state

If there is no fault state on the unit (PI1:6 = 0), the current MOVIMOT® state is sent to the master controller via PI1:8 to PI1:15 (high byte) of process data word 1 (PI1).

The following units states can occur:

State	Description
0	Inverter not ready
2	No enable
4	Inverter enabled

6.3 Fault information

When there is a fault state (PI1:6 = 1), the current fault code is sent to the master controller via PI1:8-15 (high byte) of process data word 1 (PI1). The fault number can also be used to determine which component (MQX or MOVIMOT®) is displaying the fault state:

The following fault tables show the fault codes of the individual components separately.

MQ.. fault table:

Fault code/Designation	Response	Cause	Action
10 IPOS ILLPOP	IPOS program stop DO = 0	<ul style="list-style-type: none"> Error in IPOS program, see IPOS variable H469 for more information 	<ul style="list-style-type: none"> Correct, load and reset IPOS program
14 Encoder error	Communication to MOVIMOT® stops DO = 0	<ul style="list-style-type: none"> Interruption of one or both connections to proximity encoder NV26 	<ul style="list-style-type: none"> Check the electrical connection between MQ.. and NV26.
17 Stack overflow		<ul style="list-style-type: none"> Inverter electronics is faulty, possibly due to EMC influence 	<ul style="list-style-type: none"> Check grounding and shielding and improve, if necessary If the fault occurs again, contact SEW service
18 Stack underflow			
19 NMI			
20 Undefined Opcode			
21 Protection fault			
22 Illegal word operand access			
23 Illegal instruction access			
24 Illegal external bus access			
25 EEPROM		<ul style="list-style-type: none"> Error while accessing EEPROM 	<ul style="list-style-type: none"> Call up the factory setting "Delivery state", perform a reset and set parameters again (Caution: The IPOS program will be deleted) If the fault occurs again, contact SEW service
28 Fieldbus timeout	Process output data = 0 DO = 0 (disengageable)	<ul style="list-style-type: none"> No master-slave communication took place within the configured response monitoring period 	<ul style="list-style-type: none"> Check communications routine of the master
32 IPOS index overflow	IPOS program stopped DO = 0	<ul style="list-style-type: none"> Basic programming rules violated causing stack overflow in system 	<ul style="list-style-type: none"> Check IPOS user program and correct if necessary.
37 Watchdog error	Communication to MOVIMOT® stops DO = 0	<ul style="list-style-type: none"> Error during execution of system software 	<ul style="list-style-type: none"> Consult SEW Service
41 Watchdog option		<ul style="list-style-type: none"> IPOS Watchdog, IPOS program execution time is longer than adjusted Watchdog time 	<ul style="list-style-type: none"> Check the time specified in the "_WdOn()" command.
45 Initialization error		<ul style="list-style-type: none"> Error after self-test during reset 	<ul style="list-style-type: none"> Perform a reset. If the fault reoccurs, contact SEW service



Fault code/Designation	Response	Cause	Action
77 Invalid IPOS control value	IPOS program stopped DO = 0	<ul style="list-style-type: none"> An attempt was made to set an invalid automatic mode 	<ul style="list-style-type: none"> Check write values of external controller
83 Short circuit output	None	<ul style="list-style-type: none"> DO0, DO1 or the voltage supply of the VO24 sensors is shorted 	<ul style="list-style-type: none"> Check the cabling/load of the DO0 and DO1 outputs as well as the voltage supplies of the sensors.
91 System error	None	<ul style="list-style-type: none"> One or more stations (MOVIMOT®) could not be addressed by the MQ.. within the timeout interval. 	<ul style="list-style-type: none"> Check voltage supply and RS-485 cabling. Check addresses of configured stations.
97 Copy data	Communication to MOVIMOT® stops DO = 0	<ul style="list-style-type: none"> A fault occurred while the data record was being copied. The data is not consistent 	<ul style="list-style-type: none"> Try again to copy the data or perform the factory setting "Delivery state" and a reset first.



MOVIMOT® fault table:

Fault	Cause / Solution
Timeout of communication (motor comes to a stop without error code)	<p>A Missing connection \perp, RS+, RS- between MOVIMOT® and RS-485 master. Check the connection, in particular the ground, and repair.</p> <p>B EM interference. Check the shielding of the data cables and improve if necessary.</p> <p>C Incorrect type (cyclical) in acyclical protocol time between the individual telegrams >1 s with protocol type "cyclical.". Shorten telegram cycle or select "acyclical."</p>
DC link voltage too low, supply system off was detected (motor stops, without error code)	Check power cables and supply voltage for interruption. Motor restarts automatically as soon as the supply voltage reaches normal values.
Fault code 01 Overcurrent in output stage	Short circuit of inverter output. Check the connection between inverter output and motor for short circuit. Reset the fault by switching off the 24 V _{DC} supply voltage or use MOVILINK®.
Error code 06 Phase fault (The error can only be detected when the drive is at load)	Check the supply system leads for phase fault. Reset the fault by switching off the 24 V _{DC} supply voltage or use MOVILINK®.
Error code 07 DC link voltage too high	<p>A Ramp time too short → Increase ramp time.</p> <p>B Faulty connection between brake coil/braking resistor. → Check the connection between braking resistor/brake coil. Correct, if necessary.</p> <p>C Incorrect internal resistance of brake coil/braking resistor → Check the internal resistance of the brake coil/braking resistor (see the section "Technical Data").</p> <p>D Thermal overload in braking resistor → Wrong size of braking resistor selected.</p> <p>Reset the fault by switching off the 24 V_{DC} supply voltage or use MOVILINK®.</p>
Error code 08 Speed monitoring	Speed monitoring has tripped, drive is overloaded → Reduce drive load. Reset the fault by switching off the 24 V _{DC} supply voltage or use MOVILINK®.
Fault code 11 Thermal overload of the output stage or internal unit fault	<ul style="list-style-type: none"> • Clean the heat sink • Reduce the ambient temperature • Prevent heat accumulation • Reduce the load on the drive <p>Reset the fault by switching off the 24 V_{DC} supply voltage or use MOVILINK®.</p>
Fault code 17 to 24, 37 CPU fault	Reset the fault by switching off the 24 V _{DC} supply voltage or use MOVILINK®.
Fault code 25, 94 EEPROM error	Reset the fault by switching off the 24 V _{DC} supply voltage or use MOVILINK®.
Fault code 84 Thermal overload of motor	<ul style="list-style-type: none"> • When the MOVIMOT® inverter is installed close to the motor, set DIP switch S1/5 to "ON". • For the combinations of "MOVIMOT® and motor with one lower power rating", check the setting of DIP switch S1/6. • Reduce the ambient temperature • Prevent heat accumulation • Reduce the load on the motor • Increase the speed • Check the combination of the drive and MOVIMOT® frequency inverter if the error is signaled shortly after the first release. • The temperature monitoring in the motor (TH winding thermostat) has tripped when using MOVIMOT® with the selected extra function 5 → Reduce load on the motor. <p>Reset the fault by switching off the 24 V_{DC} supply voltage or use MOVILINK®.</p>



Fault	Cause / Solution
Fault code 89 Thermal overload of brake coil or brake coil defective	<ul style="list-style-type: none"> • Extend the set ramp time • Brake inspection (see the section "Inspection and Maintenance") • Contact SEW service • If the fault should occur shortly after the initial enable, check the combination of drive (brake coil) and MOVIMOT® frequency inverter. • For combinations of "MOVIMOT® and motor with one lower power rating", check the setting of DIP switch S1/6. <p>Reset the fault by switching off the 24 V_{DC} supply voltage or use MOVILINK®.</p>
Fault code 91 Communication error between fieldbus gateway and MOVIMOT® (This error is generated by the bus module)	<ul style="list-style-type: none"> • Check electrical connection between fieldbus gateway and MOVIMOT® (RS-485) • The error is automatically reset after removing the cause, a reset via control word is not possible.



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	Stockholm	SEW-EURODRIVE AB Björkholmsvägen 10 S-14125 Huddinge	Tel. +46 8 44986-80 Fax +46 8 44986-93
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	Taipei	Ting Shou Trading Co., Ltd. 6F-3, No. 267, Sec. 2 Tung Hwa South Road, Taipei	Tel. +886 2 27383535 Fax +886 2 27368268 Telex 27 245 nestnet@ms6.hinet.net
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Assembly Sales Service	Chon Buri	SEW-EURODRIVE (Thailand) Ltd. Bangpakong Industrial Park 2 700/456, Moo.7, Tambol Donhuaroh Muang District Chon Buri 20000	Tel. +66 38 454281 Fax +66 38 454288 sewthailand@sew-eurodrive.co.th

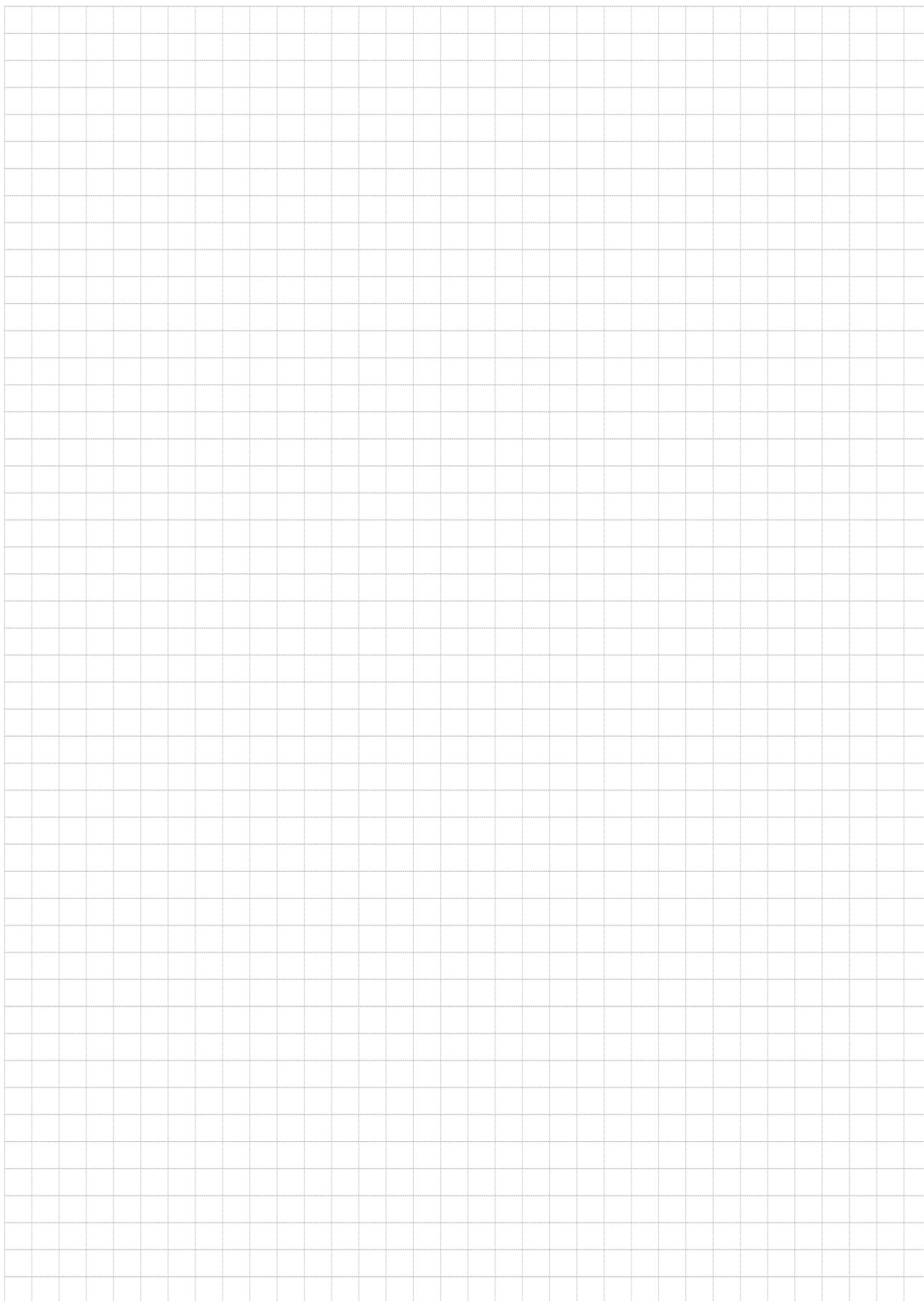


Address list

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	Hadyai	SEW-EURODRIVE (Thailand) Ltd. Hadyai Country Home Condominium 59/101 Soi.17/1 Rachas-Utid Road. Hadyai, Songkhla 90110	Tel. +66 74 359441 Fax +66 74 359442 sewhdy@ksc.th.com
	Khonkaen	SEW-EURODRIVE (Thailand) Ltd. 4th Floor, Kaow-U-HA MOTOR Bldg, 359/2, Mitraphab Road. Muang District Khonkaen 40000	Tel. +66 43 225745 Fax +66 43 324871 sewkk@cscoms.com
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	Dallas	SEW-EURODRIVE INC. 3950 Platinum Way Dallas, Texas 75237	Tel. +1 214 330-4824 Fax +1 214 330-4724 csdallas@seweurodrive.com
Additional addresses for service in the USA provided on request!			
Venezuela			
Assembly Sales Service	Valencia	SEW-EURODRIVE Venezuela S.A. Av. Norte Sur No. 3, Galpon 84-319 Zona Industrial Municipal Norte Valencia, Estado Carabobo	Tel. +58 241 832-9804 Fax +58 241 838-6275 sewventas@cantv.net sewfinanzas@cantv.net



How we're driving the world

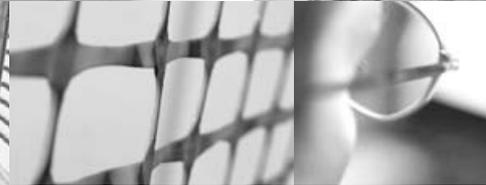
With people who think fast and develop the future with you.



With a global presence that offers responsive and reliable solutions. Anywhere.

With a worldwide service network that is always close at hand.

With drives and controls that automatically improve your productivity.



With innovative technology that solves tomorrow's problems today.

With comprehensive knowledge in virtually every branch of industry today.



With online information and software updates, via the Internet, available around the clock.

With uncompromising quality that reduces the cost and complexity of daily operations.



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