



Smart
connections.

Operating manual

INVEOR MP

Legal notice

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General note on gender equality

KOSTAL is aware of how language impacts on gender equality and always make an effort to reflect this in documentation. Nevertheless, for the sake of readability we are unable to use non-gender-specific terms throughout and use the masculine form instead.

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1. General information

Thank you for choosing an INVEOR MP drive controller from KOSTAL Industrie Elektrik GmbH!
Our INVEOR MP line of drive controllers is designed to be universally usable with all common motor types.

If you have any technical questions, please call our central service hotline:

Tel.: +49 (0)2331 80 40-848

Monday to Friday: 7 am to 5 pm
(UTC/GMT +1)

Fax: +49 (0)2331 80 40-602

E-mail: INVEOR-service@kostal.com

Website address

www.kostal-industrie-elektrik.com

1.1 Information about documentation

The following information explains how to navigate through the documentation.

Read this manual carefully in its entirety. It contains important information for operating the INVEOR MP.

We assume no liability for any damage resulting from non-observance of this manual.

This manual is an integral part of the product and applies exclusively to the INVEOR MP from KOSTAL Industrie Elektrik GmbH.

Provide the operator of the system with this manual so it is available when needed.

1.1.1 Other applicable documents

This refers to all manuals that describe how to operate the drive controller system and any other manuals for the equipment used. Download the 3D files (.stp) for INVEOR and adapter plates from www.kostal-industrie-elektrik.com/downloads/downloadmanager#Antriebstechnik

A description of parameters is available for download (www.kostal-industrie-elektrik.com/downloads/downloadmanager#Antriebstechnik) for parameterising the drive controller.

In the download, you will find all the information required for correct parameterisation.

1.1.2 Storing the documentation

Store this operating manual and all other applicable documents carefully so they are available when needed.

1.2 Notes in this manual

1.2.1 Warnings

The warnings refer to life-threatening dangers. Serious injuries possibly resulting in death may occur.

Each warning consists of the following elements:

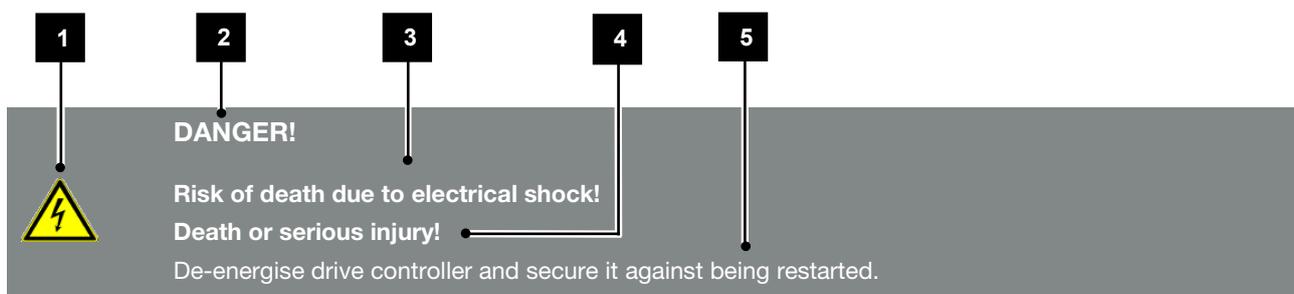


Fig. 1: Structure of the warnings

- 1 Warning symbol
- 2 Signal word
- 3 Type of danger and its source
- 4 Possible consequence(s) of failure to comply
- 5 Corrective actions

1.2.2 Warning symbols used

Symbol	Meaning
	Danger
	Danger due to electrical shock and discharge
	Danger due to electromagnetic fields

1.2.3 Signal words

Signal words are used to identify the severity of the danger.

DANGER

Indicates a direct hazard with a high level of risk, which, if not avoided, will result in death or serious injury.

WARNING

Indicates a hazard with a moderate level of risk, which, if not avoided, will result in death or serious injury.

CAUTION

Indicates a hazard with a low level of risk, which, if not avoided, may result in minor or slight injury or property damage.

1.2.4 Information notes

Information notes contain important instructions for the installation and problem-free operation of the drive controller. These must be followed at all times. The information notes also point out that failure to observe can result in damage to property or financial damages.

	IMPORTANT INFORMATION
The drive controller may only be assembled, operated, maintained and installed by trained and qualified staff.	

Fig. 2: Example of an information note

Symbols within the information notes

Symbol	Meaning
	Important information
	Damage to property possible

Other notes

Symbol	Meaning
	INFORMATION
	Enlarged view

1.3 Symbols used in this manual

Symbol	Meaning
1., 1., 3. ...	Consecutive steps in a handling instruction
→	Effect of a handling instruction
✓	Final result of a handling instruction
■	List

Fig. 3: Symbols and icons used

Abbreviations used

Abbreviation	Explanation
Tab.	Table
Fig.	Figure
It.	Item
Ch.	Chapter

1.4 Labels on the drive controller

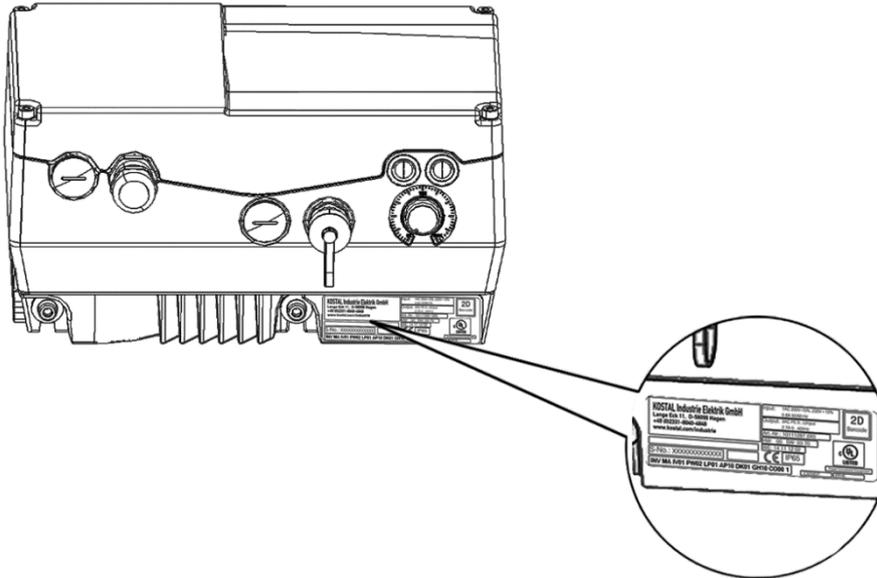


Fig. 4: Labels on the drive controller

Signs and labels are affixed to the drive controller. These may not be altered or removed.

Symbol	Meaning
	Danger due to electrical shock and discharge
	Danger due to electrical shock and discharge. Wait two minutes (discharge time of the capacitors) after shut-down
	Additional earth connection
	Observe and read operating manual

1.5 Qualified staff

In the context of this operating manual, qualified staff refers to electronics specialists who are familiar with the installation, assembly, commissioning and operation of the drive controller and the dangers involved, and whose specialist training and knowledge of relevant standards and regulations provide them with the necessary abilities.

Commissioning (i.e. beginning intended operation) is only permitted if the EMC Directive (2014/30/EU) is complied with.

The harmonised standards of DIN EN 50178; VDE 0160 must be applied for this drive controller along with DIN EN 61439-1/DIN EN 61439-2; VDE 0660-600.

This drive controller may not be operated in areas where there is a danger of explosion!

Repairs may only be performed by authorised repair bodies.

Independent and unauthorised intervention may result in death, injury or property damage. The warranty provided by KOSTAL will be invalidated in such cases.

1.6 Proper use

If the device is installed in a machine, drive controllers may not be commissioned (i.e. intended operation may not begin) until it has been determined that the machine complies with the regulations of EC Directive 2006/42/EC (Machinery Directive); DIN EN 60204-1; VDE 0113-1 must be observed.



IMPORTANT INFORMATION

- External mechanical loads on the housing are not permitted!
- Using drive controllers in equipment that is not fixed is considered as an exceptional environmental condition and is only permitted if allowed by the standards and guidelines applicable on site.

1.7 Responsibility

As a basic principle, electronic devices are not fail-safe. The operator and/or the contractor setting up the machine or system is responsible for ensuring that the drive switches to a safe state if the device fails.

The “Electrical equipment of machines” section in DIN EN 60204-1; VDE 0113-1, “Safety of machinery” describes the safety requirements for electrical control units. These are provided for the safety of people and machines and must be observed in order to retain the functional capability of the machine or system.

An emergency stop feature does not have to result in the voltage supply to the drive being switched off. To avoid dangerous situations, it may be useful for individual drives to remain operational or for specific safety procedures to be initiated.

The effectiveness of emergency stop measures is evaluated by means of a risk assessment for the machine or system and its electrical equipment, and is determined by selecting a circuit category according to DIN EN 13849 “Safety of machinery – Safety-related parts of control systems”.

1.8 CE marking

KOSTAL Industrie Elektrik GmbH hereby declares that the drive controller described in this document complies with the basic requirements and other relevant conditions of the directives listed below.

- Directive 2014/30/EU
(on the approximation of the laws of the Member States relating to electromagnetic compatibility (EMC)).
- Directive 2014/35/EU
(on the harmonisation of the laws of the Member States relating to the making available on the market of electrical equipment designed for use within certain voltage limits – in short: Low Voltage Directive).
- Directive 2011/65/EU
(Restriction of the use of certain hazardous substances in electrical and electronic equipment, in short: RoHS Directive)
- Directive 2014/53/EU
(relating to the making available on the market of radio equipment and repealing Directive 1999/5/EC)

You will find a detailed EU Declaration of Conformity at:

www.kostal-industrie-elektrik.com/downloads/downloadmanager#Antriebstechnik

1.9 Safety instructions

The following warnings, precautionary measures and information are provided for your safety and serve to prevent damage to the drive controller and the components connected to it.

This chapter contains warnings and information that are generally applicable when handling drive controllers. They are split into general information, transport & storage and disassembly & disposal.

Specific warnings and comments that apply to specific activities can be found at the start of the appropriate chapters and are repeated or added to at various critical points in these chapters.

Please read this information carefully as it is provided for your personal safety and will also prolong the life of the drive controller and connected devices.

1.9.1 General information



IMPORTANT INFORMATION

- Carefully read this operating manual and the warning signs affixed to the drive controller before installation and commissioning. Make sure that all warning signs on the drive controller are legible; replace any missing or damaged signs.

They contain important information on the installation and operation of the drive controller. In particular, note the information in the "Important information" chapter.

KOSTAL Industrie Elektrik GmbH assumes no liability for damages arising from the non-observance of this operating manual.

This operating manual is an integral part of the product. It applies exclusively to the drive controller from KOSTAL Industrie Elektrik GmbH. Keep the operating manual close to the drive controller so it is easily accessible to all users.
- The drive controller can only be operated safely if the required environmental conditions listed in the “Suitable environmental conditions” chapter are met.



DANGER!

Risk of death due to electrical shock!

Death or serious injury!

De-energise drive controller and secure it against being restarted.



DANGER!

Risk of death due to electrical shock!

Death or serious injury!

Always ground the device in accordance with DIN EN 61140; VDE 0140, NEC and other relevant standards.

The drive controller must be grounded with the motor according to relevant regulations. Non-compliance may result in death or serious injury.

If spring elements are not used when assembling the adapter plate, there must be an extra connection between the motor and drive controller to produce a correct protective conductor connection.



DANGER!

Risk of death due to revolving mechanical parts!

Death or serious injury!

De-energise drive controller and secure it against being restarted.



DANGER!

Risk of death due to fire or electrical shock!

Death or serious injury!

Always use the drive controller as intended.

Do not modify the drive controller.

Only use spare parts and accessories sold or recommended by the manufacturer.

During assembly, ensure a sufficient distance from neighbouring parts.



CAUTION!

Risk of burns from hot surfaces!

Serious burns to the skin from hot surfaces!

Allow the drive controller's cooling elements to cool sufficiently.

1.9.2 Transport & storage



DAMAGE TO PROPERTY POSSIBLE

- Risk of damage to drive controller!
- Risk of damage to drive controller from improper transport, storage, installation and assembly!
- In general, transport the drive controller correctly in its original packaging on a pallet.
- Always store the drive controller properly.
- Only allow qualified staff to undertake installation and assembly.

1.9.3 Information about commissioning



DANGER!

Risk of death due to electrical shock!

Death or serious injury!

De-energise drive controller and secure it against being restarted.

The following terminals may lead to dangerous currents even when the motor is not running:

- Supply terminals X1: L1, L2, L3
- Motor connection terminals X2: U, V, W
- Connecting terminals X6, X7: Relay contacts for relays 1 and 2



IMPORTANT INFORMATION

- If different voltages are used (e.g. +24 V/230 V), crossing cable runs are not permitted under any circumstances. The operator must also ensure compliance with the applicable regulations (e.g. double or reinforced insulation acc. to DIN EN 61800-5-1).
- The drive controller contains components susceptible to electrical discharge. These may be destroyed through improper handling. Therefore, precautionary measures against electrostatic charges must be taken when work is performed on these components.



IMPORTANT INFORMATION

- Only use mains connections with hardwiring.
- Ground the drive controller in accordance with DIN EN 61140; VDE 0140-1.
- The INVEOR may have touch currents of > 3.5 mA.
In accordance with DIN EN 61800-5-1, an extra protective grounding conductor of the same cross-section as the original protective grounding conductor should therefore be fitted. A second protective grounding conductor can be connected under the mains supply (position marked with a ground symbol) on the outside of the device. A M6 x 12 screw (4.0 Nm torque) suitable for this connection is provided with the adapter plate.
- If three-phase frequency converters are used, the use of conventional type A FI protection switches RCDs (residual current-operated protective devices) are not permissible as protection against direct or indirect contact. According to DIN VDE 0160 and EN 50178, the FI protection switch must be universal current sensitive (RCD type B).

1.9.4 Instructions concerning operation

DANGER!



**Risk of death due to electrical shock!
Death or serious injury!**

De-energise drive controller and secure it against being restarted.

DANGER!



**Risk of death due to revolving mechanical parts!
Death or serious injury!**

De-energise drive controller and secure it against being restarted.



IMPORTANT INFORMATION

Observe the following instructions during operation:

- The drive controller runs at high voltages.
- When electrical devices are operated, some of their parts are always subject to dangerous voltage.
- Emergency stop equipment according to DIN EN 60204-1; VDE 0113-1:2007-06 must function in all the control device's operating modes. Resetting the emergency stop equipment may not result in uncontrolled or undefined restarting.
- In order to ensure safe disconnection from the mains, the mains cable has to be fully disconnected from the drive controller in a synchronous manner.
- A pause of at least 3 sec. must be observed between consecutive grid connections for devices with three-phase feed-in in sizes A - B (0.55 to 5.5 kW).
- Certain parameter settings may result in the drive controller restarting automatically after the supply voltage has failed.



DAMAGE TO PROPERTY POSSIBLE

If the information is not observed, the drive controller could be damaged and destroyed during subsequent commissioning.

Observe the following instructions during operation:

- The motor parameters, especially the I²t settings, have to be configured properly to provide proper motor overload protection.
- The drive controller has internal motor overload protection. See parameters 33.010 and 33.011. I²t is ON by default. Motor overload protection can also be ensured via an external PTC.
- The drive controller must not be used as "Emergency stop equipment" (see DIN EN 60204-1; VDE 0113-1:2007-06).

1.9.5 Maintenance and inspection

The drive controllers may only be maintained and inspected by electricians with recognised training. Unless explicitly described in this operating manual, changes to hardware and software may only be undertaken by KOSTAL experts or persons authorised by KOSTAL.

Cleaning the drive controllers

Drive controllers are maintenance-free if operated as intended. If the air contains dust, the cooling ribs of the motor and drive controller have to be cleaned regularly. If devices are fitted with integrated fans, we would recommend cleaning with compressed air.

Measurement of insulation resistance on control part

An insulation test on the control card's input terminals is not permitted.

Measurement of insulation resistance on power stack

The power stack of an INVEOR MP is tested with 2.02 kV in the course of series testing.

Should the insulation resistance have to be measured during a system test, this can be done under the following conditions:

- an insulation test can be undertaken for the power stack alone,
- to avoid excessively high voltages, all the INVEOR MP's connection cables must be disconnected before testing.
- a 500 V DC insulation tester should be used.

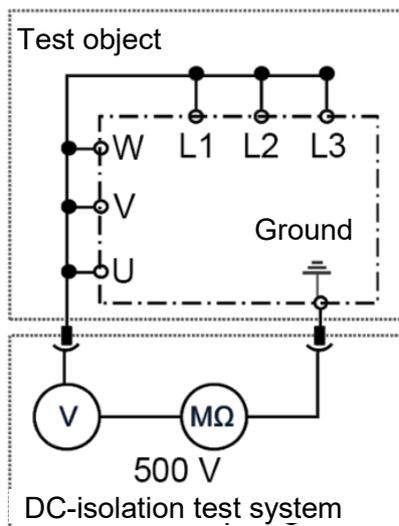


Fig. 5: Insulation test on the power stack

Pressure test on an INVEOR MP



IMPORTANT INFORMATION

A pressure test is not permitted on a standard INVEOR.

1.9.6 Repairs



DAMAGE TO PROPERTY POSSIBLE

If the information is not observed, the drive controller could be damaged and destroyed during subsequent commissioning.

- Repairs to the drive controller may only be performed by the KOSTAL Service department.

DANGER!



Risk of death due to electrical shock!
Death or serious injury!

De-energise drive controller and secure it against being restarted.



Danger due to electrical shock and discharge. Wait two minutes (discharge time of the capacitors) after shut-down.

2. Overview of the drive controller

2.1 Model description

INVEOR type										A	B	
INV MP	Inverter, motor-integrated, P									x	x	
	Size									A	B	
	A	Size A								x		
	B	Size B									x	
Features:												
Model / sector (new feature to differentiate between the sub-variants)												
VS01	Performance									x	x	
	Supply voltage									A	B	
IV01	400 V									x	x	
	Recommended motor rating									A	B	
	PW03	0.55 kW								x		
	PW04	0.75 kW								x		
	PW05	1.10 kW								x		
	PW06	1.50 kW								x		
	PW07	2.20 kW									x	
	PW08	3.00 kW									x	
	PW09	4.00 kW									x	
	PW46	2.20 kW LD								x		
	PW49	5.50 kW LD									x	
	Power-conducting plate									A	B	
	LP01	Without brake chopper								x	x	
	LP02	With brake chopper								x	x	
	Application PCB									A	B	
	AP01	Default								x	x	
	AP03	Basic								x	x	
	AP05	Standard + CANopen								x	x	
	AP06	Standard + EtherCAT								x	x	
	AP09	Standard + Profinet								x	x	
	AP14	Standard + Sercos III								x	x	
	AP16	Standard + Profibus COMX								x	x	
	AP10	Functional safety								x	x	
	AP21	Functional safety + CANopen								x	x	
	AP22	Functional safety + EtherCAT								x	x	
	AP23	Functional safety + Profinet								x	x	
	AP24	Functional safety + Sercos III								x	x	
	AP25	Functional safety + Profibus COMX								x	x	
	AP40	Standard + BT								x	x	
	AP41	Basic + BT								x	x	
	AP42	Standard + CANopen + BT								x	x	
	AP43	Standard + EtherCAT + BT								x	x	
	AP44	Standard + Profinet + BT								x	x	
	AP45	Standard + Sercos III + BT								x	x	
	AP46	Standard + Profibus COMX + BT								x	x	
	AP50	Functional safety + Bluetooth								x	x	
	AP51	Functional safety + CANopen + BT								x	x	
	AP52	Functional safety + EtherCAT + BT								x	x	
	AP53	Functional safety + Profinet + BT								x	x	
	AP54	Functional safety + Sercos III + BT								x	x	
	AP55	Functional safety + Profibus COMX + BT								x	x	
	Housing type									A	B	
	GH01	Passive cooling, potentiometer								x	x	
	GH02	Passive cooling								x	x	
	GH40	Passive cooling, HARTING, potentiometer								x	x	
	GH41	Passive cooling, HARTING								x	x	
	GH42	Passive cooling, QUICKON, potentiometer								x	x	
	GH43	Passive cooling, QUICKON								x	x	
	GH44	Passive cooling, BRAKE RESISTOR, potentiometer								x	x	
	GH45	Passive cooling, BRAKE RESISTOR								x	x	
	GH46	Passive cooling, BRAKE RESISTOR, HARTING, potentiometer								x	x	
	GH47	Passive cooling, BRAKE RESISTOR, HARTING								x	x	
	GH48	Passive cooling, BRAKE RESISTOR, QUICKON, potentiometer								x	x	
	GH49	Passive cooling, BRAKE RESISTOR, QUICKON								x	x	
	Cover type									A	B	
	DK01	Without foil keypad								x	x	
	DK02	Foil keypad, potentiometer								x	x	
	DK05	MMI option								x	x	
	DK11	Main switch								x	x	
	DK12	Main switch, foil + potentiometer								x	x	
	DK15	Main switch, MMI option								x	x	
	Optional module									A	B	
	OA00	No option module								x	x	
	OA10	Main switch								x	x	
	Customer									A	B	
	CO00	KOSTAL INVEOR										
INV MP	x	V S01	IVxx	PWxx	LPxx	APxx	GHxx	DKxx	OAxx	COxx		

2.2 Scope of delivery

Compare the scope of delivery of your product with that provided below.

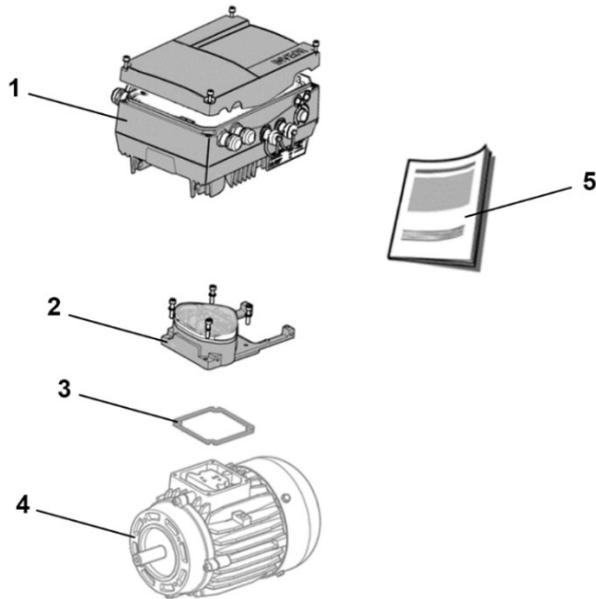


Fig. 6: Scope of delivery

Key	
Drive controller article number	
1	Drive controller (variant)
2	Adapter plate with terminal (not part of the scope of delivery)
3	Seal (not part of the scope of delivery)
Adapter plate article number	
4	Motor (not part of the scope of delivery)
5	Operating manual

2.3 MMI*/connecting cable PIN assignment

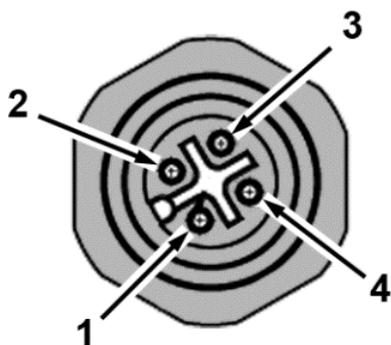


Fig. 7: M12 plug PIN assignment

Description: Round plug (plug) 4-pin M12 A-coded

M12 plug assignment	Signal
1	24 V
2	RS485 - A
3	GND
4	RS485 - B

2.4 MMI*/connecting cable PIN assignment

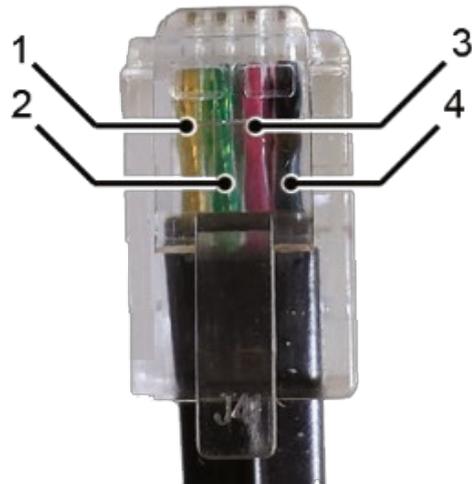


Fig. 8: RJ9 plug connector

Pin	Signal
1	yellow
2	green
3	Red
4	brown

Attention: The colours may vary!

2.5 Description of INVEOR MP drive controller

The INVEOR MP drive controller is a device for controlling the speed of three-phase AC motors.

The drive controller can be integrated in the motor (with the standard adapter plate) or fitted close to the motor (with the wall mounting adapter plate).

The permitted ambient temperatures specified in the technical data refer to operation at nominal load. In many cases, higher temperatures may be permitted after a detailed technical analysis.

These have to be approved by KOSTAL on a case-by-case basis.

* Man-machine interface

3. Installation

3.1 Safety instructions for installation



DANGER!

Risk of death due to revolving mechanical parts!

Death or serious injury!

De-energise drive controller and secure it against being restarted.

Only allow appropriately qualified staff to install the drive controller.

Only use staff who are trained in mounting, installation, commissioning and handling.

Always ground the device in accordance with DIN EN 61140; VDE 0140, NEC and other relevant standards.

The drive controller must be grounded with the motor according to relevant regulations.

Non-compliance may result in death or serious injury.

If spring elements are not used when assembling the adapter plate, there must be an extra connection between the motor and drive controller to produce a correct protective conductor connection

Unused open cable ends in the motor connection box must be insulated.

Use suitable line circuit breakers with the prescribed nominal current between the mains and drive controller.

Mains connections must be hardwired.

3.2 Recommended preliminary fuses / line protection

INVEOR M	Size A 3 x 400 V AC		Size B 3 x 400 V AC	
	Rated motor speed	up to 1.5 kW	2.2 kW LD	up to 4 kW
Line current	3.3 A	3.9 A	7.9 A	9.3 A
Line current 150% (overload 60 s)	4.95 A	4.3 A	11.85 A	10.2 A
Line current 200% (overload 3 s)	6.6 A	5.85 A	15.8 A	14 A
Line circuit breaker - recommendation	C 10		C 16	
	Characteristics C = line circuit breaker tripping between 6 – 10 times I _n			
	The cross-section of the supply line must be designed according to the transfer category and maximum permitted current. The contractor commissioning the device must ensure protection for the power line.			

3.3 Installation requirements

3.3.1 Suitable ambient conditions

Conditions	Values
Altitude of the installation location:	up to 1000 m above sea level / over 1000 m with reduced performance (1% per 100 m) (max. 2000 m), see chapter 8.2
Ambient temperature:	- 40° C to + 50 °C (different ambient temperatures may be possible in individual cases), see chapter 8.2
Relative air humidity	≤ 96 %, condensation not permitted.
Resistance to vibration and shock:	DIN EN 60721-3-3 3M7 (5 – 200 Hz, 3g)
Electromagnetic compatibility:	Immune to interference acc. to DIN EN 61800-3
Cooling:	Surface cooling: sizes A to B: free convection;

Tab. 1: Ambient conditions

- Ensure that the housing type (protection class) is suitable for the operating environment:
 - Ensure that the seal between the motor and the adapter plate is inserted correctly.
 - All unused cable screw connections must be sealed.
 - Check that the cover of the drive controller is closed and bolted down tightly.
 - Size A – B (4 x M4 x 28) 2 Nm,



DAMAGE TO PROPERTY POSSIBLE

Failure to comply with the information may result in damage to the drive controller!

When attaching a cover with integrated foil keypad, be absolutely sure that the flat ribbon cable is not pinched.

Although the drive controller can, in principle, be painted later on, the user must nevertheless check the material compatibility of the intended paint.



DAMAGE TO PROPERTY POSSIBLE

Failure to comply with this requirement may eventually result in the loss of the protection class (particularly in respect to seals and fibre-optic elements).

The INVEOR MP is supplied in RAL 9005 (black) as standard.

Disassembling the circuit boards (even for the purpose of painting the housing sections) renders the warranty void! Mounting points and sealing surfaces must be kept free of paint for purposes of EMC and grounding!

3.3.2 Suitable installation location for the motor-integrated drive controller

Ensure that the motor with a motor-integrated drive controller is only installed and operated if aligned as shown in the following diagram.

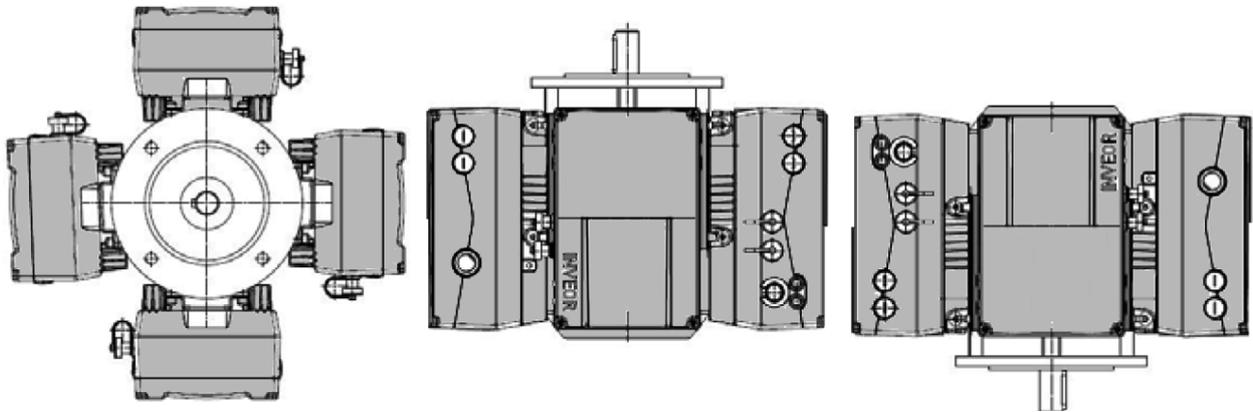


Fig. 9: Motor installation location/permitted alignments



IMPORTANT INFORMATION

Ensure that no condensate from the motor can enter the drive controller during and after installation.

3.3.3 Basic connection versions

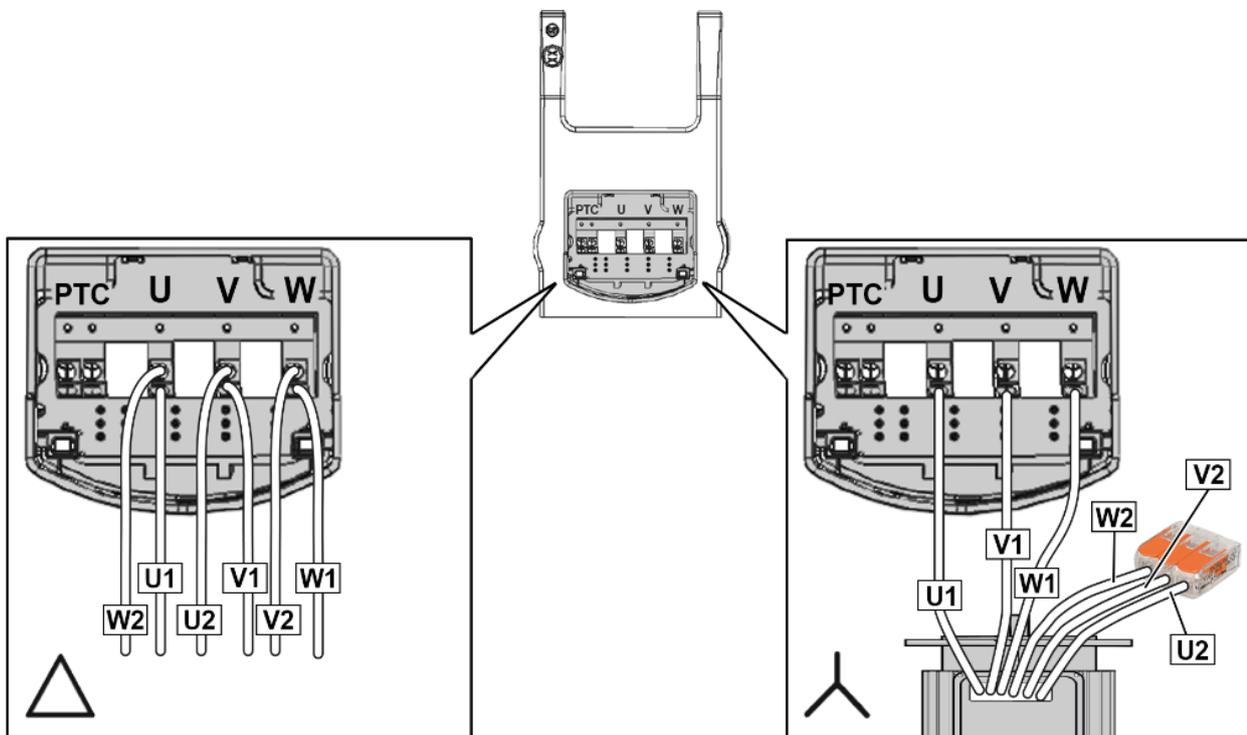


Fig. 10: Star or triangle connection, size A

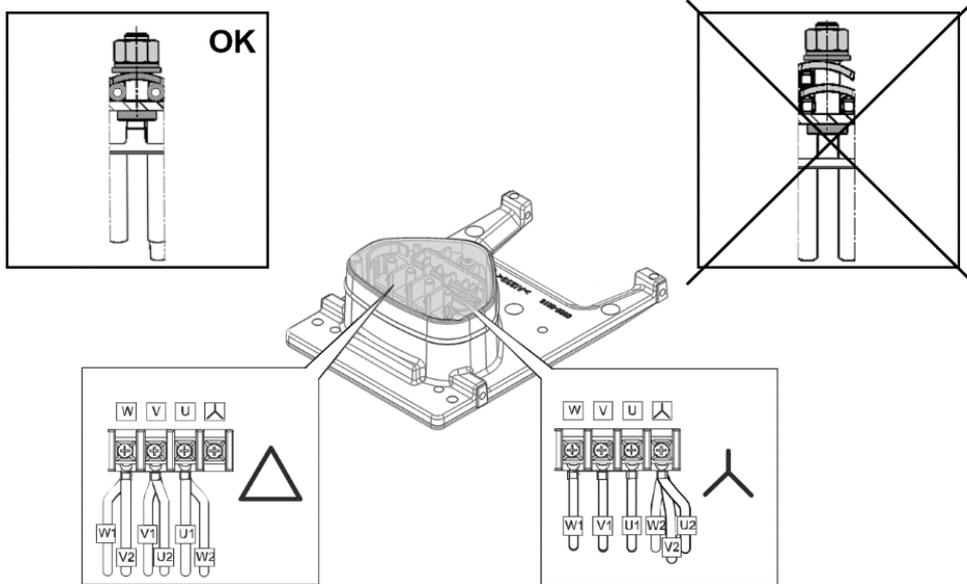
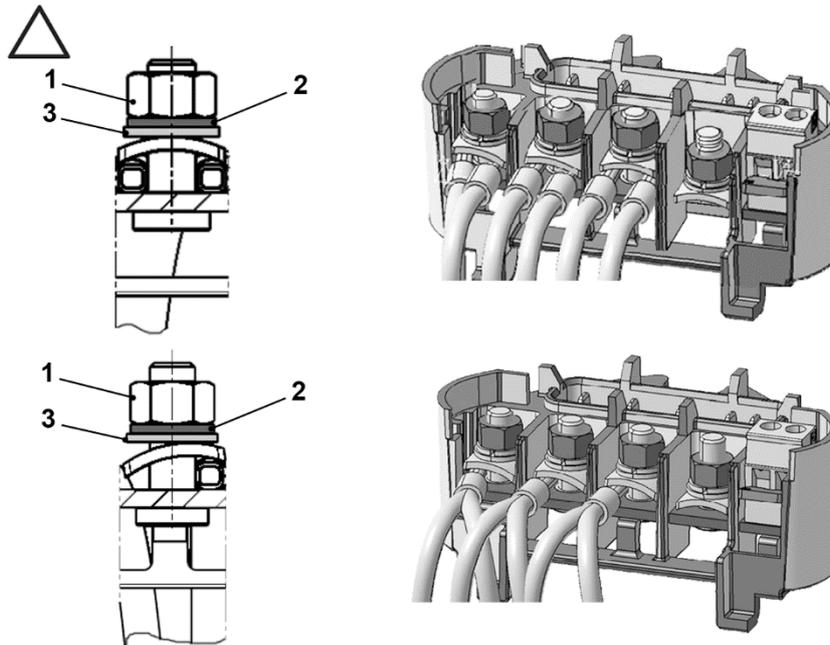


Fig. 11: Star or triangle connection, size B

Triangle connection variant, size B



1. Nut $M_A = 5 \text{ Nm}$

2. Circlip

3. Plain washer



DANGER!

Risk of death due to electrical shock!

Death or serious injury!

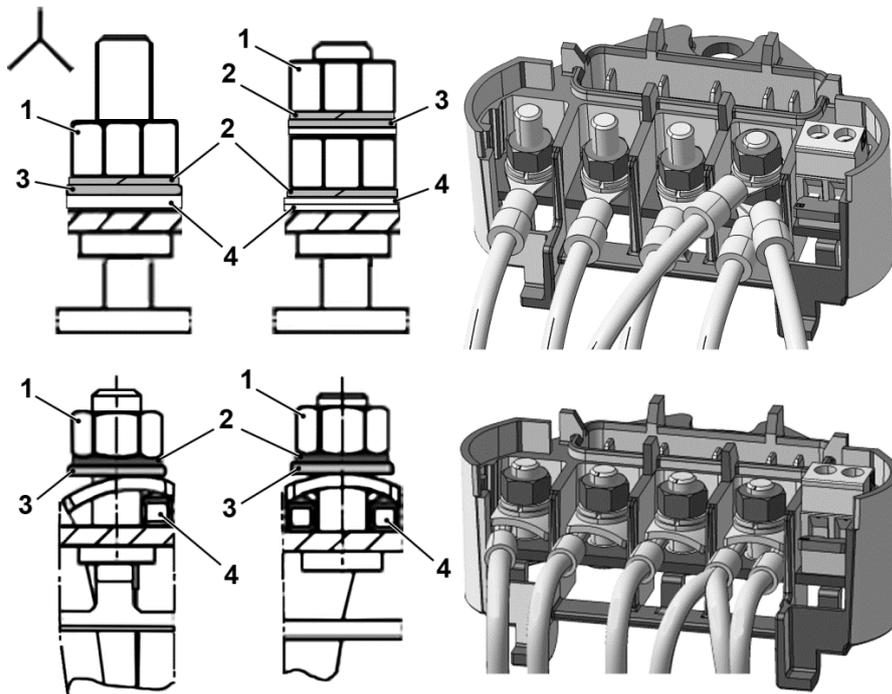
De-energise drive controller and secure it against being restarted.



IMPORTANT INFORMATION

Regularly check that the nuts (1) are secure!

Star connection variant



- | | |
|--|--|
| <ul style="list-style-type: none"> 1. Nut $M_A = 5 \text{ Nm}$ 2. Circlip | <ul style="list-style-type: none"> 3. Plain washer 4. Cable shoe |
|--|--|

DANGER!



Risk of death due to electrical shock!
Death or serious injury!
 De-energise drive controller and secure it against being restarted.
 Unused open cable ends in the motor connection box must be insulated.

DANGER!



Risk of death due to electrical shock!
Death or serious injury!
 De-energise drive controller and secure it against being restarted.

 **DAMAGE TO PROPERTY POSSIBLE**

Risk of damage to the drive controller.
 Correct phase assignment must be observed when connecting the drive controller, otherwise the motor may be overloaded.

 **IMPORTANT INFORMATION**

If a thermal resistor (PTC or Klixon) is used, the bridging contact fitted on the connection terminal for the PTC in the delivery state has to be removed.

 **IMPORTANT INFORMATION**

Regularly check that the nuts (1) are secure!

The supplied assembly material can be used to connect core end sleeves and cable shoes.
 Fig. 11 shows the different connection options.

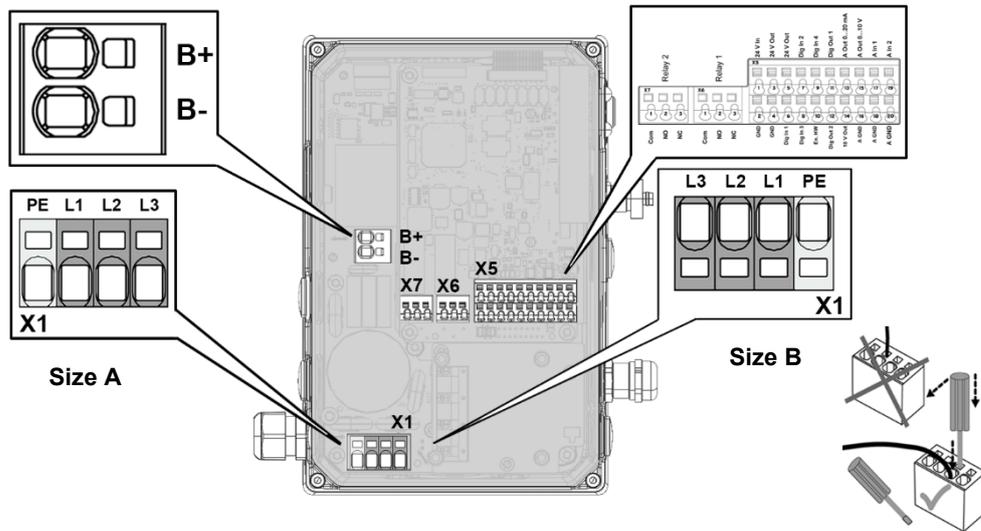
The cross-section of the supply line must be designed according to the transfer category and maximum permitted current. The contractor commissioning the device must ensure protection for the power line.

3.3.4 Short circuit and ground protection

The drive controller contains an internal short circuit and ground protection.

3.3.5 Wiring instructions

Connection overview (sizes A - B)



Sizes A - B	
X5 - X7	The control connections of the application card are located inside the drive controller. Depending on the variant, the assignment and position of the terminals may differ.
	Terminals: Plug terminal clamp with activation button (slot screwdriver, max. width 2.5 mm)
	Connection cross-section: 0.5 to 1.5 mm ² , single-wire, AWG 20 to AWG 14
	Connection cross-section: 0.75 to 1.5 mm ² , fine-wired, AWG 18 to AWG 14
	Connection cross-section: 0.5 to 1.0 mm ² , fine-wired (core end sleeves with and without plastic collars)
	Length of stripped insulation: 9 to 10 mm

Sizes A - B		
X1 mains	The terminals for the mains cable are located inside the drive controller. The INVEOR also has the option of being equipped with terminals for connecting a brake resistor. Depending on the variant, the assignment and position of the terminals may differ.	
	Core end sleeves with plastic collars and lugs are recommended.	
	Terminals:	Spring force connection (slot screwdriver, max. width 2.5 mm)
	Conductor cross-section, rigid	min. 0.2 mm ² max. 10 mm ²
	Conductor cross-section, flexible	min. 0.2 mm ² max. 6 mm
	Conductor cross-section, flexible with core end sleeve without plastic sleeve	min. 0.25 mm ² max. 6 mm
	Conductor cross-section, flexible with core end sleeve with plastic sleeve	min. 0.25 mm ² max. 4 mm
	2 conductors of the same cross-section, flexible with TWIN-AEH with plastic sleeve	min. 0.25 mm ² max. 1.5 mm
	AWG/kcmil conductor cross-section according to UL/CUL	min. 24 max. 8
	Length of stripped insulation:	15 mm
Mounting temperature:	-5 °C to +100 °C	

3.3.6 Preventing electromagnetic interferences

To ensure immunity to interference, be sure that control lines run separately from grid and motor cables. Where possible use shielded cables for analogue control circuits. At the line end, the shielding should be fitted with great care. The use of EMC cable screw connections is recommended for this purpose. These are not part of the scope of delivery.

Ensure that no parasitic currents (compensating currents etc.) can flow via an analogue control cable's shielding.

Route the control lines as far away as possible from the power lines. Under certain circumstances, separate power ducts should be used.

If lines do cross, an angle of 90 ° should be observed as far as possible.

Upstream switch elements, such as protector switches and brake coils or circuit elements that are operated via the outputs of the drive controller have to be interference-suppressed.

3.4 Installing the drive controller integrated in the motor

3.4.1 Mechanical installation

Mechanical installation of sizes A - B

Proceed as follows to mechanically install the drive controller:

1. Open the standard motor connection box.
2. Disconnect the wires from the connection terminals. Memorise or write down the connection sequence.
3. Remove the motor terminal block if necessary.
4. Remove the connection housing's retaining bolts and take the housing off.
Be careful not to damage the seal.

RC circuits are suitable as AC voltage protector switches, while free-wheeling diodes or varistors are usually used as DC voltage protector switches. These interference suppression devices are attached directly to the protector switch coils.



IMPORTANT INFORMATION

Where possible, the power for a mechanical brake should be supplied in a separate cable.

Power connections between the drive controller and motor should always be shielded or reinforced, and the shielding must have large-scale grounding at both ends! The use of EMC cable screw connections is recommended. These are not part of the scope of delivery.

Wiring suitable for EMC must be ensured.

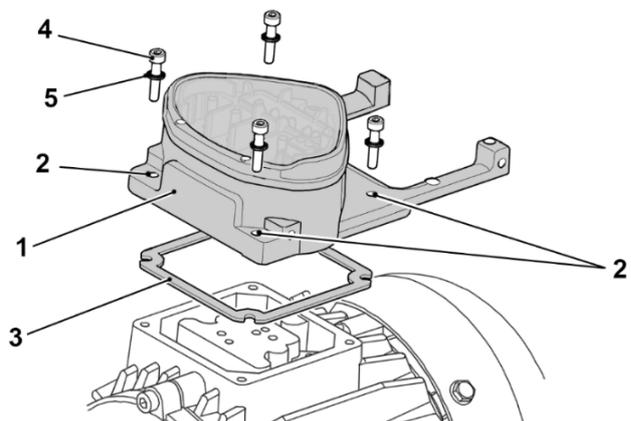


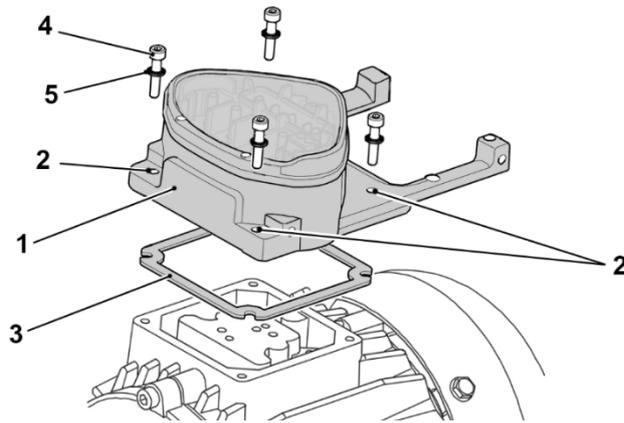
Fig. 12: Assembly sequence:
Connection box – adapter plate (sizes A - B)



INFORMATION

The standard adapter plate is a plate the underside of which is not reworked; i.e. no holes have been produced yet.

You can order individually modified adapter plates from KOSTAL for selected motors.



INFORMATION

The standard adapter plate is a plate the underside of which is not reworked; i.e. no holes have been produced yet.

You can order individually modified adapter plates from KOSTAL for selected motors.

5. Modify the adapter plate (1) by producing the necessary holes (2) for mounting on the motor.



INFORMATION

The commissioning technician is responsible for protection class compliance when sealing the adapter plate on the motor.

If you have any questions, please ask your KOSTAL contact.

6. Fit the seal (3).
7. Lead the motor connection line past the connection terminal and through the adapter plate (1) and screw down to the motor with the four retaining bolts (4) and the four spring elements (torque: 2.0 Nm).



IMPORTANT INFORMATION

When mounting the adapter plates, ensure that all four screws, including the spring elements, are tightened to the necessary torque (2 Nm)!

All contact points must be free of dirt/paint because otherwise a correct protective conductor connection is not ensured!

8. Attach the motor wires in the correct circuit.
We would recommend using isolated M5 ring cable lugs.



IMPORTANT INFORMATION

When installing the motor wires, ensure that all bolts on the terminal board are fitted with the nuts provided even if the star point is not connected!



DANGER!

Risk of death due to electrical shock!
Death or serious injury!

The drive controller must be grounded with the motor according to relevant regulations. Non-compliance may result in death or serious injury.

If spring elements (5) are not used when assembling the adapter plate, there must be an extra connection between the motor and drive controller to produce a correct protective conductor connection.

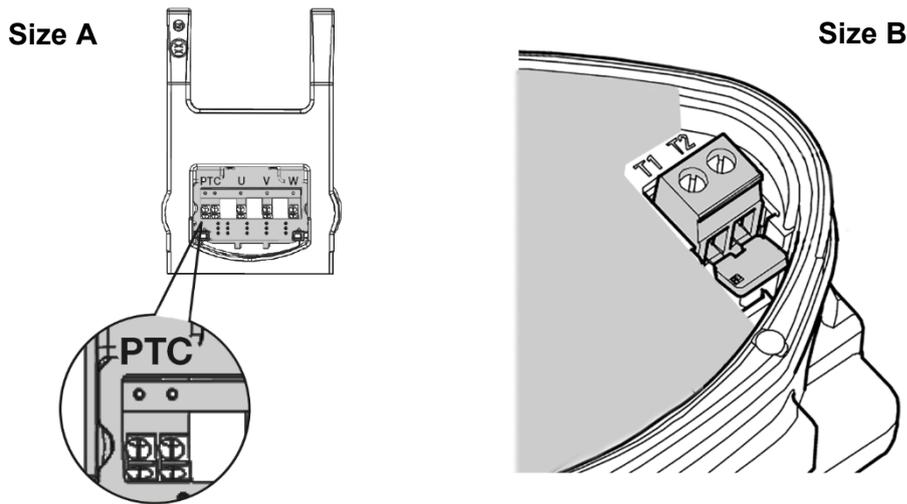
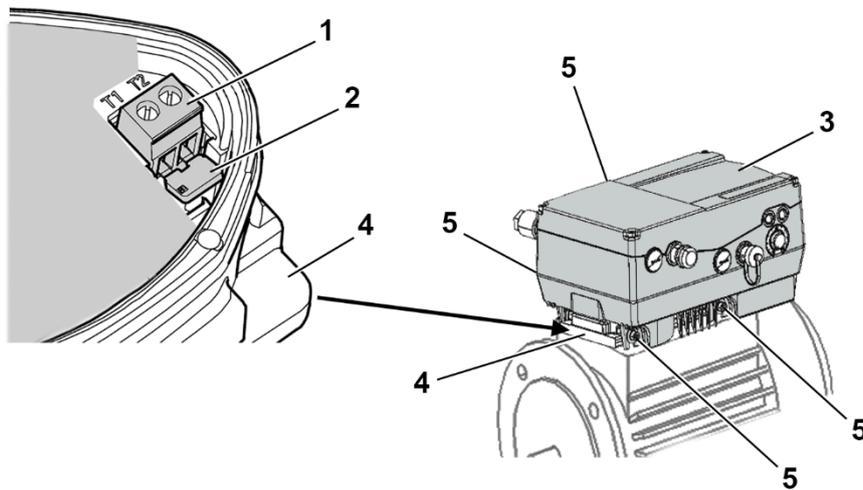


Fig. 13: Bridging contact

- If present, wire the connection cable of the motor PTC/Klixon to the T1 and T2 terminals (1) (torque: 0.6 Nm).

! **IMPORTANT INFORMATION**

During assembly, ensure that the connection cable is not crushed!



! **IMPORTANT INFORMATION**

If the motor is fitted with a temperature sensor, this is connected to the T1 and T2 terminals (1).
Remove the bridging contact (2) inserted for delivery for this purpose.
When the bridge is in place, the temperature of the motor is not monitored!
Only motor PTCs corresponding to DIN 44081/44082 may be connected!

DANGER!

⚡ Risk of death due to electrical shock! Death or serious injury!

The drive controller must be grounded with the motor according to relevant regulations. Non-compliance may result in death or serious injury.

- Plug the drive controller (3) onto the adapter plate (4) and secure uniformly using the four lateral bolts (5) (sizes A – B) (torque: 4.0 Nm).

3.4.2 Power connection

Power connection for sizes A - B

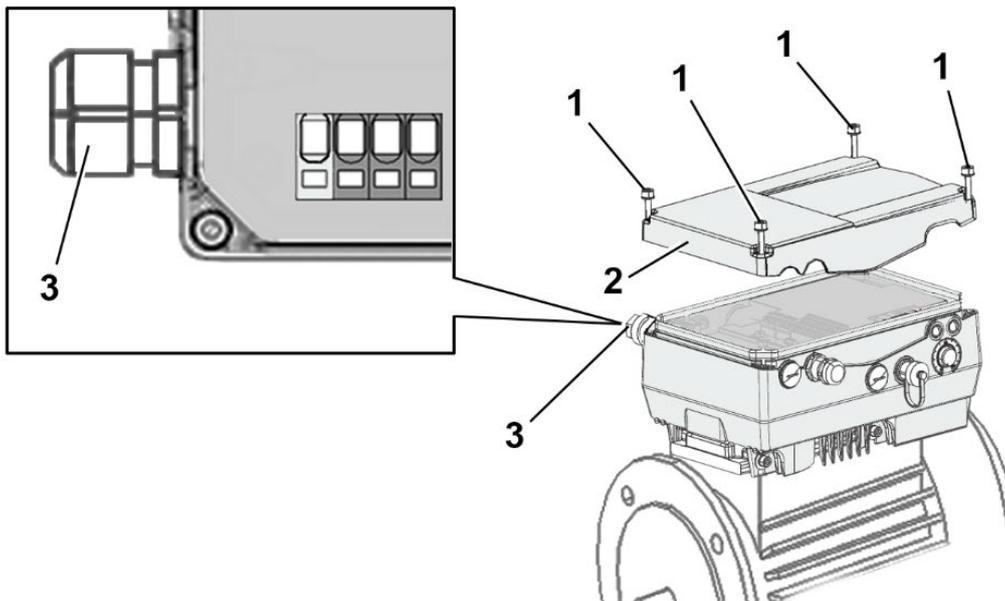


Fig. 14: Power connection sizes A - B



IMPORTANT INFORMATION

When connecting a brake resistor to an optional braking module, cables with shielding and double insulation must be used!

1. Unscrew the four screws (1) from the drive controller's housing cover (2) and then take it off.
2. Guide mains connection cable through cable screw connection (3) into housing of drive controller.

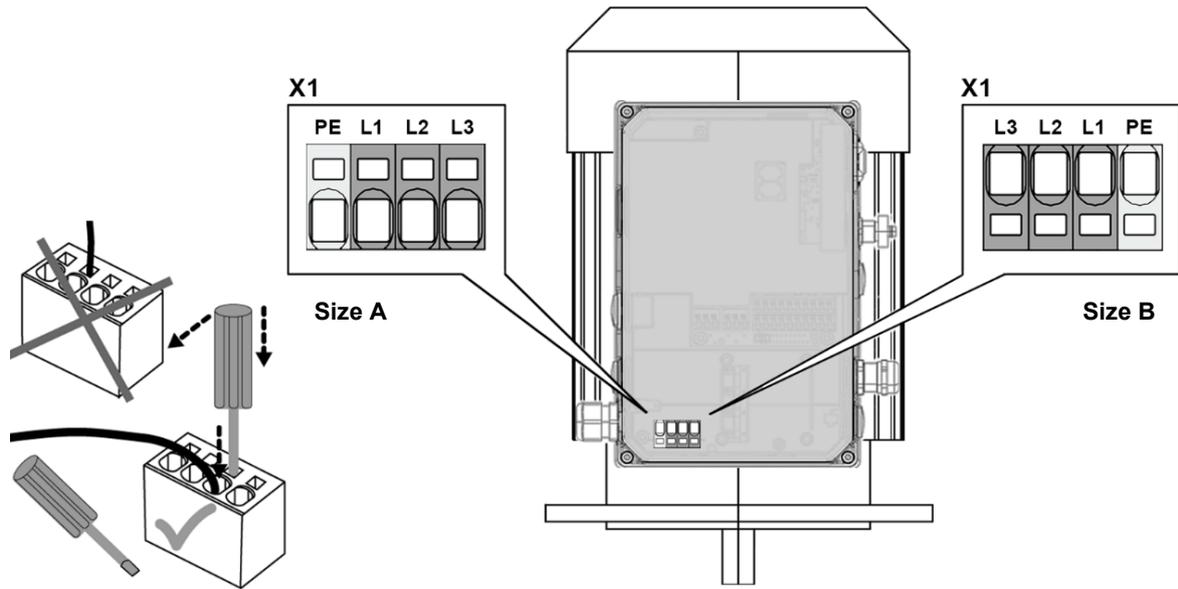


DANGER!

Risk of death due to electrical shock!

Death or serious injury!

De-energise drive controller and secure it against being restarted.



3. Connect the cables with the terminals as follows:

Size	400 V connection			
A	PE	L1	L2	L3
B	L3	L2	L1	PE

Terminal no.	Designation	Assignment
1	L1	Mains phase 1
2	L2	Mains phase 2
3	L3	Mains phase 3
4	PE	Protective conductor

Tab. 2: AC feed-in X1

Terminal no.	Designation	Assignment
1	L1	DC mains (+)
2	L2	Not assigned
3	L3	DC mains (-)
4	PE	Protective conductor

Tab. 3: DC input X1

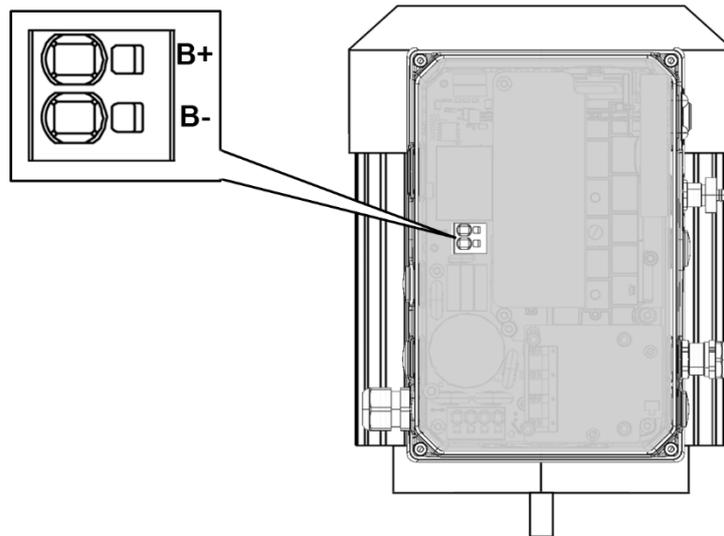


Fig. 15: Terminal assignment for brake chopper

3.4.3 Connections for brake resistor

Terminal no.	Designation	Assignment
1	B+	Connection for brake resistor (+)
2	B -	Connection for brake resistor (-)

Depending on the variant, the assignment and position of the terminals may differ.

Tab. 4 Optional terminal assignment for brake chopper

3.4.4 Connection variant with Harting plug

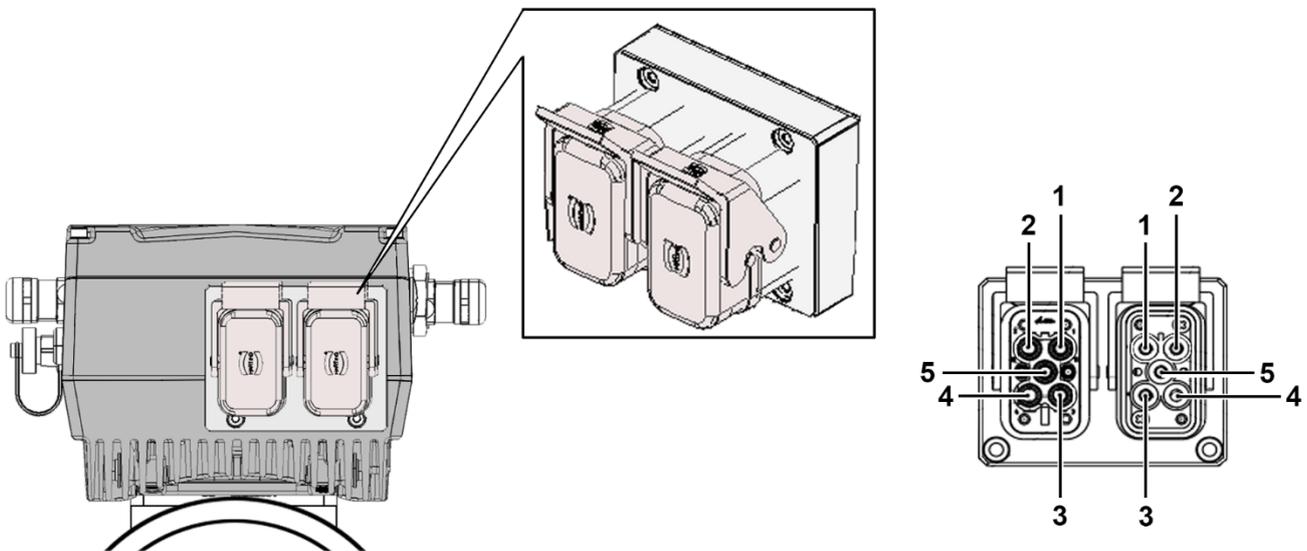


Fig. 16: Harting plug Han Q 4/2

Pin male connector	Pin female connector	Assignment
1	1	L1
2	2	L2
3	3	L3
4	4	-
5	5	PE

3.4.5 PHOENIX Quickon connection variant

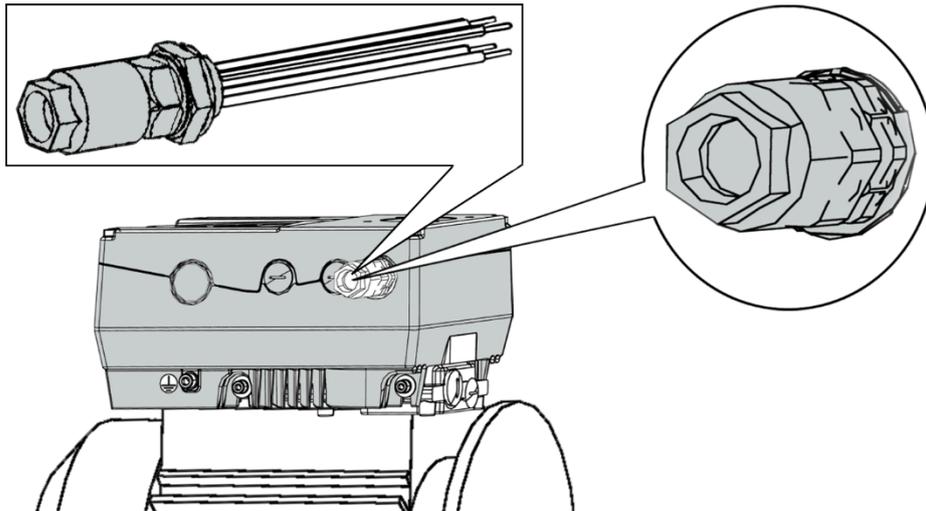


Fig. 17: PHOENIX Quickon

Pin	Colour	Assignment
1	Sw / BK	L1
2	br / BN	L2
3	gr / GY	L3
4	ge / YE	PE

3.4.6 Connection variant with main switch

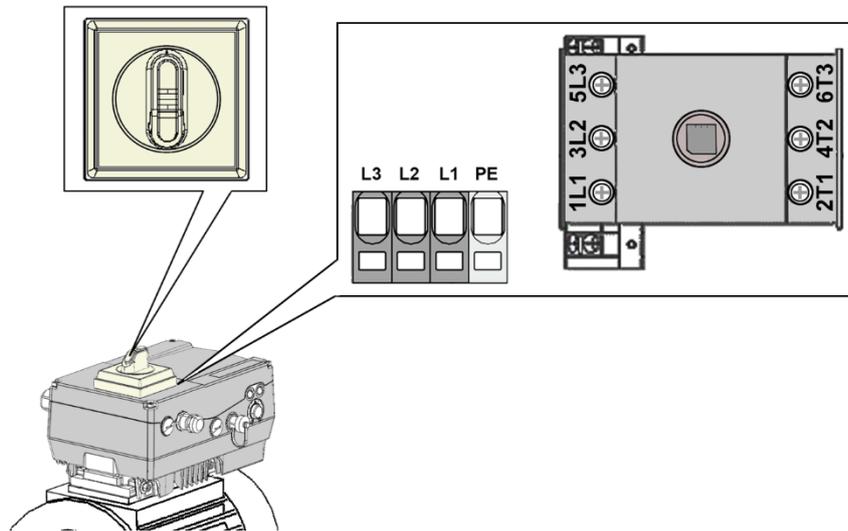


Fig. 18: Main switch

Pin	Assignment
1L1	L1
3L2	L2
5L3	L3
PE	PE

3.4.7 Connection diagram

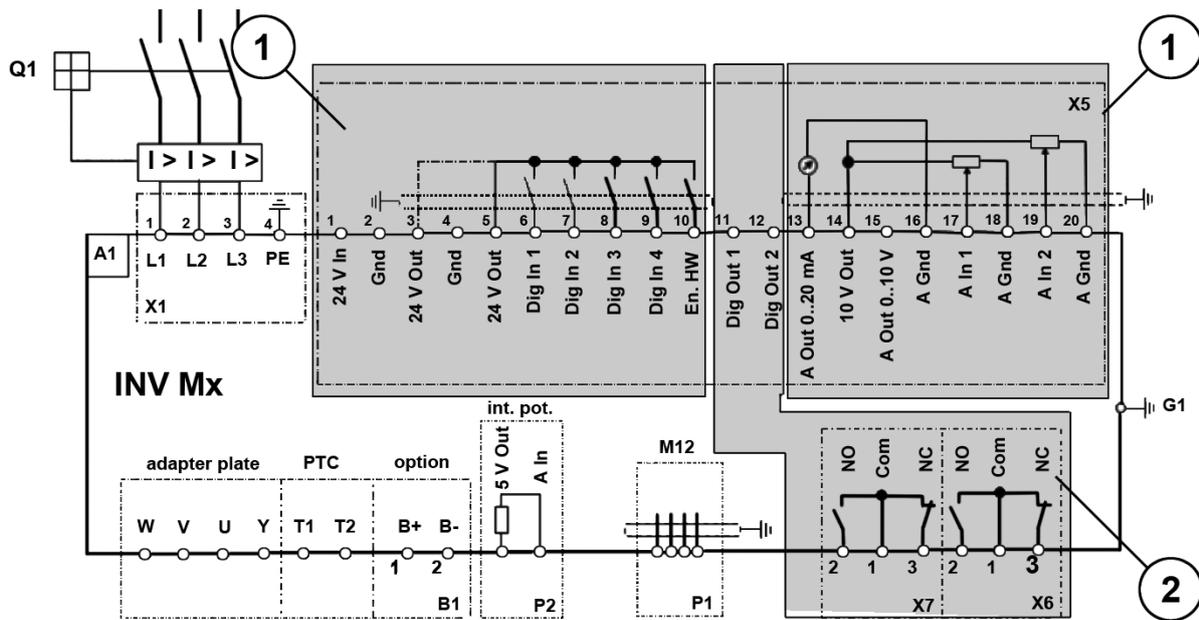


Fig. 19: Connection diagram

Characters	Explanation
A1	Drive controller type: INV MPx
B1	Connection for external brake resistor (option)
G1	M6 grounding screw (connection for residual currents > 3.5 mA)
P1	RS485 programming interface (M12 plug)
P2	Internal potentiometer
Q1	Motor protection switch or load break switch (optional)
X1	Mains terminals
X5 – X7	Digital/analogue inputs and outputs

The drive controller is ready once a 3 x 400 VAC mains supply has been activated (on terminals L1 to L3) or a DC mains supply has been activated (on terminals L1 and L3).

The drive controller can also be started up by connecting an external 24 V voltage.

3.4.8 Control connections X5, X6, X7

Control connections of the standard application board

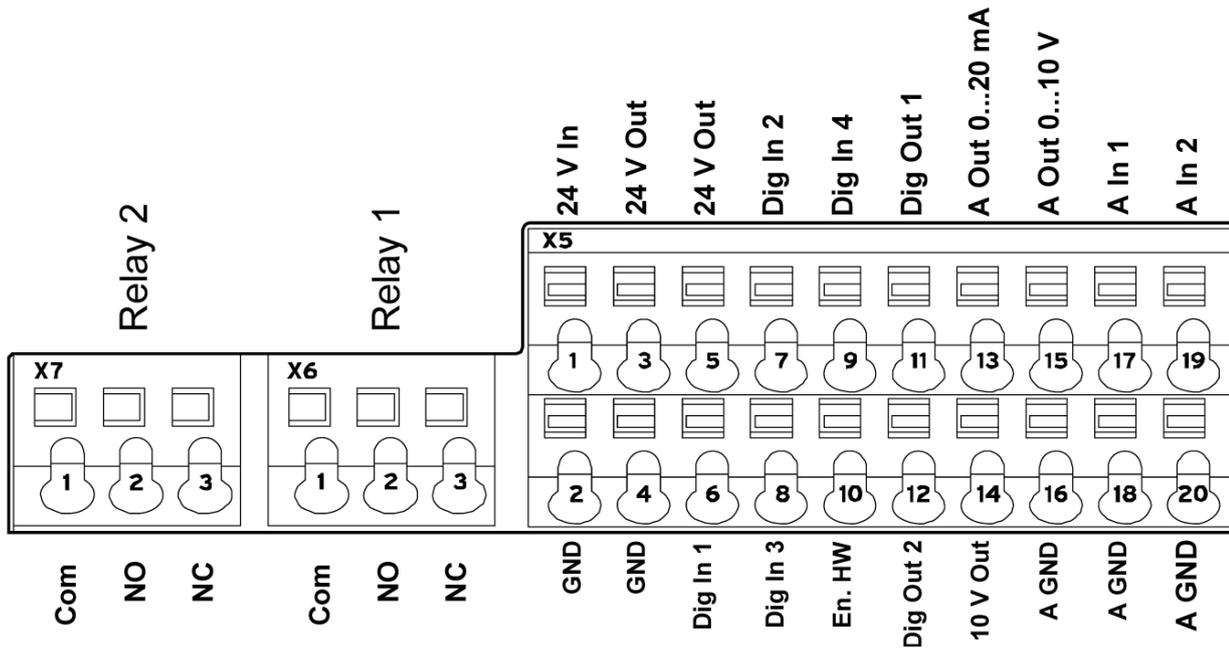
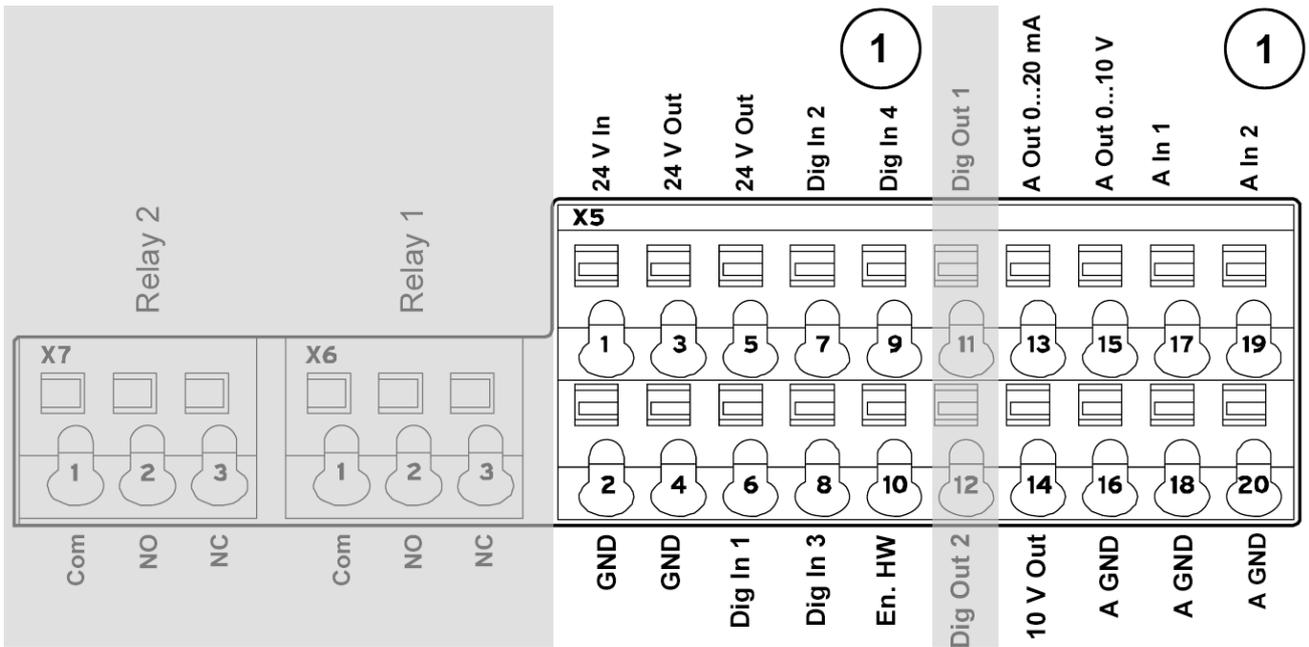


Fig. 20: Control connections of the standard application board

! **IMPORTANT INFORMATION**
 Danger of external signals being coupled in.
 Use only shielded control line!

1. Guide the required control line into the housing through the cable screw connections.
2. Connect the control cables according to the figure and/or table. Use shielded control cables.
3. Place the cover on the housing of the drive controller and bolt it tight to the following torque.

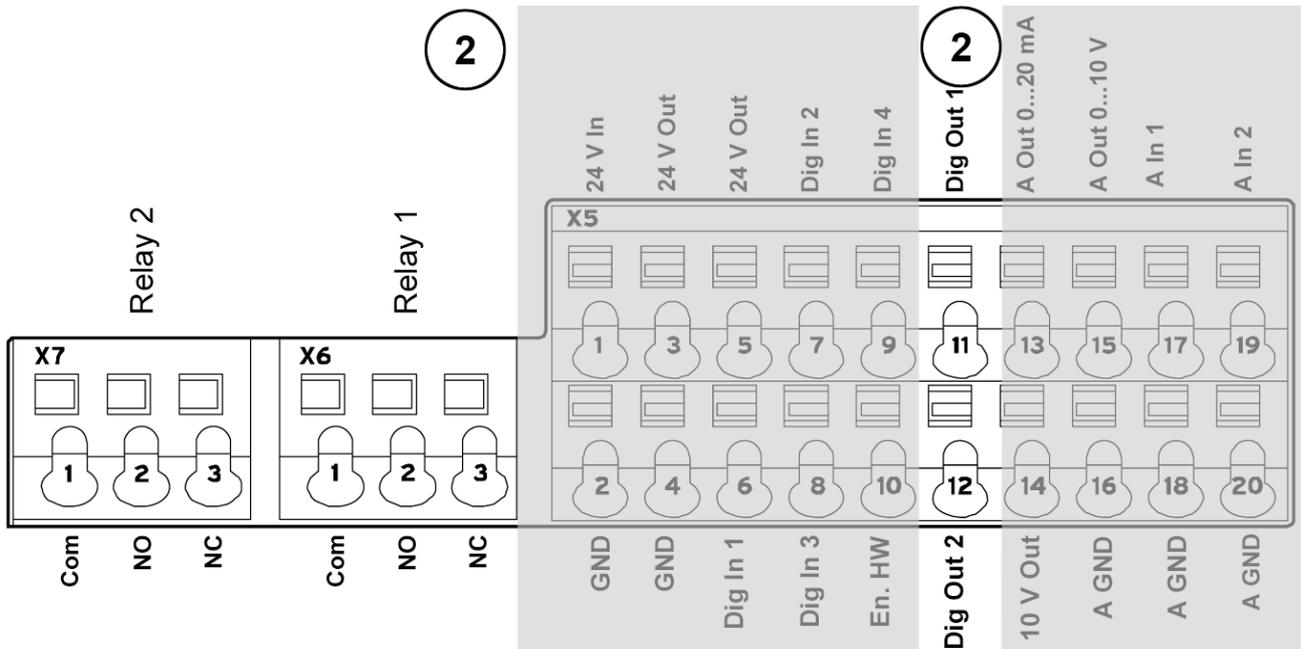
Size.	Torque
A - B	2 Nm (4 x M4 x 28)



(see also Chapter 3.4.7 Anschlussplan)

Terminal no.	Designation	Assignment
1	24 V In	Ext. power supply
2	GND (ground)	Ground
3	24 V Out	Int. power supply
4	GND (ground)	Ground
5	24 V Out	Int. power supply
6	Dig. In 1	Target value enable (parameter 1.131)
7	Dig. In 2	Free (not assigned)
8	Dig. In 3	Free (not assigned)
9	Dig. In 4	Error reset (parameter 1.180)
10	En HW (enable)	Enable hardware
13	A. Out 0 ... 20 mA	Actual frequency value (parameter 4.100)
14	10 V Out	For ext. voltage divider
15	A. Out 0 ... 10 V	Actual frequency value (parameter 4.100)
16	A GND (ground 10 V)	Ground
17	A. In 1	PID actual value (parameter 3.060)
18	A GND (Ground 10 V)	Ground
19	A. In 2	Free (not assigned)
20	A GND (ground 10 V)	Ground

Tab. 5: Terminal assignment X5 of the standard application board



(see also Chapter 3.4.7 Anschlussplan)

Terminal no.	Designation	Assignment
11	Dig. Out 1	Fault message (parameter 4.150)
12	Dig. Out 2	Free (not assigned)

X6 relay 1

Terminal no.	Designation	Assignment
1	COM	Centre contact relay 1
2	NO	Normally open relay 1
3	NC	Normally closed relay 1

Tab. 6: Terminal assignment X6 (relay 1)

i **INFORMATION**
 In the factory setting, relay 1 is programmed as “relay error” (parameter 4.190).

X7 relay

Terminal no.	Designation	Assignment
1	COM	Centre contact relay 2
2	NO	Normally open relay 2
3	NC	Normally closed relay 2

Tab. 7: Terminal assignment X7 (relay 2)

i **INFORMATION**
 In the factory setting, “no function” is assigned to relay 2 (parameter 4.210).

Control connections of the basic application board

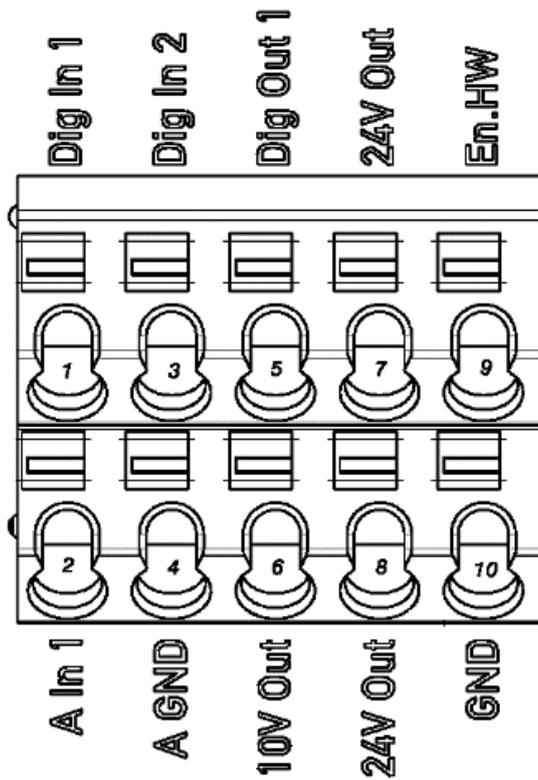


Fig. 21: Control connections of the basic application board

Terminal no.	Designation	Assignment
1	Dig. In 1	Target value enable (parameter 1.131)
2	A. In 1	Free (not assigned)
3	Dig. In 2	Free (not assigned)
4	A GND (ground 10 V)	Ground
5	Dig. Out	Fault message (parameter 4.150)
6	10 V Out	For ext. voltage divider
7	24 V Out	Int. power supply
8	24 V Out	Int. power supply
9	En HW (enable)	Enable hardware
10	GND (ground)	Ground

3.5 Installing the wall-mounted drive controller

3.5.1 Suitable installation location for wall mounting

Ensure that the installation location for an INVEOR wall mounting meets the following conditions:

- The drive controller has to be mounted on an even and fixed surface.
- The drive controller may only be mounted on non-flammable bases.
- There must be clearance of 200 mm around the drive controller to ensure free convection.

The following figure shows the assembly dimensions and the free spaces required for installing the drive controller. For the "wall mounting" version, the line length between the motor and INVEOR may not exceed 5 m (for exception, see Chapter 10.1 EMC limit classes). Only use a shielded cable with the required cross-section. There must be a PE connection (underneath the wall mounting's terminal board)!

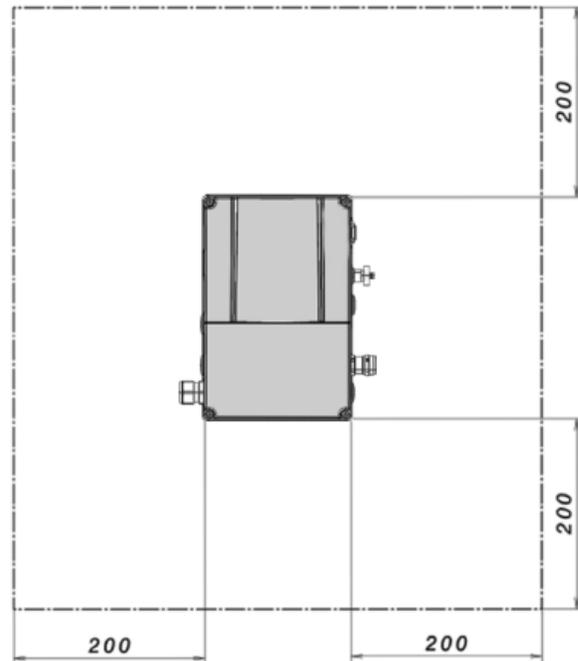


Fig. 22: Minimum clearances

3.5.2 Mechanical installation of sizes A - B

1. Open the motor connection box.



IMPORTANT INFORMATION

Depending on the required motor voltage, the star or triangle connection must be made in the motor connection box!

2. Use a suitable EMC screw connection to attach the shielded cable to the motor connection box! Ensure that the shielding contact is in order (large surface)!
3. Connect the prescribed PE connection in the motor connection box!
4. Close the motor connection box.



Fig. 23: Wiring on the motor connection box

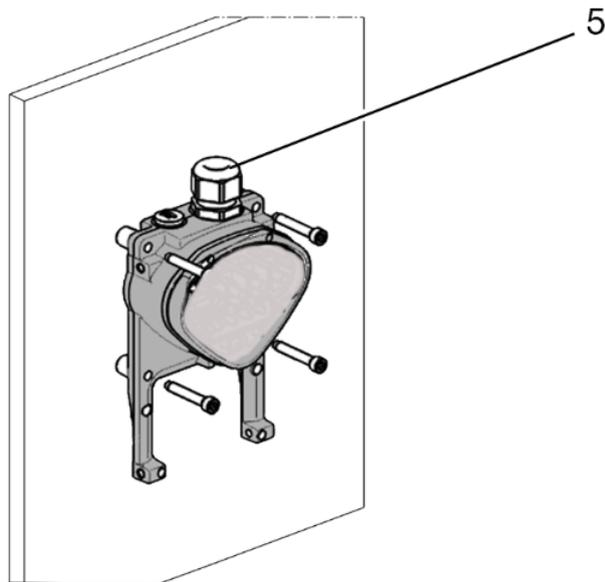


Fig. 24: Fastening the adapter plate to the wall



IMPORTANT INFORMATION

The drive controller may not be installed without an adapter plate!

- Find a position that meets the required ambient conditions described in the "[Installation requirements](#)" section.
- To achieve optimum self-convection of the drive controller, ensure that the (EMC) screw connection (5) is facing upwards during installation.
- If there is no additional ventilation for the INVEOR MP, only vertical installation is permitted.

Wiring of wall adapter plate, size A

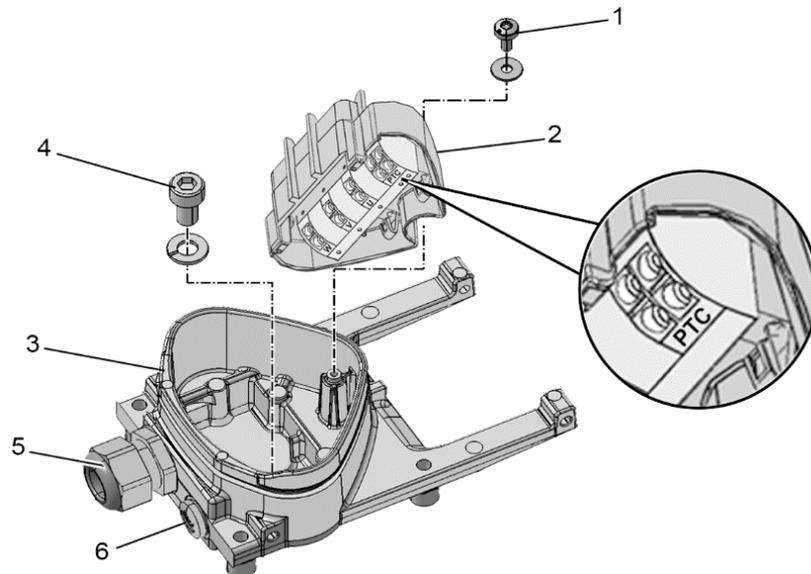
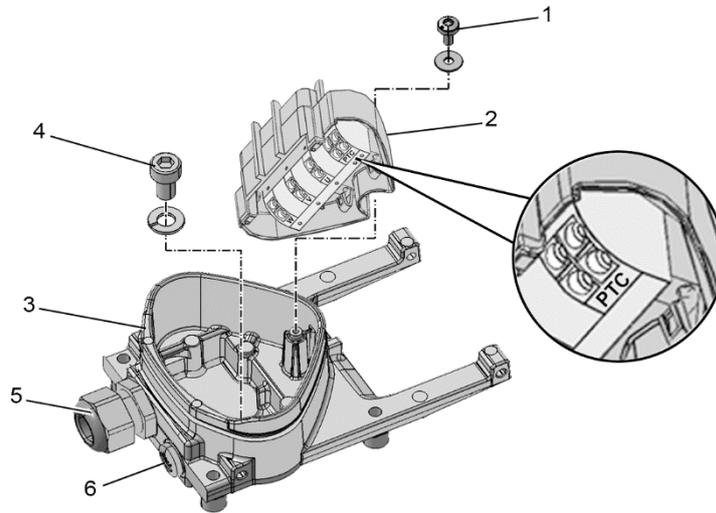


Fig. 25: Wiring of wall adapter plate, size A

1. Release the screw (1) to remove the contact plate (2) from the adapter plate (3).
The (M6 x 12) PE connection (4) is underneath the contact plate.
2. Guide the connection cable from the motor to the adapter plate (3) through the integrated EMC screw connection (5).



- This PE connection (torque: 4.0 Nm) must be made to the same ground potential as the motor.
The cross-section of the equipotential bonding line must correspond to at least the cross-section of the power cable.

DANGER!



Risk of death due to electrical shock!
Death or serious injury!

The drive controller must be grounded with the motor according to relevant regulations.

The PE connection between the motor and drive controller should be established using the hexagon socket screw (4) and the spring ring included in the scope of supply for the adapter plate (3).

- Wire the motor cable to contacts U, V, W (and the star point in some cases) in the connection terminal, as described in the "**Basic connection versions**" chapter.
- If there is a motor PTC present, connect to the corresponding terminals of contact plate (2).
Replace the dummy screw connection (6) with a suitable standard screw connection and guide the connecting cable to the motor PTC into the adapter plate (3).



IMPORTANT INFORMATION

Only motor PTCs corresponding to DIN 44081/44082 may be connected!

If the motor is **not** fitted with a temperature sensor, you must use the bridges contained in the scope of delivery of the drive controller on the terminal PTC.

- Refit the contact plate (2) in the adapter plate (3).
- Fasten the contact plate (2) using the screw (1) (torque: 1.2 Nm).



INFORMATION

After fastening the contact plate (2), ensure that it is mounted floating.

Installation

- Position the drive controller (7) on the adapter plate (3) so that the collar of the adapter dips into the opening on the floor of the cooling element.
- Fasten the drive controller (7) to the adapter plate (3) with the help of the screws (8) provided (torque: 4.0 Nm)

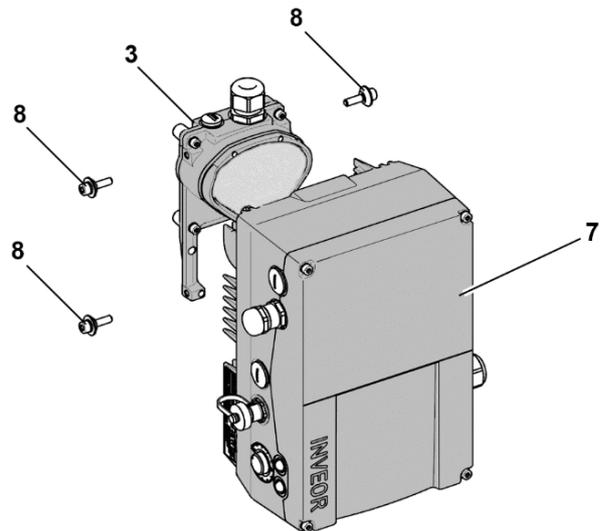


Fig. 26: Attaching the drive controller

Wiring of wall adapter plate, size B

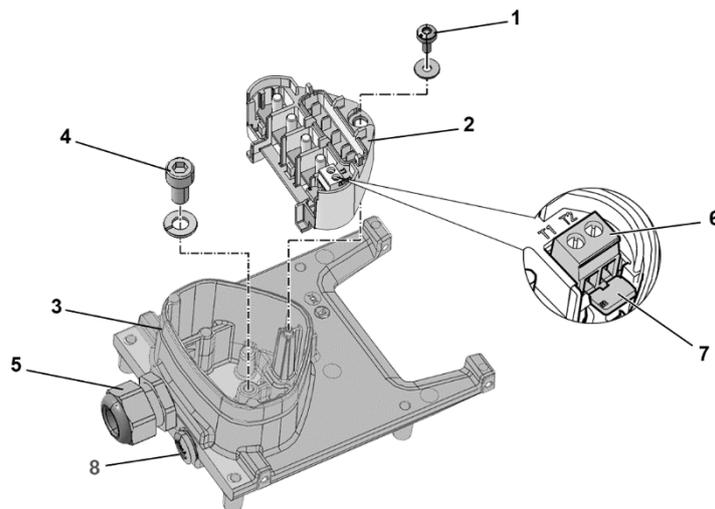


Fig. 27: Wiring of wall adapter plate, size B

- Release the screw (1) to remove the contact plate (2) from the adapter plate (3). The (M6 x 12) PE connection (4) is underneath the contact plate.
- Guide the connection cable from the motor to the adapter plate (3) through the integrated EMC screw connection (5).
- This PE connection (torque: 4.0 Nm) must be made to the same ground potential as the motor. The cross-section of the equipotential bonding line must correspond to at least the cross-section of the power cable.



DANGER!

**Risk of death due to electrical shock!
Death or serious injury!**

The drive controller must be grounded with the motor according to relevant regulations. The PE connection between the motor and drive controller should be established using the hexagon socket screw (4) and the spring ring included in the scope of supply for the adapter plate (3).

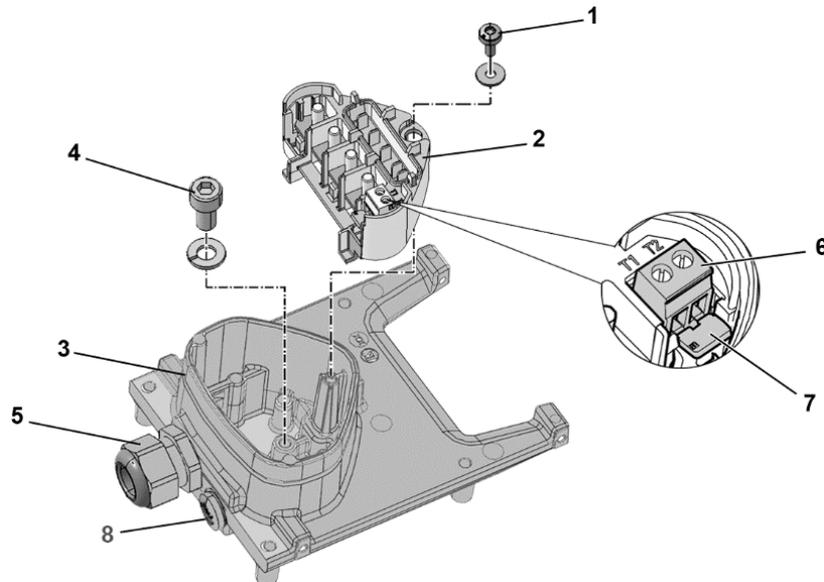


Fig. 28: Wiring of wall adapter plate, size B

4. Wire the motor cable to contacts U, V, W (and the star point in some cases) in the connection terminal, as described in the "**Basic connection versions**" chapter. Use cable shoes (M5) to do this.
5. Before connecting an existing motor PTC to the T1 and T2 terminals (6), remove the pre-assembled short-circuit bridge (7).
Replace the dummy screw (8) with a suitable standard screw connection and guide both ends to T1 and T2 (6).

! **IMPORTANT INFORMATION**

If the motor is fitted with a temperature sensor, this is connected to the T1 and T2 terminals (6). Remove the bridging contact (7) inserted for delivery for this purpose.
When the bridge is in place, the temperature of the motor is not monitored!
Only motor PTCs corresponding to DIN 44081/44082 may be connected!

6. Refit the contact plate (2) in the adapter plate (3).
7. Fasten the contact plate (2) using the screw (1) (torque: 1.2 Nm).

i **INFORMATION**

After fastening the contact plate (2), ensure that it is mounted floating.

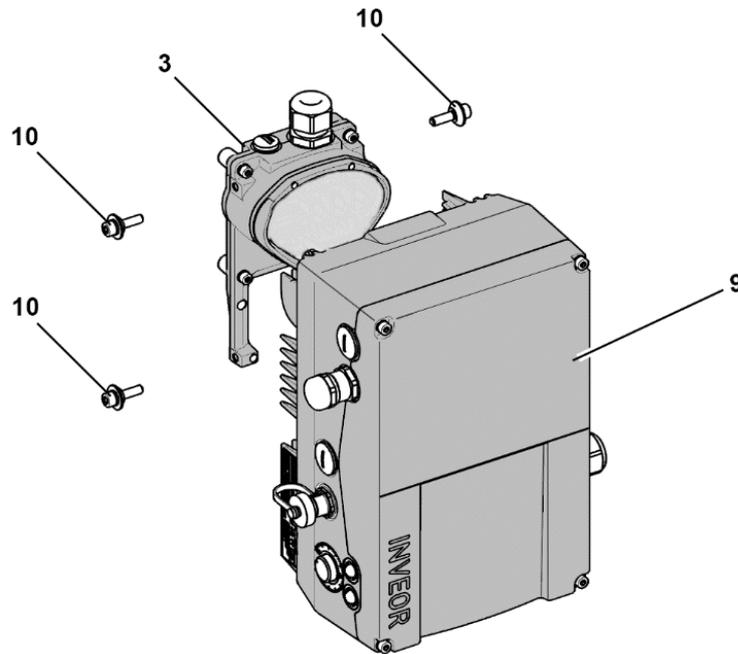


Fig. 29: Attaching the drive controller

8. Position the drive controller (9) on the adapter plate (3) so that the collar of the adapter dips into the opening on the floor of the cooling element.
9. Fasten the drive controller (9) to the adapter plate (3) with the help of the screws (10) provided (torque: 4.0 Nm).

4. Commissioning

4.1 Safety instructions for commissioning



DAMAGE TO PROPERTY POSSIBLE

If the information is not observed, the drive controller could be damaged and destroyed during subsequent commissioning. Commissioning may only be performed by qualified staff. Safety precautions and warnings must always be observed.



DANGER!

**Risk of death due to electrical shock!
Death or serious injury!**

Be sure that the power supply provides the correct voltage and is designed for the required current.

Use suitable circuit breakers with the prescribed nominal current between the mains and drive controller.

Use suitable fuses with appropriate current values between the mains and drive controller (see technical data).

The drive controller must be grounded with the motor according to relevant regulations. Non-compliance may result in serious injury.

4.2 Communication

The drive controller can be commissioned in the following ways:

- using the INVERTERpc PC software

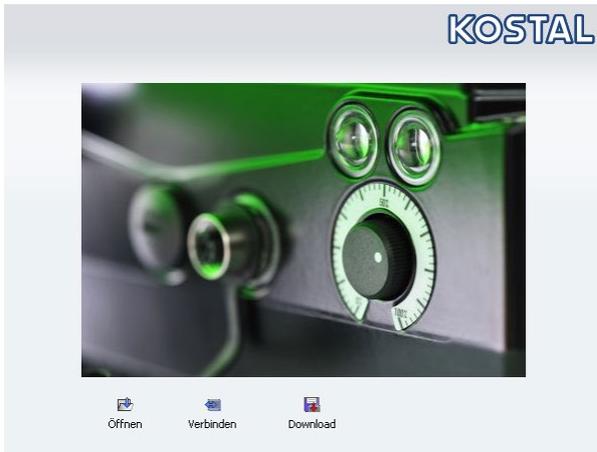


Fig. 30: PC software – start screen

- using the INVEOR MMI handheld controller*



Fig. 31: MMI handheld controller

- using the MMI* in the cover (MMI option)

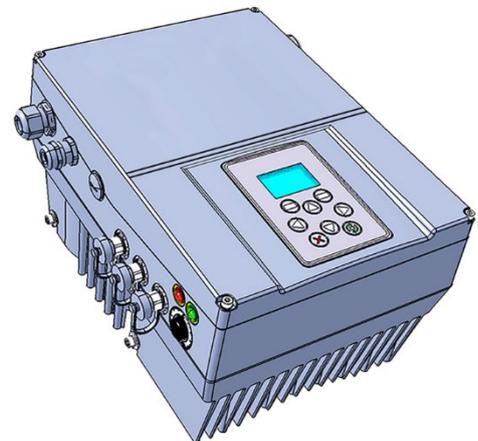


Fig. 32: MMI option

* Man-machine interface

- using Bluetooth (option)

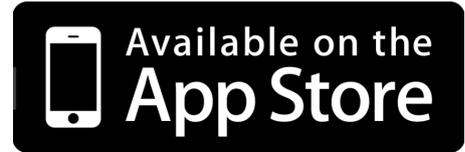


Fig. 33: INVERTERapp

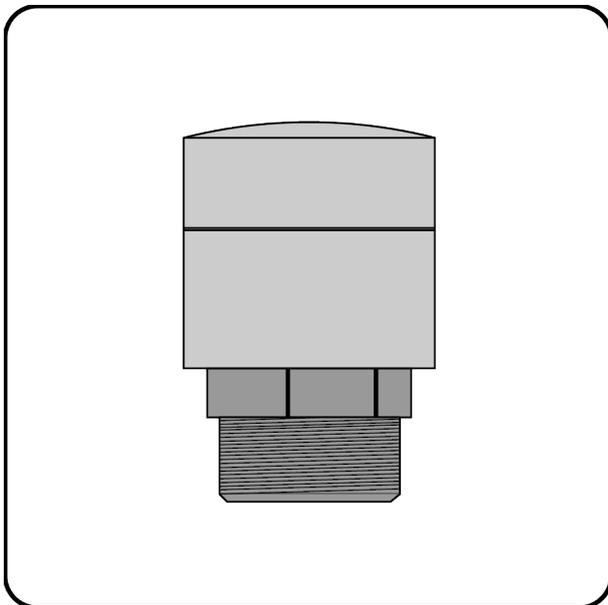


Fig. 34: Bluetooth module M16 (permanently fitted ex factory)

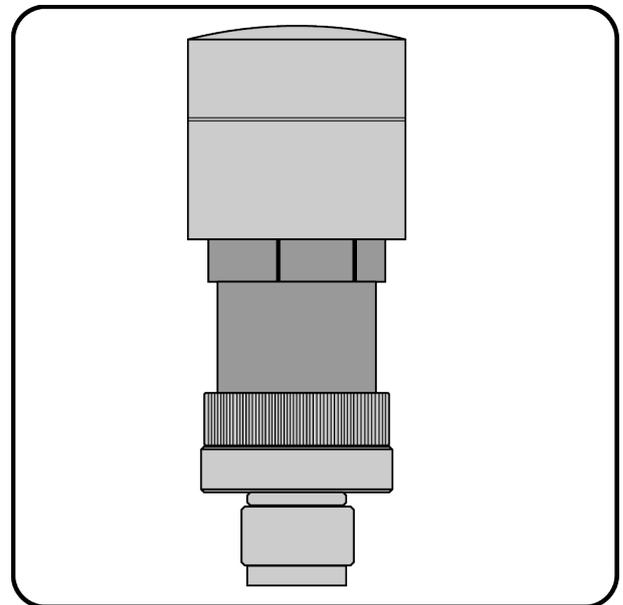


Fig. 35: Bluetooth stick M12 (optional accessories)

NOTE

If using the Bluetooth stick, the password is fixed as 000000.

4.3 Block diagram

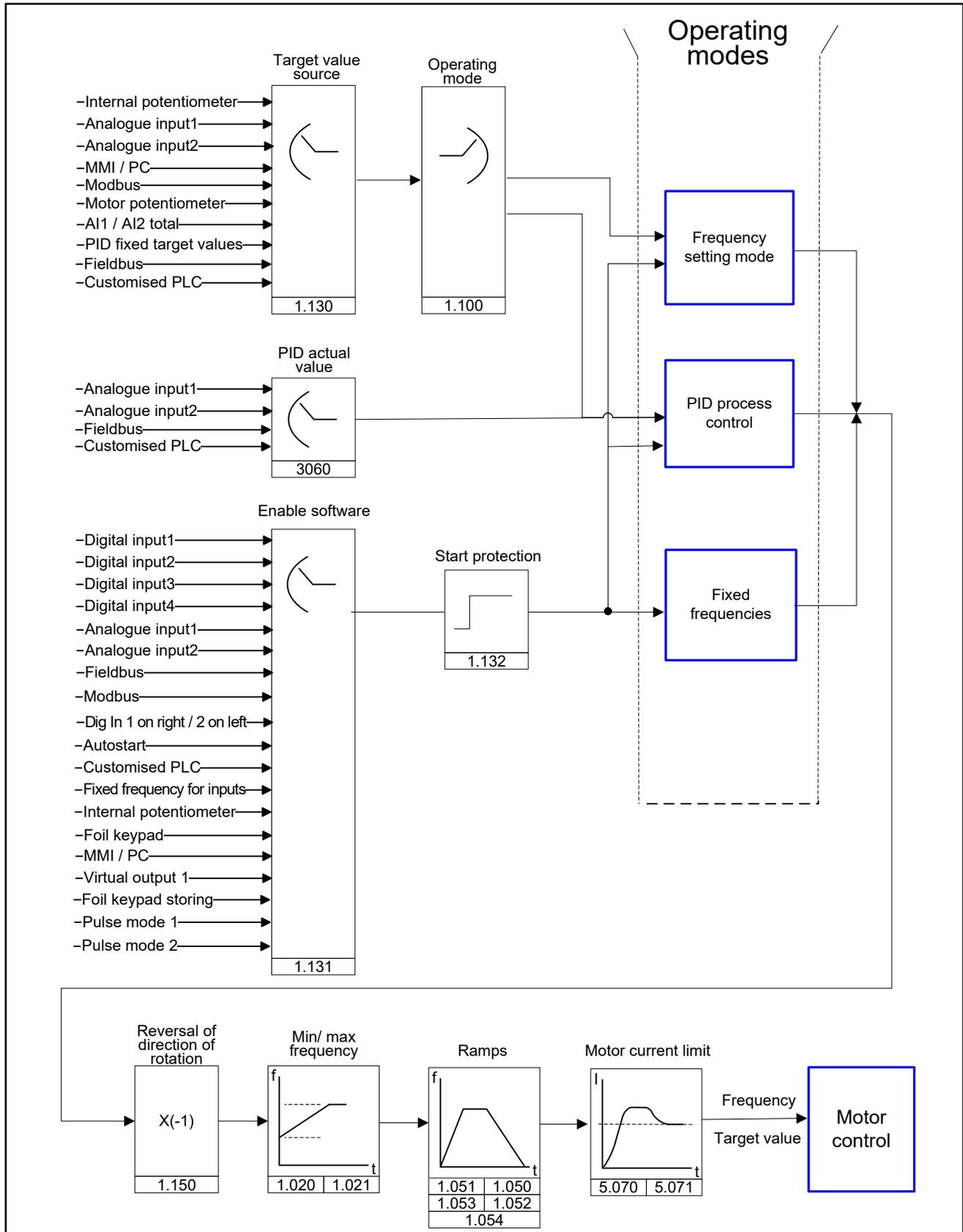


Fig. 36: General structure of target value generation

4.4 Commissioning steps



INFORMATION

Parameterisation is possible prior to device installation!
Parameterisation can be performed before the drive controller is installed in the motor.

The drive control has a 24 V low-voltage input for this purpose, which can supply the electric system without requiring mains power.

The commissioning can be performed using a USB PC communication cable to M12 plug with integrated interface converter RS485/RS232 (art. no. 10023950) or using the INVEOR MMI handheld controller with RJ9 connection cable to M12 plug (art no. 10004768).

4.4.1 Commissioning using the PC:

1. Install the INVERTERpc software (you can obtain programming software from KOSTAL free of charge. Required operating system: Windows 7 / 10 [32 / 64 bit]).
We recommend undertaking the installation process as an administrator.
2. Connect the PC to the M12 plug M1 with the optional connection cable.
3. Load or determine the motor data record (parameters 33.031 to 33.050); it may be necessary to optimise the speed control (parameters 34.090 to 34.091).
4. Perform the application settings (ramps, inputs, outputs, target values etc.).
5. Optional: Define an access level (1 – MMI, 2 – user, 3 – manufacturer).

In order to ensure an ideal operating structure for the PC software, the parameters are classified into different access levels.

The following levels exist:

1. handheld controller: – the drive controller is programmed using the handheld controller.
2. user: – the basic parameters can be programmed into the drive controller using the PC software.
3. manufacturer: - an extended selection of parameters can be programmed into the drive controller using the PC software.

See Fig. of block diagram in chapter [Quickstart guide 11](#)

4.4.2 Commissioning using PC, combined with MMI option

1. Install the INVERTERpc software (you can obtain programming software from KOSTAL free of charge. Required operating system: Windows 7 / 10 [32 / 64 bit]). We recommend undertaking the installation process as an administrator.
2. Connect the PC to the M12 plug M1 with the optional connection cable.



IMPORTANT INFORMATION

After the power on the drive controller has been switched on, the diagnosis interface (M12 PC/MMI) is initially inactive.

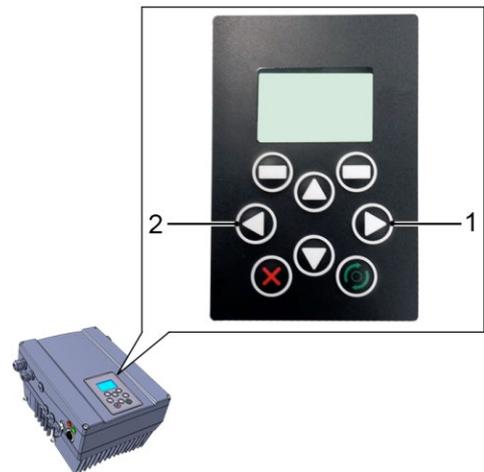
To activate this interface, the "MMI option" has to be put into standby mode.

To do this, simultaneously press buttons (1) and (2) for approx. 1.5 sec.

"Standby" appears in the MMI display and internal communication is interrupted for 25 sec.

If communication for the INVERTERpc tool is established within 25 sec., the "MMI option" remains in standby mode.

Data can now be exchanged with the PC and/or an external MMI. If communication is aborted or cannot be established within 25 sec., the "MMI option" switches from standby mode to normal mode.



Turning the display 180 °

Depending on how the INVEOR is installed within the system, the display may have to be turned 180°.

You can turn the display 180 ° using parameter 5.200 by setting the parameter value to "1"

Alternatively, the display can also be turned 180 ° in "normal mode".

To do this, simultaneously press buttons (3) and (4) for approx. 1.5 sec.

The display and functional button assignment are turned 180 °.



INFORMATION

The display is only turned 180 ° once the "Disconnect" button has been pressed in the "INVERTERpc tool".

5. Parameter

This chapter contains the following:

- an introduction to the parameters
- an overview of the most important commissioning and operation parameters

5.1 Safety instructions for working with parameters

DANGER!



Risk of death due to restarting motors! Death or serious injury!

Non-observance may result in death, serious injury or damage.

Certain parameter settings and changing parameter settings during operation may result in the INVEOR drive controller restarting automatically after the supply voltage has failed, or in undesirable changes in the operating behaviour.



INFORMATION

If parameters are changed while the device is in operation, it may take a few seconds for the effect to become noticeable.

Frequency setting mode:

The target values from the "target value source" (1.130) are rescaled into target frequency values.

0 % is the "minimum frequency" (1.020).

100 % is the "maximum frequency" (1.021).

The target value's plus or minus sign is the decisive factor in rescaling.

PID process control:

The target value for the PID process controller is imported in percentage steps as in the "PID process control" operating mode. 100 % corresponds to the working range of the connected sensor, which is read in via the actual value input (selected by the "PID actual value").

Depending on the control difference, a rotation speed value is output to the control output with the help of the amplification factors for the proportional gain (3.050), integral gain (3.051) and derivative gain (3.052).

In order to prevent the integral share from increasing infinitely in the case of uncontrollable control differences, this value is limited to a specific set value (corresponding to the "maximum frequency" (1.021)).

5.2 General information on parameters

5.2.1 Explanation of operating modes

The operating mode is the instance in which the target value is generated.

In the case of frequency setting mode, this is a simple conversion of the raw input target value into a rotation speed target value. In the case of PID process control, the target value and actual value are compared and the system then regulates to a specific process variable.

PID inverted:

The PID actual value can be inverted using parameter 3.061. The actual value is imported inversely, i.e. 0 V...10 V correspond internally to 100 %...0 %.

Please note that the target value must also be defined inversely.

An example:

A sensor with an analogue output signal (0 V...10 V) is to operate as the source of the actual value (at AIx). At an output variable of 7 V (70 %), this is to be regulated inversely. The internal actual value then corresponds to 100% – 70% = 30%.

In other words, the target value to be specified is 30 %.

Operating mode PID process controller

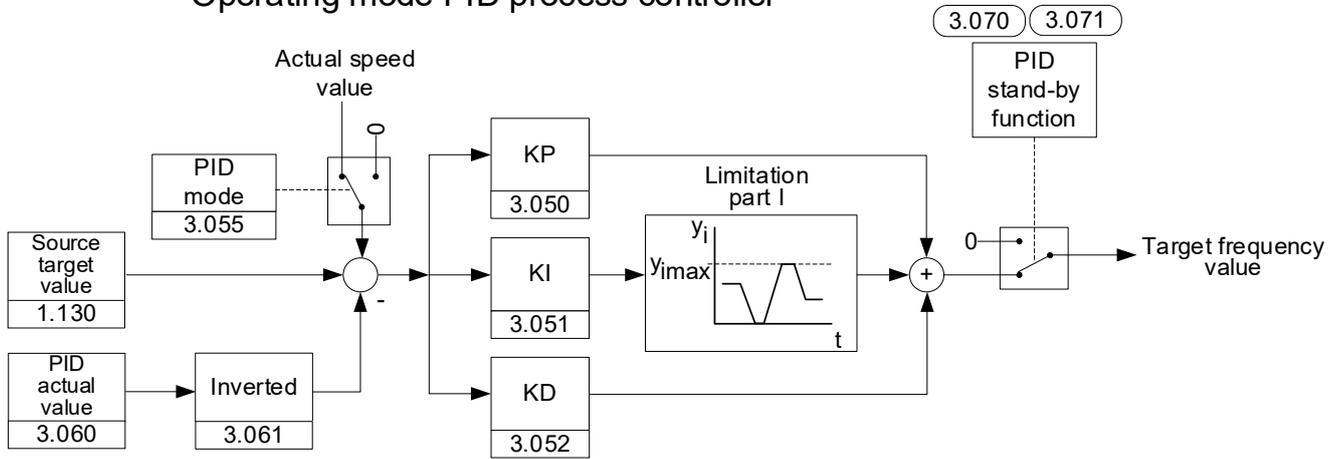


Fig. 37: PID process control

Stand-by function in PID process control

This function can provide energy savings in applications such as booster stations where PID process control is used to control to a specific process value and the pump has to run at a "minimum frequency" (1.020). As the drive controller can reduce the rotation speed of the pump in normal operation when the process variable is reducing, but it can never fall below the "minimum frequency" (1.020), this provides an opportunity for stopping the motor if it is running during a waiting time, the "PID stand-by time" (3.070) with the "minimum frequency" (1.020).

Once the actual value deviates from the target value by the set % value, the "PID stand-by hysteresis" (3.071), the control (the motor) is started again.

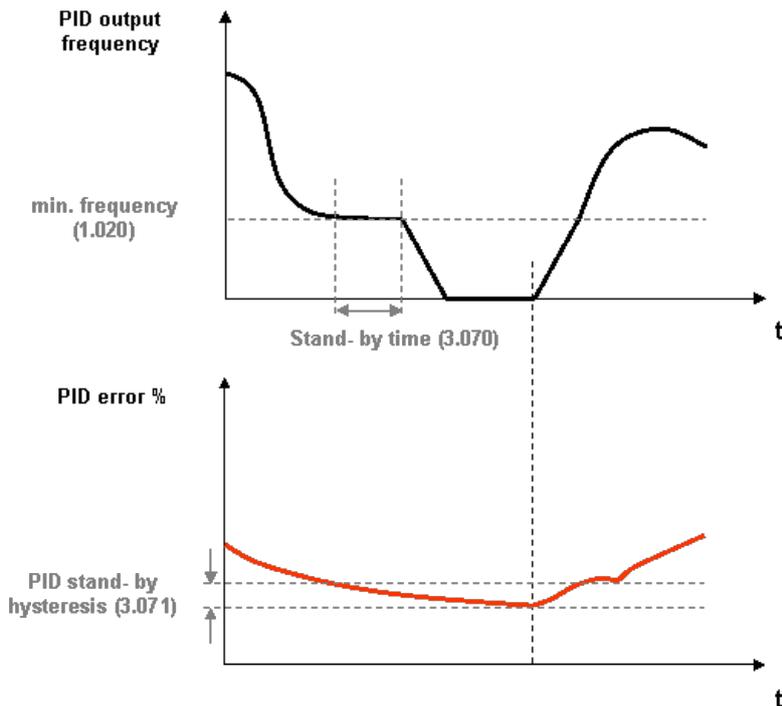


Fig. 38: Stand-by function in PID process control

Fixed frequency

This operating mode controls the drive controller with up to 7 fixed target values.

These are selected under parameter 2.050, where you can select how many fixed frequencies are to be used.

Parameter	Name	Selection options	Function	Number of digital inputs needed
2.050	Fixed frequency/mode	0	1 fixed frequency	1
		1	3 fixed frequencies	2
		2	7 fixed frequencies	3
	Foil keypad (option)	3	2 fixed frequencies	-
	Foil keypad (option)	4	4 fixed frequencies	-

Depending on the number of fixed frequencies required, up to 3 digital inputs are permanently assigned in the table.

Parameter	Name	Presetting	DI 3	DI2	DI1
1.020	Min. frequency	0 Hz	0	0	0
2.051 bis 2.057	Fixed frequency 1	10 Hz	0	0	1
2.051 bis 2.057	Fixed frequency 2	20 Hz	0	1	0
2.051 bis 2.057	Fixed frequency 3	30 Hz	0	1	1
2.051 bis 2.057	Fixed frequency 4	35 Hz	1	0	0
2.051 bis 2.057	Fixed frequency 5	40 Hz	1	0	1
2.051 bis 2.057	Fixed frequency 6	45 Hz	1	1	0
2.051 bis 2.057	Fixed frequency 7	50 Hz	1	1	1

Tab. 8: Logic table for fixed frequencies

5.2.2 Structure of the parameter tables

1	2	3	4	5
1.100	Operating mode		Unit: integer	
Relationship to parameter:	Transfer status: 2		min: 0	own value (to be entered!)
1.131 1.130 2.051 to 2.057			max: 4	
			def.: 0	
	Selection of operating mode, see page ... (reference to explanation in advance) Following successful software enabling (1.131) and hardware enabling, the drive controller runs as follows 0 = frequency setting mode, with the target value of the selected target value source (1.130), 1 = PID process controller, with the target value of the PID process controller, 2 = fixed frequencies, with the frequencies defined in parameters 2.051 – 2.057			
8	7	6		

Fig. 39 Example of a parameter table

Key			
1	Parameter number	5	Unit
2	Parameter name	6	Field for entering an own value
3	Transfer status 0 = switch drive controller off and on for transfer 1 = at speed of 0 2 = during operation	7	Explanation of the parameter
4	Value range (from – to – factory setting)	8	Other parameters related to this parameter.

5.3 Application parameters

5.3.1 Basic parameter

1.020	Minimum frequency	Unit: Hz	
Relationship to parameter: 1.150 3.070 3.080 5.085	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 599	
		def.: 0	
	The minimum frequency is the frequency which is supplied by the drive controller as soon as it is enabled and there is no additional target value. The frequency falls below this level if: a) the drive accelerates from stationary b) the frequency converter is blocked. The frequency then falls to 0 Hz before it is blocked. c) the frequency converter reverses (1.150). The field of rotation reverses at 0 Hz. d) the standby function (3.070) is active. e) the current limit is reached		

1.021	Maximum frequency	Unit: Hz	
Relationship to parameter: 1.050 1.051	Transfer status: 2	min.: 5	Own value (to be entered!)
		max.: 599	
		def.: 50	
	The maximum frequency is the highest frequency produced by the inverter depending on the target value.		

1.050	Deceleration time 1	Unit: s	
Relationship to parameter: 1.021 1.054	Transfer status: 2	min.: 0.001	Own value (to be entered!)
		max.: 1000	
		def.: 5	
	Deceleration time 1 is the time that the drive controller needs to brake to 0 Hz from the max. frequency (1.021). If the set deceleration time cannot be reached, the fastest possible deceleration time is implemented.		

1.051	Run up time 1	Unit: s	
Relationship to parameter: 1.021 1.054	Transfer status: 2	min.: 0.001	Own value (to be entered!)
		max.: 1000	
		def.: 5	
	Run up time 1 is the time that the drive controller needs to accelerate from 0 Hz to the max. frequency. The run up time can be increased as a result of certain circumstances, e.g. if the drive controller is overloaded.		

1.052	Deceleration time 2	Unit: s	
Relationship to parameter: 1.021 1.054	Transfer status: 2	min.: 0.001	Own value (to be entered!)
		max.: 1000	
		def.: 10	
	Deceleration time 2 is the time that the drive controller needs to brake to 0 Hz from the max. frequency (1.021). If the set deceleration time cannot be reached, the fastest possible deceleration time is implemented.		

Parameter

1.053	Run up time 2	Unit: s	
Relationship to parameter: 1.021 1.054	Transfer status: 2	min.: 0.001	Own value (to be entered!)
		max.: 1000	
		def.: 10	
Run up time 2 is the time that the drive controller needs to accelerate from 0 Hz to the max. frequency. The acceleration time can be increased as a result of certain circumstances, e.g. if the drive controller is overloaded.			

1.054	Ramp selection	Unit: integer	
Relationship to parameter: 1.050 - 1.053	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 9	
		def.: 0	
Selection of used ramp pair 0 = deceleration time 1 (1.050) / run up time 1 (1.051) 1 = deceleration time 2 (1.052) / run up time 2 (1.053) 2 = digital input 1 (false = ramp pair 1 / true = ramp pair 2) 3 = digital input 2 (false = ramp pair 1 / true = ramp pair 2) 4 = digital input 3 (false = ramp pair 1 / true = ramp pair 2) 5 = digital input 4 (false = ramp pair 1 / true = ramp pair 2) 6 = customer PLC 7 = analogue input 1 (must be selected in parameter 4.030) 8 = analogue input 2 (must be selected in parameter 4.060) 9 = virtual output (4.230)			

1.088	Rapid stop	Unit: s	
Relationship to parameter:	Transfer status: 2	min.: 0.1	Own value (to be entered!)
		max.: 1000	
		def.: 10	
Only for variant with functional safety The rapid stop parameter prescribes the time that the inverter requires to brake to 0 Hz from the max. speed (1.021). If the set rapid stop time cannot be achieved, the fastest possible deceleration time is implemented.			

1.100	Operating mode	Unit: integer	
Relationship to parameter: 1.130 1.131 2.051 to 2.057 3.050 to 3.071	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 3	
		def.: 0	
Selecting the operating mode Following software enabling (1.131) and hardware enabling, the drive controller runs as follows: 0 = frequency setting mode, with the target value of the selected target value source (1.130) 1 = PID process controller, with the target value of the PID process controller (3.050 – 3.071), 2 = fixed frequencies, with the frequencies defined in parameters 2.051 – 2.057 3 = selection via INVEOR soft PLC			

Parameter

1.130	Target value source	Unit: integer	
Relationship to parameter: 3.062 to 3.069	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10	
		def.: 0	
Determines the source from which the target value is to be read. 0 = internal potentiometer 1 = analogue input 1 2 = analogue input 2 3 = MMI/PC 4 = Modbus 6 = motor potentiometer 7 = sum of analogue inputs 1 and 2 8 = PID fixed target values (3.062 to 3.069) 9 = fieldbus 10 = INVEOR soft PLC			

1.131	Enable software	Unit: integer	
Relationship to parameter: 1.132 1.150 2.050 4.030 4.030 / 4.060	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 16	
		def.: 0	
<div style="background-color: #f0f0f0; padding: 5px;">  DANGER! The motor may start immediately, depending on the change made. Selection of the source for the control release. 0 = digital input 1 1 = digital input 2 2 = digital input 3 3 = digital input 4 4 = analogue input 1 (must be selected in parameter 4.030) 5 = analogue input 2 (must be selected in parameter 4.060) 6 = fieldbus 7 = Modbus 8 = digital input 1 on right / digital input 2 on left 1.150 must be set to "0" 9 = autostart The motor may start immediately if hardware is enabled and a target value has been provided. This cannot be prevented even with parameter 1.132. 10 = INVEOR soft PLC 11 = fixed frequency inputs (all inputs which were selected in parameter 2.050) 12 = internal potentiometer 13 = foil keypad (Start & Stop keys) 14 = MMI/PC 15 = virtual output (4.230) 16 = foil keypad storing 17 = edge for Dig In 1 start / Dig In 2 stop 18 = edge for Dig In 1 start on right / edge for Dig In 2 start on left / Dig In 3 stop (1.150 must be set to "0") </div>			

Parameter

1.132	Start-up protection	Unit: integer	
Relationship to parameter: 1.131	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 8	
		def.: 1	
Selection of behaviour in response to enabling software (parameter 1.131). No effect if autostart was selected. 0 = immediate start with high signal at input of control enable 1 = start only with rising edge at input of control enable 2 = digital input 1 (function active with high signal) 3 = digital input 2 (function active with high signal) 4 = digital input 3 (function active with high signal) 5 = digital input 4 (function active with high signal) 6 = INVEOR soft PLC 7 = analogue input 1 (must be selected in parameter 4.030) 8 = analogue input 2 (must be selected in parameter 4.060)			

1.150	Rotation direction	Unit: integer	
Relationship to parameter: 1.131 4.030 4.030 / 4.060	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 16	
		def.: 0	
Selection of direction of rotation specification 0 = dependent on target value (depending on the plus or minus sign of the target value: positive: forwards; negative: backwards) 1 = forwards only (no change in direction of rotation possible) 2 = backwards only (no change in direction of rotation possible) 3 = digital input 1 (0 V = forwards, 24 V = backwards) 4 = digital input 2 (0 V = forwards, 24 V = backwards) 5 = digital input 3 (0 V = forwards, 24 V = backwards) 6 = digital input 4 (0 V = forwards, 24 V = backwards) 7 = INVEOR soft PLC 8 = analogue input 1 (must be selected in parameter 4.030) 9 = analogue input 2 (must be selected in parameter 4.060) 10 = foil keypad key for reversing direction of rotation (only when motor is running) 11 = foil keypad key I forwards / 2 backwards (reversal always possible) 12 = foil keypad key I forwards / 2 backwards (reversal only possible when motor stationary) 13 = virtual output (4.230) 14 = foil keypad key for reversing direction of rotation (only in operational status) storing 15 = foil keypad key I + II storing 16 = foil keypad key I + II (only if motor is stationary) stores the last active rotation direction			

5.3.2 Fixed frequency

This mode has to be selected in parameter 1.100, see also the section on selecting the operating mode.

2.050	Fixed frequency mode	Unit: integer	
Relationship to parameter: 1.100 2.051 to 2.057	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 4	
		def.: 2	
	Selection of the digital inputs used for fixed frequencies 0 = Digital In 1 (Fixed frequency 1) (2.051) 1 = Digital In 1, 2 (Fixed frequencies 1 - 3) (2.051 to 2.053) 2 = Digital In 1, 2, 3 (Fixed frequencies 1 - 7) (2.051 to 2.057) 3 = foil keypad (key I = fixed frequency 1 / key II = fixed frequency 2) 4 = fixed frequency (key I = fixed frequency 1 / key II = fixed frequency 2) storing		

2.051 to 2.057	Fixed frequency	Unit: Hz	
Relationship to parameter: 1.020 1.021 1.100 1.150 2.050	Transfer status: 2	min.: - 599	Own value (to be entered!)
		max.: + 599	
		def.:	
	The frequencies that are to be output at the digital inputs 1 - 3 specified in parameter 2.050 depending on the switching patterns. See chapter 5.2.1 Explanation of operating modes / fixed frequency.		

5.3.3 Motor potentiometer

This mode must be selected in parameter 1.130.

The function can be used as a target value source for frequency mode and for the PID process controller.

The motor potentiometer can be used to gradually increase / decrease the target value (PID/frequency). Use parameters 2.150 to 2.154 for this purpose.

2.150	MOP digital Input	Unit: integer	
Relationship to parameter: 1.130 4.030 4.050	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 8	
		def.: 3	
	Selection of the source for increasing and reducing the target value 0 = digital input 1 + / digital input 2 - 1 = digital input 1 + / digital input 3 - 2 = digital input 1 + / digital input 4 - 3 = digital input 2 + / digital input 3 - 4 = digital input 2 + / digital input 4 - 5 = digital input 3 + / digital input 4 - 6 = analogue input 1 + / analogue input 2 - (must be selected in parameters 4.030 / 4.050) 7 = INVEOR soft PLC 8 = foil keypad (key 1 - / key 2 +)		

2.151	MOP step range	Unit: %	
Relationship to parameter: 1.020 1.021	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 1	
	Increments at which the target value changes per keystroke.		

Parameter

2.152	MOP step time	Unit: s	
Relationship to parameter:	Transfer status: 2	min.: 0.02	Own value (to be entered!)
		max.: 1000	
		def.: 0.04	
		Indicates the time during which the target value is totalled with a permanent signal.	

2.153	MOP response time	Unit: s	
Relationship to parameter:	Transfer status: 2	min.: 0.02	Own value (to be entered!)
		max.: 1000	
		def.: 0.3	
		Indicates the time for which the signal is considered permanent.	

2.154	MOP reference memory	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
		Defines whether the target value of the motor potentiometer is retained even after power outage. 0 = disable 1 = enable	

5.3.4 PID process controller

This mode must be selected in parameter 1.100,
the target value source must be selected in parameter 1.130,
see also chapter 5.2.1 Explanation of operating modes / fixed frequency.

3.050	PID-P amplification factor	Unit:	
Relationship to parameter: 1.100 1.130	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 1	
		Proportional share of PID controller amplification factor	

3.051	PID-I amplification factor	Unit: 1/s	
Relationship to parameter: 1.100 1.130	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 1	
		Integral share of PID controller amplification factor	

3.052	PID-D amplification factor	Unit: s	
Relationship to parameter: 1.100 1.130	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 0	
		Differential share of PID controller amplification factor	

Parameter

3.055	PID mode	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
Switches can be made between PID modes here: 0: Standard (no consideration of actual frequency) 1: with consideration of actual frequency			

3.060	PID actual value	Unit: integer	
Relationship to parameter: 1.100 1.130 3.061	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 3	
		def.: 0	
Selection of the input source from which the actual value for the PID process controller is imported: 0 = analogue input 1 1 = analogue input 2 2 = INVEOR soft PLC 3 = fieldbus (fixed customer-specific input variable 2)			

3.061	PID inverted	Unit: integer	
Relationship to parameter: 3.060	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
The actual value source (parameter 3.060) is inverted 0 = disable 1 = enable			

3.062 to 3.068	PID fixed target values	Unit: %	
Relationship to parameter: 1.130 3.069	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 0	
The PID fixed target values which are to be issued depending on the switching patterns at the digital inputs 1 – 3 specified in parameter 3.069 (has to be selected in parameter 1.130).			

3.069	PID fixed target mode	Unit: integer	
Relationship to parameter: 1.100 3.062 to 3.068	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 2	
		def.: 0	
Selection of the digital inputs used for fixed frequencies 0 = Digital In 1 (PID fixed target value 1) (3.064) 1 = Digital In 1, 2 (PID fixed target values 1 – 3) (3.062 to 3.064) 2 = Digital In 1, 2, 3 (PID fixed target values 1 – 7) (3.062 to 3.068)			

Parameter

3.070	PID standby time	Unit: s	
Relationship to parameter: 1.020	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10000	
		def.: 0	
<p>If the drive controller runs for the set time at its minimum frequency (parameter 1.020), the motor is stopped (0 Hz), see also Chapter 5.2.1 Explanation of operating modes / fixed frequency. 0 = disable > 0 = waiting time until stand-by function is enabled</p>			

3.071	PID stand-by hysteresis	Unit: %	
Relationship to parameter: 3.060	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 50	
		def.: 0	
<p>Condition for waking up the PID controller from stand-by. Once the control difference exceeds the set value as %, the control begins again, see also PID controller operating modes.</p>			

3.072	PID dry run time	Unit: s	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 32767	
		def.: 0	
<p>After this set time, if the PID actual value has not reached at least 5 % and the controller is running at the max. limit, the INVEOR switches off with error no. 16 PID dry run.</p>			

3.073	PID target value min	Unit: %	
Relationship to parameter: 3.074	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 0	
<p>The PID target value can be limited using 2 parameters. Example: 0 -10 V target value potentiometer Read Min PID target value = 20 % Read Max PID target value = 80 % (3.074) Target value at < 2 V = 20 % Target value at 2 V – 8 V = 20 % - 80 % Target value at > 8 V = 80 %</p>			

3.074	PID target value max	Unit: %	
Relationship to parameter: 3.073	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 100	
<p>The PID target value can be limited using 2 parameters. Example: 0 -10 V target value potentiometer Read Min PID target value = 20 % Read Max PID target value = 80 % (3.073) Target value at < 2 V = 20 % Target value at 2 V – 8 V = 20 % - 80 % Target value at > 8 V = 80 %</p>			

Parameter

3.080	PID minimum frequency 2	Unit: Hz	
Relationship to parameter: 1.020	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 400	
		def.: 0	
	The minimum frequency is calculated depending on the PID target value Example: 1.020 minimum frequency = 10 Hz 3.080 PID minimum frequency 2 = 20 Hz Minimum frequency when PID target value is 0 % = 10 Hz Minimum frequency when PID target value is 50 % = 15 Hz Minimum frequency when PID target value is 100 % = 20 Hz		

5.3.5 Analogue inputs

For analogue inputs 1 and 2 (Aix display AI1/AI2)

4.020 / 4.050	Aix input type	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 1	Own value (to be entered!)
		max.: 2	
		def.: 1	
	Function of analogue inputs 1 / 2. 1 = voltage input 2 = current input		

4.021 / 4.051	Aix standard Low	Unit: %	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 0	
	Specifies the minimum value of the analogue inputs as a percentage of the range Example: 0...10 V and/or 0...20 mA = 0 %...100 % 2...10 V or 4...20 mA = 20 %...100 %		

4.022 / 4.052	Aix standard High	Unit: %	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 100	
	Specifies the maximum value of the analogue inputs as a percentage of the range. Example: 0...10 V and/or 0...20 mA = 0 %...100 % 2...10 V or 4...20 mA = 20 %...100 %		

4.023 / 4.053	Aix dead time	Unit: %	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 0	
	Dead time as percentage of the range of the analogue inputs.		

Parameter

4.024 / 4.054	Aix filter time	Unit: s	
Relationship to parameter:	Transfer status: 2	min.: 0.02	Own value (to be entered!)
		max.: 1.00	
		def.: 0	
Filter time of analogue inputs in seconds.			

4.030 / 4.060	Aix function	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
Function of analogue inputs 1/2 0 = analogue input 1 = digital input			

4.033 / 4.063	Aix physical unit	Unit:	
Relationship to parameter: 4.034 / 4.064 4.035 / 4.065	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 15	
		def.: 0	
Selection of different physical values to be displayed. 0 = % 1 = bar 2 = mbar 3 = psi 4 = Pa 5 = m ³ /h 6 = l/min 7 = °C 8 = °F 9 = m 10 = mm			

4.034 / 4.064	Aix physical minimum	Unit:	
Relationship to parameter: 4.033 / 4.063 4.035 / 4.065	Transfer status: 2	min.: - 10000	Own value (to be entered!)
		max.: + 10000	
		def.: 0	
Selection of the lower limit of a physical value to be displayed.			

4.035 / 4.065	Aix physical maximum	Unit:	
Relationship to parameter: 4.033 / 4.063 4.034 / 4.064	Transfer status: 2	min.: - 10000	Own value (to be entered!)
		max.:+ 10000	
		def.: 100	
Selection of the upper limit of a physical value to be displayed.			

4.036 / 4.066	Aix wire break time	Unit:	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 32767	
		def.: 0.5	
Once the mains is activated, wire break detection is only activated after this set time			

Parameter

4.037 / 4.067	Aix inverted	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
<p>The signal of the analogue input can be inverted here.</p> <p>0 = disable (example: 0 V = 0 % 10 V = 100 %)</p> <p>1 = enable (example: 0 V = 100 % 10 V = 0 %)</p>			

5.3.6 Digital inputs

4.110 to 4.113	Dlx inverted	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
<p>This parameter can be used to invert the digital input.</p> <p>0 = disable</p> <p>1 = enable</p>			

5.3.7 Analogue output

4.100	AO1 function	Unit: integer	
Relationship to parameter: 4.101 4.102	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 40	
		def.: 0	
<p>Selection of the process value that is output at the analogue output. Depending on the process value selected, the standardisation (4.101 / 4.102) must be adapted.</p> <ul style="list-style-type: none"> 0 = Not assigned / INVEOR soft PLC 1 = Intermediate circuit voltage 2 = Grid voltage 3 = Motor voltage 4 = Motor current 5 = Actual frequency 6 = Speed measured externally by speed sensor (if available) 7 = Current angle or position (if available) 8 = IGBT temperature 9 = Inner temperature 10 = Analogue input 1 11 = Analogue input 2 12 = Target frequency 13 = Motor rating 14 = Torque 15 = Fieldbus 16 = PID target value 17 = PID actual value 18 = Target frequency value after ramp 19 = Actual speed value 20 = Actual frequency value sum 21 = Torque sum 22 = Target frequency value after ramp sum 23 = Target frequency value sum 24 = Actual speed value sum 			

Parameter

4.101	AO1 standard Low	Unit:	
Relationship to parameter: 4.100	Transfer status: 2	min.: - 10000	Own value (to be entered!)
		max.:+ 10000	
		def.: 0	
Describes which area is to be broken down into the 0-10 V output voltage or the 0-20 mA output current.			

4.102	AO1 standard High	Unit:	
Relationship to parameter: 4.100	Transfer status: 2	min.: - 10000	Own value (to be entered!)
		max.:+ 10000	
		def.: 0	
Describes which area is to be broken down into the 0-10 V output voltage or the 0-20 mA output current.			

5.3.8 Digital outputs

For digital outputs 1 and 2 (Dox display DO1 / DO2)

4.150 / 4.170	Dox function	Unit: integer	
Relationship to parameter: 4.151 / 4.171 4.152 / 4.172	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 51	
		def.: 0	
Selection of the process variable to which the output should switch.			
0 = Not assigned / INVEOR soft PLC			
1 = Intermediate circuit voltage			
2 = Grid voltage			
3 = Motor voltage			
4 = Motor current			
5 = Actual frequency value			
6 = -			
7 = -			
8 = IGBT temperature			
9 = Inner temperature			
10 = Error (NO)			
11 = Error inverted (NC)			
12 = Limit steps enable			
13 = Digital input 1			
14 = Digital input 2			
15 = Digital input 3			
16 = Digital input 4			
17 = Ready for operation (mains supply on, no HW enable, motor stationary)			
18 = Ready (mains supply on, HW enable set, motor stationary)			
19 = Operation (mains supply on, HW enable set, motor running)			
20 = Ready for operation + Ready			
21 = Ready for operation + Ready + Operation			
22 = Ready + Operation			
23 = Motor rating			
24 = Torque			
25 = Fieldbus			
26 = Analogue input 1			
27 = Analogue input 2			
28 = PID target value			
29 = PID actual value			
30 = STO channel 1			
Table continues on next page			

Parameter

4.150 / 4.170	Dox function	Unit: integer	
Relationship to parameter: 4.151 / 4.171 4.152 / 4.172	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 51	
		def.: 0	
	Selection of the process variable to which the output should switch. Continuation of table 31 = STO channel 2 32 = Target frequency value after ramp 33 = Target frequency value 34 = Actual speed value 35 = Actual frequency value sum 36 = Torque sum 37 = Target frequency value after ramp sum 38 = Target frequency value sum 39 = Actual speed value sum 40 = Virtual output 50 = Motor current limit enabled 51 = Nominal-actual comparison (para. 6.070 – 6.071)		

4.151 / 4.171	Dox on	Unit:	
Relationship to parameter: 4.150 / 4.170	Transfer status: 2	min.: - 32767	Own value (to be entered!)
		max.: 32767	
		def.: 0	
	If the set process variable exceeds the switch-on limit, the output is set to 1.		

4.152 / 4.172	Dox off	Unit:	
Relationship to parameter: 4.150 / 4.170	Transfer status: 2	min.: - 32767	Own value (to be entered!)
		max.: 32767	
		def.: 0	
	If the set process variable exceeds the switch-off limit, the output is again set to 0.		

5.3.9 Relay

For relays 1 and 2 (rel. X – display rel. 1/ rel. 2)

4.190 / 4.210	Rel.x function	Unit: integer	
Relationship to parameter: 4.191 / 4.211 4.192 / 4.212	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 51	
		def.: 0	
	Selection of the process variable to which the output should switch. 0 = Not assigned / INVEOR soft PLC 1 = Intermediate circuit voltage 2 = Grid voltage 3 = Motor voltage 4 = Motor current 5 = Actual frequency value 6 = - 7 = - 8 = IGBT temperature 9 = Inner temperature 10 = Error (NO) 11 = Error inverted (NC) 12 = Limit steps enable Table continues on next page		

Parameter

4.190 / 4.210	Rel.x function	Unit: integer	
Relationship to parameter: 4.191 / 4.211 4.192 / 4.212	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 51	
		def.: 0	
Selection of the process variable to which the output should switch. Continuation of table 13 = Digital input 1 14 = Digital input 2 15 = Digital input 3 16 = Digital input 4 17 = Ready for operation (mains supply on, no HW enable, motor stationary) 18 = Ready (mains supply on, HW enable set, motor stationary) 19 = Operation (mains supply on, HW enable set, motor running) 20 = Ready for operation + Ready 21 = Ready for operation + Ready + Operation 22 = Ready + Operation 23 = Motor rating 24 = Torque 25 = Fieldbus 26 = Analogue input 1 27 = Analogue input 2 28 = PID target value 29 = PID actual value 30 = STO channel 1 31 = STO channel 2 32 = Target frequency value after ramp 33 = Target frequency value 34 = Actual speed value 35 = Actual frequency value sum 36 = Torque sum 37 = Target frequency value after ramp sum 38 = Target frequency value sum 39 = Actual speed value sum 40 = Virtual output 50 = Motor current limit enabled 51 = Nominal-actual comparison (para. 6.070 – 6.071)			

4.191 / 4.211	Rel.x on	Unit:	
Relationship to parameter: 4.190 / 4.210	Transfer status: 2	min.: - 32767	Own value (to be entered!)
		max.: 32767	
		def.: 0	
If the set process variable exceeds the switch-on limit, the output is set to 1.			

4.192 / 4.212	Rel.x off	Unit:	
Relationship to parameter: 4.190 / 4.210	Transfer status: 2	min: - 32767	Own value (to be entered!)
		max: 32767	
		def.: 0	
If the set process variable exceeds the switch-off limit, the output is again set to 0.			

Parameter

4.193/ 4.213	Rel.x on delay	Unit: s	
Relationship to parameter: 4.194 / 4.214	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10000	
		def.: 0	
Specifies the length of the switch-on delay.			

4.194/ 4.214	Rel.x off delay	Unit:	
Relationship to parameter: 4.193 / 4.213	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10000	
		def.: 0	
Specifies the length of the switch-off delay.			

5.3.10 Virtual output

The virtual output can be parameterised like a relay and is available as an option with the following parameters:
 1.131 Software enable / 1.150 Direction of rotation / 1.054 Ramp selection /
 5.090 Parameter set change / 5.010 + 5.011 External error 1 + 2

4.230	VO function	Unit: integer	
Relationship to parameter: 1.054 1.131 1.150 4.231 4.232 5.010 / 5.011 5.010 / 5.011 5.090	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 51	
		def.: 0	
<p>Selection of the process variable to which the output should switch.</p> <ul style="list-style-type: none"> 0 = Not assigned / INVEOR soft PLC 1 = Intermediate circuit voltage 2 = Grid voltage 3 = Motor voltage 4 = Motor current 5 = Actual frequency value 6 = - 7 = - 8 = IGBT temperature 9 = Inner temperature 10 = Error (NO) 11 = Error inverted (NC) 12 = Limit steps enable 13 = Digital input 1 14 = Digital input 2 15 = Digital input 3 16 = Digital input 4 17 = Ready for operation (mains supply on, no HW enable, motor stationary) 18 = Ready (mains supply on, HW enable set, motor stationary) 19 = Operation (mains supply on, HW enable set, motor running) 20 = Ready for operation + Ready <p style="text-align: center;">Table continues on next page</p>			

5.3.11 Virtual output

The virtual output can be parameterised like a relay and is available as an option with the following parameters:
 1.131 Software enable / 1.150 Direction of rotation / 1.054 Ramp selection /
 5.090 Parameter set change / 5.010 + 5.011 External error 1 + 2

4.230	VO function	Unit: integer	
Relationship to parameter: 1.054 1.131 1.150 4.231 4.232 5.010 / 5.011 5.010 / 5.011 5.090	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 51	
		def.: 0	
	Selection of the process variable to which the output should switch. <p style="text-align: center;">Continuation of table</p> 21 = Ready for operation + Ready + Operation 22 = Ready + Operation 23 = Motor rating 24 = Torque 25 = Fieldbus 26 = Analogue input 1 27 = Analogue input 2 28 = PID target value 29 = PID actual value 30 = STO channel 1 31 = STO channel 2 32 = Target frequency value after ramp 33 = Target frequency value 34 = Actual speed value 35 = Actual frequency value sum 36 = Torque sum 37 = Target frequency value after ramp sum 38 = Target frequency value sum 39 = Actual speed value sum 50 = Motor current limit enabled 51 = Nominal-actual comparison (para. 6.070 – 6.071)		

4.231	VO-On	Unit:	
Relationship to parameter: 4.230	Transfer status: 2	min.: - 32767	Own value (to be entered!)
		max.: 32767	
		def.: 0	
	If the set process variable exceeds the switch-on limit, the output is set to 1.		

4.232	VO-Off	Unit:	
Relationship to parameter: 4.230	Transfer status: 2	min.: - 32767	Own value (to be entered!)
		max.: 32767	
		def.: 0	
	If the set process variable exceeds the switch-off limit, the output is again set to 0.		

Parameter

4.233	VO-On delay	Unit: s	
Relationship to parameter: 4.234	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10000	
		def.: 0	
Specifies the length of the switch-on delay.			

4.234	VO-Off delay	Unit:	
Relationship to parameter: 4.233	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10000	
		def.: 0	
Specifies the length of the switch-off delay.			

4.235	VO inverted	Unit: integer	
Relationship to parameter: 4.230	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
<p>This parameter can be used to invert the virtual output.</p> <p>0 = disable 1 = enable</p>			

5.3.12 External error

5.010 / 5.011	External error 1/2	Unit: integer	
Relationship to parameter: 4.110 / 4.113 4.230	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 7	
		def.: 0	
<p>Selection of source via which an external error can be reported.</p> <ul style="list-style-type: none"> 0 = Not assigned / INVEOR soft PLC 1 = Digital input 1 2 = Digital input 2 3 = Digital input 3 4 = Digital input 4 5 = Virtual output (parameter 4.230) 6 = Analogue input 1 (must be selected in parameter 4.030) 7 = Analogue input 2 (must be selected in parameter 4.060) <p>If there is a high signal at the selected digital input, the drive controller with error no. 23 / 24, switches external error ½.</p> <p>Parameters 4.110 to 4.113 Dix inverse can be used to invert the logic of the digital input.</p>			

5.3.13 Motor current limit

This function limits the motor current to a parameterised maximum value after a parameterised current-time zone has been reached.

This motor current limit is monitored at application level and thereby limits with relatively low dynamics. This has to be taken into consideration when selecting this function.

The maximum value is determined using the “motor current limit as %” parameter (5.070).

This is stated as a percentage and relates to the nominal motor current specified in the “motor current” type plate data (33.031).

The maximum current-time zone is calculated from the product of the “motor current limit in s” parameter (5.071) and the fixed overcurrent of 50% of the required motor current limit.

As soon as this current-time zone is exceeded, the motor current is restricted to the limit value by reducing the speed. If the output current of the drive controller exceeds the motor current (parameter 33.031) multiplied by the set limit as % (parameter 5.070) for the set time (parameter 5.071), the output current of the drive controller is limited permanently to the parametrised value.

The entire function can be deactivated by setting the “motor current limit as %” parameter (5.070) to zero.

5.070	Motor current limit as %	Unit: %	
Relationship to parameter: 5.071 33.031	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 250	
		def.: 0	
	0 = disable See description 5.3.13		

5.071	Motor current limit S	Unit: s	
Relationship to parameter: 5.070 33.031	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 1	
	See description 5.3.13		

5.075	Gearbox factor	Unit:	
Relationship to parameter: 33.034	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1000	
		def.: 1	
	A gearbox factor can be set here. The mechanical speed display can be adjusted using the gearbox factor.		

5.3.14 Blocking detection

5.080	Blocking detection	Unit: integer	
Relationship to parameter: 5.081 34.110	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
	This parameter can be used to activate blocking detection. 0 = disable 1 = enable This function only works reliably if the motor data has been entered correctly and the slip compensation has not been deactivated.		

Parameter

5.081	Blocking time	Unit: s	
Relationship to parameter: 5.080	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 50	
		def.: 2	
	Indicates the time after which a blockage is detected.		

5.082	Start-up error active	Unit: integer	
Relationship to parameter: 4.233	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 1	
	Start-up error is defined as follows: Actual value does not reach 10 % of the rated motor frequency after 30 seconds (if target frequency < 10 %, the error is not generated). If the acceleration time is parametrised as > 60 seconds, half the acceleration time is used in place of the 30 seconds. 0 = Function disabled 1 = Function enabled		

5.083	Deactivation error log 11	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10	
		def.: 0	
	If supplied with external 24 V, the logging of error no. 11 "Time out power" can be suppressed here. The error counter is not affected. 0 = Function disabled 1 = Function enabled		

5.085	F. min monitoring	Unit: s	
Relationship to parameter: 1.020	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10000	
		def.: 0	
	The delay for monitoring the minimum frequency can be set here. If the minimum frequency for the set time is not reached, error 28 is generated. 0s = function disabled >0s = function enabled The time must be long enough for the motor to be able to reliably start.		

5.086	F. max monitoring	Unit: s	
Relationship to parameter: 1.021	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 10000	
		def.: 0	
	The delay for monitoring the maximum frequency can be set here. If the maximum frequency for the set time is exceeded, error 28 is generated. 0s = function disabled >0s = function enabled		

Parameter

5.090	Parameter set change	Unit: integer	
Relationship to parameter: 4.030 / 4.060 4.230	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 12	
		def.: 0	
	Selection of the active data set. 0 = Not used 1 = Data record 1 active 2 = Data record 2 active 3 = Digital input 1 4 = Digital input 2 5 = Digital input 3 6 = Digital input 4 7 = INVEOR soft PLC 8 = Virtual output (parameter 4.230) 9 = Analogue input 1 (must be selected in parameter 4.030) 10 = Analogue input 2 (must be selected in parameter 4.060) 11 = Foil keypad key I for data record 1, key II for data record 2 12 = Foil keypad key I for data record 1, key II for data record 2 storing		
The 2nd data record is only displayed in the PC software if this parameter is <> 0. The values of the data set currently selected are always displayed in the MMI.			

5.200	Turning MMI* display	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
	Only for MMI option. Here the user can define whether the screen / key assignment is turned 180 °. 0 = Function disabled 1 = Function enabled		

5.201	Save MMI* display	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 1	Own value (to be entered!)
		max.: 5	
		def.: 1	
	The status screen displayed in the MMI * can be selected here. 1 = status 01: Target / actual frequency / motor current 2 = status 02: Speed / motor current / process value 1 3 = status 03: Speed / motor current / process value 2 4 = status 04: Speed / PID target value / PID actual value 5 = status 05: Customer PLC output variable 1 / 2 / 3		

5.202	MMI* password	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 9999	
		def.: 0	
	A password can be allocated here, which is requested when expert mode is selected in the MMI * or the app is queried. 0: Password request deactivated The password can be individually set in both data sets.		

* Man-machine interface

Parameter

5.210	MMI* option language	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 1	
		def.: 0	
<p>This parameter can be used to select the language which the MMI * option displays. 0 = local language (factory setting is German) 1 = English This setting does not affect the language choice for the MMI handheld controller.</p>			

5.3.15 Fieldbus

6.060	Fieldbus address	Unit: integer	
Relationship to parameter:	Transfer status: 0	min.: 0	Own value (to be entered!)
		max.: 127	
		def.: 0	
<p>For this address to be used, the address coding switches in the device must be set to 00. A change to the fieldbus address is only undertaken once INVEOR is restarted</p> <p>Profibus devices are automatically set to the "Default 125" address with address coding setting "00" and parameter "0".</p>			

6.061	Fieldbus baud rate	Unit: integer	
Relationship to parameter:	Transfer status: 2	min.: 1 0	Own value (to be entered!)
		max.: 8	
		def.: 2	
<p>Only for CanOpen: 0 = 1 Mbit, 2 = 500 kBit, 3 = 250 kBit, 4 = 125 kBit, 6 = 50 kBit, 7 = 20 kBit, 8 = 10 kBit</p>			

6.062	Bus time-out	Unit in s	
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)
		max.: 100	
		def.: 5	
<p>Bus timeout, if no fieldbus telegram is received after the set time has expired, the INVEOR shuts down with the "Bus timeout" error. The function is only activated once a telegram has been successfully received. 0 = Monitoring disabled</p>			



IMPORTANT INFORMATION

Changing a parameter value via the fieldbus includes direct EEPROM write access.

* Man-machine interface

Parameter

6.070 / 6.071	Target / actual value deviation	Unit: %	
Relationship to parameter: 4.150 / 4.170 4.190 / 4.210 4.230	Transfer status: 2	min.: 0 % / 0 sec.	Own value (to be entered!)
		max.: 100 % / 32767 sec.	
		def.: 0 % / 0 sec.	
	<p>A target / actual value comparison can be undertaken with this function. The result is output via the fieldbus status word or a digital output.</p> <p>Parameter 6.070 can be used to define the tolerance range of the target value.</p> <p>Parameter 6.071 can be used to set the time for which the actual value has to be outside the tolerance range before the output is reset.</p> <p>Example: Operating mode = PID control PID target value = 50 % 6.070 = 10 % 6.071 = 1 sec.</p> <p>As soon as the actual value is between 40 % and 60 %, the output is set. If the actual value is outside 40 % to 60 % for 1 sec., the output is reset.</p>		

5.3.16 Bluetooth

6.202	Bluetooth password	Unit integer	
Relationship to parameter:	Transfer status: 0	min.: 0	Own value (to be entered!)
		max.: 999999	
		def.: 000000	
	<p>The Bluetooth standard 4.2 low energy is used for communication. A 6-digit password is absolutely essential for this.</p> <p>Bluetooth module (fitted permanently ex factory) A password can be allocated here, which is requested when establishing a connection between the KOSTAL INVERTERapp and the permanently fitted Bluetooth module.</p> <p>If a password with fewer than 6 digits is entered, leading zeros are added. 0 = 000000 1 = 000001</p>		
<p>Bluetooth stick If using the Bluetooth stick, the password is fixed as 000000.</p>			

6.203	Bluetooth strength	Unit integer	
Relationship to parameter:	Transfer status: 0	min.: 0	Own value (to be entered!)
		max.: 7	
		def.: 0	
	<p>Bluetooth module (fitted permanently ex factory) The transmission power of the Bluetooth module permanently fitted ex factory can be reduced here.</p> <p>0: 4 dB 1: 0 dB 2: -4 dB 3: -8 dB 4: -12 dB 5: -16 dB 6: -20 dB 7: -30 dB</p>		
<p>Bluetooth stick If using the Bluetooth stick, the maximum transmission power is fixed.</p>			

Parameter

	Bluetooth name	Unit: Text	
Relationship to parameter: 4.150 / 4.170 4.190 / 4.210 4.230	Transfer status: 2	min.: 3 characters	Own value (to be entered!)
		max.: 10 characters	
		def.: INV-xxx-xx	
Bluetooth module (fitted permanently ex factory) The PC software (Tools Bluetooth device name) can be used to specify an individual name for the permanent Bluetooth module.			
Bluetooth stick If using the Bluetooth stick, the name "INV stick" is fixed.			

5.4 Performance parameters

5.4.1 Drive type

33.010	Drive type	Unit: integer			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 299			
		def.: 20			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
This can be used to select the motor type and type of control. 10 = ASM V/f 20 = ASM open-loop (motor identification needed) 100 = PMSM standard mode (motor identification needed) 110 = PMSM efficiency mode* 200 = RSM standard mode (motor identification needed) 210 = RSM efficiency mode* * For special motors					

5.4.2 Motor data

33.031	Motor current	Unit: A			
Relationship to parameter: 5.070	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 150			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
This is used to set the nominal motor current $I_{M,N}$ for either the star or triangle connection.					

Parameter

33.032	Motor rating	Unit: W			
Relationship to parameter:	Transfer status: 1	min.: 0		Own value (to be entered!)	
		max.: 55000			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
			x	x	x
A performance value $P_{M,N}$ has to be set here that corresponds to the nominal motor rating.					

33.034	Motor speed	Unit: rpm			
Relationship to parameter: 34.120 5.075	Transfer status: 1	min.: 0		Own value (to be entered!)	
		max.: 10000			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
The value from the motor's type plate data has to be entered here for the nominal motor rotation speed $n_{M,N}$.					

33.035	Motor frequency	Unit: Hz			
Relationship to parameter:	Transfer status: 1	min.: 10		Own value (to be entered!)	
		max.: 599			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
This is where the nominal motor frequency $f_{M,N}$ is set.					

33.050	Stator resistance	Unit: Ohm			
Relationship to parameter:	Transfer status: 1	min.: 0		Own value (to be entered!)	
		max.: 100			
		def.: 0.001			
	Drive type	V/f	ASM	PMSM	SRM
			x	x	x
The automatically calculated value (of motor identification) for stator resistance can be adjusted here.					

33.105	Leakage inductance	Unit: H			
Relationship to parameter:	Transfer status: 1	min.: 0		Own value (to be entered!)	
		max.: 1			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
			x		
The automatically calculated value (of motor identification) for leakage inductance can be adjusted here.					

Parameter

33.110	Motor voltage	Unit: V			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 1500			
		def.: 0			
Drive type	V/f	ASM	PMSM	SRM	
	x	x	x	x	
This is used to set the nominal motor voltage $U_{M,N}$ for either the star or triangle connection.					

33.111	Motor cos phi	Unit:			
Relationship to parameter:	Transfer status: 1	min.: 0.5	Own value (to be entered!)		
		max.: 1			
		def.: 0			
Drive type	V/f	ASM	PMSM	SRM	
		x		x	
The value from the motor's type plate data has to be entered here for the power factor cos phi.					

33.112	Boost v/f	Unit: V			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 200			
		def.: 0			
Drive type	V/f	ASM	PMSM	SRM	
	x				
The torque can be increased here at low frequencies. This parameter determines the output voltage at 0 Hz for increasing the available torque at low speeds.					
Note: If the breakaway torque isn't sufficient, we would recommend setting parameter 33.010 drive type to 20: ASM open-loop.					

33.201	Nominal flux	Unit: mVs			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 10000			
		def.: 0			
Drive type	V/f	ASM	PMSM	SRM	
			x		
The automatically calculated value (of motor identification) for nominal flux can be adjusted here.					

33.248	d inductance	Unit: H			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 0			
Drive type	V/f	ASM	PMSM	SRM	
			x		
The automatically calculated value (of motor identification) for series inductance can be adjusted here.					

Parameter

33.249	q inductance	Unit: H			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 0			
Drive type	V/f	ASM	PMSM	SRM	
			x		
The automatically calculated value (of motor identification) for shunt inductance can be adjusted here.					

33.255	R of f	Unit: Ohm/Hz			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 1000			
		def.: 0			
Drive type	V/f	ASM	PMSM	SRM	
			x		
The switching frequency-dependent change in resistance calculated automatically (via motor identification) is displayed here.					

5.4.3 I²t

33.016	I ² T active	Unit:			
Relationship to parameter: 33.031 33.012 – 33.014	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 1			
Drive type	V/f	ASM	PMSM	SRM	
	x	x	x	x	
I ² T can be activated here with the protective function. 0 = I ² T function disabled 1 = I ² T function enabled					

33.012 to 33.014	I ² T limit 1 to 3	Unit: %															
Relationship to parameter: 33.031 33.016	Transfer status: 2	min.: 10	Own value (to be entered!)														
		max.: 500															
		def.: 100															
Drive type	V/f	ASM	PMSM	SRM													
	x	x	x	x													
The percentage current threshold (in relation to motor current 33.031) at the start of integration can be set here for various frequency ranges.																	
<table border="1"> <thead> <tr> <th>Parameter</th> <th>Frequency range as % of rated frequency</th> <th>Default value as % of rated current</th> </tr> </thead> <tbody> <tr> <td>33.012</td> <td>0 – 50 %</td> <td>100 %</td> </tr> <tr> <td>33.013</td> <td>50 – 100%</td> <td>100 %</td> </tr> <tr> <td>33.014</td> <td>> 100 %</td> <td>100 %</td> </tr> </tbody> </table>						Parameter	Frequency range as % of rated frequency	Default value as % of rated current	33.012	0 – 50 %	100 %	33.013	50 – 100%	100 %	33.014	> 100 %	100 %
Parameter	Frequency range as % of rated frequency	Default value as % of rated current															
33.012	0 – 50 %	100 %															
33.013	50 – 100%	100 %															
33.014	> 100 %	100 %															
We recommend using winding protection contacts in heat-sensitive applications!																	

Parameter

33.011	I ² T time	Unit: s			
Relationship to parameter:	Transfer status: 2	min.: 0		Own value (to be entered!)	
		max.: 1200			
		def.: 30			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
Time for calculating the I ² t time period.					

33.138	Holding current time	Unit: s			
Relationship to parameter: 33.010	Transfer status: 2	min.: 0		Own value (to be entered!)	
		max.: 3600			
		def.: 2			
	Drive type	V/f	ASM	PMSM	SRM
			x		
This is the time during which the drive is held at continuous current after the brake ramp has been completed.					

5.4.4 Switching frequency

The internal switching frequency can be changed in order to control the power element.

A high setting reduces noise in the motor but results in increased EMC emissions and losses in the drive controller.

34.030	Switching frequency	Unit: Hz			
Relationship to parameter: 33.010	Transfer status: 2	min.: 0		Own value (to be entered!)	
		max.: 6			
		def.: 1			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
Selection of the switching frequency for the drive controller: 0 = 2 kHz 1 = 4 kHz 2 = 6 kHz 3 = 8 kHz 4 = 12 kHz 5 = 16 kHz 6 = auto* * The drive starts at the maximum switching frequency set in parameter 34.032. Depending on the interior / IGBT temperature, the switching frequency is gradually reduced to no more than the minimum switching frequency set in parameter 34.031. As soon as the temperature drops again, the switching frequency is gradually increased.					

Parameter

34.031	Auto sw.f. min	Unit: integer			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 5			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
0 = 2 kHz 1 = 4 kHz 2 = 6 kHz 3 = 8 kHz 4 = 12 kHz 5 = 16 kHz					

34.032	Auto sw.f. max	Unit: integer			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 5			
		def.: 5			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
0 = 2 kHz 1 = 4 kHz 2 = 6 kHz 3 = 8 kHz 4 = 12 kHz 5 = 16 kHz					

5.4.5 Controller data

34.015	Ramp corr. active	Unit: integer			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 1			
	Drive type	V/f	ASM	PMSM	SRM
			x	x	x
0 = the ramp correction can be disabled to increase dynamism. With slow ramps, this may lead to an unintended dead time. 1 = the ramp generator takes account of the actual frequency. An impermissibly large deviation between target and actual value is suppressed.					

34.020	Flying restart	Unit:			
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 1			
34.021	Drive type	V/f	ASM	PMSM	SRM
			x	x	
The flying restart can be used to switch the drive controller to a rotating motor.					
0 = disable 1 = enable					

Parameter

34.021	Catch time	Unit: ms			
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 10,000			
def.: 100					
Drive type		V/f	ASM	PMSM	SRM
			x	x	
<p>For asynchronous motors: The catch time can be optimised here, if the automatically determined results (of the motor identification) are insufficient.</p> <p>For synchronous motors The time during which the motor speed is determined can be set here.</p>					

34.090	Speed controller K_p	Unit: mNm / rad / s			
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 10000			
def.: 150					
Drive type		V/f	ASM	PMSM	SRM
			x	x	x
<p>The control boost of the speed controller can be optimised here, if the automatically determined results (of the motor identification) are insufficient.</p>					

34.091	Speed controller T_r	Unit: s			
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 10			
def.: 4					
Drive type		V/f	ASM	PMSM	SRM
			x	x	x
<p>For asynchronous motors: The reset time of the speed controller can be optimised here, if the automatically determined results (of the motor identification) are insufficient.</p> <p>For synchronous motors: The reset time of the speed controller must be optimised here, we would recommend a value between 0.1 s and 0.5 s.</p>					

34.110	Slip trimmer	Unit:			
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 1.5			
def.: 1					
Drive type		V/f	ASM	PMSM	SRM
			x		
<p>This parameter can be used to optimise or deactivate slippage compensation. 0 = disable (performance as on the grid) 1 = compensation for slippage. Example: 4 pole asynchronous motor at 1410 rpm, target frequency 50 Hz Motor idling 0 = approx. 1500 rpm 1 = 1500 rpm Motor at nominal point 0 = 1410 rpm 1 = 1500 rpm 50 Hz is always displayed as the actual frequency. Deactivating slip compensation may result in blocking detection no longer working reliably.</p>					

Parameter

34.130	Voltage control reserve	Unit:			
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 0.95			
Drive type		V/f	ASM	PMSM	SRM
			x	x	
This parameter can be used to adjust voltage output.					

34.220	Injection RANGE	Unit:			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 0.02			
Drive type		V/f	ASM	PMSM	SRM
				x	x
The range calculated automatically (via motor identification) during which the pulse injection procedure runs is displayed here.					

34.225	Field weakening	Unit: integer			
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 0			
Drive type		V/f	ASM	PMSM	SRM
				x	
0 = disable, the motor cannot be run in the field weakening. 1 = enable, the motor can be placed in the field weakening until the drive controller has reached its current limit or the maximum permissible electromotive force.					

34.226	Starting current	Unit: %			
Relationship to parameter:	Transfer status: 2	min.: 5	Own value (to be entered!)		
		max.: 1000			
		def.: 25			
Drive type		V/f	ASM	PMSM	SRM
				x	
Only during start-up procedure: controlled. Here the current which was stamped in the motor before starting the control can be adjusted. Value as % of nominal motor current.					

34.227	Init time PMSM	Unit: s			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 100			
		def.: 0.25			
Drive type		V/f	ASM	PMSM	SRM
				x	
Here the time during which the start up current 34.226 is stamped can be set.					

Parameter

34.228 – 34.230	PMSM start-up procedure	Unit: integer			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
				x	
0 = regulated, the drive controller is run with regulation over the entire speed range. 1 = controlled, after the stamping phase the rotation field is increased by the control with start ramp 34.229 up to start-up frequency 34.230, then switched to the controller.					

34.246	Injection RANGE	Unit: s			
Relationship to parameter:	Transfer status: 1	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 0.02			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x

36.020	Deact grid monitoring	Unit: integer			
Relationship to parameter:	Transfer status: 2	min.: 0	Own value (to be entered!)		
		max.: 1			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
		x	x	x	x
Grid monitoring can be deactivated here. 0: deactivated 1: activated					

5.4.6 Quadratic characteristic curve

34.120	Quadratic characteristic curve	Unit: integer			
Relationship to parameter: 34.121	Transfer status: 2	min.: 0		Own value (to be entered!)	
		max.: 1			
		def.: 0			
	Drive type	V/f	ASM	PMSM	SRM
		x			
The quadratic characteristic curve function can be activated here. 0 = disable 1 = enable					

34.121	Flux adjustment	Unit: %			
Relationship to parameter: 34.120	Transfer status: 2	min.: 0		Own value (to be entered!)	
		max.: 100			
		def.: 50			
	Drive type	V/f	ASM	PMSM	SRM
		x			
The percentage by which the flux is to be reduced can be set here. An overvoltage shutdown can occur if there are any major changes in operation.					

6. Error detection and troubleshooting

This chapter contains the following:

- a list of the LED flash codes for error detection
- a description of error detection using PC tools
- a list of errors and system errors
- notes on error detection with the MMI
- notes on error detection via the Bluetooth app

DANGER!

Risk of death due to electrical shock!
Death or serious injury!

De-energise drive controller and secure it against being restarted.
 If damaged parts or components need replacing, only ever replace with original parts.

 Danger due to electrical shock and discharge. Wait two minutes (discharge time of the capacitors) after shut-down.



6.1 List of the LED flash codes for error detection

When an error occurs, the LEDs on the drive controller display a flashing code that allows the errors to be diagnosed.

The following table contains an overview:

Red LED	Green LED	State
		Boot loader active (flashing in turn)
		Ready for operation (activate En_HW for operation)
		Operation / ready
		Warning
		Error
		Identification of motor data
		Initialisation
		Firmware update
		Bus error operation
		Bus error ready for operation

Tab. 9: LED flash codes

Key			
	LED off		LED on
	LED flashing		LED flashing quickly

6.2 List of errors and system errors

The driver controller shuts down if an error occurs. Consult the flash code table / PC tool for the corresponding error numbers.



IMPORTANT INFORMATION

Error messages can only be acknowledged once the error has been remedied.

Error messages can be acknowledged as follows:

- digital input (can be programmed)
- using MMI (handheld controller)
- using the Bluetooth app
- [Automatic acknowledge function](#) (Parameter 1.181)
- switch device off and on again

via fieldbus (e.g. CANOpen, Profibus DP, EtherCAT)

Errors must always be rectified before acknowledgement, otherwise the drive controller may be damaged.

The following section contains a list of possible error messages. Please contact the KOSTAL service department if you encounter errors that are not listed here.

No.	Error name	Description of error	Possible causes/remedy
1	Undervoltage 24 V application	Supply voltage for the application is less than 15 V	24 V supply overload
2	Overvoltage 24 V application	Supply voltage for the application is greater than 31 V	Internal 24 V supply is not OK or external supply is not OK
4	Warning: Customer PLC runtime environment	The customer PLC is not running	The customer PLC is being downloaded / The customer PLC has a programming error, e.g. division by 0
6	Customer PLC version error	The version of the customer PLC doesn't match the device firmware	Check the version numbers of the customer PLC and device firmware
8	Communication application<->power	Internal communication between the application plate and the power-conducting plate is not OK	EMC interference
10	Parameter distributor	The internal distribution of parameters during initialisation failed	Parameter set is incomplete
11	Time-out power	The power stack does not respond	Operation with 24 V without mains feed-in
13	Cable break at analogue in1 (4–20 mA / 2–10 V)	Current or voltage is less than the lower limit of analogue input 1 (monitoring for this error is activated automatically by setting parameter 4.021 to 20 %).	Cable break, faulty external sensor

Error detection and troubleshooting

No.	Error name	Description of error	Possible causes/remedy
14	Cable break at analogue in 2 (4–20 mA / 2–10 V)	Current or voltage is less than the lower limit of analogue input 2 (monitoring for this error is activated automatically by setting parameter 4.021 to 20 %)	Cable break, faulty external sensor
15	Blocking detection	The drive shaft of the motor is stalled. 5.080	Remove the blockage
16	PID dry run	No PID actual value despite maximum speed	PID actual value sensor defective. Extend dry run time parameter 3.072
17	Start-up error	Motor not starting up or starting up incorrectly. 5.082	Check motor connections/check motor and controller parameters; if necessary, disable error (5.082).
18	Excess temperature for FC application	Inner temperature too high	Insufficient cooling, low motor speed and high torque, switching frequency too high.
22	Acknowledgement error	The number of maximum automatic acknowledgements (1.182) was exceeded	Check error history and remedy error
23	External error 1	The parameterised fault input is active. 5.010	Correct the external error
24	External error 2	The parameterised fault input is active. 5.011	Correct the external error
25	Motor detection	Motor identification error	Check INVEOR/motor and PC / MMI / INVEOR connections / restart motor identification
26	STO inputs plausibility	The statuses of the two STO inputs have not been identical for more than 2 sec.	Incorrect activation of the STO inputs. Check corresponding external wiring.
28	Limit frequency exceeded / not met	The parameterised minimum / maximum frequency has not been met / has been exceeded.	The parameterised time 5.085 or 5.086 is too short / Motor blocked / Brake not opened / Motor overloaded
32	Trip IGBT **	Protection of the IGBT module against overcurrent has been triggered	Short circuit in the motor or motor feed line / controller settings
33	Overvoltage of intermediate circuit **	The maximum intermediate circuit voltage has been exceeded	Feedback by motor in generator mode / mains voltage too high / faulty setting for rotation speed controller / brake resistor not connected or defective / ramp times too short
34	Undervoltage of intermediate circuit	The minimum intermediate circuit voltage has not been reached	Mains voltage too low, grid connection defective / check wiring

Error detection and troubleshooting

No.	Error name	Description of error	Possible causes/remedy
35	Excess motor temperature	Motor PTC has been triggered	Overload of the motor (e.g. high torque at low motor speed) / ambient temperature too high
36	Power failure	The grid voltage has dropped briefly	Grid fluctuation / grid voltage interrupted
38	Excess IGBT module temperature	Excess IGBT module temperature	Insufficient cooling, low motor speed and high torque, switching frequency too high
39	Overcurrent **	Maximum output current of drive controller exceeded	Motor stalled / check motor connection / incorrect speed controller setting / check motor parameters / ramp times too short / brake not open
40	Excess frequency converter temperature	Inner temperature too high	Insufficient cooling / low motor speed and high torque / switching frequency too high permanent overload / reduce ambient temperature / check fan
42	I ² t motor protection shut-off	The internal I ² t motor protection (can be parametrised) has been triggered	Permanent overload
43	Ground leak **	Ground leak during a motor phase	Insulation fault
45	Motor connection disrupted	No motor current in spite of control through frequency converter	No motor connected or not completely connected. Check phases or motor connections and connect correctly when necessary. *
46	Motor parameters	Plausibility check for motor parameters failed	Parameter set not OK
47	Drive controller parameters	Plausibility check for drive controller parameters failed	Parameter set not OK, motor type 33.001 and control method 34.010 not plausible.
48	Type plate data	No motor data entered	Please enter the motor data according to the type plate
49	Power class restriction	Max. overload of the drive controller exceeded for more than 60 sec.	Check application / reduce load / use larger drive controller.
53	Motor tipped	Only for synchronous motors, field orientation lost	Load too high. Optimise controller parameters.

Tab. 10: Error detection

* In exceptional cases, the error may be displayed erroneously when idling (very low motor current) with synchronous motors.
Set parameter 33.016 accordingly when the phases or motor connections are connected correctly.

** Should the error occur again, depending on frequency, it can only be acknowledged after the following times:

- 1 -3 acknowledgements 1 s waiting time permitted =
- 4 -5 acknowledgements 5 s waiting time permitted =
- > 5 acknowledgements 30 s waiting time permitted =

The number of acknowledgements is deleted after 120 s without any errors!

7. Disassembly and disposal

This chapter contains the following:

- a description of how to disassemble the drive controller
- information on correct disposal

7.1 Drive controller disassembly

DANGER!

 **Risk of death due to electrical shock!**
Death or serious injury!
De-energise drive controller and secure it against being restarted.

 **Danger due to electrical shock and discharge. Wait two minutes (discharge time of the capacitors) after shut-down.**

1. Open drive controller cover.
2. Release cables at terminals.
3. Remove all cables.
4. Remove connection screws for drive controller / adapter plate.
5. Remove drive controller.

7.2 Information on correct disposal

Dispose of drive controller, packaging and replaced parts in accordance with the regulations of the country in which the drive controller has been installed.

The drive controller may not be disposed of with household waste.

8. Technical data

8.1 General data

8.1.1 General technical data for 400 V devices

Size		A					B			
Electrical data	Recommended motor rating ¹⁾ [kW]	0.55	0.75	1.1	1.5	2.2 LD	2.2	3.0	4.0	5.5 LD
	Supply voltage	3 x 200 V AC -10 %...480 V AC +10 % 280 V DC -10 %...680 V DC +10 % ²⁾								
	Grid frequency	50/60 Hz ± 6 %								
	Network configurations	TN / TT / IT								
	Line current [A]	1.4	1.9	2.6	3.3	3.9	4.6	6.2	7.9	9.3
	Rated current output eff. [IN at 8 kHz]	1.7	2.3	3.1	4.0	4.8	5.6	7.5	9.5	11.0
	Min. brake resistance [Ω]	100					50			
	Overload for 60 sec. in %	150				110	150			110
	Overload for 3 sec. in %	200				150	200			150
	Switching frequency	Auto, 2 kHz, 4 kHz, 6 kHz, 8 kHz, 12 kHz, 16 kHz, (factory setting 4 kHz)								
	Output frequency	0 Hz - 599 Hz								
	Mains cycles of operation	Unlimited ³⁾								
	DIN EN 61800-5 touch current	< 3.5 mA ⁴⁾								
Functions	Protective function	Overvoltage and undervoltage, I ² t restriction, short-circuit, ground leak, motor and drive controller temperature, stall prevention, blocking detection, PID dry run protection								
	Software functions	Torque control, process control (PID controller), fixed frequencies, data record changeover, flying restart, motor current limit								
	Soft PLC	IEC61131-3, FBD, ST, AWL								
Mechanical data	Housing	Two-part aluminium die-cast casing								
	Dimensions [L x W x H] mm	233 x 153 x 120					270 x 189 x 140			
	Weight including adapter plate	3.9 kg					5.0 kg			
	Protection class [IPxy]	IP 65								
	Cooling	Passive cooling								
Environmental conditions	Climate class	3K3 (50 °C)			3K3 (40 °C)	3K3 (50 °C)			3K3 (40 °C)	
	Ambient temperature	- 40 °C (non-condensing) to + 50 °C (without derating)			to + 40 °C	- 40 °C (non-condensing) to + 50 °C (without derating)			to + 40 °C	
	Storage temperature	- 40 °C...+ 85 °C								
	Altitude of the installation location	up to 1000 m above sea level/over 1000 m with reduced performance (1% per 100 m) / above 2000 m see chapter 8.2.2								
	Relative air humidity	≤ 96 %, condensation not permitted								
	Vibration resistance (DIN EN 60721-3-3)	3M7 (3g)								
EMC (DIN-EN-61800-3)	C1 option ⁵⁾ / C2									
Certificates and conformity	  									

Technical data for INVEOR MP 400 V devices (subject to technical changes)

¹⁾ Recommended motor rating (4-pole asynchronous IE3 motor) is specified based on the 400 VAC supply voltage.

²⁾ In compliance with the overvoltage category.

³⁾ < 3 s may result in power failure/intermediate circuit undervoltage faults.

⁴⁾ With 1LA7 asynchronous motor, motor-mounted.

8.1.2 Specification of interfaces

Designation	Function
Digital inputs 1 – 4	<ul style="list-style-type: none"> - Switching level low < 2 V / high > 18 V - I_{max} (at 24 V) = 3 mA - R_{in} = 8.6 kOhm
Hardware approval for input	<ul style="list-style-type: none"> - Switching level low < 3 V / high > 18 V I_{max} (at 24 V) = 8 mA
Analogue inputs 1, 2	<ul style="list-style-type: none"> - I_n +/- 10 V or 0 – 20 mA - I_n 2 – 10 V or 4 – 20 mA - 10-bit resolution - Tolerance +/- 2 % Voltage input: <ul style="list-style-type: none"> - R_{in} = 10 kOhm Current input: <ul style="list-style-type: none"> - Working resistance = 500 Ohm
Digital outputs 1, 2	<ul style="list-style-type: none"> - Short-circuit proof - I_{max} = 20 mA
Relays 1, 2	<p>1 changeover contact (NO/NC)</p> <p>Maximum switching power *</p> <ul style="list-style-type: none"> - at ohmic load (cos φ = 1): 5 A at ~ 230 V or = 30 V - at inductive load (cos φ = 0.4 and L/R = 7 ms): 2 A at ~ 230 V or = 30 V <p>Maximum reaction time: 7 ms ± 0.5 ms</p> <p>Electric life: 100 000 switching cycles</p>
Analogue output 1 (current)	<ul style="list-style-type: none"> - Short-circuit proof - I_{out} = 0.. 20 mA - Working resistance = 500 Ohm - Tolerance +/- 2 %
Analogue output 1 (voltage)	<ul style="list-style-type: none"> - Short-circuit proof - U_{out} = 0..10 V - I_{max} = 10 mA - Tolerance +/- 2 %
Power supply 24 V	<ul style="list-style-type: none"> - Auxiliary voltage U = 24 V DC - SELV - Short-circuit proof - I_{max} = 100 mA - external feed-in of 24 V possible
Power supply 10 V	<ul style="list-style-type: none"> - Auxiliary voltage U = 10 V DC - Short-circuit proof - I_{max} = 30 mA

Tab. 11: Specification of interfaces

* in terms of the UL 508C standard, the maximum allowed is 2 A!

8.2 Derating of output power

Drive controllers of the INVEOR series have two integrated PTC resistors as standard which monitor both the heat sink temperature and the inner temperature. As soon as a permissible IGBT temperature of 95 °C or a permissible inner temperature of 85 °C is exceeded, the drive controller shuts down.

All INVEOR MP type drive controllers are designed for an overload of 150% for 60 sec and 200% for 3s (every 10 min).

Reductions in the ability to handle overload and/or its duration should be taken into account in the following circumstances:

- A clocking frequency permanently set too high >4 kHz (load-dependent).
- A permanently increased heat sink temperature, caused by a blocked air flow or a thermal blockage (dirty cooling ribs).
- Depending on the type of assembly, permanently excessive ambient temperature.

The respective max. output values can be determined from the following characteristic curves.

8.2.1 Derating due to increased ambient temperature

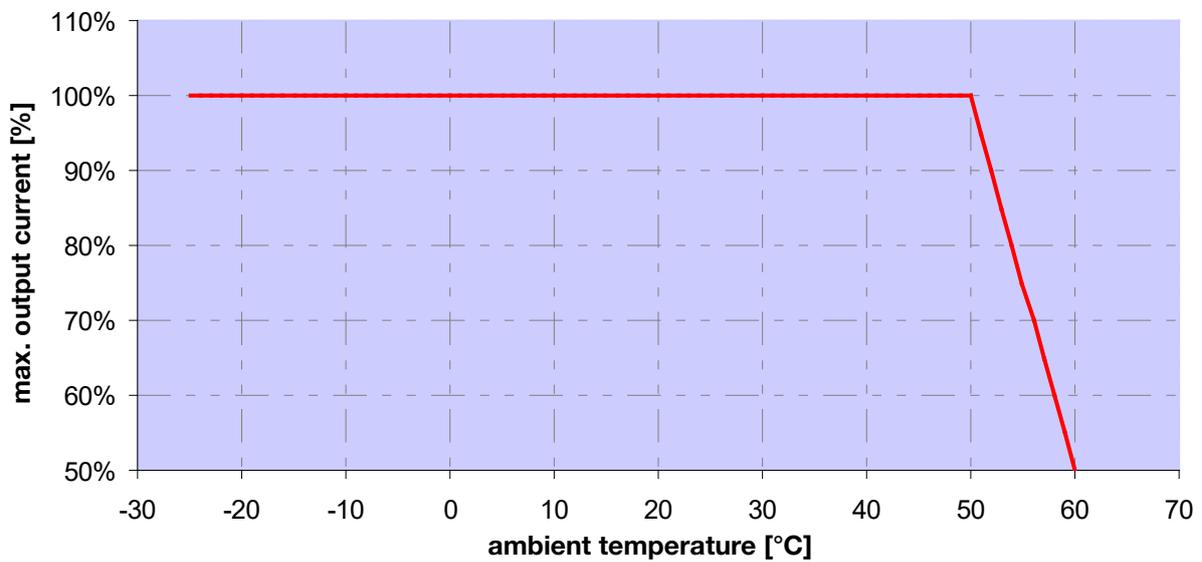


Fig. 40: Derating for motor-mounted drive controller

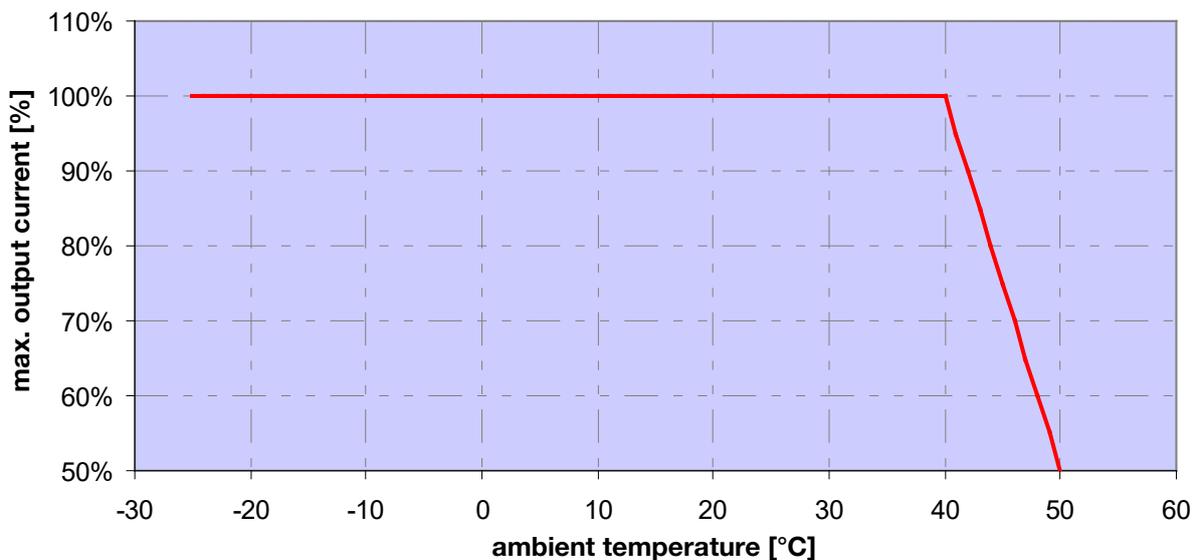


Fig. 41: Derating for wall-mounted drive controller

8.2.2 Derating due to installation altitude

The following applies to all INVEOR drive controllers:

- No reduction in performance is needed in S1 mode up to 1000 m above sea level.
- A reduction in performance of 1% every 100 m is needed from 1000 m \geq 2000 m. Overvoltage category 3 is observed!
- Overvoltage category 2 should be observed from 2000 m \geq 4000 m because of the lower air pressure!

In order to observe the overvoltage category:

- use external overvoltage protection in the INVEOR's mains cable.
- reduce the input voltage.

Please contact the KOSTAL Service department.

The respective max. output values can be determined from the following characteristic curves.

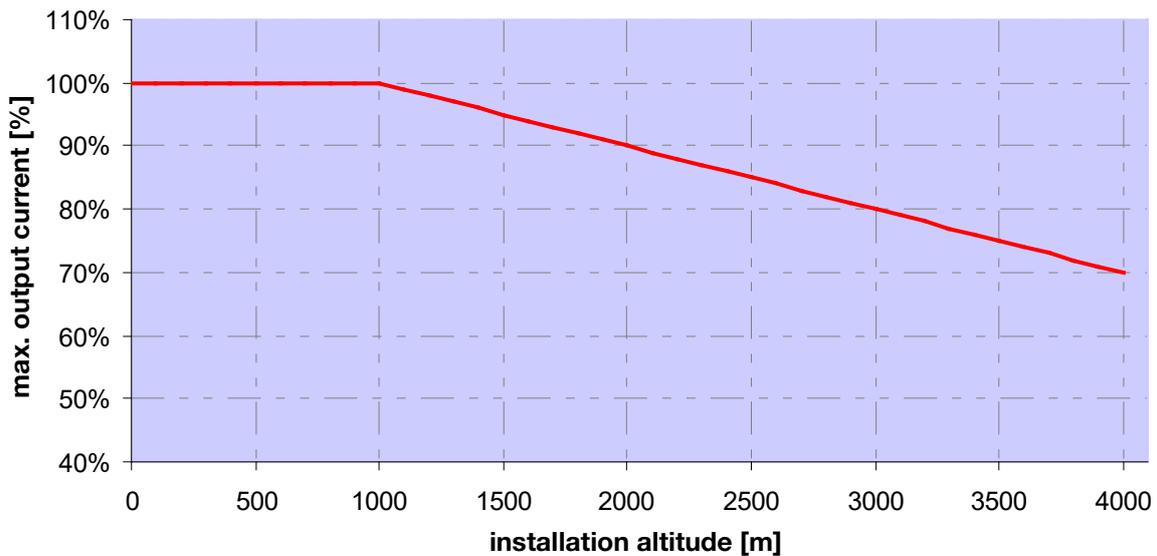


Fig. 42: Derating of maximum output current as a result of installation altitude

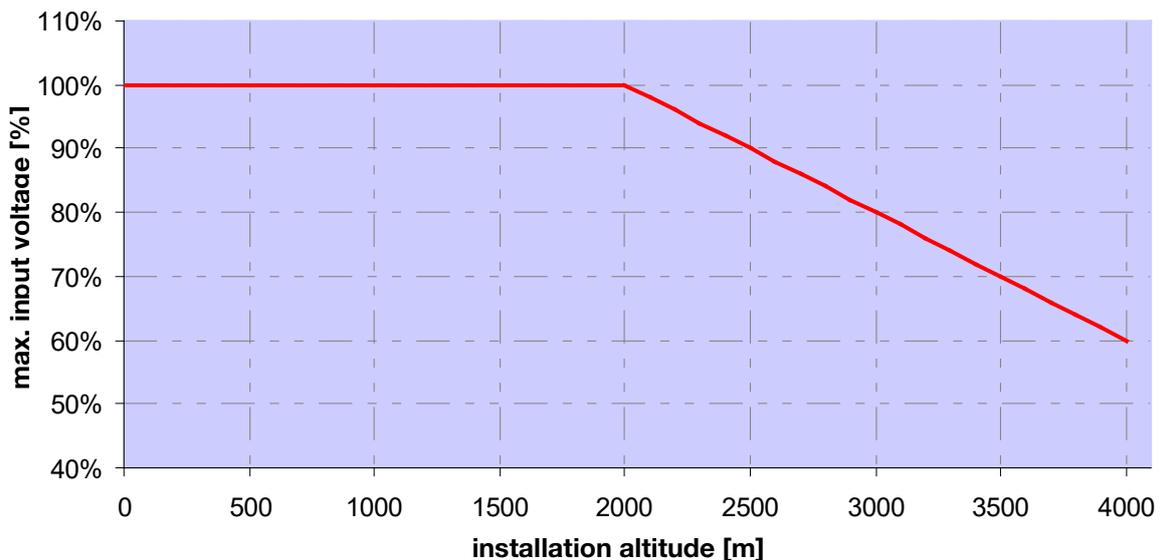


Fig. 43: Derating of maximum input voltage as a result of installation altitude

8.2.3 Derating due to switching frequency

The following diagram shows the output current, depending on switching frequency. To limit the thermal losses in the drive controller, the output current must be reduced.

Note: The switching frequency is not reduced automatically!

The max. output values can be determined from the following characteristic curve.

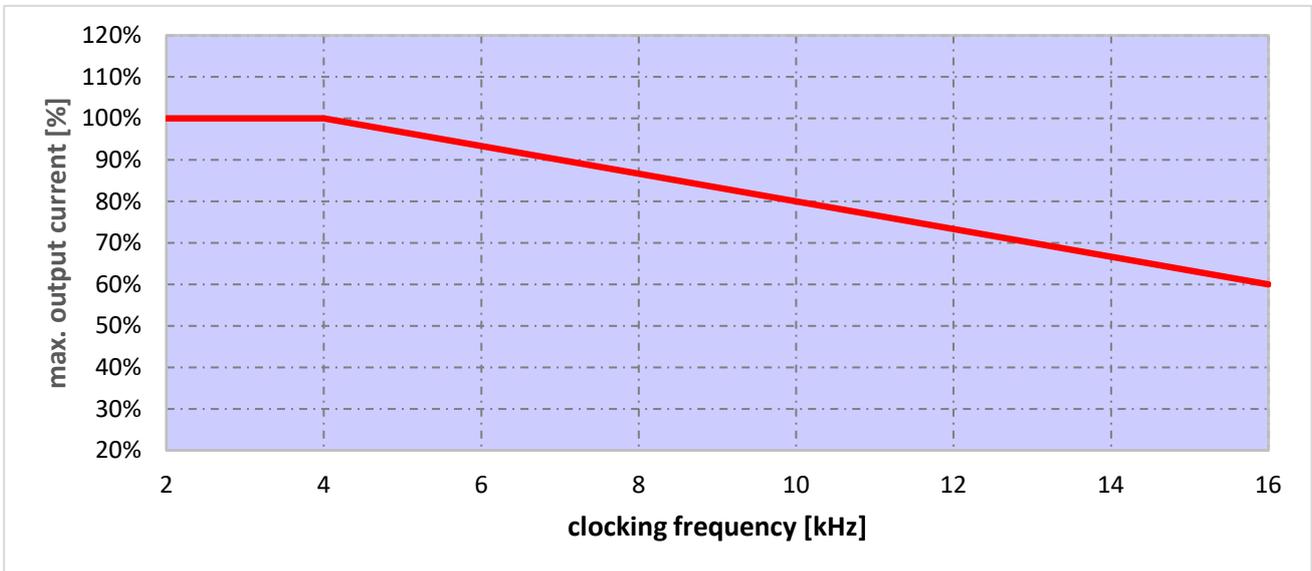


Fig. 44: Derating of maximum output current as a result of switching frequency

9. Optional accessories

This chapter contains brief descriptions of the following optional accessories

- Adapter plates
- MMI handheld controller including connection cable RJ9 on M12 plug
- Brake resistors

9.1 Adapter plates

9.1.1 Motor adapter plates

A standard motor adapter plate (with an integrated terminal board for size A up to C) is available for each INVEOR size. Download the 3D files (.stp) for INVEOR and adapter plates from

www.kostal-industrie-elektrik.com/downloads/downloadmanager#Antriebstechnik

INVEOR size	A	B
Power [kW]	0.55 to 2.2	2.2 to 5.5
Designation	ADP MA MOT 0000 A00 000 1	ADP MB MOT 0000 A00 000 1
Art. no.	10506789	10026184

The customer needs to drill the four holes for mounting the standard adapter plate on the motor. Below are technical drawings showing the possible locations of the holes for each of the respective sizes.



INFORMATION

The system integrator is responsible for whether the connection between the motor and adapter plate satisfies the mechanical requirements of the application.

Because the motor does not form part of the scope of supply of the drive controller, the system integrator must ensure the following when assembling the drive controller on the motor.

- Actual dimensions of the attachment interface
- Blind hole depth, diameter and thread type of attachment points



IMPORTANT INFORMATION

KOSTAL Industrie Elektrik GmbH assumes no liability for the connection between the motor and INVEOR!

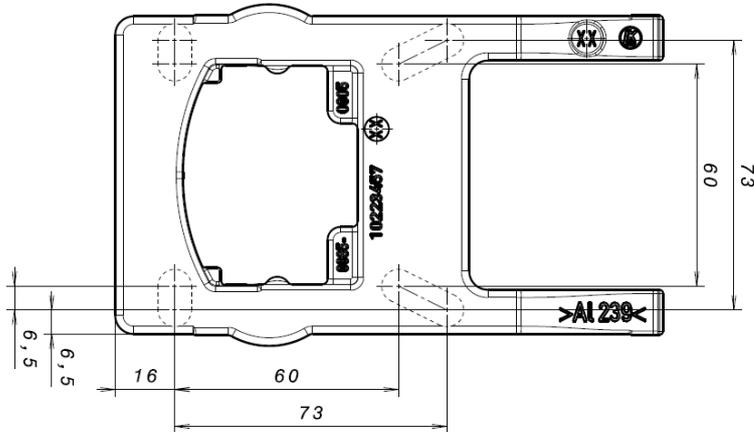


Fig. 45: Hole pattern for size A standard adapter plate

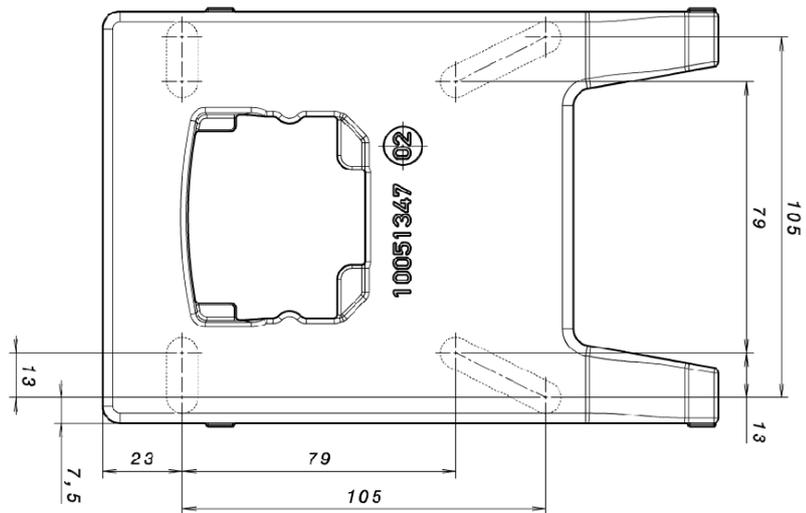


Fig. 46: Hole pattern for size B standard adapter plate

When using cylindrical head screws (cf. DIN 912 / DIN 6912) or flat head screws (cf. DIN EN ISO 7380), the hole pattern must be drilled on the INVEOR mounting frame in compliance with the applicable drawing. The drill-hole centres should be on the respective centre lines of the slots illustrated.

If the mounting frame is to be attached to a connection box that has no square hole pattern, then the drawing's diagonal centre lines are decisive.

If the mounting holes are outside the positions indicated, countersunk screws must be used to avoid fouling the attachment of the INVEOR MP.

If the existing flat seals are in a good condition, they should be reused.

9.1.2 Motor adapter plates (specific)

In addition to the standard motor adapter plates (with integrated terminal boards for sizes A to C), there are also specific versions available for various motor suppliers (on request).



INFORMATION

The system integrator is responsible for whether the connection between the motor and adapter plate satisfies the mechanical requirements of the application.

Because the motor does not form part of the scope of supply of the drive controller, the system integrator must ensure the following when assembling the drive controller on the motor.

- Actual dimensions of the attachment interface
- Blind hole depth, diameter and thread type of attachment points

9.1.3 Wall adapter plates (standard)

A standard wall adapter plate (with an integrated terminal board for sizes A to C) is available for each INVEOR size. Download the 3D files for INVEOR and adapter plates from

www.kostal-industrie-elektrik.com/downloads/downloadmanager#Antriebstechnik.

Four holes for mounting the adapter plate, as well as an EMC screw connection, are already featured.

INVEOR size	A	B
Power [kW]	0.55 to 2.2	2.2 to 5.5
Designation	ADP MA WDM 0000 A00 000 1	ADP MB WDM 0000 A00 000 1
Art. no.	10506806	10026185

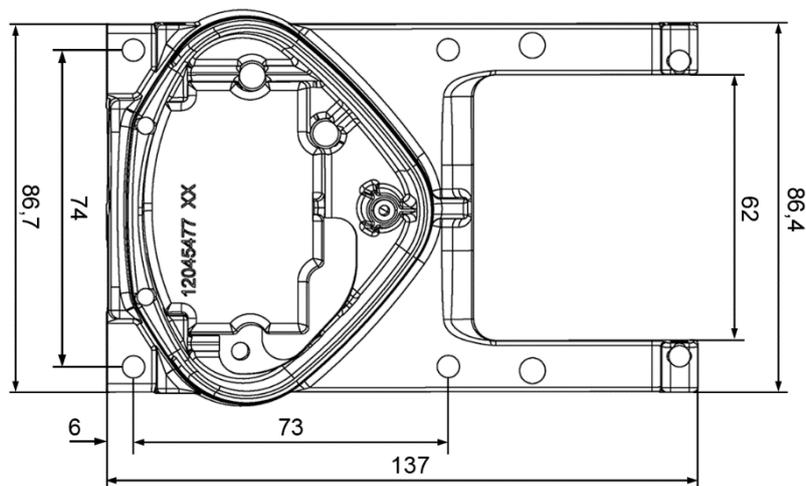


Fig. 47: Hole pattern for size A standard wall adapter plate

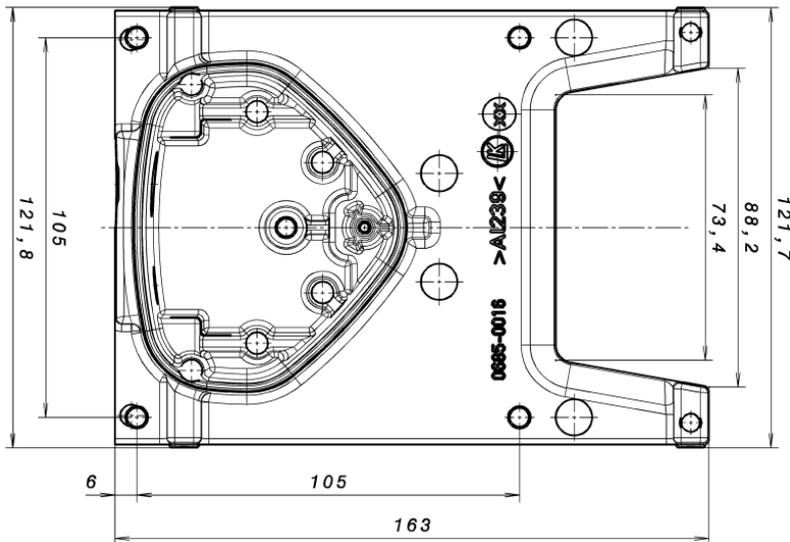


Fig. 48: Hole pattern for size B standard wall adapter plate

9.2 Foil keypad

As an option, the devices of the INVEOR family are also available as a variant with an integrated foil keypad. This keypad can be used to operate the drive controller locally.

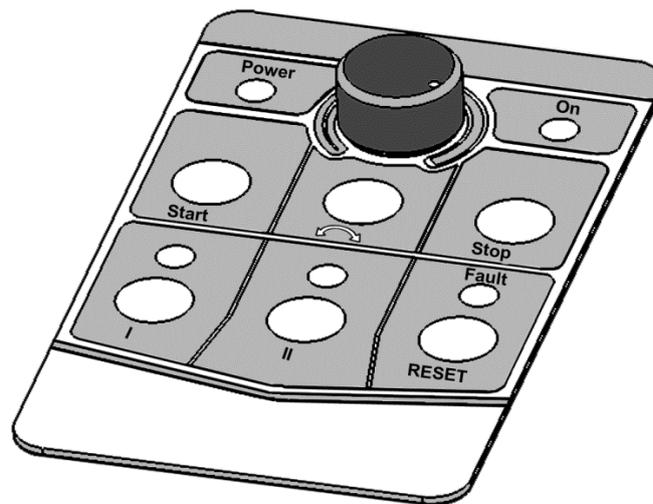


Fig. 49: Standard foil keypad

The following functionalities can be realised using the integrated foil keypad:

- **Target value specification:** A target value (parameter 1.130) can be specified using the potentiometer integrated in the foil keypad (select internal potentiometer).
- **Target value approval:** The start and stop keys integrated in the foil keypad (select foil keypad) can be used to approve the drive software (parameter 1.131).

- **Direction of rotation V1:** The direction of rotation (parameter 1.150) can be changed using the key integrated in the foil keypad (select foil keypad, direction of rotation key).
The direction of rotation can only be changed when the motor is running.

Direction of rotation V2: The direction of rotation (parameter 1.150) can be changed using keys I and II integrated in the foil keypad (select foil keypad, key I clockwise/key II anti-clockwise via stop).
The direction of rotation can only be changed when the motor is stationary.
The integrated LEDs indicate the current direction of rotation.

Direction of rotation V3: The direction of rotation (parameter 1.150) can be changed using keys I and II integrated in the foil keypad (select foil keypad, key I clockwise/key II anti-clockwise always). The direction of rotation can be changed when the motor is running and stationary. The integrated LEDs indicate the current direction of rotation.
- **Acknowledge function:** An error can be acknowledged (parameter 1.180) using the reset key integrated in the foil keypad (select foil keypad).

- **Motor potentiometer:** A motor potentiometer (parameter 2.150) can be realised using the configurable keys I and II integrated in the foil keypad (MOP digit.inp.). This function can be used to increase or decrease the target value.
The integrated LEDs indicate when the minimum/maximum target value is reached.
To activate this function, the target value specification (parameter 1.130) must be set to motor potentiometer!
- **Fixed frequency:** Two fixed frequencies (parameter 2.050) can be realised using the configurable keys I and II integrated in the foil keypad (MOP digit.inp.). This function can be used to increase or decrease the target value.
The integrated LEDs indicate the target value currently selected.

The LEDs integrated in the foil keypad provide a general indication of the drive controllers.

Power LED:	Lights up as soon as there is a voltage supply.
On LED:	Lights up during operation.
Fault LED:	Lights up when there is an error. Flashes as soon as an error can be acknowledged.

9.3 MMI handheld controller including a 3 m RJ9 connection cable with M12 plug



IMPORTANT INFORMATION

The MMI handheld controller (art. no. 10004768) may only ever be used with an INVEOR!

The MMI handheld controller is connected to the integrated INVEOR M12 interface. This operating unit allows the user to write (program) and/or to visualise all the parameters of the INVEOR.

Up to 8 complete data sets can be stored in an MMI and copied to other INVEORs.

Complete commissioning is possible as an alternative to the free INVERTERpc software.

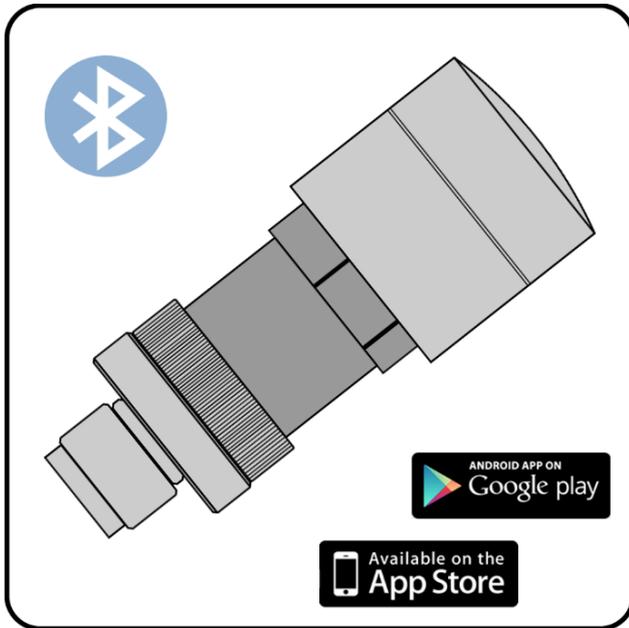
External signals are not needed.

9.4 PC communication cable USB on M12/RS485 plug (converter integrated)

As an alternative to the MMI handheld controller, an INVEOR can also be put into operation using the PC communication cable (art no. 10023950) and the INVERTERpc software.

The INVERTERpc software is available free of charge from the KOSTAL homepage at www.kostal-industrie-elektrik.com/downloads/downloadmanager#Antriebstechnik.

9.5 Bluetooth stick M12



You can start up your INVEOR MP using the Bluetooth stick and a mobile end device.

To establish communication, you can download our free KOSTAL INVERTERapp onto your mobile end device from the Google Play Store (ANDROID) or App Store (Apple IOS).

NOTE

If using the Bluetooth stick, the password is fixed as 000000.

10. Approvals, standards and guidelines

This chapter contains information about electromagnetic compatibility (EMC), and applicable guidelines, norms and standards.

For binding information about the relevant drive controller approvals, please refer to the relevant type plate!

10.1 EMC limit classes

Please note that EMC limit classes are only reached if the standard switching frequency of 8 kHz is complied with. Depending on the installation material used and/or extreme ambient conditions, it might be necessary to use additional sheath wave filters (ferrite rings). If mounting on a wall, the shielded motor cable must not exceed a maximum length of 3 m!

Wiring suitable for EMC also requires that EMC screw connections be used on both sides (drive controller and motor).



IMPORTANT INFORMATION

In a residential environment, this product can cause high-frequency disturbances that may require interference suppression measures.

10.2 Classification acc. to IEC/EN 61800-3

The generic standard defines test procedures and severity levels for every environment in the drive controller category; these have to be complied with.

Definition of environment

First environment (residential, commercial and industrial area):

All "areas" that are directly supplied by a public low-voltage connection, such as:

- residential area, e.g. houses, apartments etc.
- retail area, e.g. shops, supermarkets
- public institutions, e.g. theatres, stations
- outside areas, e.g. petrol stations and parking areas
- light industry, e.g. workshops, laboratories, small businesses

Second environment (industry):

Industrial environments with their own supply network that is separated from the public low-voltage supply by a transformer.

10.3 Standards and guidelines

The following specifically apply:

- Directive on Electromagnetic Compatibility (Directive 2014/30/EU)
- Low Voltage Directive (Directive 2014/35/EU)

11. Quickstart guide

11.1 Quickstart guide

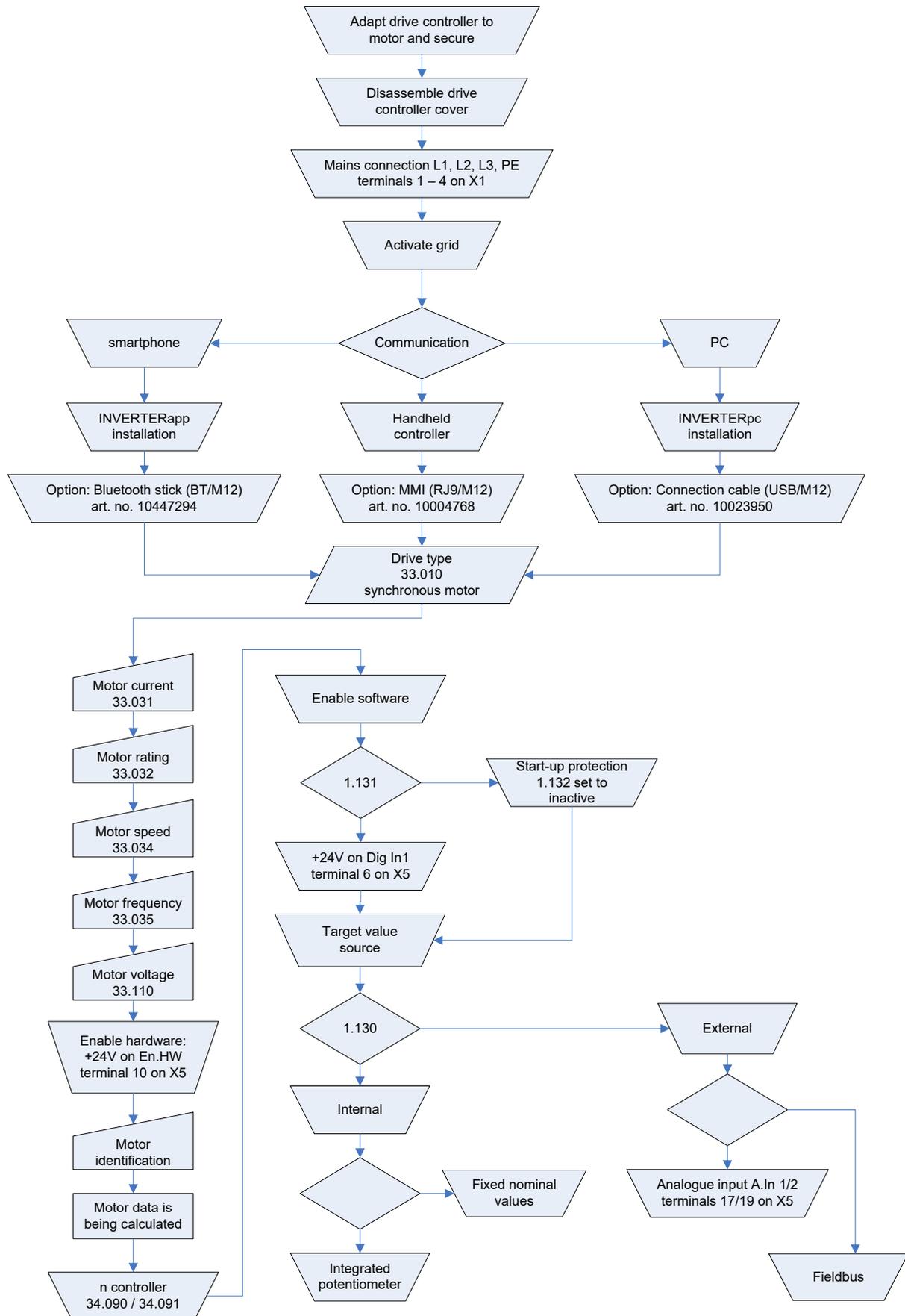


Fig. 50: Block diagram for quick start ASM

11.2 Quickstart guide for synchronous motors

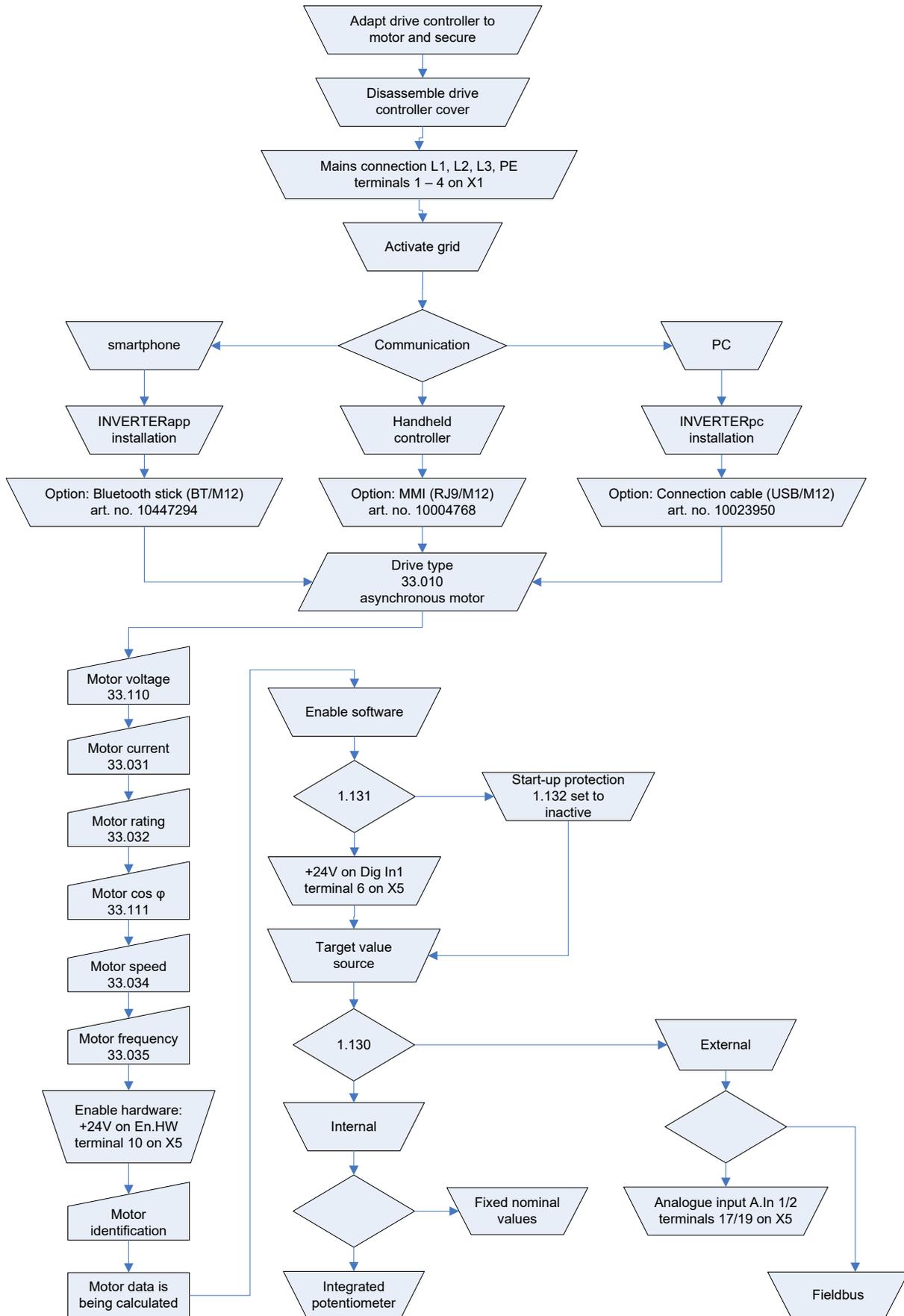


Fig. 51: Block diagram for quick start

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