

## **Driver Specification for Linear Motor Drive Tables**

## ■ Specification of MR-J4, a driver for NT38V

- Low-voltage (DC24V) specification and compact design of 100×90×30 mm. It contributes to miniaturization of devices and compactness.
- Servo gain adjustment, including machine resonance suppression filter, advanced vibration control II, and robust filter, can be completed simply by turning on the one-touch tuning function. Easy driving of the cutting-edge vibration suppression function allows the machine to produce its best performance.
- Machine diagnosis, startup and adjustment of the linear motor can be easily performed thanks to parameter settings, monitor display and machine analyzer of the setup software (MR Configurator2).

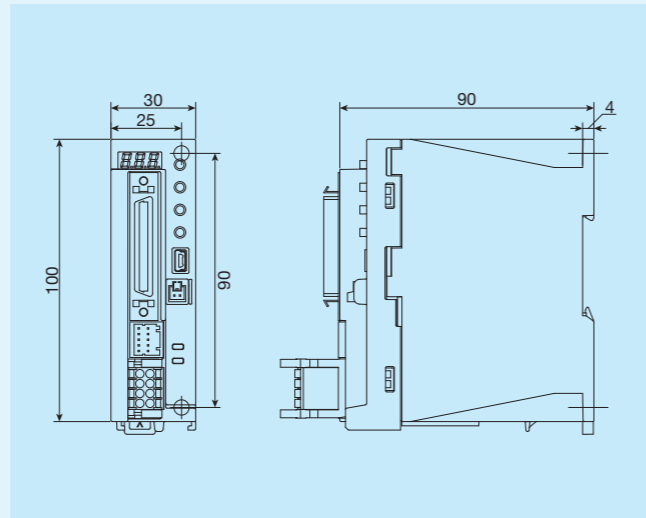


Table 1 Specifications for MR-J4

| Identification Number   |                                    | MR-J4-03A6-NL156J154/ MR-J4-03A6-NL156J155   |
|---|------------------------------------|--|
| Output  | Rated voltage                      | Three-phase AC13V  |
|   | Rated current                      | 2.4A   |
| Main circuit power supply input   | Voltage                            | DC24V  |
|   | Rated current                      | 2.4A   |
|   | Allowable power fluctuation        | DC21.6V to 26.4V   |
| Control circuit power supply input  | Voltage                            | DC24V  |
|   | Rated current                      | 0.2A   |
|   | Allowable power fluctuation        | DC21.6V to 26.4V   |
|   | Power consumption                  | 5.0W   |
| Power supply for interface  |                                    | DC24V ±10% (required current capacity: 0.3 A)  |
| Control method  |                                    | Sine wave PWM control/current control method   |
| Allowable regenerative power for servo amplifier built-in regenerative resistor |                                    | 0.7W   |
| Dynamic brake   |                                    | Built-in   |
| Communication function  |                                    | USB: connection with personal computer, etc. (MR Configurator2 supported)  |
| Encoder output pulse  |                                    | Supported (ABZ-phase pulse)  |
| Analog monitor  |                                    | 2-channel  |
| Position control mode   | Maximum input pulse frequency      | 4 Mpulses/s (with differential receiver), 200 kpulses/s (with open collector)  |
|   | Command pulse magnification        | Electronic gears A/Bx A = 1 to 1.6777215, B = 1 to 16777215, 1/10 < A/B < 4000   |
|   | Positioning complete width setting | 0 pulses to ±65535 pulses (command pulse unit)   |
| Positioning mode  |                                    | Point table method   |
| Protective function   |                                    | Overcurrent interrupt, regeneration overvoltage interrupt, overloading interrupt (electric thermal), servomotor overheat protection, encoder error protection, regeneration error protection, undervoltage protection, momentary power failure protection, overspeed protection, excessive error protection, magnetic pole detection protection, linear servo control error protection |
| Compliant overseas standards  | CE marking                         | LVD:EN 61800-5-1/EN 60959-1<br>EMC:EN 61800-3  |
|   | UL standard                        | UL 508C (NMM S2)   |
| Structure (protection degree)   |                                    | Natural air cooling and opening (IP20)   |
| Environmental conditions  | Ambient temperature                | Operation: 0 to 55° C (keep freeze free), Storage: -20 to 65° C (keep freeze free)   |
|   | Ambient humidity                   | Operation/storage: 5% to 90% RH or lower (keep condensation free)  |
|   | Atmosphere                         | Indoors (no exposure to direct sunlight)<br>Must be free from corrosive gas, flammable gas, oil mist and dust  |
|   | Altitude                           | 1,000 m or lower   |
| Vibration resistance  |                                    | 5.9 m/s <sup>2</sup> or less, 10 Hz to 55 Hz (X, Y, Z directions)  |
| Mass  |                                    | 0.2 kg   |

## ■ Specification of NCR, a driver for NT...H

- The driver and positioning unit are integrated, and the system is miniaturized with its wiring streamlined.
- Higher reliability and usability such as driftless, elimination of adjustment fluctuation, improvement of man-machine interface have been pursued with digital control.
- Easy positioning operation and pulse train operation are supported by mode selection, for applications to wide range of usages.
- Torque control and speed control are available.
- Control suitable for machine rigidity is made possible by full-scale software servo functions such as linear / S-curve acceleration and deceleration, feed forward, torque command filter, gain switching at shutdown and low speed, disturbance compensation control, etc.
- Peripheral devices such as touch panel, higher-level controller, etc. can be connected via serial communication.
- Dedicated editing software can be connected via USB 2.0 (full speed).

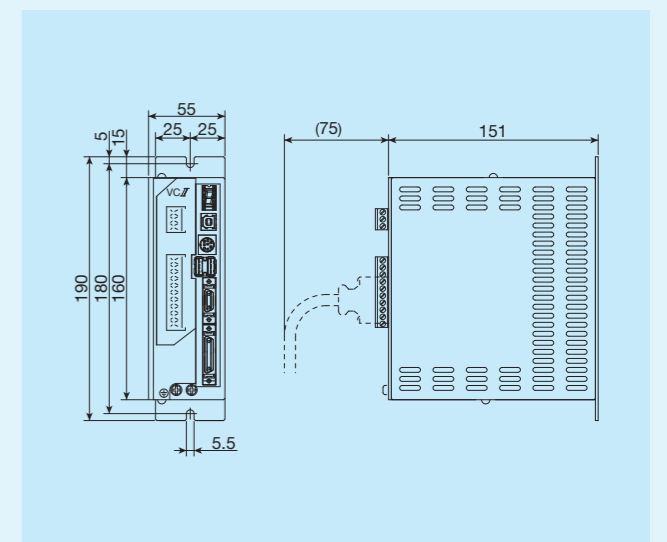


Table 2 Specifications for NCR

| Identification Number  |  | NCR-DDA0A1A-051D-T08   |
|------------------------|--|--|
| Basic specification    | Maximum rated current                                  | 1.1 Arms   |
|                        | Max. momentary current                                 | 3.3 Arms   |
|                        | Power plant capacity                                   | 0.15kVA  |
|                        | Input power (main circuit and control circuit)         | Single-phase AC100~115V (allowable power fluctuation AC90~121V) 50/60Hz ±5%  |
| Control method         |  | Three-phase sine wave PWM method   |
| Control mode           |  | Position (position control data / pulse train)   |
| Command input          | Pulse train command                                    | Line driver system is supported The maximum input frequency is indicated below<br>(1) Pulse with 90-degree phase difference: 4Mpps (16Mpps after 4-time multiplication)<br>(2) Directional pulse: 4Mpps (3) Directional + shift pulse: 4 Mpps  |
|                        | Speed control operation                                | Analog speed command and internal speed command (3 points)   |
|                        | Torque control operation                               | Analog torque command and internal torque command (3 points)   |
|                        | Easy positioning operation                             | 3 positioning modes: Manual mode / Return to origin mode / Easy positioning mode   |
| Input/ Output function | Contact input signal                                   | [8 basic input signal points (initial value)]<br>Servo on, reset, command pulse input prohibition, mode selection 1, mode selection 2, startup, speed selection, torque selection<br><Following signals are used by assigning remote control or input signals><br>Emergency stop, proportional control, address specification, speed override, deviation clear, torque limit, forward direction overtravel, reverse direction overtravel, etc. |
|                        | Contact output signal                                  | [4 basic output signal points (initial value)]<br>Servo ready, alarm, warning, positioning complete<br><Following signals are used by assigning remote control or output signals><br>Torque limit, speed zero, in speed operation mode, in torque operation mode, in easy positioning mode, in pulse train operation mode, encoder marker, etc.  |
|                        | Encoder feedback pulse output                          | Pulse train output with 90-degree phase difference<br>(frequency dividing output allowed. The maximum output frequency of 2 signals of A / B phase is 20Mpps after 4-time multiplication)  |
|                        | Encoder feedback pulse input                           | Pulse train input with 90-degree phase difference<br>(The maximum input frequency of 2 signals of A / B phase is 20Mpps after 4-time multiplication)   |
| Monitor output         |  | (1) Analog monitor: 2 points (2 points selected by parameters from various motion status can be monitored.)<br>(2) Various types of monitoring is possible with USB-ready dedicated editing software.  |
| Internal function      | Protective function                                    | IPM failure, overvoltage, undervoltage, overspeed, overload, regeneration resistance overload, deviation overflow, communication failure, data error, CPU failure, encoder failure, automatic magnetic pole detection failure, absolute encoder failure, etc.  |
|                        | Communication function                                 | Various data can be transmitted / received via serial communication (RS-422A).<br>Dedicated editing software can be connected via USB 2.0 (full speed)   |
| Operating environment  | Ambient temperature in operation / Storage temperature | 0 to 55° C / -20 to 66° C  |
|                        | Operating humidity                                     | 85%RH or lower (keep condensation free)  |
|                        | Vibration resistance                                   | 0.5G 10~55Hz   |
|                        | Service space  | Altitude of 1000 m or below, indoor (no corrosive gas and dust)  |
| Mass                   |  | 1.0kg  |

## Specifications for ADVA

### Applicable model numbers

NT series: NT55V, NT80V, NT88H, NT...XZ, NT...XZH

SA series: all model numbers

LT series: all model numbers

- In addition to the conventional pulse train command input, high speed motion network EtherCAT is also supported.
- 10 input terminals, 6 output terminals, and analog input (0 to ±10 V) can be controlled by intelligent terminals.
- The high controllability shortens the settling time, realizing further improvement of productivity.
- Machine diagnosis, startup and adjustment of linear motor can be easily performed thanks to parameter settings, monitor display, operation trace and automatic tuning function of the setup software.

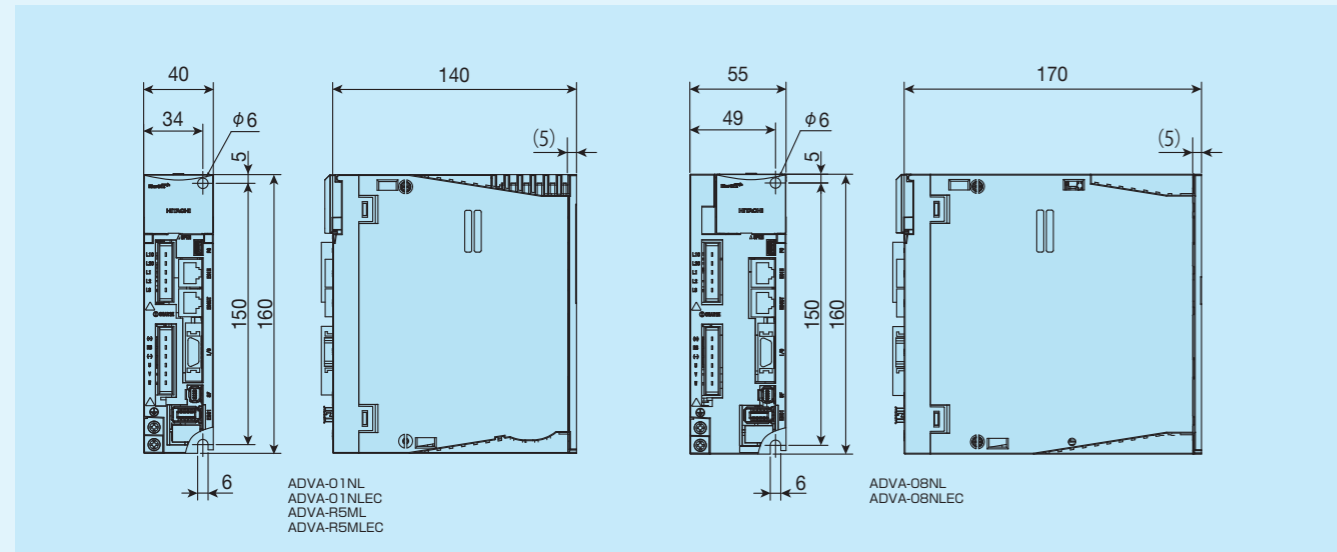


Table 3 Specifications for ADVA

| Item   | ADVA-01NL<br>ADVA-01NLEC   | ADVA-08NL<br>ADVA-08NLEC | ADVA-R5ML<br>ADVA-R5MLEC                |
|--|--|--------------------------|---|
| Input power  | Single-phase / Three-phase AC 200 to 230 V<br>50 / 60Hz  |                          | Single-phase AC100 to 115V<br>50 / 60Hz |
| Rated current / momentary current                          | 1.2Arms / 3.6Arms  | 5.1Arms / 15.3Arms       | 1.2Arms / 3.6Arms                       |
| Power plant capacity                                       | 0.3kVA   | 1.3kVA                   | 0.3kVA                                  |
| Protective structure (1)                                   | Semi-enclosed IP20   |                          |   |
| Control mode   | Position control / Speed control / Thrust force control  |                          |   |
| Speed command  | Analog input: 0 to ±10 V / Maximum speed (gain configurable) or EtherCAT   |                          |   |
| Thrust force command                                       | Analog input: 0 to ±10 V / Maximum thrust force (gain configurable) or EtherCAT  |                          |   |
| Position command   | Line driver signal: 20 Mpps (non-isolated input / after 4-time multiplication)<br>Open collector signal: 2 Mpps (isolated input / after 4-time multiplication) or EtherCAT   |                          |   |
| Contact input / output                                     | [Input] Intelligent terminal selects 10 input terminal (6 input terminal for EtherCAT specification) function by parameter<br>DC12 / 24 V Contact signal / Open collector signal input (with internal DC24 V power supply)<br>[Output] Intelligent terminal selects 6 output terminal (4 output terminal for EtherCAT specification) function by parameter<br>(Open collector signal output: sink output)  |                          |   |
| Built-in operator  | Pulse train command specification: Five digit numeric display, five key push button / DIP switch (Modbus communication setting)<br>EtherCAT specification: 2-digit numeric display, DIP switch (node address setting for EtherCAT)   |                          |   |
| External operator  | Windows 7/8 (32-bit, 64-bit) PC can be connected (USB 2.0 full speed)  |                          |   |
| Regenerative braking circuit                               | Built-in   |                          |   |
| Dynamic brake (2)  | Built-in (motion condition configurable)   |                          |   |
| Protective function  | Overcurrent, overload, braking resistor overload, main circuit overvoltage, memory error, main circuit under voltage, CT failure, CPU error 1, external trip (motor temperature error), servo ON ground detection, control circuit under voltage, servo amplifier temperature error, drive prohibition error, power module failure, safety circuit failure, emergency shutdown, encoder failure, mismatch error, power reactivation request, magnetic pole position estimation error, magnetic pole position estimation not executed, position deviation error, speed deviation error, overspeed error, momentary power failure, main circuit power supply failure, drive range error (network communication error, DC synchronization error, under voltage display) |                          |   |
| Ambient temperature in operation / Storage temperature (3) | 0 ~ 55°C / -10 ~ 70°C  |                          |   |
| Operating humidity   | 20 to 90% RH (keep condensation free)  |                          |   |
| Vibration resistance (4)                                   | 5.9m/s <sup>2</sup> (0.6G) 10 to 55Hz  |                          |   |
| Service space  | Altitude of 1000 m or below, indoor (no corrosive gas and dust)  |                          |   |
| Mass   | 0.7kg  | 1.2kg                    | 0.7kg                                   |

Notes (1) Protection method is compliant with JEM1030.

(2) Use the dynamic brake for emergency stop

(3) The storage temperature is the temperature during transportation.

(4) Compliant with JIS C60068-2-6:2010.

## Setup software

- Used for setting, referencing, changing, printing and saving driver parameters.
- Allows for real-time monitoring of operational status and output status.
- Indicates speed and current, etc. on charts.
- Supports commissioning and gain tuning.

Table 4 Operating environment of the setup software

| Item | Operating conditions   |
|------|--|
| PC   | CPU: Pentium 4 1.8 GHz or higher<br>HDD free space: 1 GB or more<br>Display resolution: 1024x768 or higher recommended |
| OS   | Windows Vista 32-bit SP1<br>Windows 7 (32-bit, 64-bit)<br>Windows 8 (32-bit, 64-bit)                                   |

Remark: Windows® is a registered trademark of Microsoft Corporation in USA and other countries.  
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## Automatic tuning function

By using the automatic tuning function of the setup software for ADVA, non-expert users can easily perform high-accuracy gain adjustment.

<Operating conditions>

Main body: NT55V25/05R + ADVA-01NL/NT55V25

Carrying mass: 200g Speed: 500mm/s Positioning complete width: ±5μm Traveling distance: 10mm

Acceleration/deceleration time: 12ms

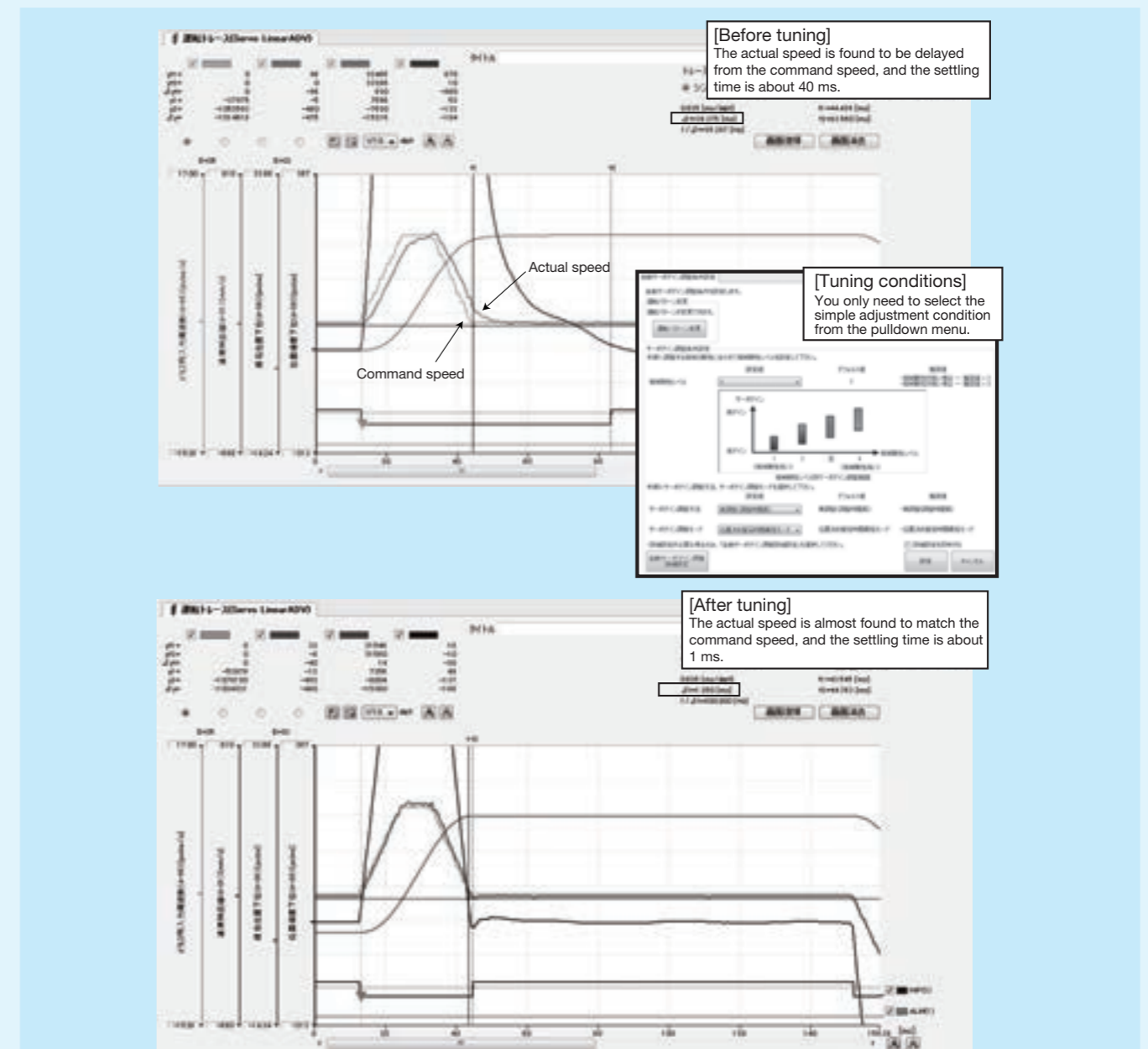


Fig. 2 Automatic tuning

# MR-J4

## Specifications for MR-J4

### Applicable model numbers

NT series: NT55V, NT80V  
SA series: all model numbers

- Supports SSCNET III/H (high-speed serial bus). Higher speed and accuracy are realized by optical communication system.
- Servo gain adjustment, including machine resonance suppression filter, advanced vibration control II, and robust filter, can be completed simply by turning on the one-touch tuning function. Easy driving of the cutting-edge vibration suppression function allows the machine to produce its best performance.
- Machine diagnosis, startup and adjustment of linear motor can be easily performed thanks to parameter settings, monitor display and machine analyzer of the setup software (MR Configurator2).

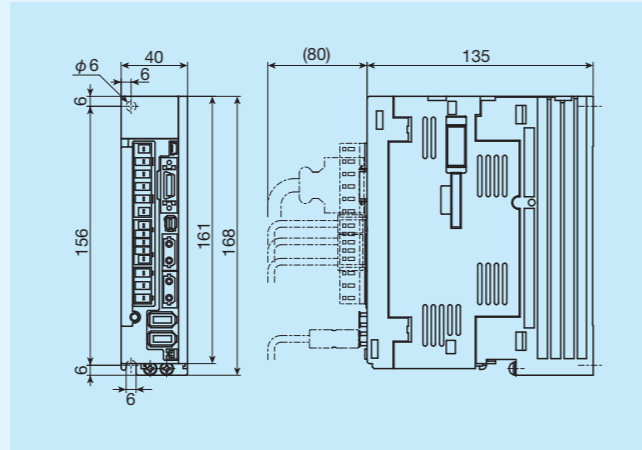
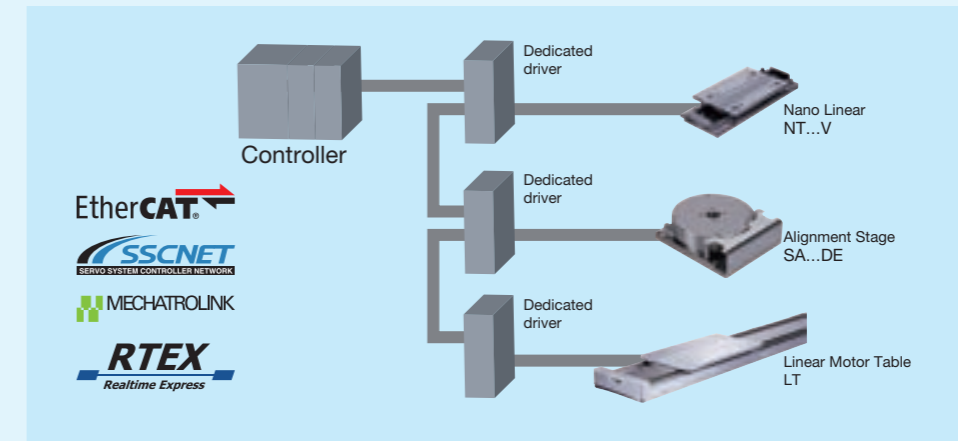


Table 5 Specifications for MR-J4

| Item                  |                                 | Identification Number  | MR-J4-10B-RJ  |
|-----------------------|---------------------------------|--|---|
| Basic specification   | Output                          | Rated voltage  | Three-phase AC170V  |
|                       |                                 | Rated current  | 1.1A  |
|                       | Main circuit power supply       | Voltage / Frequency  | Single-phase / Three-phase AC200-240V 50/60Hz                                 |
|                       |                                 | Allowable power fluctuation  | Single-phase / Three-phase AC170-264V   |
|                       |                                 | Allowable frequency fluctuation  | Within ± 5%   |
|                       |                                 | Control circuit power supply   | Voltage / Frequency   |
|                       | Allowable power fluctuation     |  | Single-phase AC170-264V   |
|                       | Allowable frequency fluctuation |  | Within ± 5%   |
|                       | Power consumption               |  | 30W   |
|                       |                                 | Power supply for interface   | DC24V ± 10% (required current capacity: 0.3A (includes CN8 connector signal)) |
|                       | Structure (protection class)    | Natural air cooling and opening (IP20)   |   |
|                       | Control method                  | Sine wave PWM control/current control method   |   |
|                       | Machine end encoder interface   | Mitsubishi high-speed serial communication / ABZ-phase differential input signal   |   |
| Input/Output function | Encoder output pulse            | Supported (ABZ-phase pulse)  |   |
|                       | Analog monitor                  | 2ch  |   |
| Internal function     | Communication function          | USB: connection with personal computer, etc. (MR Configurator2 supported)  |   |
|                       | Dynamic brake                   | Built-in   |   |
|                       | Protective function             | Overcurrent interrupt, regeneration overvoltage interrupt, overloading interrupt (electric thermal), servomotor overheat protection, encoder error protection, regeneration error protection, undervoltage protection, momentary power failure protection, overspeed protection, excessive error protection, magnetic pole detection protection, linear servo control error protection |   |
| Operating environment | Ambient temperature             | 0 to 55° C (keep freeze free), Storage: 20 to 65° C (keep freeze free)   |   |
|                       | Ambient humidity                | 90%RH or lower (keep condensation free), Storage: 90%RH or lower (keep condensation free)  |   |
|                       | Atmosphere                      | Indoor (no exposure to direct sun light), must be free from corrosive gas, flammable gas, oil mist and dust  |   |
|                       | Altitude                        | 1 000m or lower  |   |
|                       | Vibration resistance            | 5.9m/s <sup>2</sup> or less, 10Hz to 55Hz (X, Y, Z directions)   |   |
| Mass                  |                                 | 0.8kg  |   |

# Motion Network

Drivers for linear motor drive tables include those supporting motion networks EtherCAT, SSCNET III/H, MECHATROLINK, and RTEX. Motion networks realize higher performance and higher accuracy of devices free from pulse frequency constraint in pulse train command, noise effects in analog command (voltage command), voltage drop due to cable length and effects of temperature drifting. Reduction of wiring can also be achieved, so a synchronization system with more than one table can easily be established.



| Model        | Features   |
|--------------|--|
| EtherCAT     | This is an Ethernet-based open network communication system developed by Beckhoff of Germany, allowing the real time control. High speed communication and high accuracy inter-node synchronization realize the higher performance and higher accuracy of devices. In addition, Ethernet cables available on the market can be used and various wiring types can be supported. |
| SSCNET III/H | This is a motion network communication system for servo system control developed by Mitsubishi Electric Corporation. It applies the optical fiber cables, so noise immunity is improved relative to conventional SSCNET.   |
| MECHATROLINK | The open field network communication that connects the controller and various components. Developed by Yaskawa Electric Corporation and managed by MECHATROLINK Members Association.   |
| RTEX         | RTEX (Realtime Express) is an advanced network developed independently by Panasonic Corporation, in order to deliver the high real time performance required for servos. It offers extremely high-speed communication (100Mbps), and supports commercially available LAN cables to help reduce system costs.   |