



Interface function	RUN STOP	Work enable						
	F/R	Change direction						
	BRAKE	Brake signal input						
	VRM 5V COM	Sims signal/pwm signal speed regulating signal input						
	F/OUT	Speed signal output						
	ALM	Fault alarm output						
	RS-232 CAN RS-485	Communication Interface	485					
	HALL U V W	Hall signal input						
	U V W	Motor signal output						

	Set up	Enter the menu	Range	Unit	Default		coefficient	ram	Machine address	Function code	Address	Data example	CRC
	PR55	Driver code/number	1-255	—	1	Driver communication address		0	1	06	00 55	00 01	
	PR01	Number of poles, that will limit the minimum speed	1~10	—	4	Number of poles for the motor	1	1	1	06	00 01	00 04	
	PR02	Overcurrent alarm value	10~50	A	50	Software overcurrent alarm value	1	2	1	06	00 02	00 28	
	PR03	Limit current value	6~30	A	30	Power output software limit current value	1	3	1	06	00 03	00 0A	
	PR04	PWM output maximum value	10-99	%	99	The work output is under PR10, and the time to last PR15 will generate overload alarms	1	4	1	06	00 04	00 63	
	PR05	Control mode	0-5	—	2	0: Internal speed as instruction speed (closed loop) PR06 1: 5V voltage input as instruction speed (PR06 maximum) 2: 5V voltage input as PWM opening control 10~99%range 3: PWM opening control fixed value PR07 (1~10K ST) 4: 12V voltage input as instruction speed (100A has NXP) 5: 12V voltage input as PWM opening control (100A with NXP) 6: External ADC opening speed adjustment 7: External ADC closed -loop speed adjustment 8: External PWM opening speed adjustment	1	5	1	06	00 05	00 02	
	PR06	Closed -loop control speed	100-8000	rpm	3000	When the control mode is 0, the motor speed; When the control mode is 1, the maximum speed of the motor.	1	6	1	06	00 06	0B B8	
	PR07	Open ring control PWM output value	100~990	0.10%	500	When the control mode is 3, the controller PWM output value; When the control mode is 2, the controller PWM has a maximum output value.	1	7	1	06	00 07	03 DE	
	PR08	Input port level	0-1	—	0	0: Do not take reverse, low level is effective 1: Reverse, the high level is effective	1	8	1	06	00 08	00 00	
	PR09	Motor tachy -speed alarm value	100-9999	rpm	3500	Speed alarm value	1	9	1	06	00 09	0D AC	
	PR10	Speed duration alarm value	0-9999	mS	0	If it is 0, it will not start the alarm, and the other values will start the alarm	1	10	1	06	00 0A	00 00	
	PR11	Acceleration	10-100	rpm/m S	60	Start speed	1	11	1	06	00 0B	00 3C	
	PR12	Deceleration	10-100	rpm/m S	60	Stop speed	1	12	1	06	00 0C	00 3C	
	PR13	Baud rate	0~4	bps	2	0=9600 1=19200 2=38400 3=57600 4=115200	1	13	1	06	00 0D	00 02	
	PR15	Overload time	0-9999	mS	0	If it is 0, the alarm is not started. The controller PWM output has been working on the largest output, and at the same time the speed does not meet the requirements, the speed closed -loop mode is started	1	15	1	06	00 0F	00 00	
	PR16	Brake braking minimum startup speed (pay attention to the impact of the anti -electrocomputer)	1-1000	RPM	100	Value is directly proportional to the brake anti -electromotive force	1	16	1	06	00 10	00 64	
	PR17	The way to stop, the brake stop is loose	0-1	—	0	0: Free stop 1: Brake brake stop	1	17	1	06	00 11	00 00	
	PR34	485 motor start	0-1	—	0	0 : Stop 1 : Start	1	34	1	06	00 22	00 00	
	PR35	485 motor rotated direction	0-1	—	0	0 : CW 1 : CCW	1	35	1	06	00 23	00 00	
	PR36	485 motor brake	0-1	—	0	0 : loose brake 1 : Brake	1	36	1	06	00 24	00 00	
	PR37	Instruction source selection	0-1	—	0	0: IO port 1: 485 instruction	1	37	1	06	00 25	00 00	
	PR	Parameter saving	0-1	—	1	0: Not save 1: Save	1	AA 55	1	06	AA 55	00 01	
	PR256	Motor speed		rpm		Current motor speed	1	256	1	03	01 00	00 00	
	PR257	Target speed		rpm		Determined by the control mode PR05, the current setting speed	1	257	1	03	01 01	00 00	
	PR258	Underground software version		—		Year+month, such as 2004 stands for April Y2020	1	258	1	03	01 02	00 00	
	PR259	10V instruction speed: monitor the speed value of the current 10V simulation instruction conversion		rpm		100A model parameter	1	258	1	03	01 03	00 00	
	PR260	Potentiometer instruction speed		rpm			1	260	1	03	01 04	00 00	
	PR261	10V instruction AD value: 10V simulation AD value		mv		100A model parameter	1	261	1	03	01 05	00 00	
	PR262	Potentiometer instruction AD value		mV		5V input channel, monitor the current potentiometer analog voltage value	1	262	1	03	01 06	00 00	

PR263	Hall signal		—		Hall signal status value	1	263	1	03	01 07	00 00	
PR264	bus voltage		V		The current bus voltage value, unit: V	0.01	264	1	03	01 08	00 00	
PR266	Motor torque percentage		%		The current motor torque value, such as 30%of the strength is working	1	266	1	03	01 0A	00 00	
PR267	Driver temperature		°C		30A model does not have this parameter	1	267	1	03	01 0B	00 00	
PR268	Work current (peak)		A		Bus current peak	0.01	268	1	03	01 0C	00 00	
PR269	Work current (average)		A		Bus average current	0.01	269	1	03	01 0D	00 00	
PR270	Motor temperature		°C	/		1	270	1	03	01 0E	00 00	
PR271	Mechanical angle		radian	/		0.001	271	1	03	01 0F	00 00	
PR272	Electrical angle		radian		Hall position angle	0.001	272	1	03	01 10	00 00	
PR273	Fault				ER ** Content in the failure	1	273	1	03	01 11	00 00	
PR274	Fault shielding				ER ** content in the fault can be shielded	1	274	1	06	01 12	00 00	

Er** Fault	Fault	Meaning	LED flickering									
	Er01	Stall	1									
	Er02	Overcurrent alarm	2									
	Er03	Hall sensor	3									
	Er04	Low voltage	4									
	Er05	Over-voltage	5									
	Er06	exceed the speed limit	9									
	Er10	Overload	8									
	Er11	Overcurrent for hardware										
	Er12	IGBT fault										
	Er13	Driver overheat										
	Er14	Motor lack phase										
	Er15	Exceed of current										
	Er16	Communication failure										