



Mitsubishi Electric AC Servo System

MITSUBISHI ELECTRIC SERVO SYSTEM  
**MELSERVO-JET**

**MR-JET**  
**User's Manual**  
**(Troubleshooting)**

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-MR-JET-\_G  
-MR-JET-\_G-N1



# ABOUT THE MANUAL

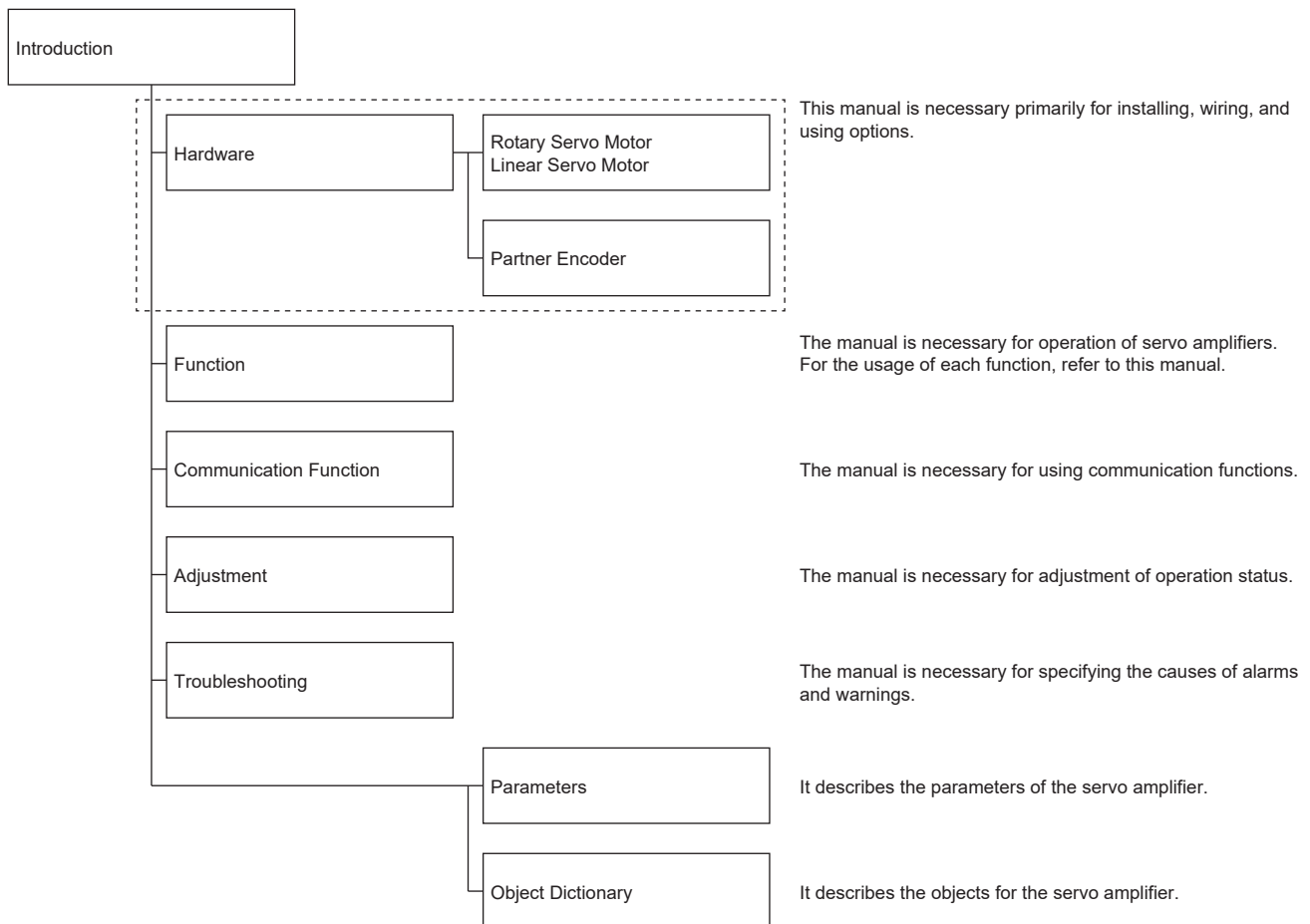
## Point

e-Manuals are Mitsubishi Electric FA electronic book manuals that can be browsed with a dedicated tool.

e-Manuals enable the following:

- Searching for desired information in multiple manuals at the same time (manual cross searching)
- Jumping from a link in a manual to another manual for reference
- Browsing for hardware specifications by scrolling over the components shown in product illustrations
- Bookmarking frequently referenced information
- Copying sample programs to engineering tools

If using the servo for the first time, prepare and use the following related manuals to ensure that the servo is used safely. For the related manuals, refer to the User's Manual (Introduction).



This manual covers the following servo amplifiers.

- MR-JET-\_G/MR-JET-\_G-N1

In this manual, the servo amplifier names are abbreviated as shown below.

Abbreviation	Servo amplifier
[G]	MR-JET-_G/MR-JET-_G-N1

## Global standards and regulations

Compliance with the indicated global standards and regulations is current as of the release date of this manual. Some standards and regulations may have been modified or withdrawn.

# U.S. CUSTOMARY UNITS

U.S. customary units are not shown in this manual. Convert the values if necessary according to the following table.

Quantity	SI (metric) unit	U.S. customary unit
Mass	1 [kg]	2.2046 [lb]
Length	1 [mm]	0.03937 [inch]
Torque	1 [N•m]	141.6 [oz•inch]
Moment of inertia	1 [ $\times 10^{-4}$ kg•m <sup>2</sup> ]	5.4675 [oz•inch <sup>2</sup> ]
Load (thrust load/axial load)	1 [N]	0.2248 [lbf]
Temperature	N [ $^{\circ}$ C] $\times$ 9/5 + 32	N [ $^{\circ}$ F]

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# 1 SERVO AMPLIFIER TROUBLESHOOTING

## 1.1 Outline

If an error occurs in the servo system, the corresponding alarm or warning is displayed. When an alarm occurs, ALM (Malfunction) turns off.

If an alarm or warning is displayed, take appropriate measures according to the following:

☞ Page 16 Handling methods for alarms/warnings

### Restrictions

- The following alarms are not recorded in the alarm history.

[AL. 010.1 Voltage drop in the control circuit power]

[AL. 037 Parameter error]

- With the exception of [AL. 0F0 Tough drive warning], warnings are not recorded in the alarm history.
- Alarms marked with "△" in the "Alarm deactivation" column have the deactivation conditions shown in the following table.

Detail No.	Alarm deactivation condition
030.1	Approximately 30 minutes of cooling time have passed since the cause of the alarm occurrence was removed.
042.1	Set the servo parameters as follows.
042.2	When in fully closed loop control: Set [Pr. PE03.3 Fully closed loop control error - Reset selection] to "1".
042.3	When a linear servo motor or a direct drive motor is used: Set [Pr. PL04.3 [AL. 042 Servo control error] detection controller reset condition selection] to "1".
042.8	
042.9	
042.A	
046.1	Approximately 30 minutes of cooling time have passed since the cause of the alarm occurrence was removed.
046.5	
046.6	
050.1	
050.2	
050.3	
050.4	
050.5	
050.6	
051.1	
051.2	
130.1	



## Precautions

- As soon as an alarm occurs, switch to servo-off status and shut off the power supply.
- If an abnormality related to overheating occurs, remove the cause of the abnormality and allow a cooling time of approximately 30 minutes.
- The alarm canceling method in [AL. 042 Servo control error] can be changed with [Pr. PL04.3 [AL. 042 Servo control error] detection controller reset condition selection] or [Pr. PE03.3 Fully closed loop control error - Reset selection].
- If an alarm which is related to the communication with the controller occurs, resetting the communication may not cancel the alarm.
- In the alarm list, alarms marked with "○" in any of the safety reset-related columns must be canceled while all the safety sub-functions have stopped. These alarms cannot be canceled unless all the safety sub-functions have stopped.
- After performing the check/action, cycle the power of the servo amplifier.
- If the alarm remains active even after the check/action of each alarm, the servo amplifier may have malfunctioned. Replace the servo amplifier, then check the repeatability.
- If the same problem continues even after replacing the servo amplifier, there may be a problem with the surrounding environment or with other devices.
- When [AL. 025 Absolute position erased] occurs, perform homing again to prevent an unexpected operation.
- To prevent malfunctions of the servo amplifier and servo motor, do not deactivate the alarm repeatedly to resume if any of the following alarms occur. Remove the cause of occurrence and allow 30 minutes or more for cooling, then resume the operation.

[AL. 030 Regenerative error]

[AL. 045 Main circuit device overheat]

[AL. 046 Servo motor overheat]

[AL. 050 Overload 1]

[AL. 051 Overload 2]

- To prevent malfunctions of the servo amplifier and servo motor, do not cycle the power of the servo amplifier repeatedly to resume if any of the following warnings occur. If the power of the servo amplifier is switched off/on during the warnings, allow more than 30 minutes for cooling before resuming operation.

[AL. 091 Servo amplifier overheat warning]

[AL. 0E0 Excessive regeneration warning]

[AL. 0E1 Overload warning 1]

- When [AL. 0E6 Servo forced stop warning], [AL. 0E9 Main circuit off warning], or [AL. 0EA ABS servo-on warning] occurs, the servo amplifier is changed to servo-off status. If any other warning occurs, the operation can still be continued, but an alarm may occur.

# 1.2 List of alarm No./warning No.

## Explanation of the list

### Motor stop method

Alarms and warnings which have "SD" in the "Motor stop method" column stop the servo motor with the dynamic brake after forced stop deceleration. Alarms and warnings which have "DB" or "EDB" in the "Motor stop method" column stop the servo motor with the dynamic brake.

#### ■ Stop method at occurrence of alarms/warnings

The servo amplifier has the following stop methods:

DB: Dynamic brake stop (for a servo amplifier without dynamic brake, the servo motor coasts)

SD: Forced stop deceleration

These stop methods are applicable when [Pr. PA04] is set to the initial value. The stop method can be changed from SD to DB with [Pr. PA04 Function selection A-1].

EDB: Stop with an electronic dynamic brake (enabled only for specific servo motors)

Refer to "Stop method at occurrence of alarms/warnings" in the following manual for the specific servo motors.

📖 MR-JET User's Manual (Function)

### Alarm deactivation

After the cause of the alarm has been removed, the alarm can be deactivated by using the methods marked with "○" in the "Alarm deactivation" column. Alarms marked with "△" in the "Alarm deactivation" column have the deactivation conditions.

📖 Page 6 Restrictions

Alarms are deactivated by alarm reset, communication reset, or power cycling. Alarms can also be deactivated by software reset instead of power cycling.

Refer to "Alarm function" in the following manual.

📖 MR-JET User's Manual (Function)

### Motor stop warning

Warnings that have "○" in the "Motor stop warning" column stop the servo motor when the warning occurs. If a warning that stops the servo motor occurs, WNGSTOP (Motor stop warning) will turn on.

# List

No.	Detail No.	Alarm/Warning	Motor stop method	Alarm deactivation			Motor stop warning
				Alarm reset	Communication reset	Power cycling	
010	010.1	Alarm	EDB	○	○	○	—
	010.2	Alarm	SD	○	○	○	—
011	011.1	Alarm	DB	×	×	○	—
012	012.1	Alarm	DB	×	×	○	—
	012.2	Alarm	DB	×	×	○	—
	012.4	Alarm	DB	×	×	○	—
	012.5	Alarm	DB	×	×	○	—
	012.6	Alarm	DB	×	×	○	—
	012.7	Alarm	DB	×	×	○	—
	012.8	Alarm	DB	×	×	○	—
	013	013.1	Alarm	DB	×	×	○
013.2		Alarm	DB	×	×	○	—
013.4		Alarm	DB	×	×	○	—
013.5		Alarm	DB	×	×	○	—
014		014.1	Alarm	DB	×	×	○
	014.2	Alarm	DB	×	×	○	—
	014.3	Alarm	DB	×	×	○	—
	014.4	Alarm	DB	×	×	○	—
	014.5	Alarm	DB	×	×	○	—
	014.8	Alarm	DB	×	×	○	—
	014.9	Alarm	DB	×	×	○	—
	014.C	Alarm	DB	×	×	○	—
016	016.1	Alarm	DB	×	×	○	—
	016.2	Alarm	DB	×	×	○	—
	016.3	Alarm	DB	×	×	○	—
	016.5	Alarm	DB	×	×	○	—
	016.6	Alarm	DB	×	×	○	—
	016.7	Alarm	DB	×	×	○	—
	016.A	Alarm	DB	×	×	○	—
	016.B	Alarm	DB	×	×	○	—
	016.C	Alarm	DB	×	×	○	—
	016.D	Alarm	DB	×	×	○	—
	016.E	Alarm	DB	×	×	○	—
	016.F	Alarm	DB	×	×	○	—
017	017.1	Alarm	DB	×	×	○	—
	017.3	Alarm	DB	×	×	○	—
	017.4	Alarm	DB	×	×	○	—
	017.5	Alarm	DB	×	×	○	—
	017.7	Alarm	DB	×	×	○	—
	017.9	Alarm	DB	×	×	○	—
019	019.1	Alarm	DB	×	×	○	—
	019.2	Alarm	DB	×	×	○	—
	019.3	Alarm	DB	×	×	○	—
	019.6	Alarm	DB	×	×	○	—
01A	01A.1	Alarm	DB	×	×	○	—
	01A.2	Alarm	DB	×	×	○	—
	01A.4	Alarm	DB	×	×	○	—
	01A.5	Alarm	DB	×	×	○	—

No.	Detail No.	Alarm/Warning	Motor stop method	Alarm deactivation			Motor stop warning
				Alarm reset	Communication reset	Power cycling	
01E	01E.1	Alarm	DB	×	×	○	—
	01E.2	Alarm	DB	×	×	○	—
01F	01F.1	Alarm	DB	×	×	○	—
	01F.2	Alarm	DB	×	×	○	—
020	020.1	Alarm	EDB	×	×	○	—
	020.2	Alarm	EDB	×	×	○	—
	020.3	Alarm	EDB	×	×	○	—
	020.5	Alarm	EDB	×	×	○	—
	020.6	Alarm	EDB	×	×	○	—
	020.7	Alarm	EDB	×	×	○	—
021	021.1	Alarm	EDB	×	×	○	—
	021.2	Alarm	EDB	×	×	○	—
	021.3	Alarm	EDB	×	×	○	—
	021.4	Alarm	EDB	×	×	○	—
	021.5	Alarm	EDB	×	×	○	—
	021.6	Alarm	EDB	×	×	○	—
024	024.1	Alarm	DB	×	×	○	—
	024.2	Alarm	DB	○	○	○	—
025	025.1	Alarm	DB	×	×	○	—
027	027.1	Alarm	DB	○	○	○	—
	027.2	Alarm	DB	○	○	○	—
	027.3	Alarm	DB	○	○	○	—
	027.4	Alarm	DB	○	○	○	—
	027.5	Alarm	DB	○	○	○	—
	027.6	Alarm	DB	○	○	○	—
	027.7	Alarm	DB	○	○	○	—
028	028.1	Alarm	EDB	×	×	○	—
	028.2	Alarm	EDB	×	×	○	—
02A	02A.1	Alarm	EDB	×	×	○	—
	02A.2	Alarm	EDB	×	×	○	—
	02A.3	Alarm	EDB	×	×	○	—
	02A.4	Alarm	EDB	×	×	○	—
	02A.5	Alarm	EDB	×	×	○	—
	02A.6	Alarm	EDB	×	×	○	—
	02A.7	Alarm	EDB	×	×	○	—
	02A.8	Alarm	EDB	×	×	○	—
030	030.1	Alarm	DB	△	△	○	—
	030.2	Alarm	DB	×	×	○	—
	030.3	Alarm	DB	△	△	○	—
031	031.1	Alarm	SD	○	○	○	—
032	032.1	Alarm	DB	×	×	○	—
	032.2	Alarm	DB	○	○	○	—
	032.3	Alarm	DB	×	×	○	—
	032.4	Alarm	DB	○	○	○	—
033	033.1	Alarm	EDB	○	○	○	—
035	035.1	Alarm	SD	○	○	○	—
037	037.1	Alarm	DB	×	○	○	—
	037.2	Alarm	DB	×	○	○	—
	037.3	Alarm	DB	×	○	○	—
	037.6	Alarm	DB	×	○	○	—
	037.7	Alarm	DB	×	○	○	—

No.	Detail No.	Alarm/Warning	Motor stop method	Alarm deactivation			Motor stop warning
				Alarm reset	Communication reset	Power cycling	
03A	03A.1	Alarm	EDB	×	×	○	—
042	042.1	Alarm	EDB	△	△	○	—
	042.2	Alarm	EDB	△	△	○	—
	042.3	Alarm	EDB	△	△	○	—
	042.8	Alarm	EDB	△	△	○	—
	042.9	Alarm	EDB	△	△	○	—
	042.A	Alarm	EDB	△	△	○	—
045	045.1	Alarm	EDB	○	○	○	—
	045.2	Alarm	EDB	○	○	○	—
046	046.1	Alarm	SD	△	△	○	—
	046.2	Alarm	SD	△	△	○	—
	046.3	Alarm	SD	△	△	○	—
	046.4	Alarm	SD	△	△	○	—
	046.5	Alarm	DB	△	△	○	—
	046.6	Alarm	DB	△	△	○	—
	046.7	Alarm	DB	△	△	○	—
047	047.1	Alarm	SD	×	×	○	—
	047.2	Alarm	SD	×	×	○	—
050	050.1	Alarm	SD	△	△	○	—
	050.2	Alarm	SD	△	△	○	—
	050.3	Alarm	SD	△	△	○	—
	050.4	Alarm	SD	△	△	○	—
	050.5	Alarm	SD	△	△	○	—
	050.6	Alarm	SD	△	△	○	—
051	051.1	Alarm	DB	△	△	○	—
	051.2	Alarm	DB	△	△	○	—
052	052.1	Alarm	SD	○	○	○	—
	052.3	Alarm	SD	○	○	○	—
	052.4	Alarm	SD	○	○	○	—
	052.5	Alarm	EDB	○	○	○	—
	052.6	Alarm	SD	○	○	○	—
054	054.1	Alarm	EDB	○	○	○	—
056	056.2	Alarm	EDB	○	○	○	—
	056.3	Alarm	EDB	○	○	○	—
	056.5	Alarm	EDB	○	○	○	—
061	061.1	Alarm	DB	○	○	○	—
069	069.1	Alarm	SD	○	○	○	—
	069.2	Alarm	SD	○	○	○	—
	069.3	Alarm	SD	○	○	○	—
	069.4	Alarm	SD	○	○	○	—
	069.5	Alarm	SD	○	○	○	—
	069.6	Alarm	SD	○	○	○	—

No.	Detail No.	Alarm/Warning	Motor stop method	Alarm deactivation			Motor stop warning
				Alarm reset	Communication reset	Power cycling	
070	070.1	Alarm	DB	×	×	○	—
	070.2	Alarm	DB	×	×	○	—
	070.3	Alarm	DB	×	×	○	—
	070.5	Alarm	DB	×	×	○	—
	070.6	Alarm	DB	×	×	○	—
	070.7	Alarm	DB	×	×	○	—
	070.A	Alarm	DB	×	×	○	—
	070.B	Alarm	DB	×	×	○	—
	070.C	Alarm	DB	×	×	○	—
	070.D	Alarm	DB	×	×	○	—
	070.E	Alarm	DB	×	×	○	—
070.F	Alarm	DB	×	×	○	—	
071	071.1	Alarm	EDB	×	×	○	—
	071.2	Alarm	EDB	×	×	○	—
	071.3	Alarm	EDB	×	×	○	—
	071.7	Alarm	EDB	×	×	○	—
072	072.1	Alarm	EDB	×	×	○	—
	072.2	Alarm	EDB	×	×	○	—
	072.3	Alarm	EDB	×	×	○	—
	072.4	Alarm	EDB	×	×	○	—
	072.5	Alarm	EDB	×	×	○	—
	072.6	Alarm	EDB	×	×	○	—
076	076.2	Alarm	DB	×	×	○	—
	076.3	Alarm	DB	×	×	○	—
086	086.1	Alarm	SD	○	×	○	—
	086.2	Alarm	SD	○	×	○	—
	086.3	Alarm	SD	○	×	○	—
	086.4	Alarm	SD	○	×	○	—
	086.5	Alarm	SD	○	×	○	—
	086.6	Alarm	SD	○	×	○	—
088/888/ 88888	088.1/088/ 888/88888	Alarm	DB	×	×	○	—
	088.2	Alarm	DB	×	×	○	—
	088.4	Alarm	DB	×	×	○	—
	088.8	Alarm	DB	×	×	○	—
08E	08E.1	Alarm	SD	○	○	○	—
	08E.2	Alarm	SD	○	○	○	—
	08E.3	Alarm	SD	○	○	○	—
	08E.4	Alarm	SD	○	○	○	—
	08E.5	Alarm	SD	○	○	○	—

No.	Detail No.	Alarm/Warning	Motor stop method	Alarm deactivation			Motor stop warning
				Alarm reset	Communication reset	Power cycling	
08F	08F.1	Alarm	Refer to the alarm columns with alarm No. in 100s ([AL. 1_ _]).				
	08F.2	Alarm	Refer to the alarm columns with alarm No. in 200s ([AL. 2_ _]).				
	08F.3	Alarm	For manufacturer setting				
	08F.4	Alarm	For manufacturer setting				
	08F.5	Alarm	For manufacturer setting				
	08F.6	Alarm	For manufacturer setting				
	08F.7	Alarm	For manufacturer setting				
	08F.8	Alarm	For manufacturer setting				
	08F.9	Alarm	For manufacturer setting				
	08F.A	Alarm	For manufacturer setting				
	08F.B	Alarm	For manufacturer setting				
	08F.C	Alarm	For manufacturer setting				
	08F.D	Alarm	For manufacturer setting				
	08F.E	Alarm	For manufacturer setting				
	08F.F	Alarm	For manufacturer setting				
090	090.1	Warning	—	—	—	—	○
	090.2	Warning	—	—	—	—	○
	090.5	Warning	—	—	—	—	○
091	091.1	Warning	—	—	—	—	×
092	092.1	Warning	—	—	—	—	×
	092.3	Warning	—	—	—	—	×
096	096.1	Warning	—	—	—	—	○
	096.2	Warning	—	—	—	—	○
098	098.1	Warning	DB	—	—	—	○
	098.2	Warning	DB	—	—	—	○
099	099.1	Warning	—	—	—	—	○
	099.2	Warning	—	—	—	—	○
	099.4	Warning	—	—	—	—	○
	099.5	Warning	—	—	—	—	○
	099.6	Warning	—	—	—	—	○
	099.7	Warning	—	—	—	—	○
	099.8	Warning	—	—	—	—	○
	099.9	Warning	—	—	—	—	○
09B	09B.1	Warning	—	—	—	—	×
	09B.3	Warning	—	—	—	—	×
	09B.4	Warning	—	—	—	—	×
09E	09E.2	Warning	DB	—	—	—	○
	09E.3	Warning	DB	—	—	—	○
	09E.4	Warning	DB	—	—	—	○
	09E.5	Warning	DB	—	—	—	○
	09E.6	Warning	DB	—	—	—	○
	09E.7	Warning	DB	—	—	○	○
	09E.8	Warning	DB	—	—	○	○
	09E.9	Warning	DB	—	—	—	○
09E.A	Warning	DB	—	—	—	○	
09F	09F.1	Warning	—	—	—	—	×
0E0	0E0.1	Warning	—	—	—	—	×

No.	Detail No.	Alarm/Warning	Motor stop method	Alarm deactivation			Motor stop warning
				Alarm reset	Communication reset	Power cycling	
0E1	0E1.1	Warning	—	—	—	—	×
	0E1.2	Warning	—	—	—	—	×
	0E1.3	Warning	—	—	—	—	×
	0E1.4	Warning	—	—	—	—	×
	0E1.5	Warning	—	—	—	—	×
	0E1.6	Warning	—	—	—	—	×
	0E1.7	Warning	—	—	—	—	×
	0E1.8	Warning	—	—	—	—	×
0E2	0E2.1	Warning	—	—	—	—	×
	0E2.2	Warning	—	—	—	—	×
0E3	0E3.1	Warning	—	—	—	—	×
	0E3.2	Warning	—	—	—	—	×
	0E3.5	Warning	—	—	—	—	×
0E6	0E6.1	Warning	SD	—	—	—	○
0E8	0E8.1	Warning	—	—	—	—	×
	0E8.2	Warning	—	—	—	—	×
0E9	0E9.1	Warning	DB	—	—	—	○
	0E9.2	Warning	DB	—	—	—	○
	0E9.3	Warning	DB	—	—	—	○
0EC	0EC.1	Warning	—	—	—	—	×
0ED	0ED.1	Warning	—	—	—	—	×
0F0	0F0.1	Warning	—	—	—	—	×
	0F0.3	Warning	—	—	—	—	×
0F2	0F2.1	Warning	—	—	—	○	×
	0F2.2	Warning	—	—	—	○	×
	0F2.3	Warning	—	—	—	○	×
	0F2.4	Warning	—	—	—	○	×
	0F2.5	Warning	—	—	—	○	×
	0F2.6	Warning	—	—	—	○	×
0F3	0F3.1	Warning	—	—	—	—	×
0F4	0F4.4	Warning	—	—	—	—	○
	0F4.6	Warning	—	—	—	—	○
	0F4.7	Warning	—	—	—	—	○
	0F4.8	Warning	—	—	—	—	○
	0F4.A	Warning	—	—	—	—	○
0FE	0FE.1	Warning	Refer to the warning columns with warning No. in 100s ([AL. 1_ _]).				
	0FE.2	Warning	Refer to the warning columns with warning No. in 200s ([AL. 2_ _]).				
	0FE.3	Warning	For manufacturer setting				
	0FE.4	Warning	For manufacturer setting				
	0FE.5	Warning	For manufacturer setting				
	0FE.6	Warning	For manufacturer setting				
	0FE.7	Warning	For manufacturer setting				
	0FE.8	Warning	For manufacturer setting				
	0FE.9	Warning	For manufacturer setting				
	0FE.A	Warning	For manufacturer setting				
	0FE.B	Warning	For manufacturer setting				
	0FE.C	Warning	For manufacturer setting				
	0FE.D	Warning	For manufacturer setting				
	0FE.E	Warning	For manufacturer setting				
0FE.F	Warning	For manufacturer setting					
118	118.1	Alarm	DB	×	×	○	—



No.	Detail No.	Alarm/Warning	Motor stop method	Alarm deactivation			Motor stop warning
				Alarm reset	Communication reset	Power cycling	
119	119.1	Alarm	DB	×	×	○	—
	119.2	Alarm	DB	×	×	○	—
	119.3	Alarm	DB	×	×	○	—
	119.4	Alarm	DB	×	×	○	—
	119.5	Alarm	DB	×	×	○	—
	119.6	Alarm	DB	×	×	○	—
	119.7	Alarm	DB	×	×	○	—
	119.8	Alarm	DB	×	×	○	—
11A	11A.1	Alarm	—	—	—	○	—
	11A.2	Alarm	—	—	—	○	—
	11A.3	Alarm	—	—	—	○	—
130	130.1	Alarm	DB	○	○	○	×
139	139.2	Alarm	DB	×	×	○	—
17A	17A.1	Alarm	EDB	×	×	○	—
	17A.2	Alarm	EDB	×	×	○	—
	17A.3	Alarm	EDB	×	×	○	—
	17A.4	Alarm	EDB	×	×	○	—
	17A.5	Alarm	EDB	×	×	○	—
	17A.6	Alarm	EDB	×	×	○	—
	17A.7	Alarm	EDB	×	×	○	—
	17A.8	Alarm	EDB	×	×	○	—
188	188.1	Alarm	DB	×	×	○	—
19D	19D.1	Warning	—	—	—	—	×
	19D.2	Warning	—	—	—	—	×
19E	19E.1	Warning	—	—	—	—	—
	19E.2	Warning	—	—	—	—	—
	19E.3	Warning	—	—	—	—	—
1E9	1E9.1	Warning	—	—	—	—	×
1F6	1F6.1	Warning	—	—	—	—	×
	1F6.2	Warning	—	—	—	—	×
	1F6.3	Warning	—	—	—	—	×
	1F6.4	Warning	—	—	—	—	×
	1F6.5	Warning	—	—	—	—	×
	1F6.6	Warning	—	—	—	—	×
1F8	1F8.1	Warning	—	—	—	—	×
	1F8.2	Warning	—	—	—	—	×
201 - 28F	—	Alarm	For manufacturer setting				
290 - 2FF	—	Warning	For manufacturer setting				

# 1.3 Handling methods for alarms/warnings

Remove the cause of the alarm and warning in accordance with this section. MR Configurator2 can be referenced to find the causes of warnings.

## [AL. 010\_Undervoltage]

- The power supply voltage has dropped.

### [AL. 010.1\_Voltage drop in the control circuit power]

Cause	Check/action method	Model
<b>1.</b> The power connector is not properly connected.	Check the connection of the power supply. Refer to "Example power circuit connections" in the following manual. ☐MR-JET User's Manual (Hardware)	[G]
<b>2.</b> The voltage of the power supply is too low.	Check if the voltage of the power supply is equal to or lower than the specified value. 200 V class: 160 V AC	
<b>3.</b> An instantaneous power failure lasted for longer than the specified time.  • When [Pr. PA20.2 Instantaneous power failure tough drive selection] is set to "0" (disabled), the specified time is 60 ms. • When [Pr. PA20.2] is set to "1" (enabled), the value set in [Pr. PF25 Instantaneous power failure tough drive detection time] is the specified time.	Check if the power supply has a problem. After checking, cycle the power of the servo amplifier.	
<b>4.</b> When using a 1-phase power supply, the power supply wiring is incorrect.	Refer to "Example power circuit connections" in the following manual. ☐MR-JET User's Manual (Hardware)	

### [AL. 010.2\_Voltage drop in the main circuit power]

Cause	Check/action method	Model
<b>1.</b> The power connector is not properly connected.	Check the power supply wiring. Refer to "Example power circuit connections" in the following manual. ☐MR-JET User's Manual (Hardware)	[G]
<b>2.</b> The voltage of the power supply is too low.	Check if the voltage of the power supply is equal to or lower than the specified value. When the voltage is equal to or lower than the specified value, increase the voltage of the power supply. • 200 V class: 160 V AC	
<b>3.</b> When this alarm occurs, the bus voltage is too low at acceleration.	Check if the bus voltage during acceleration is lower than the specified value. If the bus voltage is lower than the specified value, increase the acceleration time constant or the power supply capacity. • 200 V class: 200 V DC	
<b>4.</b> The power supply capacity is insufficient.	Check if the specified power supply capacity is satisfied.	
<b>5.</b> Main circuit capacitor has deteriorated.	After checking the operation time and ambient temperature, replace the servo amplifier if the main circuit capacitor has reached the end of its service life. Refer to "Parts with a service life" in the User's Manual (Introduction).	
<b>6.</b> The servo amplifier has malfunctioned.	Check the value of the bus voltage. If the bus voltage is lower than the specified value even though the voltage of the power supply is within specifications, replace the servo amplifier. • 200 V class: 200 V DC	

## [AL. 011\_Switch setting error]

- The settings of the DIP switch are incorrect.
- The settings of the rotary switch are incorrect.

### [AL. 011.1\_Rotary switch setting error]

Cause	Check/action method	Model
<b>1.</b> Each selected network has its settable range, and the values set with the rotary switches (SW1/SW2) were set out of the range.	Check the settings of the rotary switches (SW1/SW2). If the value set with the rotary switch does not match the actual value, the servo amplifier may have malfunctioned. Replace the servo amplifier. Specifications on the setting of the rotary switches vary depending on each network. Refer to "Switch setting and display of the servo amplifier" in the User's Manual (Introduction).	[G]


## [AL. 012\_Memory error 1 (RAM)]

- The internal part of the servo amplifier (RAM) has malfunctioned.


### [AL. 012.1\_RAM error 1]

Cause	Check/action method	Model
1. An internal part of the servo amplifier has malfunctioned.	Noise from the power supply may have caused the failure. Disconnect all cables except for those for the power supply, then check the repeatability. If the failure continues, the servo amplifier may have malfunctioned. Replace the servo amplifier.	[G]
2. There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. <a href="#">MR-JET User's Manual (Hardware)</a>	


### [AL. 012.2\_RAM error 2]

 Page 18 [AL. 012.1\_RAM error 1]


### [AL. 012.4\_RAM error 4]

 Page 18 [AL. 012.1\_RAM error 1]


### [AL. 012.5\_RAM error 5]

 Page 18 [AL. 012.1\_RAM error 1]


### [AL. 012.6\_RAM error 6]

 Page 18 [AL. 012.1\_RAM error 1]

### [AL. 012.7\_RAM error 7]

 Page 18 [AL. 012.1\_RAM error 1]

### [AL. 012.8\_RAM error 8]

 Page 18 [AL. 012.1\_RAM error 1]


### [AL. 012.9\_For manufacturer setting]

This is for manufacturer setting.


## [AL. 013\_CPU error]

- An internal part of the servo amplifier has malfunctioned.
- A clock transmitted from the controller has an error.


### [AL. 013.1\_CPU error 1]

Cause	Check/action method	Model
<b>1.</b> An internal part of the servo amplifier has malfunctioned.	Noise from the power supply may have caused the failure. Disconnect all cables except for those for the power supply, then check the repeatability. If the failure continues, replace the servo amplifier.	[G]
<b>2.</b> A clock transmitted from the controller has an error.	Check if this alarm occurs when the servo amplifier is connected to the controller. If the alarm occurs, replace the controller.	
<b>3.</b> The servo amplifier of the next axis has malfunctioned.	Replace the servo amplifier of the next axis, then check the repeatability.	
<b>4.</b> There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Check if the connector has shorted. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	


### [AL. 013.2\_CPU error 2]

 Page 19 [AL. 013.1\_CPU error 1]

### [AL. 013.4\_CPU error 4]

 Page 19 [AL. 013.1\_CPU error 1]


### [AL. 013.5\_CPU error 5]

 Page 19 [AL. 013.1\_CPU error 1]


## [AL. 014\_Control process error]

- The process did not complete within the specified time.
- The internal part of the servo amplifier (communication IC) has malfunctioned.


### [AL. 014.1\_Control process error 1]

Cause	Check/action method	Model
1. The servo parameter settings are incorrect.	Return the servo parameter to the value it had before the alarm occurrence, then check if the problem occurs again.	[G]
2. There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Check if the connector has shorted. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	
3. The servo amplifier has malfunctioned.	Replace the servo amplifier.	


### [AL. 014.2\_Control process error 2]

Cause	Check/action method	Model
1. A synchronous signal transmitted from the controller has an error.	Replace the controller, then check the repeatability.	[G]
2. The servo parameter settings are incorrect.	Return the servo parameter to the value it had before the alarm occurrence, then check if the problem occurs again.	
3. There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Check if the connector has shorted. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	
4. The servo amplifier has malfunctioned.	Replace the servo amplifier.	


### [AL. 014.3\_Control process error 3]

 Page 20 [AL. 014.1\_Control process error 1]


### [AL. 014.4\_Control process error 4]

 Page 20 [AL. 014.1\_Control process error 1]


### [AL. 014.5\_Control process error 5]

 Page 20 [AL. 014.1\_Control process error 1]


### [AL. 014.8\_Control process error 8]

 Page 20 [AL. 014.1\_Control process error 1]

### [AL. 014.9\_Control process error 9]

 Page 20 [AL. 014.1\_Control process error 1]

### [AL. 014.C\_Control process error 12]

 Page 20 [AL. 014.1\_Control process error 1]

## [AL. 016\_ Encoder initial communication error 1]

- There is a communication error between the encoder and servo amplifier.

### [AL. 016.1\_ Encoder initial communication - Receive data error 1]

Cause	Check/action method	Model
1. There is a problem with the encoder cable.	Check if the encoder cable has been disconnected, incorrectly wired, or has shorted. If there is a problem with the encoder cable, replace or repair the cable.	[G]
2. If an A/B/Z-phase differential output type encoder is being used on the servo motor side, the servo amplifier is not compatible with the A/B/Z-phase differential output type encoder.	Check if the servo amplifier is compatible with the A/B/Z-phase differential output type encoder. Refer to "Compatible linear encoder list" in the following manual. □MR-JET Partner's Encoder User's Manual	
3. If an A/B/Z-phase differential output type encoder is being used on the servo motor side, the connection with the encoder is incorrect.	Check if the wiring of the A/B/Z-phase differential output type encoder is correct. Check if the encoder is wired to PSEL. Refer to "A/B/Z-phase differential output type encoder" in the following manual. □MR-JET Partner's Encoder User's Manual	
4. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
5. The encoder has malfunctioned.	Replace the servo motor.	
6. There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Check if the connector has shorted. Refer to "Noise reduction techniques" in the following manual. □MR-JET User's Manual (Hardware)	

### [AL. 016.2\_ Encoder initial communication - Receive data error 2]

☞ Page 21 [AL. 016.1\_ Encoder initial communication - Receive data error 1]

### [AL. 016.3\_ Encoder initial communication - Receive data error 3]

Cause	Check/action method	Model
1. The encoder cable is disconnected.	Check if the encoder cable is connected correctly.	[G]
2. The servo parameter settings for the communication method are incorrect.	Set the servo parameter correctly according to the encoder cable communication method (two-wire type/four-wire type). [G]: [Pr. PC04.3 Encoder cable communication method selection]	
3. There is a problem with the encoder cable.	Check if the encoder cable has been disconnected or has shorted. If there is a problem with the encoder cable, replace or repair the cable.	
4. The power supply voltage has become unstable.	Check the power supply voltage. If an instantaneous power failure is occurring in the power supply, review the power supply environment.	
5. If an A/B/Z-phase differential output type encoder is being used on the servo motor side, the connection with the encoder is incorrect.	Check if the wiring of the A/B/Z-phase differential output type encoder is correct. Check if the encoder is wired to PSEL. Refer to "A/B/Z-phase differential output type encoder" in the following manual. □MR-JET Partner's Encoder User's Manual	
6. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
7. The encoder has malfunctioned.	Replace the servo motor.	
8. There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Check if the connector has shorted. Refer to "Noise reduction techniques" in the following manual. □MR-JET User's Manual (Hardware)	

### [AL. 016.5\_ Encoder initial communication - Transmission data error 1]

☞ Page 21 [AL. 016.1\_ Encoder initial communication - Receive data error 1]

## [AL. 016.6\_Encoder initial communication - Transmission data error 2]

☞ Page 21 [AL. 016.1\_Encoder initial communication - Receive data error 1]

## [AL. 016.7\_Encoder initial communication - Transmission data error 3]

☞ Page 21 [AL. 016.1\_Encoder initial communication - Receive data error 1]

## [AL. 016.A\_Encoder initial communication - Process error 1]

Cause	Check/action method	Model
1. The servo amplifier has malfunctioned.	Replace the servo amplifier.	[G]
2. The encoder has malfunctioned.	Replace the servo motor.	
3. There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Check if the connector has shorted. Refer to "Noise reduction techniques" in the following manual. ☞MR-JET User's Manual (Hardware)	

## [AL. 016.B\_Encoder initial communication - Process error 2]

☞ Page 22 [AL. 016.A\_Encoder initial communication - Process error 1]

## [AL. 016.C\_Encoder initial communication - Process error 3]

☞ Page 22 [AL. 016.A\_Encoder initial communication - Process error 1]

## [AL. 016.D\_Encoder initial communication - Process error 4]

☞ Page 22 [AL. 016.A\_Encoder initial communication - Process error 1]

## [AL. 016.E\_Encoder initial communication - Process error 5]

☞ Page 22 [AL. 016.A\_Encoder initial communication - Process error 1]

## [AL. 016.F\_Encoder initial communication - Process error 6]


☞ Page 22 [AL. 016.A\_Encoder initial communication - Process error 1]




## [AL. 017\_Board error]

- There is a problem with an internal part of the servo amplifier.


### [AL. 017.1\_Board error 1]

Cause	Check/action method	Model
1. There is a problem with the current detection circuit.	Check that this alarm occurs in the servo-on status. If the alarm occurs, the servo amplifier may have malfunctioned. Replace the servo amplifier.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	


### [AL. 017.3\_Board error 2]

 Page 23 [AL. 017.1\_Board error 1]


### [AL. 017.4\_Board error 3]

Cause	Check/action method	Model
1. The firmware version of the servo amplifier is not supported.	The firmware version is not supported. Perform a firmware update to revert to the firmware version prior to the update.	[G]
2. The recognition signal of the servo amplifier was not read properly.	Disconnect all cables except for those for the power supply, then check the repeatability. If the failure continues, the servo amplifier may have malfunctioned. Replace the servo amplifier.	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	


### [AL. 017.5\_Board error 4]

Cause	Check/action method	Model
1. There is a problem with rotary switches (SW1/SW2).	After checking the conditions of the rotary switches, cycle the power, then check the repeatability. If the failure continues, the servo amplifier may have malfunctioned. Replace the servo amplifier.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	

### [AL. 017.7\_Board error 7]

Cause	Check/action method	Model
1. The firmware version of the servo amplifier is not supported.	The firmware version is not supported. Perform a firmware update to revert to the firmware version prior to the update.	[G]
2. The recognition signal of the servo amplifier was not read properly.	Disconnect all cables except for those for the power supply, then check the repeatability. If the failure continues, the servo amplifier may have malfunctioned. Replace the servo amplifier.	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals.  MR-JET User's Manual (Hardware)	

## [AL. 017.9\_Board error 8]

Cause	Check/action method	Model
1. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	[G]
2. The servo amplifier has malfunctioned.	Replace the servo amplifier.	


## [AL. 019\_Memory error 3]

- The internal part of the servo amplifier (Flash-ROM) has malfunctioned.


### [AL. 019.1\_Flash-ROM error 1]

Cause	Check/action method	Model
1. The Flash-ROM has malfunctioned.	Noise from the power supply may have caused the failure. Disconnect all cables except for those for the power supply, then check the repeatability. If the failure continues, replace the servo amplifier.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. <a href="#">MR-JET User's Manual (Hardware)</a>	
3. A firmware installation failed.	Install the firmware again.	


### [AL. 019.2\_Flash-ROM error 2]

 Page 25 [AL. 019.1\_Flash-ROM error 1]

### [AL. 019.3\_Flash-ROM error 3]

 Page 25 [AL. 019.1\_Flash-ROM error 1]

### [AL. 019.6\_Flash-ROM error 6]

 Page 25 [AL. 019.1\_Flash-ROM error 1]

## [AL. 01A\_Servo motor combination error]

- The combination of the servo amplifier and servo motor is incorrect.
- The combination of the servo amplifier and servo motor constant file is incorrect.

### [AL. 01A.1\_Servo motor combination error 1]

Cause	Check/action method	Model
1. The servo amplifier and the servo motor have been connected incorrectly.	Refer to "Servo amplifier/motor combinations" in the following manual. ☐MR-JET User's Manual (Hardware)	[G]
2. A rotary servo motor that does not support the firmware version of the servo amplifier is connected to the servo amplifier.	Referring to "Servo amplifier/motor combinations" in the following manual, check if there are any restrictions on the firmware version. ☐MR-JET User's Manual (Hardware)	
3. A servo motor whose manufacture date is old has been connected.	Refer to "Servo amplifier/motor combinations" in the following manual. ☐MR-JET User's Manual (Hardware)	
4. [Pr. PA17 Servo motor series setting] and [Pr. PA18 Servo motor type setting] were not set based on the servo motor to be used.	Check if [Pr. PA17] and [Pr. PA18] have been set correctly.	
5. The encoder has malfunctioned.	Replace the servo motor.	


### [AL. 01A.2\_Servo motor control mode combination error]

Cause	Check/action method	Model
1. The combination of the servo motor being used and the setting of [Pr. PA01.1 Operation mode selection] is not appropriate.	Check the [Pr. PA01.1] setting.	[G]
2. In the fully closed loop control mode, the servo motor-side encoder and the load-side encoder are incorrectly connected to the servo amplifier.	Refer to "USING A FULLY CLOSED LOOP SYSTEM" in the following manuals. ☐MR-JET User's Manual (Hardware)	

### [AL. 01A.4\_Servo motor combination error 2]

Cause	Check/action method	Model
1. The servo amplifier has malfunctioned.	Replace the servo amplifier.	[G]


### [AL. 01A.5\_Servo motor combination error 3]

Cause	Check/action method	Model
<p><b>1.</b> The servo motor that was connected at the startup of the absolute position detection system was changed to a different servo motor.</p> <p><b>2.</b> At occurrence of [AL. 025 Absolute position erased], the power was cycled without leaving the servo motor for 5 s.</p> <p><b>3.</b> The servo motor was replaced.</p> <p><b>4.</b> After a servo amplifier with the factory settings has been connected to a controller for the first time, the fully closed loop control mode and an absolute position detection system were set with the controller, then the servo amplifier was turned on again.</p>	For details of actions to be taken, contact your local sales office.	[G]
<b>5.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier.	
<b>6.</b> The encoder has malfunctioned.	Replace the servo motor.	
<b>7.</b> There is a problem with the surrounding environment.	<p>Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause.</p> <p>If there is noise, take countermeasures to reduce the noise.</p> <p>Refer to "Noise reduction techniques" in the following manual.</p> <p> MR-JET User's Manual (Hardware)</p>	


## [AL. 01E\_ Encoder initial communication error 2]

- The encoder has malfunctioned.

### [AL. 01E.1\_ Encoder malfunction]

Cause	Check/action method	Model
1. The encoder has malfunctioned.	Replace the servo motor.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	

### [AL. 01E.2\_ Load-side encoder malfunction]

Cause	Check/action method	Model
1. The load-side encoder has malfunctioned.	Replace the load-side encoder.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals.  MR-JET User's Manual (Hardware)	

## [AL. 01F\_ Encoder initial communication error 3]

- The connected encoder is not compatible with the servo amplifier.

### [AL. 01F.1\_Incompatible encoder]

Cause	Check/action method	Model
<b>1.</b> An incompatible servo motor or an incompatible linear encoder was connected to the servo amplifier.	Refer to "Servo amplifier/motor combinations" in the following manual. <input type="checkbox"/> MR-JET User's Manual (Hardware) Refer to "Compatible encoder list" in the following manual. <input type="checkbox"/> MR-JET Partner's Encoder User's Manual	[G]
<b>2.</b> The firmware version of the servo amplifier does not support the servo motor or linear encoder.	Refer to "Servo amplifier/motor combinations" in the following manual. <input type="checkbox"/> MR-JET User's Manual (Hardware) Refer to "Compatible encoder list" in the following manual. <input type="checkbox"/> MR-JET Partner's Encoder User's Manual	
<b>3.</b> The encoder or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	

### [AL. 01F.2\_Incompatible load-side encoder]

Cause	Check/action method	Model
<b>1.</b> A load-side encoder incompatible with the servo amplifier was connected.	Check the model name of the load-side encoder.	[G]
<b>2.</b> The firmware version of the servo amplifier does not support the load-side encoder.	Refer to "Compatible encoder list" in the following manual. <input type="checkbox"/> MR-JET Partner's Encoder User's Manual	
<b>3.</b> The load-side encoder has malfunctioned.	Replace the load-side encoder, then check the repeatability. If the error does not repeat, replace the load-side encoder.	

## [AL. 020\_ Encoder normal communication error 1]

- There is a communication error between the encoder and servo amplifier.

### [AL. 020.1\_ Encoder normal communication - Receive data error 1]

Cause	Check/action method	Model
1. There is a problem with the encoder cable.	Check if the encoder cable has been disconnected or has shorted. If there is a problem with the cable, repair or replace the cable. If an A/B/Z-phase differential output type encoder is being used, check if the encoder is wired correctly. Refer to "A/B/Z-phase differential output type encoder" in the following manual. MR-JET Partner's Encoder User's Manual	[G]
2. The external conductor of the encoder cable is not connected to the ground plate of the connector.	Check if the external conductor of the encoder cable is connected to the ground plate of the connector. Refer to "Shielding CN2 side connectors" in the following manual. Rotary Servo Motor User's Manual (For MR-JET)	
3. The servo parameter settings for the communication method are incorrect.	Set the servo parameter correctly according to the encoder cable communication method (two-wire type/four-wire type). [G]: [Pr. PC04.3 Encoder cable communication method selection]	
4. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
5. The encoder has malfunctioned.	Replace the servo motor.	
6. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. MR-JET User's Manual (Hardware)	

### [AL. 020.2\_ Encoder normal communication - Receive data error 2]



Page 30 [AL. 020.1\_ Encoder normal communication - Receive data error 1]

### [AL. 020.3\_ Encoder normal communication - Receive data error 3]



Cause	Check/action method	Model
1. The Z-phase signal cannot be detected despite being on.	Check if the Z-phase pulse signals (PZ and PZR) of the encoder cable have been disconnected or have shorted. Refer to the specifications provided by the encoder manufacturer or "A/B/Z-phase differential output type encoder" in the following manual. MR-JET Partner's Encoder User's Manual	[G]
2. There is a problem with the encoder cable.	Page 30 [AL. 020.1_ Encoder normal communication - Receive data error 1]	
3. The external conductor of the encoder cable is not connected to the ground plate of the connector.		
4. The servo parameter settings for the communication method are incorrect.		
5. The servo amplifier has malfunctioned.		
6. The encoder has malfunctioned.		
7. There is a problem with the surrounding environment.		



### [AL. 020.5\_Encoder normal communication - Transmission data error 1]

Cause	Check/action method	Model
1. If an A/B/Z-phase differential output type encoder is being used, the wiring of the encoder is incorrect.	Check if the A/B-phase pulse signals (PA, PAR, PB, and PBR) of the encoder cable have been disconnected or have shorted. Refer to the specifications provided by the encoder manufacturer or "A/B/Z-phase differential output type encoder" in the following manual.  MR-JET Partner's Encoder User's Manual	[G]
2. There is a problem with the encoder cable.	 Page 30 [AL. 020.1_Encoder normal communication - Receive data error 1]	
3. The external conductor of the encoder cable is not connected to the ground plate of the connector.		
4. If an A/B/Z-phase differential output type encoder is being used, the servo parameter settings are incorrect.		
5. The servo amplifier has malfunctioned.		
6. The encoder has malfunctioned.		
7. There is a problem with the surrounding environment.		

### [AL. 020.6\_Encoder normal communication - Transmission data error 2]

Cause	Check/action method	Model
1. If an A/B/Z-phase differential output type encoder is being used, the wiring of the encoder is incorrect.	Check if the Z-phase pulse signals (PZ and PZR) of the encoder cable have been disconnected or have shorted. Refer to the specifications provided by the encoder manufacturer or "A/B/Z-phase differential output type encoder" in the following manual.  MR-JET Partner's Encoder User's Manual	[G]
2. There is a problem with the encoder cable.	 Page 30 [AL. 020.1_Encoder normal communication - Receive data error 1]	
3. The external conductor of the encoder cable is not connected to the ground plate of the connector.		
4. If an A/B/Z-phase differential output type encoder is being used, the servo parameter settings are incorrect.		
5. The servo amplifier has malfunctioned.		
6. The encoder has malfunctioned.		
7. There is a problem with the surrounding environment.		

### [AL. 020.7\_Encoder normal communication - Transmission data error 3]

 Page 30 [AL. 020.1\_Encoder normal communication - Receive data error 1]

## [AL. 021\_ Encoder normal communication error 2]

- The encoder detected an error signal.

### [AL. 021.1\_ Encoder data error 1]

Cause	Check/action method	Model
1. An excessive speed or acceleration was detected due to an oscillation or other factors.	Decrease the control gain, then check the repeatability. If the error does not repeat, use the encoder with a lower gain.	[G]
2. The external conductor of the encoder cable is not connected to the ground plate of the connector.	Check if the external conductor of the encoder cable is connected to the ground plate of the connector. Refer to "Shielding CN2 side connectors" in the following manual. Rotary Servo Motor User's Manual (For MR-JET)	
3. The encoder power supply voltage dropped considerably in the encoder cable wiring.	When cables are fabricated by the customer, check if wires with specifications equivalent to the recommended wires are used for the encoder cable. Use the wires with specifications equivalent to the recommended wires if they are not used. Refer to "Wires for option cables" in the following manual. Rotary Servo Motor User's Manual (For MR-JET)	
4. There is a problem with the encoder cable.	Check for a loose connection with a tester. If there is a loose connection, repair or replace the encoder cable.	
5. The encoder has malfunctioned.	Replace the servo motor.	
6. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. MR-JET User's Manual (Hardware)	



### [AL. 021.2\_ Encoder data update error]

Cause	Check/action method	Model
1. The encoder has malfunctioned.	Replace the servo motor.	[G]
2. The external conductor of the encoder cable is not connected to the ground plate of the connector.	Check if the external conductor of the encoder cable is connected to the ground plate of the connector. Refer to "Shielding CN2 side connectors" in the following manual. Rotary Servo Motor User's Manual (For MR-JET)	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. MR-JET User's Manual (Hardware)	


### [AL. 021.3\_ Encoder data waveform error]

Page 32 [AL. 021.2\_ Encoder data update error]


### [AL. 021.4\_No encoder signal]

Cause	Check/action method	Model
<b>1.</b> A signal of the encoder has not been input.	Check if the encoder cable is wired correctly.	[G]
<b>2.</b> The external conductor of the encoder cable is not connected to the ground plate of the connector.	Check if the external conductor of the encoder cable is connected to the ground plate of the connector. Refer to "Shielding CN2 side connectors" in the following manual.  Rotary Servo Motor User's Manual (For MR-JET)	
<b>3.</b> There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	

### [AL. 021.5\_ Encoder hardware error 1]

 Page 32 [AL. 021.2\_ Encoder data update error]

### [AL. 021.6\_ Encoder hardware error 2]

 Page 32 [AL. 021.2\_ Encoder data update error]

## [AL. 024\_Main circuit error]

- The servo motor power cable has a ground fault.
- The servo motor has a ground fault.

### [AL. 024.1\_Ground fault detected via hardware detection circuit]

Cause	Check/action method	Model
1. The servo motor power cable has a ground fault or has shorted.	Check if the servo motor power cable has a ground fault. If the servo motor power cable has a ground fault, correct the wiring. Check if the servo motor power cable has shorted. If the servo motor power cable has shorted, replace the servo motor power cable.	[G]
2. The servo motor has a ground fault.	After disconnecting the servo motor power cables on the servo motor side, check the insulation between phases (U/V/W/⊕). If the servo motor has a ground fault or has shorted, replace the servo motor.	
3. The servo amplifier power supply input cable and servo motor power cable have shorted.	After shutting off the power, make sure that the servo amplifier power supply input cable and servo motor power cable are not in contact with each other. If the cables are contacting, correct the wiring.	
4. The servo amplifier has malfunctioned.	Check that this alarm occurs as the servo motor power cables (U/V/W) are disconnected. If the alarm occurs, replace the servo amplifier.	
5. The wiring of the regenerative resistor (regenerative option) is incorrect.	Check if the regenerative resistor (regenerative option) is wired correctly. If the regenerative resistor (regenerative option) is wired incorrectly, correct the wiring.	
6. The regenerative resistor (regenerative option) and the servo amplifier are connected in a wrong combination.	Check if the combination of the regenerative resistor (regenerative option) and the servo amplifier is correct as specified. Refer to "Regenerative option" in the following manual. MR-JET User's Manual (Hardware)	
7. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. MR-JET User's Manual (Hardware)	

### [AL. 024.2\_Ground fault detected via software detection processing]

Cause	Check/action method	Model
1. The servo motor power cable has a ground fault or has shorted.	Check if the servo motor power cable has a ground fault. If the servo motor power cable has a ground fault, correct the wiring. Check if the servo motor power cable has shorted. If the servo motor power cable has shorted, replace the servo motor power cable.	[G]
2. The servo motor has a ground fault.	After disconnecting the servo motor power cables on the servo motor side, check the insulation between phases (U/V/W/⊕). If the servo motor has a ground fault or has shorted, replace the servo motor.	
3. The servo amplifier power supply input cable and servo motor power cable have shorted.	After shutting off the power, make sure that the servo amplifier power supply input cable and servo motor power cable are not in contact with each other. If the cables are contacting, correct the wiring.	
4. The servo amplifier has malfunctioned.	Check that this alarm occurs as the servo motor power cables (U/V/W) are disconnected. If the alarm occurs, replace the servo amplifier.	
5. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. MR-JET User's Manual (Hardware)	

## [AL. 025\_Absolute position erased]

- The absolute position data has an error.
- Power was switched on for the first time in the absolute position detection system.


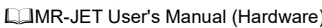
### [AL. 025.1\_Servo motor encoder absolute position erased]

Cause	Check/action method	Model
<b>1.</b> Power was switched on for the first time in the absolute position detection system.	If the power was switched on for the first time after the absolute position detection system is set, check that the battery is mounted correctly before homing. When using a Mitsubishi Electric servo motor equipped with a batteryless absolute position encoder, allow the alarm to occur for 5 s, then cycle the power. Perform homing.	[G]
<b>2.</b> The Mitsubishi Electric servo motor equipped with a batteryless absolute position encoder that was connected to the absolute position detection system at startup was changed to another servo motor.	Connect the servo motor that was connected at the startup of the absolute position detection system. Start up the absolute position detection system again.	
<b>3.</b> After the power supply was shut off, the battery was removed in a situation such as the following: <ul style="list-style-type: none"> <li>• The battery was disconnected from the servo amplifier while the power supply was off.</li> </ul>	If the battery was disconnected as described in the left column, check that the battery is mounted correctly before homing.	
<b>4.</b> The power was shut off in either of the following situations: <ul style="list-style-type: none"> <li>• The power was shut off while the battery was not connected to the servo amplifier.</li> </ul>	If the power supply was shut off as described in the left column, check that the battery is mounted correctly before homing.	
<b>5.</b> The battery voltage is too low. The battery is exhausted.	Check the battery voltage with a tester. If the voltage is lower than 3 V DC, replace the battery, then execute homing.	
<b>6.</b> The voltage dropped considerably in the encoder cable wired to the battery.	Check if the recommended wires are being used for the encoder cable. If the recommended wires are not being used, use the recommended wires, then execute homing. Refer to "Wires for option cables" in the following manual. <input type="checkbox"/> Rotary Servo Motor User's Manual (For MR-JET)	
<b>7.</b> There is a problem with the battery cable.	Check for a loose connection with a tester. If there is a loose connection, use a recommended cable, then execute homing.	
<b>8.</b> There is a loose connection of the encoder cable on the servo motor side.	Check for a loose connection with a tester. Measure the voltage on the servo motor side. If there is a loose connection, repair or replace the encoder cable, then execute homing.	
<b>9.</b> There is a problem with the encoder cable.	If there is a problem with the encoder cable, replace or repair the cable, then execute homing.	
<b>10.</b> When the Mitsubishi Electric servo motor equipped with a batteryless absolute position encoder was used, an external force rotated the servo motor shaft at a high speed at power failure.	Make sure that the servo motor shaft will not be rotated by an external force at a high speed. After removing the cause, execute homing, then turn the servo motor shaft at least 180 degrees.	
<b>11.</b> There is a problem with the surrounding environment when using the Mitsubishi Electric servo motor equipped with a batteryless absolute position encoder.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals. <input type="checkbox"/> MR-JET User's Manual (Hardware) After removing the cause, execute homing, then turn the servo motor shaft at least 180 degrees.	
<b>12.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier.	
<b>13.</b> The encoder has malfunctioned.	Replace the servo motor.	

## [AL. 027\_Initial magnetic pole detection error]

- The initial magnetic pole detection cannot be performed properly.


### [AL. 027.1\_Initial magnetic pole detection - Abnormal termination]

Cause	Check/action method	Model
1. A moving part collided against the machine.	If the moving part collides, move the start position of the magnetic pole detection.	[G]
2. The wiring of the servo motor power cable is incorrect.	Check the motor power cable for abnormality. Refer to "Power supply cable wiring diagrams" in the Linear Servo Motor User's Manual.	
3. The linear encoder resolution setting differs from the setting value.	Check the settings of [Pr. PL02 Linear encoder resolution setting - Numerator] and [Pr. PL03 Linear encoder resolution setting - Denominator].	
4. The mounting direction of the linear encoder is incorrect.	Check the polarities of the linear encoder and the linear servo motor. If the mounting direction is incorrect, mount the encoder correctly. Change the setting of "Encoder pulse count polarity selection" as required. [G]: [Pr. PC27.0 Encoder pulse count polarity selection] Refer to "Setting of linear encoder direction and linear servo motor direction" in the following manual.  MR-JET User's Manual (Hardware)	
5. The direct current exciting voltage level is too low.	<ul style="list-style-type: none"> <li>• When in position detection method</li> </ul> Check if the travel distance in the magnetic pole detection is small. If the travel distance is small, set a larger value in [Pr. PL09 Magnetic pole detection voltage level]. <ul style="list-style-type: none"> <li>• When in minute position detection method</li> </ul> Check if the travel distance in the magnetic pole detection is too large, or if a vibration is occurring. If the travel distance is too large or a vibration is occurring, review the settings of [Pr. PL17.0 Response selection] and [Pr. PL17.1 Load to motor mass ratio/load to motor inertia ratio selection]. Refer to "Magnetic pole detection" in the following manual.  MR-JET User's Manual (Hardware)	


### [AL. 027.2\_Initial magnetic pole detection - Time out error]

Cause	Check/action method	Model
1. Servo-on was turned on while the primary side of the linear servo motor was not stopped.	Stop the linear servo motor, then turn on the servo-on again.	[G]
2. Only one of the limit switches is on during magnetic pole detection.	Check the limit switches and remove the cause. Move the start position of the magnetic pole detection.	
3. The direct current exciting voltage level is too low at the time of the initial magnetic pole detection.	<ul style="list-style-type: none"> <li>• When in position detection method</li> </ul> Check if the travel distance in the magnetic pole detection is small. If the travel distance is small, set a larger value in [Pr. PL09 Magnetic pole detection voltage level].	


### [AL. 027.3\_Initial magnetic pole detection - Limit switch error]

Cause	Check/action method	Model
1. In the magnetic pole detection, both limit switches are turned off.	Check the limit switch status. If both of the limit switches are turned off, turn on the limit switches.	[G]
2. The settings of the magnetic pole detection are incorrect.	Check the settings of the servo parameter and other relevant areas. Refer to "Magnetic pole detection" in the following manual.  MR-JET User's Manual (Hardware)	

### [AL. 027.4\_Initial magnetic pole detection - Estimation error]

 Page 36 [AL. 027.1\_Initial magnetic pole detection - Abnormal termination]

### [AL. 027.5\_Initial magnetic pole detection - Speed deviation error]

 Page 36 [AL. 027.1\_Initial magnetic pole detection - Abnormal termination]

### [AL. 027.6\_Initial magnetic pole detection - Position deviation error]

 Page 36 [AL. 027.1\_Initial magnetic pole detection - Abnormal termination]


### [AL. 027.7\_Initial magnetic pole detection - Current error]

 Page 36 [AL. 027.1\_Initial magnetic pole detection - Abnormal termination]

## [AL. 028\_Linear encoder error 2]

- There is a problem with the operating environment of the linear encoder.

### [AL. 028.1\_Linear encoder environmental error]

Cause	Check/action method	Model
<b>1.</b> The ambient temperature of the linear encoder is outside of specifications.	Check the ambient temperature and the specifications of the linear encoder.	[G]
<b>2.</b> The signal level of the linear encoder dropped.	Check the mounting condition of the linear encoder.	
<b>3.</b> A linear encoder alarm was detected.	Refer to "DETAILED EXPLANATION OF [AL. 028 LINEAR ENCODER ERROR 2]" in the following manual.  MR-JET Partner's Encoder User's Manual	

### [AL. 028.2\_Load-side linear encoder environmental error]




 Page 38 [AL. 028.1\_Linear encoder environmental error]



## [AL. 02A\_Linear encoder error 1]

- An error of the linear encoder was detected. The content of the errors varies depending on each encoder manufacturer.

### [AL. 02A.1\_Linear encoder error 1-1]

Cause	Check/action method	Model
1. There is a problem with the way that the linear encoder and the head are mounted.	Adjust the positions of the linear encoder and the head.	[G]
2. The external conductor of the encoder cable is not connected to the ground plate of the connector.	Check if the external conductor of the encoder cable is connected to the ground plate of the connector. Refer to "Shielding CN2 side connectors" in the following manual.  Rotary Servo Motor User's Manual (For MR-JET)	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	
4. A linear encoder alarm was detected.	Refer to "DETAILED EXPLANATION OF [AL. 02A LINEAR ENCODER ERROR 1]" in the following manual.  MR-JET Partner's Encoder User's Manual	

### [AL. 02A.2\_Linear encoder error 1-2]

 Page 39 [AL. 02A.1\_Linear encoder error 1-1]

### [AL. 02A.3\_Linear encoder error 1-3]

 Page 39 [AL. 02A.1\_Linear encoder error 1-1]

### [AL. 02A.4\_Linear encoder error 1-4]

 Page 39 [AL. 02A.1\_Linear encoder error 1-1]

### [AL. 02A.5\_Linear encoder error 1-5]

 Page 39 [AL. 02A.1\_Linear encoder error 1-1]

### [AL. 02A.6\_Linear encoder error 1-6]

 Page 39 [AL. 02A.1\_Linear encoder error 1-1]

### [AL. 02A.7\_Linear encoder error 1-7]

 Page 39 [AL. 02A.1\_Linear encoder error 1-1]

### [AL. 02A.8\_Linear encoder error 1-8]

 Page 39 [AL. 02A.1\_Linear encoder error 1-1]

## [AL. 030\_Regenerative error]

- The permissible regenerative power of the built-in regenerative resistor or regenerative option was exceeded.
- The regenerative transistor in the servo amplifier has malfunctioned.

### [AL. 030.1\_Regenerative heat error]

Cause	Check/action method	Model
1. The settings of the regenerative resistor (regenerative option) are incorrect.	Check the regenerative resistor (regenerative option) in use and the setting value of [Pr. PA02 Regenerative option]. Refer to "Regenerative option" in the following manual. ☞MR-JET User's Manual (Hardware)	[G]
2. The regenerative resistor (regenerative option) is not connected.	Check if the regenerative resistor (regenerative option) is connected correctly. Refer to "Regenerative option" in the following manual. ☞MR-JET User's Manual (Hardware)	
3. The regenerative resistor (regenerative option) and the servo amplifier are connected in a wrong combination.	Check if the combination of the regenerative resistor (regenerative option) and the servo amplifier is correct as specified. Refer to "Regenerative option" in the following manual. ☞MR-JET User's Manual (Hardware)	
4. The power supply voltage is too high.	Check if the voltage of the input power supply exceeds the upper limit of the permissible voltage. If the power supply voltage exceeds the upper limit, reduce the power supply voltage. 200 V class: 264 V AC	
5. The regenerative power is too large.	Check whether the regenerative load ratio exceeds the upper limit value when the alarm occurs. If the alarm is not cleared even after taking the following corrective actions, replace the servo amplifier. <ul style="list-style-type: none"> <li>• Reduce the frequency of positioning.</li> <li>• Set a longer deceleration time constant.</li> <li>• Reduce the load.</li> <li>• Use a regenerative option if it is not being used.</li> </ul>	

### [AL. 030.2\_Regenerative signal error]

Cause	Check/action method	Model
1. The servo amplifier has malfunctioned.	Check if the regenerative resistor (regenerative option) is overheating. If the regenerative resistor is overheating, replace the servo amplifier.	[G]

### [AL. 030.3\_Regenerative feedback signal error]

Cause	Check/action method	Model
1. The servo amplifier has malfunctioned.	Remove the wire of the regenerative option or built-in regenerative resistor, then check if the alarm occurs at power on. If the alarm occurs, replace the servo amplifier.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ground fault, ambient temperature, and other conditions, then take countermeasures against its cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. ☞MR-JET User's Manual (Hardware)	

## [AL. 031\_Overspeed]

- The servo motor speed exceeded the maximum speed.

1

### [AL. 031.1\_Servo motor speed error]

Cause	Check/action method	Model
<b>1.</b> The settings of the electronic gear are incorrect.	Check the setting value of the electronic gear. Refer to "Electronic gear function" in the following manual. MR-JET User's Manual (Function)	[G]
<b>2.</b> The command from the controller is excessive.	Check if the command from the controller exceeds the maximum speed. To change the judgment value used to the permissible speed, change the setting of [Pr. PA28.4 Speed range limit selection].	
<b>3.</b> The backlash compensation set in the controller is excessive.	Refer to the manual for the controller being used to check if the setting value is correct.	
<b>4.</b> A speed command exceeding the overspeed alarm trigger level was input.	Check that the actual servo motor speed is higher than the overspeed alarm trigger level.	
<b>5.</b> The servo motor reaches the maximum torque (maximum thrust) at acceleration.	Check if the torque (thrust) is the maximum torque (maximum thrust) at the acceleration. If the torque (thrust) is the maximum torque (maximum thrust), increase the acceleration/deceleration time constants or reduce the load.	
<b>6.</b> The servo system is unstable and oscillating.	Check if the servo motor is oscillating. If the servo motor is oscillating, adjust the servo gain or reduce the load.	
<b>7.</b> The velocity waveform overshoot.	Check if the velocity waveform has overshoot because of the short acceleration/deceleration time constant. If the velocity waveform has overshoot, increase the acceleration/deceleration time constant.	
<b>8.</b> The connection destination of the servo motor power cable or the encoder cable is incorrect.	Check for any incorrect connection destination of the motor power cable or encoder cable. Refer to "Example power circuit connections" in the following manual. MR-JET User's Manual (Hardware)	
<b>9.</b> The connection of the servo motor is incorrect.	Check the U/V/W wiring. Refer to "Example power circuit connections" in the following manual. MR-JET User's Manual (Hardware) Refer to "Turning on servo amplifier for the first time" in the User's Manual (Introduction).	
<b>10.</b> The encoder or linear encoder has malfunctioned.	Check if this alarm occurs when the servo motor rotates at the lower speed than the maximum speed. If the alarm occurs, replace the servo motor or the linear encoder. To change the judgment value used to the permissible speed, change the setting of [Pr. PA28.4].	

## [AL. 032\_Overcurrent]

- A current higher than the permissible current flowed in the servo amplifier.

### [AL. 032.1\_Overcurrent detected via hardware detection circuit (during operation)]

Cause	Check/action method	Model
1. The servo amplifier has malfunctioned.	Check if the servo motor power cable has a ground fault. If the servo motor power cable has a ground fault, correct the wiring. Check that this alarm occurs as the servo motor power cables (U/V/W) are disconnected. If the alarm occurs, replace the servo amplifier.	[G]
2. The servo motor power cable has a ground fault or has shorted.	Check if the servo motor power cable has shorted. If the servo motor power cable has shorted, replace the servo motor power cable.	
3. The servo motor has malfunctioned.	After disconnecting the servo motor power cables on the servo motor side, check the insulation between phases (U/V/W/⊕ or ⊖). If the servo motor has a ground fault or has shorted, replace the servo motor.	
4. The dynamic brake has malfunctioned.	After confirming that the Cause 1, 2, and 3 did not apply, check if this alarm occurs when turning on the servo-on command. If the alarm occurs, replace the servo amplifier. If the alarm does not occur, check 5.	
5. The wiring of the regenerative resistor (regenerative option) is incorrect.	Check if the regenerative resistor (regenerative option) is wired correctly. If the regenerative resistor (regenerative option) is wired incorrectly, correct the wiring.	
6. The regenerative resistor (regenerative option) and the servo amplifier are connected in a wrong combination.	Check if the combination of the regenerative resistor (regenerative option) and the servo amplifier is correct as specified. Refer to "Regenerative option" in the following manual. ☞MR-JET User's Manual (Hardware)	
7. The connection destination of the servo motor power cable or the encoder cable is incorrect.	Check the connection destination of the motor power cable or encoder cable. Refer to "Example power circuit connections" in the following manual. ☞MR-JET User's Manual (Hardware)	
8. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If a problem is not found with the surrounding environment, perform the following check/action methods. ☞ Page 51 [AL. 045.1_Main circuit device overheat error 1] If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. ☞MR-JET User's Manual (Hardware)	

### [AL. 032.2\_Overcurrent detected via software detection processing (during operation)]

Cause	Check/action method	Model
1. The servo gain is too high.	Check if there is vibration. If there is vibration, reduce the value in [Pr. PB09 Speed control gain].	[G]
2. The servo amplifier has malfunctioned.	Check that this alarm occurs as the servo motor power cables (U/V/W) are disconnected. If the alarm occurs, replace the servo amplifier.	
3. The servo motor power cable has a ground fault or has shorted.	Check if the servo motor power cable has a ground fault. If the servo motor power cable has a ground fault, correct the wiring. Check if the servo motor power cable has shorted. If the servo motor power cable has shorted, replace the servo motor power cable.	
4. The servo motor has malfunctioned.	After disconnecting the servo motor power cables on the servo motor side, check the insulation between phases (U/V/W/⊕ or ⊖). If the servo motor has a ground fault or has shorted, replace the servo motor.	
5. The connection destination of the servo motor power cable or the encoder cable is incorrect.	Check the connection destination of the motor power cable or encoder cable. Refer to "Example power circuit connections" in the following manual. ☞MR-JET User's Manual (Hardware)	
6. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. ☞MR-JET User's Manual (Hardware)	

**[AL. 032.3\_Overcurrent detected via hardware detection circuit (during a stop)]**

☞ Page 42 [AL. 032.1\_Overcurrent detected via hardware detection circuit (during operation)]

**[AL. 032.4\_Overcurrent detected via software detection processing (during a stop)]**

☞ Page 42 [AL. 032.2\_Overcurrent detected via software detection processing (during operation)]

## [AL. 033\_Overvoltage]

- The value of the bus voltage exceeded the specified value.  
200 V class: 400 V DC

### [AL. 033.1\_Main circuit voltage error]


Cause	Check/action method	Model
1. The settings of the regenerative resistor (regenerative option) are incorrect.	Check the regenerative resistor (regenerative option) in use and the setting value of [Pr. PA02.0-1 Regenerative option selection]. Refer to "Regenerative option" in the following manual. MR-JET User's Manual (Hardware)	[G]
2. The regenerative resistor (regenerative option) is not connected.	Check if the regenerative resistor (regenerative option) is connected correctly. Refer to "Regenerative option" in the following manual. MR-JET User's Manual (Hardware)	
3. The built-in regenerative resistor or regenerative option is disconnected.	Measure the resistance value of the built-in regenerative resistor or regenerative option. If the resistance value is abnormal, take corrective actions as follows: <ul style="list-style-type: none"> <li>• When using a built-in regenerative resistor, replace the servo amplifier.</li> <li>• When using a regenerative option, replace the regenerative option.</li> </ul> Refer to "Regenerative option" in the following manual. MR-JET User's Manual (Hardware)	
4. The regeneration capacity is insufficient.	Set a longer deceleration time constant, then check the repeatability. If the error does not repeat, take corrective actions as follows: <ul style="list-style-type: none"> <li>• When using a built-in regenerative resistor, use a regenerative option.</li> <li>• When using a regenerative option, use one with a larger capacity.</li> </ul>	
5. The power supply voltage is too high.	Check if the voltage of the input power supply exceeds the upper limit of the permissible voltage. If the power supply voltage exceeds the upper limit, reduce the power supply voltage. 200 V class: 264 V AC	
6. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. MR-JET User's Manual (Hardware)	

## [AL. 035\_Command frequency error]

- The input command pulse frequency is too high.

1

### [AL. 035.1\_Command frequency error]

Cause	Check/action method	Model
<b>1.</b> The command from the controller is excessive.	Check if the command from the controller exceeds the maximum speed. If the command exceeds the maximum speed, review the operation pattern. To change the judgment value used to the permissible speed, change the setting of [Pr. PA28.4 Speed range limit selection].	[G]
<b>2.</b> The backlash compensation set in the controller is excessive.	Refer to the manual for the controller being used to check if the setting value is correct.	
<b>3.</b> The controller has malfunctioned.	Replace the controller.	
<b>4.</b> There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	

## [AL. 037\_Parameter error]

- Servo parameter setting values are incorrect.
- Point table setting values are incorrect.

### [AL. 037.1\_Parameter setting range error]

Cause	Check/action method	Model
1. A parameter was set outside of the setting range.	[G]: Check the parameter error No. on the alarm display screen of MR Configurator2 or with another method, then review the setting value of the parameter.	[G]
2. An inconsistent combination of parameters has been set.	[G]: Check the parameter error No. on the alarm display screen of MR Configurator2 or with another method, then review the setting value of the parameter.	
3. The setting value of the parameter has changed due to the servo amplifier malfunction.	Replace the servo amplifier.	

### [AL. 037.2\_Parameter combination error]

Cause	Check/action method	Model
1. An inconsistent combination of parameters has been set.	[G]: Check the parameter error No. on the alarm display screen of MR Configurator2 or with another method, then review the setting value of the parameter.	[G]

### [AL. 037.3\_Point table setting error]

Cause	Check/action method	Model
1. Point table setting values are incorrect.	Check if the setting value of the point table is within the setting range. Check the error number of the point table with [Point table error No.(Obj. 2A43h:01h)]. Or check the setting value in the point table screen of MR Configurator2.	[G]
2. The setting value of the point table has changed due to the servo amplifier malfunction.	Replace the servo amplifier.	

### [AL. 037.6\_Parameter mismatch error]

Cause	Check/action method	Model
1. Mismatching with the saved parameters occurred because of the error in writing parameters.	[G]: Check the servo parameter error No. on the alarm display screen of MR Configurator2 or with another method. Rewrite the setting value because the value before or after writing has been displayed.	[G]
2. The setting value of the parameter changed as the servo amplifier malfunctioned.	Replace the servo amplifier.	

### [AL. 037.7\_Network parameter setting error]

Cause	Check/action method	Model
1. There is a problem with the network parameter settings.	Check if the setting value of the network parameter is within the setting range. [G]: Check the servo parameter error No. on the alarm display screen of MR Configurator2 or with another method. Rewrite the setting value because the value before or after writing has been displayed.	[G]
2. The setting value of the network parameter changed as the servo amplifier malfunctioned.	Replace the servo amplifier.	



## [AL. 03A\_Inrush current suppression circuit error]

- The inrush current suppression circuit error was detected.

### [AL. 03A.1\_Inrush current suppression circuit error]

Cause	Check/action method	Model
<b>1.</b> The inrush current suppressor circuit has malfunctioned.	Replace the servo amplifier.	[G]

## [AL. 042\_Servo control error]

- A servo control error occurred. (When a linear servo motor is used)





### [AL. 042.1\_Servo control error based on position deviation]

Cause	Check/action method	Model
1. [Pr. PA17 Servo motor series setting] and [Pr. PA18 Servo motor type setting] were not set based on the servo motor to be used.	Check if [Pr. PA17] and [Pr. PA18] have been set correctly.	[G]
2. The settings of the encoder resolution differ from the actual value.	Check the settings of [Pr. PL02 Linear encoder resolution setting - Numerator] and [Pr. PL03 Linear encoder resolution setting - Denominator]. Refer to "Linear encoder resolution setting" in the following manual. MR-JET User's Manual (Hardware)	
3. The mounting direction of the encoder is incorrect.	Check the polarities of the linear encoder and the linear servo motor. If the mounting direction is incorrect, mount the encoder correctly. Change the setting of "Encoder pulse count polarity selection" as required. [G]: [Pr. PC27.0 Encoder pulse count polarity selection] Refer to "Setting of linear encoder direction and linear servo motor direction" in the following manual. MR-JET User's Manual (Hardware)	
4. The connection of the servo motor is incorrect.	Check the wiring. Refer to "SIGNALS AND WIRING" in the following manual. MR-JET User's Manual (Hardware)	
5. The initial magnetic pole detection was not executed.	Execute the magnetic pole detection, then check the repeatability. Refer to "Magnetic pole detection" in the following manual. MR-JET User's Manual (Hardware)	
6. The setting value of the position deviation error detection level is too low.	Check the value of the droop pulses. If the deviation is too large, review the operation status. Review the setting of [Pr. PL05 Position deviation error detection level] as required.	


### [AL. 042.2\_Servo control error based on speed deviation]

Cause	Check/action method	Model
1. [Pr. PA17 Servo motor series setting] and [Pr. PA18 Servo motor type setting] were not set based on the servo motor to be used.	Check if [Pr. PA17] and [Pr. PA18] have been set correctly.	[G]
2. The settings of the encoder resolution differ from the actual value.	Check the settings of [Pr. PL02 Linear encoder resolution setting - Numerator] and [Pr. PL03 Linear encoder resolution setting - Denominator]. Refer to "Linear encoder resolution setting" in the following manual. MR-JET User's Manual (Hardware)	
3. The mounting direction of the encoder is incorrect.	Check the polarities of the linear encoder and the linear servo motor. Change the setting of "Encoder pulse count polarity selection" as required. [G]: [Pr. PC27.0 Encoder pulse count polarity selection] Refer to "Setting of linear encoder direction and linear servo motor direction" in the following manual. MR-JET User's Manual (Hardware)	
4. The connection of the servo motor is incorrect.	Check the wiring. Refer to "SIGNALS AND WIRING" in the following manual. MR-JET User's Manual (Hardware)	
5. The initial magnetic pole detection was not executed.	Execute the magnetic pole detection, then check the repeatability. Refer to "Magnetic pole detection" in the following manual. MR-JET User's Manual (Hardware)	
6. The setting value of the speed deviation error detection level is too low.	Calculate the deviation between the speed command and actual speed. If the deviation is too large, review the operation status. Review the setting of [Pr. PL06 Speed deviation error detection level] as required.	


### [AL. 042.3\_Servo control error based on torque/thrust deviation]

Cause	Check/action method	Model
1. [Pr. PA17 Servo motor series setting] and [Pr. PA18 Servo motor type setting] were not set based on the servo motor to be used.	Check if [Pr. PA17] and [Pr. PA18] have been set correctly.	[G]
2. The settings of the encoder resolution differ from the actual value.	Check the settings of [Pr. PL02 Linear encoder resolution setting - Numerator] and [Pr. PL03 Linear encoder resolution setting - Denominator]. Refer to "Linear encoder resolution setting" in the following manual.  MR-JET User's Manual (Hardware)	
3. The mounting direction of the encoder is incorrect.	Check the polarities of the linear encoder and the linear servo motor. Change the setting of "Encoder pulse count polarity selection" as required. [G]: [Pr. PC27.0 Encoder pulse count polarity selection] Refer to "Setting of linear encoder direction and linear servo motor direction" in the following manual.  MR-JET User's Manual (Hardware)	
4. The connection of the servo motor is incorrect.	Check the wiring. Refer to "SIGNALS AND WIRING" in the following manual.  MR-JET User's Manual (Hardware)	
5. The initial magnetic pole detection was not executed.	Check the repeatability. Refer to "Magnetic pole detection" in the following manual.  MR-JET User's Manual (Hardware)	
6. The setting value in the torque/thrust deviation error detection level is too low.	Calculate the deviation between the current command and torque/thrust. If the deviation is too large, review the power-supply environment or the operation status. Review the setting of [Pr. PL07 Torque deviation error detection level] as required.	


### [AL. 042.8\_Fully closed loop control error based on position deviation]

Cause	Check/action method	Model
1. The settings of the load-side encoder resolution differ from the actual value.	Check the settings of [Pr. PE04 Fully closed loop control - Feedback pulse electronic gear 1 - Numerator] and [Pr. PE05 Fully closed loop control - Feedback pulse electronic gear 1 - Denominator].	[G]
2. The mounting direction of the load-side encoder is incorrect.	Check the mounting direction of the load-side encoder. Change the setting of "Encoder pulse count polarity selection" as required. [G]: [Pr. PC27.0 Encoder pulse count polarity selection] Refer to "Checking position data of the load-side encoder" in the following manuals.  MR-JET User's Manual (Hardware)	
3. The setting value of the position deviation error detection level is too low.	Check the value of the motor-side/load-side position deviation. If the deviation is too large, review the mechanism of the equipment or the operation status. Review the setting of [Pr. PE03 Fully closed loop control error - Detection function selection] or [Pr. PE07 Fully closed loop control - Position deviation error detection level] as required.	

## [AL. 042.9\_Fully closed loop control error based on speed deviation]

Cause	Check/action method	Model
1. The settings of the load-side encoder resolution differ from the setting value.	Check the settings of [Pr. PE04 Fully closed loop control - Feedback pulse electronic gear 1 - Numerator] and [Pr. PE05 Fully closed loop control - Feedback pulse electronic gear 1 - Denominator].	[G]
2. The mounting direction of the load-side encoder is incorrect.	Check the mounting direction of the load-side encoder. Change the setting of "Encoder pulse count polarity selection" as required. [G]: [Pr. PC27.0 Encoder pulse count polarity selection] Refer to "Checking position data of the load-side encoder" in the following manuals.  MR-JET User's Manual (Hardware)	
3. The setting value of the speed deviation error detection level is too low.	Calculate the motor-side/load-side speed deviation. If the deviation is too large, review the mechanism of the equipment or the operation status. Review the setting of [Pr. PE03 Fully closed loop control error - Detection function selection] or [Pr. PE06 Fully closed loop control - Speed deviation error detection level] as required.	

## [AL. 042.A\_Fully closed loop control error based on position deviation during command stop]

 Page 49 [AL. 042.8\_Fully closed loop control error based on position deviation]

## [AL. 045\_Main circuit device overheat]

- The inside of the servo amplifier overheated.

### [AL. 045.1\_Main circuit device overheat error 1]

Cause	Check/action method	Model
<b>1.</b> The ambient temperature exceeded the specified value (55 °C).	Check the ambient temperature, and if the temperature exceeds the specified value, lower the ambient temperature.	[G]
<b>2.</b> The servo amplifier does not meet the specifications of close mounting.	Check the specifications of close mounting. Refer to "Mounting direction and clearances" in the following manual. MR-JET User's Manual (Hardware)	
<b>3.</b> The power was turned on and off repeatedly under the overload status.	Check if the overload status occurred frequently. If the overload status occurred frequently, review the operation pattern.	
<b>4.</b> A cooling fan, heat sink, or opening is clogged.	Clean the cooling fan, heat sink, or openings.	
<b>5.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier.	

### [AL. 045.2\_Main circuit device overheat error 2]

Page 51 [AL. 045.1\_Main circuit device overheat error 1]

## [AL. 046\_Servo motor overheat]

- The servo motor overheated.

### [AL. 046.1\_Servo motor temperature error 1]

Cause	Check/action method	Model
1. The ambient temperature of the servo motor has exceeded the specified value.	Check the ambient temperature of the servo motor, and if the temperature exceeds the specified value, lower the ambient temperature. Refer to "Environment" in the following manual. <input type="checkbox"/> Rotary Servo Motor User's Manual (For MR-JET) Refer to "Environment" in the Linear Servo Motor User's Manual.	[G]
2. The servo motor is overloaded.	Check the effective load ratio. If the effective load ratio exceeds 100 %, reduce the load or review the operation pattern.	
3. The thermal sensor in the encoder has malfunctioned.	Check the servo motor temperature when the alarm occurs. If the servo motor temperature is too low, the thermal sensor in the encoder is faulty. Replace the servo motor.	

### [AL. 046.2\_Servo motor temperature error 2]

Cause	Check/action method	Model
1. The ambient temperature of the linear servo motor or servo motor with thermistors has exceeded the specified value.	Check the ambient temperature of the linear servo motor or servo motor with thermistors. If the ambient temperature exceeds the specified value, lower the ambient temperature. Refer to "Environment" in the following manual. <input type="checkbox"/> Rotary Servo Motor User's Manual (For MR-JET) Refer to "Environment" in the Linear Servo Motor User's Manual.	[G]
2. The servo motor is overloaded.	Check the effective load ratio. If the effective load ratio exceeds 100 %, reduce the load or review the operation pattern.	
3. There is a problem with the thermistor wire.	Check if the thermistor wire has shorted. If the thermistor wire has shorted, replace or repair the cable. If the thermistor wire has not shorted, replace the servo motor.	

### [AL. 046.3\_Thermistor disconnected error]

Cause	Check/action method	Model
1. A servo motor thermistor wire is not connected.	Check if the servo motor thermistor wire is connected.	[G]
2. A servo motor thermistor wire is disconnected.	Check for disconnection in the servo motor thermistor wire. If the servo motor thermistor wire is disconnected, repair the wire.	

### [AL. 046.4\_Thermistor circuit error]

Cause	Check/action method	Model
1. The thermistor circuit of the servo amplifier has malfunctioned.	Replace the servo amplifier.	[G]

### [AL. 046.5\_Servo motor temperature error 3]

☞ Page 52 [AL. 046.1\_Servo motor temperature error 1]

### [AL. 046.6\_Servo motor temperature error 4]

Cause	Check/action method	Model
1. A current larger than the continuous output current of the servo motor flowed.	Check the effective load ratio. If the effective load ratio is too high, reduce the load or review the operation pattern. Alternatively, replace the servo motor with a larger-capacity servo motor.	[G]

## [AL. 046.7\_Servo motor temperature error 5]

Cause	Check/action method	Model
<b>1.</b> Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

## [AL. 047\_Cooling fan error]

- The speed of the servo amplifier cooling fan decreased.
- The fan speed decreased to 30 % or less of the rated speed of the alarm occurrence level.

### [AL. 047.1\_Cooling fan stop error]

Cause	Check/action method	Model
<b>1.</b> A foreign object was caught in the cooling fan.	Check if a foreign object is caught in the cooling fan. If a foreign object is found, remove it.	[G]
<b>2.</b> The cooling fan has reached the end of its service life.	Replace the fan unit.	

### [AL. 047.2\_Deceased cooling fan speed error]

Cause	Check/action method	Model
<b>1.</b> A foreign object was caught in the cooling fan.	Check if a foreign object is caught in the cooling fan. If a foreign object is found, remove it.	[G]
<b>2.</b> The cooling fan has reached the end of its service life.	Replace the fan unit.	



## [AL. 050\_Overload 1]

- The load exceeded the overload protection characteristics of the servo amplifier.

### [AL. 050.1\_Thermal overload error 1 during operation]

Cause	Check/action method	Model
1. The servo motor power cable was disconnected.	Check the servo motor power cable, then repair or replace the cable.	[G]
2. The connection of the servo motor is incorrect.	Check the U/V/W wiring. Refer to "Example power circuit connections" in the following manual. □MR-JET User's Manual (Hardware)	
3. The electromagnetic brake has not been released. (The electromagnetic brake has been activated.)	Check if the electromagnetic brake has been released during operation.	
4. A current larger than the continuous output current of the servo motor flowed.	Check the effective load ratio and operation pattern. If the effective load ratio is too high, reduce the load or replace the servo motor with a larger-capacity servo motor. Alternatively, review the operation pattern.	
5. The servo system is unstable and resonating.	Adjust the gain so that the system does not resonate. Refer to the following manual. □MR-JET User's Manual (Adjustment)	
6. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
7. The encoder (servo motor) or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	
8. There is a problem with the mounting environment of the servo motor.	Check the servo motor shaft for any eccentric load due to a center deviation. If there is a problem, review the mounting environment.	

### [AL. 050.2\_Thermal overload error 2 during operation]

☞ Page 55 [AL. 050.1\_Thermal overload error 1 during operation]

### [AL. 050.3\_Thermal overload error 4 during operation]

☞ Page 55 [AL. 050.1\_Thermal overload error 1 during operation]

### [AL. 050.4\_Thermal overload error 1 during a stop]

Cause	Check/action method	Model
1. A moving part collided against the machine.	Review the operation pattern to avoid collision. Check that there is no interference with the machine.	[G]
2. The servo motor power cable was disconnected.	Check the servo motor power cable, then repair or replace the cable.	
3. Hunting occurs during servo-lock.	Adjust the gain so that hunting does not occur. Refer to the following manual. □MR-JET User's Manual (Adjustment)	
4. The electromagnetic brake has not been released. (The electromagnetic brake has been activated.)	Check if the electromagnetic brake has been released during operation.	
5. A current larger than the continuous output current of the servo motor flowed.	Check the effective load ratio. If the effective load ratio is too high, reduce the load. Alternatively, replace the servo motor with a larger-capacity servo motor.	
6. The servo system is unstable and resonating.	Adjust the gain so that the system does not resonate. Refer to the following manual. □MR-JET User's Manual (Adjustment)	
7. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
8. The encoder (servo motor) or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	

## **[AL. 050.5\_Thermal overload error 2 during a stop]**

☞ Page 55 [AL. 050.4\_Thermal overload error 1 during a stop]

## **[AL. 050.6\_Thermal overload error 4 during a stop]**

☞ Page 55 [AL. 050.4\_Thermal overload error 1 during a stop]

## [AL. 051\_Overload 2]

- Maximum output current continuously flowed due to machine collision or other causes.

### [AL. 051.1\_Thermal overload error 3 during operation]

Cause	Check/action method	Model
1. The servo motor power cable was disconnected.	Repair or replace the servo motor power cable.	[G]
2. The connection of the servo motor is incorrect.	Check the U/V/W wiring. Refer to "Example power circuit connections" in the following manual. MR-JET User's Manual (Hardware)	
3. The connection of the encoder cable is incorrect.	Check if the encoder cable is connected correctly.	
4. The torque is insufficient.	Check the peak load ratio. If the torque is saturated, reduce the load or review the operation pattern. Alternatively, replace the servo motor with a larger-capacity servo motor.	
5. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
6. The encoder (servo motor) or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	


### [AL. 051.2\_Thermal overload error 3 during a stop]

Cause	Check/action method	Model
1. A moving part collided against the machine.	Review the operation pattern to avoid collision. Check if the machine is not interfering with the servo motor.	[G]
2. The servo motor power cable was disconnected.	☞ Page 57 [AL. 051.1_Thermal overload error 3 during operation]	
3. The connection of the servo motor is incorrect.		
4. The connection of the encoder cable is incorrect.		
5. The torque is saturated.		
6. The servo amplifier has malfunctioned.		
7. The encoder or linear encoder has malfunctioned.		


## [AL. 052\_ Excessive error]

- Droop pulses exceeded the alarm occurrence level.

### [AL. 052.1\_ Excessive droop pulse 1]

Cause	Check/action method	Model
1. The servo motor power cable was disconnected.	Repair or replace the servo motor power cable.	[G]
2. The connection of the servo motor is incorrect.	Check the U/V/W wiring for forgotten screws, loose screws, and incorrect wiring. Refer to "Example power circuit connections" in the following manual.  MR-JET User's Manual (Hardware)	
3. The connection of the encoder cable is incorrect.	Check if the encoder cable is connected correctly.	
4. The torque limit has been enabled.	If the torque has been limited, increase the torque limit value.	
5. A moving part collided against the machine.	Review the operation pattern to avoid collision.	
6. The electromagnetic brake has not been released. (The electromagnetic brake has been activated.)	Check if the electromagnetic brake has been released during operation.	
7. The torque is insufficient.	Check the peak load ratio. If the torque is saturated, reduce the load or review the operation pattern. Alternatively, replace the servo motor with a larger-capacity servo motor.	
8. The power supply voltage has dropped.	If the bus voltage is too low, review the power supply voltage and power supply capacity.	
9. Acceleration time constant is too short.	Set a longer acceleration/deceleration time constant, then check the repeatability. If the error does not repeat, increase the acceleration/deceleration time constant.	
10. The position control gain is too small.	Increase the position control gain, then check the repeatability. If the error does not repeat, increase the value in [Pr. PB08 position control gain].	
11. The excessive error alarm trigger level was not set correctly.	Check the setting of the excessive error alarm trigger level. [G]: [Pr. PC01], [Pr. PC06.3]	
12. The servo motor shaft was rotated by an external force or the moving part of the linear servo motor was moved by an external force.	Measure the actual position under the servo-lock status. When an external force rotates the servo motor or moves the linear servo motor, review the machine.	
13. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
14. The encoder or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	


### [AL. 052.3\_ Excessive droop pulse 2]

 Page 58 [AL. 052.1\_ Excessive droop pulse 1]

### [AL. 052.4\_ Excessive error during 0 torque limit]

Cause	Check/action method	Model
1. The torque limit value is 0.	Do not input a command when the torque limit value is 0.	[G]

### [AL. 052.5\_ Excessive droop pulse 3]

 Page 58 [AL. 052.1\_ Excessive droop pulse 1]

## [AL. 052.6\_ Excessive droop pulse at servo-off]

Cause	Check/action method	Model
<b>1.</b> The servo motor shaft was rotated by an external force or the moving part of the linear servo motor was moved by an external force.	Make sure that the servo motor is not rotated (moved) by an external force.	[G]
<b>2.</b> When the servo motor was rotating or when the linear servo motor was moving, servo-on was executed.	Turn servo-on when the servo motor stops.	
<b>3.</b> The controller has malfunctioned.	Replace the controller, then check the repeatability.	
<b>4.</b> The encoder or the servo motor has malfunctioned.	Replace the servo motor or linear encoder, then check the repeatability.	
<b>5.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier, then check the repeatability.	

## [AL. 054\_Oscillation detection]

- The oscillation of the servo motor was detected.

### [AL. 054.1\_Oscillation detection error]

Cause	Check/action method	Model
<b>1.</b> The servo system is unstable and oscillating.	Check the torque ripple with MR Configurator2. If the torque ripple is vibrating, adjust the servo gain with the auto tuning. Set the machine resonance suppression filter.	[G]
<b>2.</b> The resonance frequency has changed due to aging.	Measure the resonance frequency of the equipment and compare the value with the setting value of the machine resonance suppression filter. If the resonance frequency of the equipment and the value of the filter differs, change the setting of the machine resonance suppression filter.	
<b>3.</b> The encoder or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	

## [AL. 056\_Forced stop error]

- The servo motor failed to decelerate normally during a forced stop deceleration.

### [AL. 056.2\_Speed exceeded during forced stop]

Cause	Check/action method	Model
1. The forced stop deceleration time constant is short.	Set a larger value in "Deceleration time constant at forced stop", then check the repeatability. If the error does not repeat, adjust the deceleration time constant. [G]: [Pr. PC24 Deceleration time constant at forced stop]	[G]
2. The torque limit has been enabled.	If the torque has been limited, review the torque limit value.	
3. The servo system is unstable and oscillating.	Check the torque ripple with MR Configurator2. If the torque ripple is vibrating, adjust the servo gain with the auto tuning. Set the machine resonance suppression filter.	
4. The encoder or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	

### [AL. 056.3\_Estimated excess distance during forced stop]

Cause	Check/action method	Model
1. The forced stop deceleration time constant is short.	Set a larger value in "Deceleration time constant at forced stop", then check the repeatability. If the error does not repeat, adjust the deceleration time constant. [G]: [Pr. PC24 Deceleration time constant at forced stop]	[G]
2. The torque limit has been enabled.	If the torque has been limited, review the torque limit value.	
3. The encoder or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	

### [AL. 056.5\_Travel distance exceeded during forced stop 2]

☞ Page 61 [AL. 056.2\_Speed exceeded during forced stop]

## [AL. 061\_Operation error]

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- The operation of positioning function is incorrect.

### [AL. 061.1\_Point table setting range error]


Cause	Check/action method	Model
1. "1" or "3" is set for the auxiliary function of the last point table.	Review the settings of the auxiliary function.	[G]




## [AL. 069\_Command error]

- When the software limit was activated, the command position exceeded 32 bits (-2147483648 to 2147483647).
- When the software limit was activated, the command position exceeded 30 bits (-536870912 to 536870911) from the value that was set.
- The command position exceeded 30 bits (-536870912 to 536870911) from the position which was detected after detecting LSP (Forward rotation stroke end) or LSN (Reverse rotation stroke end).
- The command position exceeded 30 bits (-536870912 to 536870911) from the position that was detected after detecting FLS (Upper stroke limit) or RLS (Lower stroke limit).


### [AL. 069.1\_Forward rotation-side software limit detection - Command excess error]

Cause	Check/action method	Model
1. The command position exceeded 32 bits when the software limit was activated.	Check if the command is set for a position which exceeds 32 bits. Set the command position correctly.	[G]
2. The command position has exceeded 30 bits from the software limit setting value.	Check the software limit. [Pr. PT15 Software position limit +] [Pr. PT17 Software position limit -]	
3. The controller has malfunctioned.	Replace the controller.	
4. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	


### [AL. 069.2\_Reverse rotation-side software limit detection - Command excess error]

 Page 63 [AL. 069.1\_Forward rotation-side software limit detection - Command excess error]


### [AL. 069.3\_Forward rotation stroke end detection - Command excess error]

Cause	Check/action method	Model
1. The command position exceeded 30 bits from the position that was detected after detecting LSP (Forward rotation stroke end).	Review the operation pattern so that the command does not exceed 30 bits.	[G]
2. The forward rotation stroke limit switch is not connected to LSP (Forward rotation stroke end).	Check if the limit switch is connected correctly.	
3. The controller has malfunctioned.	Replace the controller.	
4. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	


### [AL. 069.4\_Reverse rotation stroke end detection - Command excess error]

Cause	Check/action method	Model
1. The command position exceeded 30 bits from the position which was detected after detecting LSN (Reverse rotation stroke end).	Review the operation pattern so that the command does not exceed 30 bits.	[G]
2. The reverse rotation stroke limit switch is not connected to LSN (Reverse rotation stroke end).	Check if the limit switch is connected correctly.	
3. The controller has malfunctioned.	Replace the controller.	
4. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	

### [AL. 069.5\_Upper stroke limit detection - Command excess error]

Cause	Check/action method	Model
1. The command position exceeded 30 bits from the position which was detected after detecting FLS (Upper stroke limit).	Review the operation pattern so that the command does not exceed 30 bits.	[G]
2. The upper stroke limit switch is not wired or the switch is positioned incorrectly.	Check if the limit switch is connected correctly or if the switch is positioned incorrectly.	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	
4. The controller has malfunctioned.	Replace the controller.	

### [AL. 069.6\_Lower stroke limit detection - Command excess error]

Cause	Check/action method	Model
1. The command position exceeded 30 bits from the position which was detected after detecting RLS (Lower stroke limit).	Review the operation pattern so that the command does not exceed 30 bits.	[G]
2. The lower stroke limit switch is not wired or the switch is positioned incorrectly.	Check if the limit switch is connected correctly or if the switch is positioned incorrectly.	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	
4. The controller has malfunctioned.	Replace the controller.	

## [AL. 070\_Load-side encoder initial communication error 1]

- There is a communication error between the load-side encoder and servo amplifier.

### [AL. 070.1\_Load-side encoder initial communication - Receive data error 1]

Cause	Check/action method	Model
1. There is a problem with the load-side encoder cable.	Check if the load-side encoder cable has been disconnected, incorrectly wired, or has shorted. If there is a problem with the cable, replace or repair the cable.	[G]
2. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
3. The load-side encoder has malfunctioned.	Replace the load-side encoder.	
4. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals. MR-JET User's Manual (Hardware)	

### [AL. 070.2\_Load-side encoder initial communication - Receive data error 2]

☞ Page 65 [AL. 070.1\_Load-side encoder initial communication - Receive data error 1]


### [AL. 070.3\_Load-side encoder initial communication - Receive data error 3]

Cause	Check/action method	Model
1. The load-side encoder cable is disconnected.	Check if the load-side encoder cable is connected correctly.	[G]
2. There is a problem with the load-side encoder cable.	Check if the load-side encoder cable has been disconnected or has shorted. If there is a problem with the load-side encoder cable, replace or repair the cable.	
3. When an external power supply was used for the load-side encoder, the voltage of the external power supply became unstable.	Review the power supply capacity and the voltage of the external power supply.	
4. When using a four-wire type linear encoder, the servo amplifier is not compatible with the four-wire type linear encoder.	Check if the servo amplifier is compatible with the four-wire type linear encoder. Refer to "Parts identification" in the User's Manual (Introduction).	
5. The servo amplifier has malfunctioned.	Replace the servo amplifier.	
6. The load-side encoder has malfunctioned.	Replace the load-side encoder.	
7. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals. MR-JET User's Manual (Hardware)	
8. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	


### [AL. 070.5\_Load-side encoder initial communication - Transmission data error 1]

Cause	Check/action method	Model
1. There is a problem with the load-side encoder cable.	☞ Page 65 [AL. 070.1_Load-side encoder initial communication - Receive data error 1]	[G]
2. The servo amplifier has malfunctioned.		
3. The load-side encoder has malfunctioned.		
4. There is a problem with the surrounding environment.		


### [AL. 070.6\_Load-side encoder initial communication - Transmission data error 2]

Cause	Check/action method	Model
1. There is a problem with the load-side encoder cable.	 Page 65 [AL. 070.1_Load-side encoder initial communication - Receive data error 1]	[G]
2. The servo amplifier has malfunctioned.		
3. The load-side encoder has malfunctioned.		
4. There is a problem with the surrounding environment.		

### [AL. 070.7\_Load-side encoder initial communication - Transmission data error 3]

 Page 65 [AL. 070.1\_Load-side encoder initial communication - Receive data error 1]


### [AL. 070.A\_Load-side encoder initial communication - Process error 1]

Cause	Check/action method	Model
1. The servo amplifier has malfunctioned.	Replace the servo amplifier.	[G]
2. The load-side encoder has malfunctioned.	Replace the load-side encoder.	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals.  MR-JET User's Manual (Hardware)	

### [AL. 070.B\_Load-side encoder initial communication - Process error 2]

 Page 65 [AL. 070\_Load-side encoder initial communication error 1]

### [AL. 070.C\_Load-side encoder initial communication - Process error 3]

 Page 65 [AL. 070\_Load-side encoder initial communication error 1]


### [AL. 070.D\_Load-side encoder initial communication - Process error 4]

 Page 65 [AL. 070\_Load-side encoder initial communication error 1]

### [AL. 070.E\_Load-side encoder initial communication - Process error 5]

 Page 65 [AL. 070\_Load-side encoder initial communication error 1]



### [AL. 070.F\_Load-side encoder initial communication - Process error 6]

 Page 65 [AL. 070\_Load-side encoder initial communication error 1]


## [AL. 071\_Load-side encoder normal communication error 1]

- There is a communication error between the load-side encoder and servo amplifier.


### [AL. 071.1\_Load-side encoder normal communication - Receive data error 1]

Cause	Check/action method	Model
<b>1.</b> There is a problem with the load-side encoder cable.	Check if the encoder cable has been disconnected, incorrectly wired, or has shorted. If there is a problem with the encoder cable, replace or repair the cable.	[G]
<b>2.</b> The external conductor of the encoder cable is not connected to the ground plate of the connector.	Check if the external conductor of the encoder cable is connected to the ground plate of the connector. Refer to "Shield procedure of CN2 side connectors" in the following manual.  Rotary Servo Motor User's Manual (For MR-JET)	
<b>3.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier.	
<b>4.</b> The load-side encoder has malfunctioned.	Replace the load-side encoder.	
<b>5.</b> There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals.  MR-JET User's Manual (Hardware)	


### [AL. 071.2\_Load-side encoder normal communication - Receive data error 2]

 Page 67 [AL. 071.1\_Load-side encoder normal communication - Receive data error 1]

### [AL. 071.3\_Load-side encoder normal communication - Receive data error 3]

 Page 67 [AL. 071.1\_Load-side encoder normal communication - Receive data error 1]

### [AL. 071.7\_Load-side encoder normal communication - Transmission data error 3]

 Page 67 [AL. 071.1\_Load-side encoder normal communication - Receive data error 1]

## [AL. 072\_Load-side encoder normal communication error 2]

- The load-side encoder detected an error signal.

### [AL. 072.1\_Load-side encoder data error 1]

Cause	Check/action method	Model
1. An excessive speed or acceleration was detected due to an oscillation or other factors.	Decrease the control gain, then check the repeatability. If the error does not repeat, use the encoder with a lower gain.	[G]
2. The load-side encoder has malfunctioned.	Replace the load-side encoder.	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, external magnetic field, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals. ☞MR-JET User's Manual (Hardware)	

### [AL. 072.2\_Load-side encoder data update error]

Cause	Check/action method	Model
1. The load-side encoder has malfunctioned.	Replace the load-side encoder.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals. ☞MR-JET User's Manual (Hardware)	

### [AL. 072.3\_Load-side encoder data waveform error]

☞ Page 68 [AL. 072.2\_Load-side encoder data update error]

### [AL. 072.4\_No load-side encoder signal]

Cause	Check/action method	Model
1. A signal of the load-side encoder has not been input.	Check if the encoder cable is wired correctly.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals. ☞MR-JET User's Manual (Hardware)	

### [AL. 072.5\_Load-side encoder hardware error 1]

☞ Page 68 [AL. 072.2\_Load-side encoder data update error]

### [AL. 072.6\_Load-side encoder hardware error 2]

☞ Page 68 [AL. 072.2\_Load-side encoder data update error]

## [AL. 076\_Load-side encoder error]

- There is an error in a parameter.

### [AL. 076.2\_Load-side encoder error 2]

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]


### [AL. 076.3\_Load-side encoder error 3]

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

## [AL. 086\_Network communication error]

- An error occurred in the network communication.

### [AL. 086.1\_Network communication error 1]

Cause	Check/action method	Model
<b>1.</b> A network cable is disconnected.	Check if the network cable is connected correctly. Turn off the power supply of the servo amplifier, then connect the network cable correctly.	[G]
<b>2.</b> The wiring of the network cable was incorrect.	Check if the connection of network cable is correct.	
<b>3.</b> A network cable is disconnected.	Check for disconnection in the network cable.	
<b>4.</b> Devices on the network (including repeaters such as hubs) are turned off.	Check that the devices on the network are turned on.	
<b>5.</b> The network was disconnected by an incorrect procedure.	Check if the network was disconnected by a correct procedure for each type of network. Refer to "Disconnecting the communication" or "Network disconnection procedure" in the User's Manual (Communication function).	
<b>6.</b> Data transmission from the controller was interrupted for a certain time.	Check if data transmission from the controller has not been interrupted. If the data transmission has been interrupted, review the controller communication setting.	
<b>7.</b> The settings of the controller were incorrect.	Check the controller settings. When using CC-Link IE TSN, review communication settings such as those for increasing the transient transmission time of the controller. Alternatively, reduce the number of servo amplifiers that enter the network midway.	
<b>8.</b> There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware)	
<b>9.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier.	
<b>10.</b> The controller has malfunctioned.	Replace the controller.	
<b>11.</b> Devices on the network (including repeaters such as hubs) have malfunctioned.	Replace the devices on the network.	

### [AL. 086.2\_Network communication error 2]

 Page 70 [AL. 086.1\_Network communication error 1]

### [AL. 086.3\_Network communication error 3]

 Page 70 [AL. 086.1\_Network communication error 1]

### [AL. 086.4\_Network communication error 4]

 Page 70 [AL. 086.1\_Network communication error 1]

### [AL. 086.5\_Network communication error 5]

 Page 70 [AL. 086.1\_Network communication error 1]

### [AL. 086.6\_Network communication error 6]

 Page 70 [AL. 086.1\_Network communication error 1]



## [AL. 088\_Watchdog 1]/[AL. 888\_Watchdog 1]/[AL. 88888\_Watchdog 1]

- The CPU or other component parts have malfunctioned.

### [AL. 088.1\_Watchdog 1-1]/[AL. 088\_Watchdog 1-1]/[AL. 888\_Watchdog 1-1]/[AL. 88888\_Watchdog 1-1]

Cause	Check/action method	Model
<b>1.</b> An internal part of the servo amplifier has malfunctioned.	Replace the servo amplifier.	[G]

### [AL. 088.2\_Watchdog 1-2]

☞ Page 71 [AL. 088.1\_Watchdog 1-1]/[AL. 088\_Watchdog 1-1]/[AL. 888\_Watchdog 1-1]/[AL. 88888\_Watchdog 1-1]

### [AL. 088.4\_Watchdog 1-4]

☞ Page 71 [AL. 088.1\_Watchdog 1-1]/[AL. 088\_Watchdog 1-1]/[AL. 888\_Watchdog 1-1]/[AL. 88888\_Watchdog 1-1]

### [AL. 088.8\_Watchdog 1-8]

☞ Page 71 [AL. 088.1\_Watchdog 1-1]/[AL. 088\_Watchdog 1-1]/[AL. 888\_Watchdog 1-1]/[AL. 88888\_Watchdog 1-1]

## [AL. 08E\_Serial communication error]

- A communication error occurred between the servo amplifier and the personal computer or the controller.
- An error occurred in Mitsubishi Electric serial communication (USB communication).

### [AL. 08E.1\_Serial communication receive error]

Cause	Check/action method	Model
<b>1.</b> The settings of the personal computer or other equipment are incorrect.	Check the settings of the personal computer and other equipment.	[G]
<b>2.</b> There is a problem with the communication cable.	Check the communication cable, then check the repeatability.	
<b>3.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier, then check the repeatability.	
<b>4.</b> There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Check if the connector has shorted. Refer to "Noise reduction techniques" in the following manual. MR-JET User's Manual (Hardware)	

### [AL. 08E.2\_Serial communication checksum error]

Cause	Check/action method	Model
<b>1.</b> The settings of the personal computer or other equipment are incorrect.	Check the settings of the personal computer and other equipment.	[G]

### [AL. 08E.3\_Serial communication character error]

Cause	Check/action method	Model
<b>1.</b> An unsupported character was transmitted.	Check the character code at the time of transmission. If an unsupported character was transmitted, correct the transmission data.	[G]
<b>2.</b> The communication protocol has a problem.	Check if the transmission data complies with the communication protocol.	
<b>3.</b> The settings of the personal computer or other equipment are incorrect.	Check the settings of the personal computer and other equipment.	

### [AL. 08E.4\_Serial communication command error]

Cause	Check/action method	Model
<b>1.</b> An unsupported command was transmitted.	Check the command at the time of transmission. If an unsupported command was transmitted, correct the transmission data.	[G]
<b>2.</b> The communication protocol has a problem.	Check if the transmission data complies with the communication protocol.	
<b>3.</b> The settings of the personal computer or other equipment are incorrect.	Check the settings of the personal computer and other equipment.	

### [AL. 08E.5\_Serial communication data number error]

Cause	Check/action method	Model
<b>1.</b> An unsupported data number was transmitted.	Check the data number at the time of transmission. If an unsupported data number was transmitted, correct the transmission data.	[G]
<b>2.</b> The communication protocol has a problem.	Check if the transmission data complies with the communication protocol.	
<b>3.</b> The settings of the personal computer or other equipment are incorrect.	Check the settings of the personal computer and other equipment.	

## [AL. 08F\_Two-digit alarm No. display alarm]

- A three-digit alarm is occurring.

### [AL. 08F.1\_Two-digit alarm No. display alarm for AL. 100 to AL. 1FF]

Cause	Check/action method	Model
1. An alarm with alarm No. in 100s ([AL. 1_ _]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 08F.2\_Two-digit alarm No. display alarm for AL. 200 to AL. 2FF]

Cause	Check/action method	Model
1. An alarm with alarm No. in 200s ([AL. 2_ _]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 08F.3\_Two-digit alarm No. display alarm for AL. 300 to AL. 3FF]

Cause	Check/action method	Model
1. An alarm with alarm No. in 300s ([AL. 3_ _]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 08F.4\_Two-digit alarm No. display alarm for AL. 400 to AL. 4FF]

Cause	Check/action method	Model
1. An alarm with alarm No. in 400s ([AL. 4_ _]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 08F.5\_Two-digit alarm No. display alarm for AL. 500 to AL. 5FF]

Cause	Check/action method	Model
1. An alarm with alarm No. in 500s ([AL. 5_ _]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 08F.6\_Two-digit alarm No. display alarm for AL. 600 to AL. 6FF]

Cause	Check/action method	Model
1. An alarm with alarm No. in 600s ([AL. 6_ _]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 08F.7\_Two-digit alarm No. display alarm for AL. 700 to AL. 7FF]

Cause	Check/action method	Model
1. An alarm with alarm No. in 700s ([AL. 7_ _]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 08F.8\_Two-digit alarm No. display alarm for AL. 800 to AL. 8FF]

Cause	Check/action method	Model
1. An alarm with alarm No. in 800s ([AL. 8_ _]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 08F.9\_Two-digit alarm No. display alarm for AL. 900 to AL. 9FF]**

Cause	Check/action method	Model
1. An alarm with alarm No. in 900s ([AL. 9_]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 08F.A\_Two-digit alarm No. display alarm for AL. A00 to AL. AFF]**

Cause	Check/action method	Model
1. An alarm with alarm No. in A00s ([AL. A_]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 08F.B\_Two-digit alarm No. display alarm for AL. B00 to AL. BFF]**

Cause	Check/action method	Model
1. An alarm with alarm No. in B00s ([AL. B_]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 08F.C\_Two-digit alarm No. display alarm for AL. C00 to AL. CFF]**

Cause	Check/action method	Model
1. An alarm with alarm No. in C00s ([AL. C_]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 08F.D\_Two-digit alarm No. display alarm for AL. D00 to AL. DFF]**

Cause	Check/action method	Model
1. An alarm with alarm No. in D00s ([AL. D_]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 08F.E\_Two-digit alarm No. display alarm for AL. E00 to AL. EFF]**

Cause	Check/action method	Model
1. An alarm with alarm No. in E00s ([AL. E_]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 08F.F\_Two-digit alarm No. display alarm for AL. F00 to AL. FFF]**

Cause	Check/action method	Model
1. An alarm with alarm No. in F00s ([AL. F_]) is occurring.	Check the alarm number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

## [AL. 090\_Homing incomplete warning]

- Homing has not been finished.
- Homing did not complete properly.
- Homing was executed with the Z-phase unpassed.

### [AL. 090.1\_Homing incomplete]

Cause	Check/action method	Model
<b>1.</b> Homing has not been executed.	Check if homing was executed. If homing was not executed, execute homing.	[G]
<b>2.</b> Positioning operation was executed without homing after [AL. 025 Absolute position erased] occurred in the absolute position detection system.	Execute homing after dealing with [AL. 025]. Refer to "Homing mode (hm)" in the following manual. □□MR-JET User's Manual (Function)	
<b>3.</b> Homing completion 2 (S_ZP2) turned off after homing was executed.	Remove the causes that turned off homing completion 2 (S_ZP2), then execute homing again. Refer to "Homing method list" in the following manual. □□MR-JET User's Manual (Function)	
<b>4.</b> [AL. 069 Command error] occurred.	Execute homing after dealing with [AL. 069]. Refer to "Homing mode (hm)" in the following manual. □□MR-JET User's Manual (Function)	

### [AL. 090.2\_Homing abnormal termination]

Cause	Check/action method	Model
<b>1.</b> The proximity dog is not connected to DOG.	Check if the proximity dog is connected correctly. Check the status of the input signal on the I/O monitor screen of MR Configurator2.	[G]
<b>2.</b> The stroke limit was detected after homing was started.	Check if the stroke limit switch is connected to the servo amplifier correctly, or check if the stroke limit has been reached.	
<b>3.</b> Deceleration from the homing speed to the creep speed was not possible.	There is a possibility that the proximity dog turned off before deceleration from the homing speed to the creep speed was completed. Review the dog position, or review the parameter values of the homing speed, the creep speed, and the travel distance after proximity dog.	

### [AL. 090.5\_Z-phase unpassed]

Cause	Check/action method	Model
<b>1.</b> Homing was executed while the servo motor did not pass the Z-phase.	Review the homing start position and the proximity dog position so that the servo motor passes the Z-phase signal until the proximity dog turns off after homing started.	[G]
<b>2.</b> The Z-phase signal was not detected normally.	Check if the Z-phase signal of the servo motor was detected normally. Replace the servo motor.	

## [AL. 091\_Servo amplifier overheat warning]

- The temperature inside of the servo amplifier has reached a warning level.

### [AL. 091.1\_Main circuit device overheat warning]

Cause	Check/action method	Model
<b>1.</b> The ambient temperature of the servo amplifier exceeded the specified value (55 °C).	Lower the ambient temperature.	[G]
<b>2.</b> The servo amplifier does not meet the specifications of close mounting.	Check the specifications of close mounting. Refer to "Mounting direction and clearances" in the following manual. □□MR-JET User's Manual (Hardware)	
<b>3.</b> Cooling performance has deteriorated due to clogging of the heat sink and other factors.	Remove causes such as the clogging of the heat sink.	

## [AL. 092\_Battery cable disconnection warning]

- The battery voltage for the absolute position detection system has decreased.

### [AL. 092.1\_Encoder battery cable disconnection warning]

Cause	Check/action method	Model
<b>1.</b> The battery is not connected to the servo amplifier.	Check if the battery is connected correctly.	[G]
<b>2.</b> The battery cable is disconnected.	Check if the battery cable has malfunctioned.	
<b>3.</b> The battery voltage is too low. The battery is exhausted.	Check the battery voltage with a tester. If the voltage is lower than 3.1 V DC, replace the battery.	
<b>4.</b> There is a problem with the encoder cable.	Check if the BAT wiring of the encoder cable has been disconnected or has shorted.	
<b>5.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier, then check the repeatability.	
<b>6.</b> The encoder has malfunctioned.	Replace the servo motor, then check the repeatability.	

### [AL. 092.3\_Battery degradation]

Cause	Check/action method	Model
<b>1.</b> The battery voltage is too low. The battery is exhausted.	Check the battery voltage with a tester. If the voltage is lower than 3.0 V DC, replace the battery.	[G]
<b>2.</b> The battery has malfunctioned.	Replace the battery, then check the repeatability.	

## [AL. 096\_Home position setting warning]

- Homing failed.

### [AL. 096.1\_In-position warning at homing]

Cause	Check/action method	Model
<b>1.</b> During homing, INP (In-position) did not turn on within the specified time.	Adjust gains so that the droop pulses are set within the In-position range. Remove the cause of droop pulse occurrence, then perform homing.	[G]

### [AL. 096.2\_Command input warning at homing]

Cause	Check/action method	Model
<b>1.</b> A command was input during homing.	Ensure that a command is not input during homing.	[G]
<b>2.</b> Creep speed is too high.	Decelerate the creep speed, then perform homing.	



## [AL. 098\_Software position limit warning]

- The software position limit set by servo parameters has been reached.

### [AL. 098.1\_Forward rotation-side software stroke limit reached]

Cause	Check/action method	Model
1. A software position limit has been reached.	Check the operation pattern.	[G]
2. A software position limit has been reached in the JOG operation mode.	Operate the system in the range of the software position limit. Adjust the parameters or objects related to the JOG operation mode as necessary.	
3. The software position limit was set within the actual operation range.	Check if [Pr. PT15 Software position limit +] and [Pr. PT17 Software position limit -] are set correctly.	

### [AL. 098.2\_Reverse rotation-side software stroke limit reached]

☞ Page 79 [AL. 098.1\_Forward rotation-side software stroke limit reached]

## [AL. 099\_Stroke limit warning]

- The stroke limit signal is off.

### [AL. 099.1\_Forward rotation stroke end off]

Cause	Check/action method	Model
1. The forward rotation stroke limit switch is not connected to LSP.	Check if the limit switch is connected correctly. The status of the input signal can be confirmed on the I/O monitor screen of MR Configurator2.	[G]
2. The forward rotation stroke end was exceeded during driving.	Check the operation pattern.	
3. The limit switch has malfunctioned. The sensor has not been adjusted correctly.	Check if the limit switch is functioning correctly or if the sensor has been adjusted correctly.	

### [AL. 099.2\_Reverse rotation stroke end off]

Cause	Check/action method	Model
1. The reverse rotation stroke limit switch is not connected to LSN.	Check if the limit switch is connected correctly. The status of the input signal can be confirmed on the I/O monitor screen of MR Configurator2.	[G]
2. The reverse rotation stroke end was exceeded during driving.	Check the operation pattern.	
3. The limit switch has malfunctioned. The sensor has not been adjusted correctly.	Check if the limit switch is functioning correctly or if the sensor has been adjusted correctly.	

### [AL. 099.4\_Upper stroke limit off]

Cause	Check/action method	Model
1. The upper stroke limit switch is not connected to FLS of the controller.	Check if the limit switch is connected correctly. The status of the input signal can be confirmed on the I/O monitor screen of MR Configurator2.	[G]
2. The upper stroke limit was exceeded during driving.	Check the operation pattern.	
3. The limit switch has malfunctioned. The sensor has not been adjusted correctly.	Check if the limit switch is functioning correctly or if the sensor has been adjusted correctly.	

### [AL. 099.5\_Lower stroke limit off]

Cause	Check/action method	Model
1. The lower stroke limit switch is not connected to RLS of the controller.	Check if the limit switch is connected correctly. The status of the input signal can be confirmed on the I/O monitor screen of MR Configurator2.	[G]
2. The lower stroke limit was exceeded during driving.	Check the operation pattern.	
3. The limit switch has malfunctioned. The sensor has not been adjusted correctly.	Check if the limit switch is functioning correctly or if the sensor has been adjusted correctly.	

### [AL. 099.6\_Forced stop deceleration based on forward rotation stroke end]

☞ Page 80 [AL. 099.1\_Forward rotation stroke end off]

### [AL. 099.7\_Forced stop deceleration based on reverse rotation stroke end]

☞ Page 80 [AL. 099.2\_Reverse rotation stroke end off]

## [AL. 099.8\_Upper stroke limit off 2]

☞ Page 80 [AL. 099.4\_Upper stroke limit off]

## [AL. 099.9\_Lower stroke limit off 2]

☞ Page 80 [AL. 099.5\_Lower stroke limit off]

## [AL. 09B\_ Excessive error warning]

- Droop pulses exceeded the warning occurrence level.

### [AL. 09B.1\_ Excessive droop pulse 1 warning]

Cause	Check/action method	Model
<b>1.</b> The servo motor power cable was disconnected.	Repair or replace the servo motor power cable.	[G]
<b>2.</b> The connection of the servo motor is incorrect.	Check the U/V/W wiring. Refer to "Example power circuit connections" in the following manual. □MR-JET User's Manual (Hardware)	
<b>3.</b> The connection of the encoder cable is incorrect.	Check if the encoder cable is connected correctly.	
<b>4.</b> The torque limit has been enabled.	If the torque has been limited, increase the torque limit value.	
<b>5.</b> A moving part collided against the machine.	Review the operation pattern to avoid collision.	
<b>6.</b> The torque is insufficient.	Check the peak load ratio. If the torque is saturated, reduce the load or review the operation pattern. Alternatively, replace the servo motor with a larger-capacity servo motor.	
<b>7.</b> The power supply voltage has dropped.	If the bus voltage is too low, review the power supply voltage and power supply capacity.	
<b>8.</b> Acceleration/deceleration time constant is insufficient.	Set a longer acceleration/deceleration time constant, then check the repeatability.	
<b>9.</b> The position control gain is too small.	Increase the value of [Pr. PB08 Position control gain].	
<b>10.</b> The servo motor shaft was rotated by an external force. The moving part of the linear servo motor was moved by an external force.	Measure the actual position under the servo-lock status. When an external force rotates the servo motor or moves the linear servo motor, review the machine.	
<b>11.</b> The encoder or linear encoder has malfunctioned.	Replace the servo motor or linear encoder.	

### [AL. 09B.3\_ Excessive droop pulse 2 warning]

☞ Page 82 [AL. 09B.1\_ Excessive droop pulse 1 warning]

### [AL. 09B.4\_ Excessive error warning during 0 torque limit]

Cause	Check/action method	Model
<b>1.</b> The torque limit value is 0.	Do not input a command when the torque limit value is 0.	[G]

## [AL. 09E\_Network warning]

- An error exists in the network data reception.
- An error exists in the network settings.


### [AL. 09E.2\_Communication cycle setting warning]

Cause	Check/action method	Model
1. An unsupported communication cycle was set.	Review the settings on the master side.	[G]
2. The communication cycle was set to 250 $\mu$ s or less while the communication speed was set to 100 Mbps for CC-Link IE TSN.	Change the communication cycle to 500 $\mu$ s or more, or change the communication speed of the controller and the servo amplifier to 1 Gbps.	
3. The communication cycle for CC-Link IE TSN Class A has been set to a lower value than 500 $\mu$ s or a higher value than 500 ms.	For CC-Link IE TSN Class A, set the communication cycle to a value between 500 $\mu$ s and 500 ms inclusive.	

### [AL. 09E.3\_Number of cyclic points warning]

Cause	Check/action method	Model
1. A value larger than the maximum size was set to the cyclic points number.	Change the communication cycle, or review the mapping. For the maximum number of cyclic points, refer to "Communication specifications" in the User's Manual (Communication Function).	[G]

### [AL. 09E.4\_Parameter file warning]

Cause	Check/action method	Model
1. There is an error on the parameter file of the parameter automatic setting.	Replace the parameter automatic setting file.	[G]
2. The processing of the automatic parameter setting was interrupted.	 Page 70 [AL. 086.1_Network communication error 1]	

### [AL. 09E.5\_Cyclic communication setting warning]

Cause	Check/action method	Model
1. An unsupported communication cycle was set.	Review the settings on the master side.	[G]

### [AL. 09E.6\_IP address setting warning]

Cause	Check/action method	Model
1. Duplication of an IP address has been detected.	To ensure that there is no duplication of IP addresses, review [Pr. NPA01 IP address setting], [Pr. NPA02 IP address], and the rotary switch setting.	[G]

### [AL. 09E.7\_Parameter unreflected warning]

Cause	Check/action method	Model
1. Parameter automatic setting was performed for the parameters that require power cycling.	Cycle the power.	[G]

### [AL. 09E.8\_Master station error detection warning]

Cause	Check/action method	Model
1. An error was detected on the master side.	Check the status on the master side.	[G]

### [AL. 09E.9\_Control mode setting warning]

Cause	Check/action method	Model
1. An unsupported control mode was selected.	Check the synchronous/asynchronous mode and the control mode. Refer to "Availability of synchronous mode in control mode" in the User's Manual (Communication Function).	[G]

### [AL. 09E.A\_Communication cycle setting warning]

Cause	Check/action method	Model
1. Servo parameter settings primarily for the control mode and functions that are not supported by the network communication cycle currently in use have been selected.	Check the servo parameters and change the communication cycle to one that is compatible with the set control mode and functions. For the function restrictions of the network communication cycle, refer to "Restrictions on the MR-JET-_G_" in the User's Manual (Introduction).	[G]
2. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	

## [AL. 09F\_Battery warning]

- The battery voltage for the absolute position detection system has decreased.

### [AL. 09F.1\_Low battery]

Cause	Check/action method	Model
<b>1.</b> The battery is not connected to the servo amplifier.	Check if the battery is connected correctly.	[G]
<b>2.</b> The battery voltage is too low. The battery is exhausted.	Check the voltage of the battery with a tester, and if the voltage is lower than 4.9 V DC, replace the battery.	
<b>3.</b> There is a problem with the encoder cable.	Check if the BAT wiring of the encoder cable has been disconnected or has shorted.	
<b>4.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier, then check the repeatability.	
<b>5.</b> The encoder has malfunctioned.	Replace the servo motor, then check the repeatability.	

### [AL. 09F.2\_For manufacturer setting]

This is for manufacturer setting.

## [AL. 0E0\_Excessive regeneration warning]

- [AL. 030.1 Regenerative heat error] may occur.

### [AL. 0E0.1\_Excessive regeneration warning]

Cause	Check/action method	Model
<b>1.</b> The regenerative load ratio exceeded 85 %.	 Page 40 [AL. 030.1_Regenerative heat error]	[G]



## [AL. 0E1\_Overload warning 1]

- [AL. 050 Overload 1] or [AL. 051 Overload 2] may occur.

### [AL. 0E1.1\_Thermal overload warning 1 during operation]

Cause	Check/action method	Model
1. The load was over 85 % of the alarm trigger level of [AL. 050.1 Thermal overload error 1 during operation].	☞ Page 55 [AL. 050.1_Thermal overload error 1 during operation]	[G]

### [AL. 0E1.2\_Thermal overload warning 2 during operation]

Cause	Check/action method	Model
1. The load was over 85 % of the alarm trigger level of [AL. 050.2 Thermal overload error 2 during operation].	☞ Page 55 [AL. 050.2_Thermal overload error 2 during operation]	[G]

### [AL. 0E1.3\_Thermal overload warning 3 during operation]

Cause	Check/action method	Model
1. The load was over 85 % of the alarm trigger level of [AL. 051.1 Thermal overload error 3 during operation].	☞ Page 57 [AL. 051.1_Thermal overload error 3 during operation]	[G]

### [AL. 0E1.4\_Thermal overload warning 4 during operation]

Cause	Check/action method	Model
1. The load was over 85 % of the alarm trigger level of [AL. 050.3 Thermal overload error 4 during operation].	☞ Page 55 [AL. 050.3_Thermal overload error 4 during operation]	[G]

### [AL. 0E1.5\_Thermal overload warning 1 during a stop]

Cause	Check/action method	Model
1. The load was over 85 % of the alarm trigger level of [AL. 050.4 Thermal overload error 1 during a stop].	☞ Page 55 [AL. 050.4_Thermal overload error 1 during a stop]	[G]


### [AL. 0E1.6\_Thermal overload warning 2 during a stop]

Cause	Check/action method	Model
1. The load was over 85 % of the alarm trigger level of [AL. 050.5 Thermal overload error 2 during a stop].	☞ Page 56 [AL. 050.5_Thermal overload error 2 during a stop]	[G]

### [AL. 0E1.7\_Thermal overload warning 3 during a stop]

Cause	Check/action method	Model
1. The load was over 85 % of the alarm trigger level of [AL. 051.2 Thermal overload error 3 during a stop].	☞ Page 57 [AL. 051.2_Thermal overload error 3 during a stop]	[G]


## [AL. 0E1.8\_Thermal overload warning 4 during a stop]

Cause	Check/action method	Model
<b>1.</b> The load was over 85 % of the alarm trigger level of [AL. 050.6 Thermal overload error 4 during a stop].	 Page 56 [AL. 050.6_Thermal overload error 4 during a stop]	[G]


## [AL. 0E2\_Servo motor overheat warning]

- [AL. 046.2 Servo motor overheat] may occur.

### [AL. 0E2.1\_Servo motor temperature warning]

Cause	Check/action method	Model
<b>1.</b> The temperature of the servo motor reached 85 % of the occurrence level of [AL. 046.2 Servo motor overheat].	 Page 52 [AL. 046.2_Servo motor temperature error 2]	[G]

### [AL. 0E2.2\_Servo motor temperature warning 2]

Cause	Check/action method	Model
<b>1.</b> The temperature inside of the servo motor has reached a warning level.	 Page 52 [AL. 046.1_Servo motor temperature error 1]	[G]


## [AL. 0E3\_Absolute position counter warning]

- The multi-revolution counter of the absolute position encoder exceeded the maximum range.
- There is an error in the absolute position encoder pulses.


### [AL. 0E3.1\_Multi-revolution counter travel distance exceeded warning]

Cause	Check/action method	Model
1. In the absolute position system, the travel distance from the home position became 32768 rev or more.	Review the operation range. After the power is cycled, perform homing again.	[G]
2. When an absolute position detection system is configured in the cyclic synchronous mode with a Motion module manufactured by Mitsubishi Electric, [Pr. PC29.5 [AL. 0E3 Absolute position counter warning] selection] is not set to "0" (disabled).	Set [Pr. PC29.5] to "0" (disabled).	

### [AL. 0E3.2\_Absolute position counter warning]

Cause	Check/action method	Model
1. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual.  MR-JET User's Manual (Hardware) After the power is cycled, perform homing again.	[G]
2. The encoder has malfunctioned.	Replace the servo motor.	

### [AL. 0E3.5\_Encoder absolute position counter warning]

 Page 90 [AL. 0E3.2\_Absolute position counter warning]

## [AL. 0E6\_Servo forced stop warning]

- EM2 (Forced stop 2) or EM1 (Forced stop 1) was turned off.

### [AL. 0E6.1\_Forced stop warning]

Cause	Check/action method	Model
<b>1.</b> EM2/EM1 was turned off.	After ensuring safety, turn EM2/EM1 on.	[G]
<b>2.</b> An external 24 V DC power supply has not been input.	Input the external 24 V DC power supply.	
<b>3.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier.	

## [AL. 0E8\_Decreased cooling fan speed warning]

- The cooling fan speed decreased to a warning level or lower.

### [AL. 0E8.1\_Decreased cooling fan speed]

Cause	Check/action method	Model
1. A foreign object was caught in the cooling fan.	Remove the foreign object.	[G]
2. The cooling fan has reached the end of its service life.	Check the total of the power-on time of the servo amplifier. If the service life of the cooling fan is exceeded, replace the servo amplifier or the fan unit.	

### [AL. 0E8.2\_Cooling fan stop]

Page 92 [AL. 0E8.1\_Decreased cooling fan speed]

## [AL. 0E9\_Main circuit off warning]

- The servo-on command was input with the power supply off.
- The bus voltage dropped when the servo motor was rotating at 50 r/min or lower.

### [AL. 0E9.1\_Servo-on signal on during main circuit off]

Cause	Check/action method	Model
<b>1.</b> The bus voltage is less than the specified value. • 200 V class: 215 V DC	Review the wiring. Check the power supply capacity.	[G]
<b>2.</b> The servo-on command was input with the power supply off.	Turn on the power.	
<b>3.</b> The power supply wiring is disconnected.	Connect the power supply.	
<b>4.</b> The power supply capacity is insufficient.	Check if the specified power supply capacity is satisfied.	
<b>5.</b> Main circuit capacitor has deteriorated.	After checking the operation time and ambient temperature, replace the servo amplifier if the main circuit capacitor has reached the end of its service life. Refer to "Parts with a service life" in the User's Manual (Introduction).	
<b>6.</b> The servo amplifier has malfunctioned.	Replace the servo amplifier.	

### [AL. 0E9.2\_Bus voltage drop during low speed operation]

Cause	Check/action method	Model
<b>1.</b> The bus voltage dropped under the specified value when the servo motor was rotating at 50 r/min or lower. • 200 V class: 200 V DC	Review the power supply capacity. Increase the acceleration time constant.	[G]

### [AL. 0E9.3\_Ready-on signal on during main circuit off]

☞ Page 93 [AL. 0E9.1\_Servo-on signal on during main circuit off]

## [AL. 0EC\_Overload warning 2]

- Operation was repeated with a high load ratio while the servo motor shaft was not rotating.

### [AL. 0EC.1\_Overload warning 2]

Cause	Check/action method	Model
1. The load is excessive or the capacity is insufficient.	Reduce the load. Alternatively, replace the servo motor with a larger-capacity servo motor.	[G]



## [AL. 0ED\_Output watt excess warning]

- The output wattage (speed × torque) of the servo motor exceeded the rated output, and that status continued steadily.


### [AL. 0ED.1\_Output watt excess warning]

Cause	Check/action method	Model
<b>1.</b> The output wattage of the servo motor (speed × torque or thrust) steadily exceeds 120 % of the rated output (continuous thrust).	Reduce the servo motor speed. Reduce the load. Alternatively, replace the servo motor with a larger-capacity servo motor.	[G]

## [AL. 0F0\_Tough drive warning]

- The tough drive function was activated.

### [AL. 0F0.1\_Instantaneous power failure tough drive warning]

Cause	Check/action method	Model
<b>1.</b> The power supply voltage has dropped.	 Page 16 [AL. 010.1_Voltage drop in the control circuit power]	[G]

### [AL. 0F0.3\_Vibration tough drive warning]

Cause	Check/action method	Model
<b>1.</b> The setting value of the machine resonance suppression filter was changed due to a machine resonance.	Set the machine resonance suppression filter. Check the machine status for loose screws and other problems.	[G]

## [AL. 0F2\_Drive recorder warning]

- Writing/reading/clearing of the drive recorder data failed.

### [AL. 0F2.1\_Drive recorder warning 1]

Cause	Check/action method	Model
1. There is an error in the drive recorder data.	Check if clearing the alarm history of the drive recorder with MR Configurator2 disables the warning.	[G]
2. There is a memory error.	<ul style="list-style-type: none"> <li>☞ Page 103 [AL. 119.1_Memory error 4-1]</li> <li>☞ Page 103 [AL. 119.7_Memory free space error 4-1]</li> <li>☞ Page 104 [AL. 119.8_Memory free space error 4-2]</li> </ul>	
3. The Flash-ROM has malfunctioned.	Replace the servo amplifier.	

### [AL. 0F2.2\_Drive recorder warning 2]

☞ Page 97 [AL. 0F2.1\_Drive recorder warning 1]

### [AL. 0F2.3\_Drive recorder warning 3]

☞ Page 97 [AL. 0F2.1\_Drive recorder warning 1]

### [AL. 0F2.4\_Drive recorder warning 4]

☞ Page 97 [AL. 0F2.1\_Drive recorder warning 1]

### [AL. 0F2.5\_Drive recorder warning 5]

☞ Page 97 [AL. 0F2.1\_Drive recorder warning 1]

### [AL. 0F2.6\_Drive recorder warning 6]

☞ Page 97 [AL. 0F2.1\_Drive recorder warning 1]

## [AL. 0F3\_Oscillation detection warning]

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- The oscillation of the servo motor was detected.

## [AL. 0F3.1\_Oscillation detection warning]

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☞ Page 60 [AL. 054.1\_Oscillation detection error]

## [AL. 0F4\_Positioning warning]

- The target position or the acceleration/deceleration time constant was set outside of the setting range.

### [AL. 0F4.4\_Target position setting range error warning]

Cause	Check/action method	Model
1. The target position was set outside of the setting range.	Set the target position correctly, then cancel the warning (turn on C_ORST).	[G]

### [AL. 0F4.6\_Acceleration time constant setting range error warning]

Cause	Check/action method	Model
1. The acceleration time constant was set outside of the setting range.	Set [Pr. PT49 Speed acceleration time constant] correctly, then cancel the warning by turning on C_ORST (Operation alarm reset).	[G]

### [AL. 0F4.7\_Deceleration time constant setting range error warning]

Cause	Check/action method	Model
1. The deceleration time constant was set outside of the setting range.	Set [Pr. PT50 Speed deceleration time constant] correctly, then cancel the warning by turning on C_ORST (Operation alarm reset).	[G]

### [AL. 0F4.8\_Control command input error warning]

Cause	Check/action method	Model
1. The relative position command was input while the unit was set to "degree".	If Controlword bit 6 is on while [Pr. PT01.2 Unit for position data] is set to "2", turn off Controlword bit 6, then cancel the warning (turn on C_ORST).	[G]

### [AL. 0F4.A\_Fully closed loop control - Switching warning]

Cause	Check/action method	Model
1. Switching between the semi closed loop control and fully closed loop control was executed during the homing mode (hm) or profile position mode (pp).	Stop the operation in the homing mode (hm) or profile position mode (pp). Cancel the warning by turning on C_ORST.	[G]

## [AL. 0FE\_Two-digit warning No. display warning]

- A three-digit warning is occurring.

### [AL. 0FE.1\_Two-digit warning No. display warning for AL. 100 to AL. 1FF]

Cause	Check/action method	Model
<b>1.</b> A warning with warning No. in 100s ([AL. 1_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 0FE.2\_Two-digit warning No. display warning for AL. 200 to AL. 2FF]

Cause	Check/action method	Model
<b>1.</b> A warning with warning No. in 200s ([AL. 2_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 0FE.3\_Two-digit warning No. display warning for AL. 300 to AL. 3FF]

Cause	Check/action method	Model
<b>1.</b> A warning with warning No. in 300s ([AL. 3_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 0FE.4\_Two-digit warning No. display warning for AL. 400 to AL. 4FF]

Cause	Check/action method	Model
<b>1.</b> A warning with warning No. in 400s ([AL. 4_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 0FE.5\_Two-digit warning No. display warning for AL. 500 to AL. 5FF]

Cause	Check/action method	Model
<b>1.</b> A warning with warning No. in 500s ([AL. 5_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 0FE.6\_Two-digit warning No. display warning for AL. 600 to AL. 6FF]

Cause	Check/action method	Model
<b>1.</b> A warning with warning No. in 600s ([AL. 6_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

### [AL. 0FE.7\_Two-digit warning No. display warning for AL. 700 to AL. 7FF]

Cause	Check/action method	Model
<b>1.</b> A warning with warning No. in 700s ([AL. 7_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 0FE.8\_Two-digit warning No. display warning for AL. 800 to AL. 8FF]**

Cause	Check/action method	Model
1. A warning with warning No. in 800s ([AL. 8_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 0FE.9\_Two-digit warning No. display warning for AL. 900 to AL. 9FF]**

Cause	Check/action method	Model
1. A warning with warning No. in 900s ([AL. 9_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 0FE.A\_Two-digit warning No. display warning for AL. A00 to AL. AFF]**

Cause	Check/action method	Model
1. A warning with warning No. in A00s ([AL. A_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 0FE.B\_Two-digit warning No. display warning for AL. B00 to AL. BFF]**

Cause	Check/action method	Model
1. A warning with warning No. in B00s ([AL. B_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 0FE.C\_Two-digit warning No. display warning for AL. C00 to AL. CFF]**

Cause	Check/action method	Model
1. A warning with warning No. in C00s ([AL. C_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 0FE.D\_Two-digit warning No. display warning for AL. D00 to AL. DFF]**

Cause	Check/action method	Model
1. A warning with warning No. in D00s ([AL. D_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

**[AL. 0FE.E\_Two-digit warning No. display warning for AL. E00 to AL. EFF]**

Cause	Check/action method	Model
1. A warning with warning No. in E00s ([AL. E_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]


**[AL. 0FE.F\_Two-digit warning No. display warning for AL. F00 to AL. FFF]**

Cause	Check/action method	Model
1. A warning with warning No. in F00s ([AL. F_ _]) is occurring.	Check the warning number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2, and take corrective action.	[G]

## [AL. 118\_ Encoder diagnosis]

- The servo amplifier is in the test operation mode.

### [AL. 118.1\_ Encoder communication circuit diagnosis in progress]

Cause	Check/action method	Model
<b>1.</b> The servo amplifier is in the encoder communication circuit diagnosis mode.	Cancel the encoder communication circuit diagnosis mode. Refer to "Encoder communication diagnosis function" in the following manual.  MR-JET User's Manual (Function)	[G]



## [AL. 119\_Memory error 4]

- There is a memory error.

### [AL. 119.1\_Memory error 4-1]

Cause	Check/action method	Model
1. There is a problem with the surrounding environment.	Check the power supply for noise. If there is noise, take countermeasures to reduce the noise. Check if the connector has shorted. Refer to "Noise reduction techniques" in the following manual. □□MR-JET User's Manual (Hardware)	[G]
2. An internal part of the servo amplifier has malfunctioned.	Replace the servo amplifier.	

### [AL. 119.2\_Memory error 4-2]

☞ Page 103 [AL. 119.1\_Memory error 4-1]

### [AL. 119.3\_Memory error 4-3]

Cause	Check/action method	Model
1. The firmware has been updated.	Update it to the latest firmware version, then check the repeatability. If the failure continues, the servo amplifier may have malfunctioned. Replace the servo amplifier.	[G]
2. Take actions in accordance with the items shown below. ☞ Page 103 [AL. 119.1_Memory error 4-1]		

### [AL. 119.4\_Memory error 4-4]

☞ Page 103 [AL. 119.1\_Memory error 4-1]

### [AL. 119.5\_Memory error 4-5]

Cause	Check/action method	Model
1. The firmware has been updated.	Cycle the power, then check the repeatability. If the failure continues, the servo amplifier may have malfunctioned. Replace the servo amplifier.	[G]
2. Take actions in accordance with the items shown below. ☞ Page 103 [AL. 119.1_Memory error 4-1]		

### [AL. 119.6\_Memory error 4-6]

☞ Page 103 [AL. 119.1\_Memory error 4-1]

### [AL. 119.7\_Memory free space error 4-1]

Cause	Check/action method	Model
1. The free memory space is insufficient.	Delete unnecessary files to free up the memory. If no files can be deleted, make a backup of necessary data such as parameters, then initialize the servo amplifier and check the repeatability. If the failure continues, replace the servo amplifier. Refer to "Servo amplifier setting initialization" in the User's Manual (Introduction).	[G]

## [AL. 119.8\_Memory free space error 4-2]

Cause	Check/action method	Model
<b>1.</b> Too many files are saved in the memory.	Delete files to reduce the number of files. If deleting files does not solve the problem, make a backup of necessary data such as parameters, then initialize the servo amplifier and check the repeatability. If the failure continues, replace the servo amplifier. Refer to "Servo amplifier setting initialization" in the User's Manual (Introduction).	[G]

## [AL. 11A\_Servo motor constant error]

- The servo motor constant file is damaged.

### [AL. 11A.1\_Servo motor constant file error]

Cause	Check/action method	Model
1. Writing of the servo motor constant file failed.	There is a possibility that the servo motor constant file is damaged primarily due to noise entering the file while the file was written. After writing the servo motor constant again, cycle the power. For details of actions to be taken, contact your local sales office.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. <a href="#">MR-JET User's Manual (Hardware)</a>	
3. The Flash-ROM has malfunctioned.	Replace the servo amplifier.	

### [AL. 11A.2\_Servo motor constant file extension error]

Cause	Check/action method	Model
1. A file with an extension other than ".mmd2" was written as the servo motor constant file.	Delete the written file, then write another file with the extension ".mmd2". For details of actions to be taken, contact your local sales office.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. <a href="#">MR-JET User's Manual (Hardware)</a>	

### [AL. 11A.3\_Servo motor constant file amount error]

Cause	Check/action method	Model
1. Two or more servo motor constant files were written in the servo motor constant folder.	Delete the written files, then write only one servo motor constant file. For details of actions to be taken, contact your local sales office.	[G]
2. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manual. <a href="#">MR-JET User's Manual (Hardware)</a>	
3. The Flash-ROM has malfunctioned.	Replace the servo amplifier.	

## [AL. 130\_Regenerative error 2]

- The regenerative power exceeds the permissible regenerative power of the built-in regenerative resistor or regenerative option.
- The regenerative transistor in the servo amplifier has malfunctioned.

### [AL. 130.1\_Regenerative heat error]

Cause	Check/action method	Model
<b>1.</b> The settings of the regenerative resistor (regenerative option) are incorrect.	Refer to "Regenerative option" in the following manual. MR-JET User's Manual (Hardware)	[G]
<b>2.</b> The regenerative resistor (regenerative option) is not connected.	Refer to "Regenerative option" in the following manual. MR-JET User's Manual (Hardware)	
<b>3.</b> The regenerative resistor (regenerative option) and the servo amplifier are connected in a wrong combination.	Check the combination of the regenerative resistor (regenerative option) and the servo amplifier. Refer to "Regenerative option" in the following manual. MR-JET User's Manual (Hardware)	
<b>4.</b> The power supply voltage is too high.	Check if the voltage of the input power supply exceeds the upper limit of the permissible voltage. If it exceeds the limit, lower the power supply voltage. 200 V class: 264 V AC	
<b>5.</b> The regenerative power is too large.	Check whether the regenerative load ratio exceeds the upper limit value when the alarm occurs. Take the corrective actions as follows. <ul style="list-style-type: none"> <li>• Reduce the frequency of positioning.</li> <li>• Set a longer deceleration time constant.</li> <li>• Reduce the load.</li> <li>• Use a regenerative option if it is not being used.</li> </ul>	

## [AL. 139\_Open-phase error]

- An open phase occurred in the power supply of the servo amplifier.
- An open phase occurred in the servo motor power line.

### [AL. 139.2\_Output open-phase error]

Cause	Check/action method	Model
1. An open phase occurred in the servo motor power line.	Check that the servo motor power line is connected with the servo amplifier. Check that the servo motor power supply is connected with the servo amplifier. Check if the servo motor power line is closed. If the servo motor power line is open, replace the servo motor power line.	[G]
2. The winding inside the servo motor is disconnected.	Replace the servo motor, then check the repeatability.	

## [AL. 17A\_Load-side linear encoder error 1]

- A problem with the linear encoder was detected in the fully closed loop control mode. The content of the errors varies depending on each encoder manufacturer.

### [AL. 17A.1\_Load-side linear encoder error 1-1]

Cause	Check/action method	Model
1. The linear encoder and the head have been incorrectly mounted.	Adjust the positions of the linear encoder and the head.	[G]
2. The external conductor of the encoder cable is not connected to the ground plate of the connector.	Refer to "Shield procedure of CN2 side connectors" in the following manual. ☞MR-JET Partner's Encoder User's Manual	
3. There is a problem with the surrounding environment.	Check the noise, ambient temperature, and other conditions, and implement appropriate countermeasures for the cause. If there is noise, take countermeasures to reduce the noise. Refer to "Noise reduction techniques" in the following manuals. ☞MR-JET User's Manual (Hardware)	
4. A linear encoder alarm was detected.	Refer to "DETAILED EXPLANATION OF [AL. 02A LINEAR ENCODER ERROR 1]" in the following manual. ☞MR-JET Partner's Encoder User's Manual	

### [AL. 17A.2\_Load-side linear encoder error 1-2]

☞ Page 108 [AL. 17A.1\_Load-side linear encoder error 1-1]

### [AL. 17A.3\_Load-side linear encoder error 1-3]

☞ Page 108 [AL. 17A.1\_Load-side linear encoder error 1-1]

### [AL. 17A.4\_Load-side linear encoder error 1-4]

☞ Page 108 [AL. 17A.1\_Load-side linear encoder error 1-1]

### [AL. 17A.5\_Load-side linear encoder error 1-5]

☞ Page 108 [AL. 17A.1\_Load-side linear encoder error 1-1]

### [AL. 17A.6\_Load-side linear encoder error 1-6]

☞ Page 108 [AL. 17A.1\_Load-side linear encoder error 1-1]

### [AL. 17A.7\_Load-side linear encoder error 1-7]

☞ Page 108 [AL. 17A.1\_Load-side linear encoder error 1-1]

### [AL. 17A.8\_Load-side linear encoder error 1-8]

☞ Page 108 [AL. 17A.1\_Load-side linear encoder error 1-1]

## [AL. 188\_Watchdog 2]

- The CPU or other component parts have malfunctioned.


### [AL. 188.1\_Watchdog 2-1]

Cause	Check/action method	Model
<b>1.</b> An internal part of the servo amplifier has malfunctioned.	Replace the servo amplifier.	[G]


## [AL. 19D\_IP address setting change warning]

- The IP address setting with an engineering tool was incorrect.

### [AL. 19D.1\_IP address change unreflected warning]

Cause	Check/action method	Model
<b>1.</b> The IP address setting with an engineering tool was configured after the communication with the master station was established.	Cycle the power of the servo amplifier or reset the software to apply changes to the settings. For the IP address setting with an engineering tool, refer to "IP address setting function via the master station" in the following manual.  MR-JET-G User's Manual (Communication Function)	[G]

### [AL. 19D.2\_IP address change failed warning 1]

Cause	Check/action method	Model
<b>1.</b> When [Pr. NPA01 IP address setting] is set to "0" (the rotary switch is used.) and the rotary switch is set to a value other than "0", the IP address setting with an engineering tool was configured.	Set [Pr. NPA01 IP address setting] to "1" (the network parameter is used.). Alternatively, configure the IP address setting after setting the rotary switch to "0". For the IP address setting with an engineering tool, refer to "IP address setting function via the master station" in the following manual.  MR-JET-G User's Manual (Communication Function)	[G]



## [AL. 19E\_Network warning 2]

- An error exists in the network settings.

### [AL. 19E.1\_Parameter automatic backup setting warning]

Cause	Check/action method	Model
1. An error was detected in the parameter automatic backup setting.	Check if the master station supports power interruption protection. If power interruption protection is not supported, set [Pr. PN20 Parameter automatic backup update interval] to "0" to disable the automatic backup function.	[G]

### [AL. 19E.2\_Control mode setting warning 2]

Cause	Check/action method	Model
1. An unsupported control mode was used.	Check if the control mode corresponds to the communication cycle. For the correspondence between communication cycles and control modes, refer to "Restrictions on the MR-JET-_G_" in the User's Manual (Introduction).	[G]
2. A control mode that does not support CC-Link IE TSN Class A was used.	Check if the control mode supports CC-Link IE TSN Class A. For the correspondence between CC-Link IE TSN Class A and control modes, refer to "Restrictions on CC-Link IE TSN Class A" in the User's Manual (Introduction).	

### [AL. 19E.3\_Safety communication setting warning]

Cause	Check/action method	Model
1. The safety communication setting of the controller has been enabled for a servo amplifier on which the safety communication has been disabled.	If not using the safety communication, disable the safety communication setting of the controller. If using the safety communication, enable the safety communication setting of the servo amplifier.	[G]

## [AL. 1F6\_Manufacturer setting error]

- A value of the servo parameters for manufacturer setting has been set incorrectly.

### [AL. 1F6.1\_Manufacturer setting error]

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

### [AL. 1F6.2\_Manufacturer setting error]

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

### [AL. 1F6.3\_Manufacturer setting error]

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

### [AL. 1F6.4\_Manufacturer setting error]

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

### [AL. 1F6.5\_Manufacturer setting error]

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

### [AL. 1F6.6\_Manufacturer setting error]

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

## [AL. 1F8\_Memory warning 1]

- There is a memory error.

### [AL. 1F8.1\_Memory writing frequency warning]

Cause	Check/action method	Model
<b>1.</b> The frequency of writing to the memory exceeded the guaranteed number.	Prepare for replacing the servo amplifier by making a backup of necessary data or by other means. This warning can be disabled by [Pr. PF02.4 Memory writing frequency warning enable/disable selection]. The memory may be broken if the memory is used continuously while [Pr. PF02.4] is disabled.	[G]

### [AL. 1F8.2\_Memory free space warning]

Cause	Check/action method	Model
<b>1.</b> The available free space in the memory is insufficient.	Delete unnecessary files to free up the memory. If no files can be deleted, make a backup of necessary data such as parameters, then initialize the servo amplifier. Refer to "Servo amplifier setting initialization" in the User's Manual (Introduction). This warning can be disabled by [Pr. PF02.5 Memory free space warning enable/disable selection]. [AL. 119.7 Memory free space error 4-1] may occur if the memory is used continuously while [Pr. PF02.5] is disabled.	[G]

## [AL. 201 - 28F\_Manufacturer setting error]

- A value of the servo parameters for manufacturer setting has been set incorrectly.

Cause	Check/action method	Model
1. Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

## [AL. 290 - 2FF\_Manufacturer setting warning]

- A value of the servo parameters for manufacturer setting has been set incorrectly.

Cause	Check/action method	Model
<b>1.</b> Values of the servo parameters for manufacturer setting have been changed.	Set the servo parameters for manufacturer setting to the initial values.	[G]

# 1.4 Trouble which does not trigger an alarm/warning

This section shows examples of trouble which will not trigger an alarm or warning as well as the possible causes of such trouble. Refer to this section and remove each cause of trouble.

## Precautions

- When the servo amplifier, servo motor, controller, or encoder malfunctions, the cases shown in this section may occur.
- If the servo motor does not rotate, also check the "No Motor Rotation" area in MR Configurator2.

## The display shows "A" (unconnected to the controller)

Possible cause	Check/action method	Model
1. The power supply of the controller has been turned off.	Switch on the power of the controller.	[G]
2. The power supply of the device between the controller and servo amplifier has been turned off.	Turn on the power of the device between the controller and servo amplifier.	
3. The amplifier-less operation function of the controller is enabled.	Cancel the amplifier-less operation function of the controller.	
4. A network cable was disconnected.	Replace the network cable. [G]: Ethernet cable Check if the connector (CN1A/CN1B) is disconnected.	
5. An incompatible controller is connected. Or, the network settings of the controller and the network settings of the servo amplifiers do not match.	Connect with a compatible controller. Check that the controller and servo amplifiers use the same network type.	
6. The settings of the rotary switch are incorrect.	Check if there is another servo amplifier assigned to the same axis No. Check if the settings of the controller and servo amplifiers are correct.	
7. The communication cycle does not match.	Refer to the servo system controller instruction manual and check the communication cycle. Check the communication error detection time of the servo amplifier.	
8. The communication speed (1 Gbps or 100 Mbps) does not match between the controller and servo amplifiers.	Check that the communication speeds of the controller and servo amplifiers are the same.	

## The display shows "r"

Possible cause	Check/action method	Model
1. The system is in servo-off or ready-off state.	Turn on the servo-on for all the axes.	[G]

## The display shows "T"

Possible cause	Check/action method	Model
1. The test operation mode is enabled.	Disable the test operation with the parameter. Refer to "Test operation" in the User's Manual (Introduction).	[G]

## The display is off

Possible cause	Check/action method	Model
1. The external I/O terminal has shorted.	If disconnecting the encoder connector and I/O signal connector solves the trouble, the cable wiring may have shorted. Review the wiring.	[G]
2. The power has not been supplied.	Turn on the power.	
3. The power supply voltage has dropped.	Increase the voltage of the power supply.	
4. The external fuse was disconnected.	Check if the external fuse is disconnected.	

## The servo motor does not operate

Possible cause	Check/action method	Model
<b>1.</b> The connection of the servo motor is incorrect.	Check the U/V/W wiring. Refer to "Example power circuit connections" in the following manual. □ MR-JET User's Manual (Hardware)	[G]
<b>2.</b> A servo motor power cable or an encoder cable is connected to an incorrect axis.	Check if the encoder cable and the servo motor power cable are connected to the same axis.	
<b>3.</b> An alarm or warning is occurring.	Check the contents of the alarm or warning, and remove its cause.	
<b>4.</b> The system is in the test operation mode. Test operation selection has been enabled.	Cancel the test operation mode. [G]: [Pr. PC05.1 Test operation selection]	
<b>5.</b> The motor-less operation has been enabled.	Disable the motor-less operation. [G]: [Pr. PC05.0 Motor-less operation selection]	
<b>6.</b> The torque is insufficient for the large load.	Check the instantaneous torque with MR Configurator2. If the torque reaches the maximum torque or the torque limit value, reduce the load or replace the servo motor with a larger-capacity servo motor.	
<b>7.</b> An unintended torque limit has been enabled.	Cancel the torque limit.	
<b>8.</b> The setting value for the torque limit is incorrect.	Check if the torque limit value is "0". Refer to "Torque limit" in the following manual. □ MR-JET User's Manual (Function)	
<b>9.</b> The machine is interfering with the servo motor.	Remove the interference.	
<b>10.</b> For a servo motor with an electromagnetic brake, the brake has not been released.	Turn on the electromagnetic brake power.	
<b>11.</b> LSP (Forward rotation stroke end) and LSN (Reverse rotation stroke end) are not on.	Check if [AL. 099 Stroke limit warning] has occurred. Turn on LSP and LSN.	
<b>12.</b> FLS (Upper stroke limit) and RLS (Lower stroke limit) are not turned on.	Check if [AL. 099 Stroke limit warning] has occurred. Turn on FLS and RLS.	
<b>13.</b> A software position limit is reached.	Check if [AL. 098 Software position limit warning] has occurred. Place the moving part in the range of the software position limit.	
<b>14.</b> The servo-on has not been turned on.	Turn on the servo-on.	
<b>15.</b> The settings of the electronic gear are incorrect.	Set appropriate values for the electronic gear.	
<b>16.</b> The setting value of the point table is incorrect.	Review the setting value of the point table.	
<b>17.</b> The setting/specification of the point table number selection is incorrect.	Check the [Target point table (Obj. 2D60h)] setting.	
<b>18.</b> Quick Stop has been activated.	Cancel Quick Stop.	
<b>19.</b> Halt has been activated.	Cancel Halt.	
<b>20.</b> An error is occurring on the controller side.	Remove the error of the controller.	
<b>21.</b> The parameter settings are incorrect on the controller side.	Review the parameter settings on the controller side.	
<b>22.</b> The position command has not been input correctly.	Review the settings of the controller or the servo program.	

## The increase in the servo motor speed is insufficient or excessive

Possible cause	Check/action method	Model
1. The settings of the speed command, speed limit, or electronic gear are incorrect.	Review the settings of the speed command, speed limit, and electronic gear.	[G]
2. The connection of the servo motor is incorrect.	Check the U/V/W wiring. Refer to "Example power circuit connections" in the following manual. □MR-JET User's Manual (Hardware)	
3. The power supply voltage has dropped.	Increase the voltage of the power supply.	
4. For a servo motor with an electromagnetic brake, the brake has not been released.	Turn on the electromagnetic brake power.	
5. When the override function is enabled, the override value is set incorrectly.	Review the setting of [Speed override (Obj. 2DB0h)].	

## Vibration of servo motor at low frequency

Possible cause	Check/action method	Model
1. The estimated value of the load to motor inertia ratio by auto tuning is incorrect. The value of the load to motor inertia ratio which was set manually is incorrect.	Execute the auto tuning or one-touch tuning to set the load to motor inertia ratio again. When setting manually, set the load to motor inertia ratio correctly. Refer to "ADJUSTMENT METHOD" in the following manual. □MR-JET User's Manual (Adjustment)	[G]
2. The command from the controller is unstable.	Review the command from the controller. Check if the Ethernet cable is disconnected or has other problems.	
3. When the servo motor stops, torque at acceleration/deceleration overshoots exceeding the limit of the servo motor.	If the torque at acceleration/deceleration reaches the maximum torque, reduce the generated torque by increasing the acceleration/deceleration time, reducing the load, or other measures.	
4. The servo gain is too low or the response of the auto tuning is too low.	Increase the servo gain or the value of [Pr. PA09 Auto tuning response].	



## There is an unusual noise in the servo motor

Possible cause	Check/action method	Model
<b>1.</b> The servo gain is too high or the response of the auto tuning is too high.	Increase the servo gain or the value of [Pr. PA09 Auto tuning response].	[G]
<b>2.</b> The bearing has reached the end of its service life.	If the servo motor can be operated safely, remove the load and check for the noise in the servo motor itself. If the servo motor is removable from the machine, remove the servo motor power cable, then release the brake, and rotate the servo motor by an external force to check for a noise. If a noise occurs, the bearing is at the end of its service life. Replace the servo motor. If no noise occurs, perform maintenance on the load side.	
<b>3.</b> For a servo motor with an electromagnetic brake, the brake has not been released.	Turn on the electromagnetic brake power.	
<b>4.</b> When a servo motor with an electromagnetic brake is used, the brake release timing is incorrect.	Review the timing of the electromagnetic brake release. Take into account that the electromagnetic brake has a release delay time.	

## The servo motor vibrates

Possible cause	Check/action method	Model
<b>1.</b> The servo gain is too high or the response of the auto tuning is too high.	Decrease the servo gain to check if the trouble is solved or decrease the value of [Pr. PA09 Auto tuning response].	[G]
<b>2.</b> The machine is vibrating (resonating).	Perform one-touch tuning or adaptive tuning, or set the machine resonance suppression filter.	
<b>3.</b> The load side is vibrating.	Perform vibration suppression control tuning or set the vibration suppression control.	
<b>4.</b> Noise entered the encoder cable, causing the miscount of the feedback pulses.	Check if numerical values of the cumulative feedback pulses are skipped with MR Configurator2. Take countermeasures against noise, such as laying the encoder cable apart from the power cables.	
<b>5.</b> There is a backlash between the servo motor and machine (such as a gear and coupling).	If the coupling and the mechanical part are nearly broken, or there is a backlash, perform an inspection and maintenance.	
<b>6.</b> The rigidity of the servo motor mounting part is too low.	Increase the rigidity of the mounting part by increasing the board thickness, reinforcing the part with ribs, or other means.	
<b>7.</b> The connection of the servo motor is incorrect.	Check the U/V/W wiring. Refer to "Example power circuit connections" in the following manual. MR-JET User's Manual (Hardware)	
<b>8.</b> An unbalanced torque of the machine is too large.	Check if the vibration also changes as the servo motor speed changes. Adjust the balance of the machine.	
<b>9.</b> The eccentricity due to a core gap is too large.	Check the mounting accuracy of the servo motor and machine.	
<b>10.</b> A load for the shaft of the servo motor is too large.	Make the load for the shaft of the servo motor equal to or less than the permissible load of the servo motor. Refer to "Standard specifications list" in the following manual. Rotary Servo Motor User's Manual (For MR-JET)	
<b>11.</b> An external vibration propagated to the servo motor.	Prevent the vibration from the external vibration source.	

## Poor speed accuracy (Unstable speed of servo motor)

Possible cause	Check/action method	Model
1. The servo gain is too low or the response of auto tuning is too low.	Increase the servo gain or the value of [Pr. PA09 Auto tuning response].	[G]
2. The servo gain is too high or the response of the auto tuning is too high.	Decrease the servo gain to check if the trouble is solved. Alternatively, decrease the value of [Pr. PA09].	
3. The torque is insufficient for the large load.	Check the instantaneous torque with MR Configurator2. If the torque reaches the maximum torque or the torque limit value, reduce the load or replace the servo motor with a larger-capacity servo motor.	
4. An unintended torque limit has been enabled.	On the status display or MR Configurator2, check if TLC (Limiting torque) is turned on. Cancel the torque limit. Refer to "Torque limit" in the following manual. □MR-JET User's Manual (Function)	
5. The setting value for the torque limit is incorrect.	Increase the torque limit value. Refer to "Torque limit" in the following manual. □MR-JET User's Manual (Function)	
6. For a servo motor with an electromagnetic brake, the brake has not been released.	Turn on the electromagnetic brake power.	
7. The command from the controller is unstable.	Review the command from the controller. Alternatively, check if the Ethernet cable is disconnected or has other problems.	
8. The power supply voltage is lower than specifications.	Adjust the power supply voltage within the range of specifications.	

## The machine vibrates unsteadily when it stops

Possible cause	Check/action method	Model
1. The servo gain is too low or the response of the auto tuning is too low.	Increase the servo gain or the value of [Pr. PA09 Auto tuning response].	[G]

## Overshoot/undershoot occurs

Possible cause	Check/action method	Model
1. The servo gain is too low or too high. The response of auto tuning is too low or too high.	Adjust the response of auto tuning and readjust the gain.	[G]
2. The setting of [Pr. PB06 Load to motor inertia ratio/load to motor mass ratio] is incorrect.	Check if the setting value of [Pr. PB06] matches the actual load moment of inertia or load mass. If the value does not match, set the parameter correctly.	
3. The maximum torque is insufficient due to the excessive load or the capacity of the servo motor is insufficient.	Check the instantaneous torque on the status display. Check if the torque reaches the torque limit value. Keep the torque outside the torque limit value by increasing the acceleration/deceleration time or by reducing the load. Alternatively, use a servo motor with a larger capacity.	
4. The setting of the torque limit value is too small.	Check the instantaneous torque on the status display. Check if the torque reaches the torque limit value. Increase the torque limit value so that the torque does not reach the limit value.	
5. The backlash of the machine part is too large.	Perform an inspection and maintenance of the coupling and the machine.	

## The servo motor starts moving immediately after the power-on of the servo amplifier or servo-on

Possible cause	Check/action method	Model
1. When a servo motor with an electromagnetic brake is used, the brake release timing is incorrect.	Review the timing of the electromagnetic brake release.	[G]
2. The connection of the servo motor is incorrect.	Check the U/V/W wiring. Refer to "Example power circuit connections" in the following manual. ☞MR-JET User's Manual (Hardware)	
3. The control mode was switched without performing position follow-up on the controller side.	Perform position follow-up on the controller side before switching the control mode.	

## The home position deviates at the homing

Possible cause	Check/action method	Model
1. When performing the dog type homing, the point where the proximity dog turns off is close to the point where a Z-phase pulse is detected (CR input position).	Check if a fixed amount (in one revolution) deviates. Adjust the position of the proximity dog.	[G]
2. The in-position range is too large.	Set the value in [Pr. PA10 In-position range] for a narrower range than the current setting.	
3. The proximity dog switch has malfunctioned or the proximity dog switch is improperly mounted.	Repair or replace the proximity dog switch. Adjust the mounting of the proximity dog switch.	
4. The program on the controller side is incorrect.	Review the program on the controller side, such as home position address settings and sequence programs.	
5. An incorrect homing method has been selected.	Review the homing method selection.	

## The position deviates during operation after the homing

Possible cause	Check/action method	Model
1. The electronic gear is incorrect.	Review the settings of the electronic gear. Refer to "Electronic gear function" in the following manual. ☞MR-JET User's Manual (Function)	[G]
2. The servo gain is too low or the response of auto tuning is too low.	Check if the trouble is solved by increasing the value of [Pr. PA09 Auto tuning response]. Adjust the servo gain.	
3. The proportional control (PID control) is enabled.	Disable the proportional control (PID control).	
4. The in-position range is too large.	Review the setting of [Pr. PA10 In-position range].	
5. Mechanical slippage occurred or the backlash of the mechanical part is too large.	Check for a slip or backlash in the mechanical part.	

## A position mismatch occurs at power restoration in an absolute position detection system


Possible cause	Check/action method	Model
1. While the servo amplifier was in power-off status, an external force rotated the servo motor at a speed exceeding the maximum permissible speed at power failure (6000 r/min). (The acceleration time was 0.2 s or less.)	Extend the acceleration time. Keep the speed under the maximum permissible speed at power failure.	[G]
2. When the servo motor was rotated at a speed exceeding 3000 r/min by an external force, the servo amplifier power was turned on.	Check if the servo amplifier power was turned on when the servo motor was rotated at a speed exceeding 3000 r/min by an external force.	

## Communication with the servo amplifier fails using MR Configurator2

- For details, refer to the "HELP" window in MR Configurator2.

Possible cause	Check/action method	Model
1. The communication settings are incorrect.	Check the communication settings, such as the baud rate and ports.	[G]
2. The model being connected differs from the model set in the model selection.	Check if the model selection has been set correctly.	
3. The driver has been set incorrectly.	Refer to "PRECAUTIONS FOR COMMUNICATING WITH THE SERVO AMPLIFIER" on the "HELP" window in MR Configurator2.	
4. They are off-line.	Set them to on-line.	
5. There is a problem with the communication cable.	Replace the communication cable.	
6. The communication cable is not connected.	Connect the communication cable.	
7. Power is not being supplied to the servo amplifier.	Supply the power to the servo amplifier.	


## Electromagnetic brake went out

Possible cause	Check/action method	Model
1. The electromagnetic brake has reached the end of its service life.	Remove the servo motor and all the wiring from the machine, and check if the servo motor shaft is rotated by an external force. If the motor rotates, the brake has a failure. Replace the servo motor. Refer to "Characteristics of electromagnetic brake" in the following manual.  Rotary Servo Motor User's Manual (For MR-JET)	[G]

## Electromagnetic brake cannot be released

Possible cause	Check/action method	Model
1. The wiring is incorrect.	Check the output signals.	[G]
2. A signal of an output device has not been output correctly.	Check if the output device cable is wired correctly, or check if the load of the output device is within specifications.	

## Coasting distance of the servo motor became longer

Possible cause	Check/action method	Model
1. The load increased and exceeded the permissible load to motor inertia.	Reduce the load.	[G]
2. The electromagnetic brake malfunctioned as the brake reached the end of its service life.	Remove the servo motor and all the wiring from the machine, and check if the servo motor shaft can be rotated by the hands. If the motor rotates, the brake has a failure. Replace the servo motor. Refer to "Characteristics of electromagnetic brake" in the following manual.  Rotary Servo Motor User's Manual (For MR-JET)	
3. The electronic dynamic brake is disabled.	Enable the electronic dynamic brake with [Pr. PF06.0 Electronic dynamic brake selection].	

## Executed point table does not work

Possible cause	Check/action method	Model
1. Positioning to the same position are repeated.	Operation is repeatedly started by specifying the same point table number. Review the specification of the point table number or the operating procedure. Positioning to the same position address is repeated by selecting "8, 9, 10, 11" (continuous operation) in the auxiliary function of the point table. Review the setting value of the point table number or the operating procedure.	[G]
2. A point table number for which no value has been set is specified.	Set the correct value to the specified point table. Or, specify the point table number for which a value has been set.	

## 1.5 Two-digit display of alarm/warning number

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For some objects, the alarm/warning number can only be read in two digits. For three-digit alarm/warning numbers, check the number using an object that can read three-digit numbers, the servo amplifier display, or MR Configurator2.



# REVISIONS

\*The manual number is given on the bottom left of the back cover.

Revision date	*Manual number	Description
November 2019	IB(NA)-0300483ENG-A	First edition
July 2020	IB(NA)-0300483ENG-B	■Alarms and warnings related to the following functions are added: Linear servo motor control mode, profile mode
October 2020	IB(NA)-0300483ENG-C	■Alarms and warnings related to the following function are added: Degree function
March 2021	IB(NA)-0300483ENG-D	■Alarms and warnings related to the following function are added: Positioning mode (point table method)
July 2021	IB(NA)-0300483ENG-E	■Alarms and warnings related to the following function are added: CC-Link IE Field Network Basic
July 2022	IB(NA)-0300483ENG-F	■Alarms and warnings related to the following functions are added/edited: Batteryless absolute position encoder, fully closed loop system, CC-Link IE TSN Class A
January 2023	IB(NA)-0300483ENG-G	[AL. 1F6 Manufacturer setting error] is added.
January 2024	IB(NA)-0300483ENG-H	■Alarms and warnings related to the following function are added: IP address setting function via the master station

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# WARRANTY

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## Warranty

### **1. Warranty period and coverage**

We will repair any failure or defect hereinafter referred to as "failure" in our FA equipment hereinafter referred to as the "Product" arisen during warranty period at no charge due to causes for which we are responsible through the distributor from which you purchased the Product or our service provider. However, we will charge the actual cost of dispatching our engineer for an on-site repair work on request by customer in Japan or overseas countries. We are not responsible for any on-site readjustment and/or trial run that may be required after a defective unit are repaired or replaced.

[Term]

For terms of warranty, please contact your original place of purchase.

[Limitations]

(1) You are requested to conduct an initial failure diagnosis by yourself, as a general rule.

It can also be carried out by us or our service company upon your request and the actual cost will be charged. However, it will not be charged if we are responsible for the cause of the failure.

(2) This limited warranty applies only when the condition, method, environment, etc. of use are in compliance with the terms and conditions and instructions that are set forth in the instruction manual and user manual for the Product and the caution label affixed to the Product.

(3) Even during the term of warranty, the repair cost will be charged on you in the following cases;

1. a failure caused by your improper storing or handling, carelessness or negligence, etc., and a failure caused by your hardware or software problem
2. a failure caused by any alteration, etc. to the Product made on your side without our approval
3. a failure which may be regarded as avoidable, if your equipment in which the Product is incorporated is equipped with a safety device required by applicable laws and has any function or structure considered to be indispensable according to a common sense in the industry
4. a failure which may be regarded as avoidable if consumable parts designated in the instruction manual, etc. are duly maintained and replaced
5. any replacement of consumable parts (battery, fan, smoothing capacitor, etc.)
6. a failure caused by external factors such as inevitable accidents, including without limitation fire and abnormal fluctuation of voltage, and acts of God, including without limitation earthquake, lightning and natural disasters
7. a failure generated by an unforeseeable cause with a scientific technology that was not available at the time of the shipment of the Product from our company
8. any other failures which we are not responsible for or which you acknowledge we are not responsible for

### **2. Term of warranty after the stop of production**

(1) We may accept the repair at charge for another seven (7) years after the production of the product is discontinued. The announcement of the stop of production for each model can be seen in our Sales and Service, etc.

(2) Please note that the Product (including its spare parts) cannot be ordered after its stop of production.

### **3. Service in overseas countries**

Our regional FA Center in overseas countries will accept the repair work of the Product. However, the terms and conditions of the repair work may differ depending on each FA Center. Please ask your local FA center for details.

### **4. Exclusion of loss in opportunity and secondary loss from warranty liability**

Regardless of the gratis warranty term, Mitsubishi shall not be liable for compensation to:

- (1) Damages caused by any cause found not to be the responsibility of Mitsubishi.
- (2) Loss in opportunity, lost profits incurred to the user by Failures of Mitsubishi products.
- (3) Special damages and secondary damages whether foreseeable or not, compensation for accidents, and compensation for damages to products other than Mitsubishi products.
- (4) Replacement by the user, maintenance of on-site equipment, start-up test run and other tasks.

### **5. Change of Product specifications**

Specifications listed in our catalogs, manuals or technical documents may be changed without notice.

### **6. Application and use of the Product**

- (1) For the use of our AC Servo, its applications should be those that may not result in a serious damage even if any failure or malfunction occurs in AC Servo, and a backup or fail-safe function should operate on an external system to AC Servo when any failure or malfunction occurs.
- (2) Our AC Servo is designed and manufactured as a general purpose product for use at general industries. Therefore, applications substantially influential on the public interest for such as atomic power plants and other power plants of electric power companies, and also which require a special quality assurance system, including applications for railway companies and government or public offices are not recommended, and we assume no responsibility for any failure caused by these applications when used.  
In addition, applications which may be substantially influential to human lives or properties for such as airlines, medical treatments, railway service, incineration and fuel systems, man-operated material handling equipment, entertainment machines, safety machines, etc. are not recommended, and we assume no responsibility for any failure caused by these applications when used. We will review the acceptability of the abovementioned applications, if you agree not to require a specific quality for a specific application. Please contact us for consultation.
- (3) Mitsubishi Electric shall have no responsibility or liability for any problems involving programmable controller trouble and system trouble caused by DoS attacks, unauthorized access, computer viruses, and other cyberattacks.

# TRADEMARKS

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IB(NA)-0300483ENG-H(2401)MEE

MODEL:

MODEL CODE:

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