
TOSVERT VF-AS1/VF-PS1

PID control Instruction Manual

Toshiba Schneider Inverter Corporation

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1. Introduction

VF-AS1 and VF-PS1 have PID control function.

You can select the PID control type for your applications.

Process PID control: For temperature or pressure control of fan and pump, which is performed gently in response to change the speed.

Speed PID control : For speed control of a winder, which is performed at high speed in response to change the speed.

Dancer control : For dancer positioning control of winder system

Stop holding P control: Stop position control function by servo lock. <VF-AS1 only>

Note) See the manual E6581319 for detail of "Stop holding P control".
E6581319: PG feedback board instruction manual

This manual constructs the following.

Chapter 2: Explanation about three PID control types for VF-AS1 and VF-PS1.

Chapter 3: Difference in parameters of three PID control types.

Chapter 4: Explanation about the parameters you need to set for PID control.

Chapter 5: Explanation about the parameters for adjustment.

Chapter 6: Setting about analog input characteristics.

You need to convert the process value and the feedback value into the frequency for PID control.

Chapter 7: Parameter list of PID control.

First, check your PID control type in chapter 2.

And see chapter 3 to 6 for your setting and adjustment.

See chapter 7 for adjustment range of each parameter.

2. PID control function

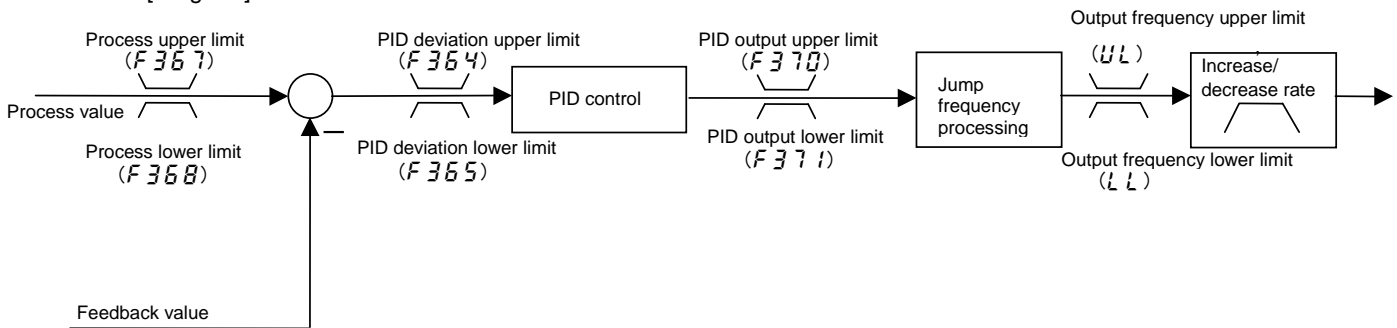
VF-AS1 and VF-PS1 have three types of PID control functions.
You can select the type of PID control for applications by setting parameter.

2.1. Process PID control

Process PID control is selected for temperature or pressure control of fan and pump, which is performed gently in response to change the speed.

[Process PID control (F359= 1)]

[Diagram]



[Parameter setting]

See the chapter 4 and 5 for detail of parameter setting.

1) Select the PID control type.

Title	Function	Setting
F359	PID control switching	1(process PID control)

2) Select the input of process value and feedback value.

You need to convert temperature or pressure into frequency for setting.

Item	Title	Function
Process value	F204	Frequency setting mode selection 1
	F207	Frequency setting mode selection 2
Feedback value	F360	PID control feedback control signal selection

Frequency free unit conversion function enables to set process value and feedback value easily

See the chapter 7 for detail.

3) Set the following parameters to suit the motor if necessary.

Title	Function
FH	Maximum frequency
UL	Upper limit frequency
LL	Lower limit frequency
F270~F275	Jump frequency 1 to 3
F240	Operation starting frequency
F241	Operation starting frequency hysteresis
F243	Stop frequency setting

4) Set the following parameter to suit the system.

- a) Set the acceleration time and deceleration time to small for quick response.
But too small setting cause inverter trip.

Title	Function
<i>ACC</i>	Acceleration time 1
<i>DEC</i>	Deceleration time 1

- b) Set the following parameters if necessary.

Item	Title	Function
Limit the input level of process value.	<i>F367</i>	Process upper limit
	<i>F368</i>	Process lower limit
Limit the PID output.	<i>F370</i>	PID output upper limit
	<i>F371</i>	PID output lower limit
Switc the PID forward /reverse characteristic.	Input terminal function: 54/55: PID forward/reverse switching	
Output of agreement signal between process value and feedback value. <VF-PS1 only>	<i>F374</i>	Frequency command agreement detection range
	Output terminal function: 144 to 149: Frequency command agreement signal (RR/S4, VI,RX)	

5) Adjust the PID control gain.

- a) Fundamental adjustment

Item	Title	Function
PID control gain	<i>F362</i>	Proportional (P) gain
	<i>F363</i>	Integral (I) gain
	<i>F365</i>	Differential (D) gain

- b) Adjust the following parameters if necessary.

Deviation means difference between process value and feedback value.

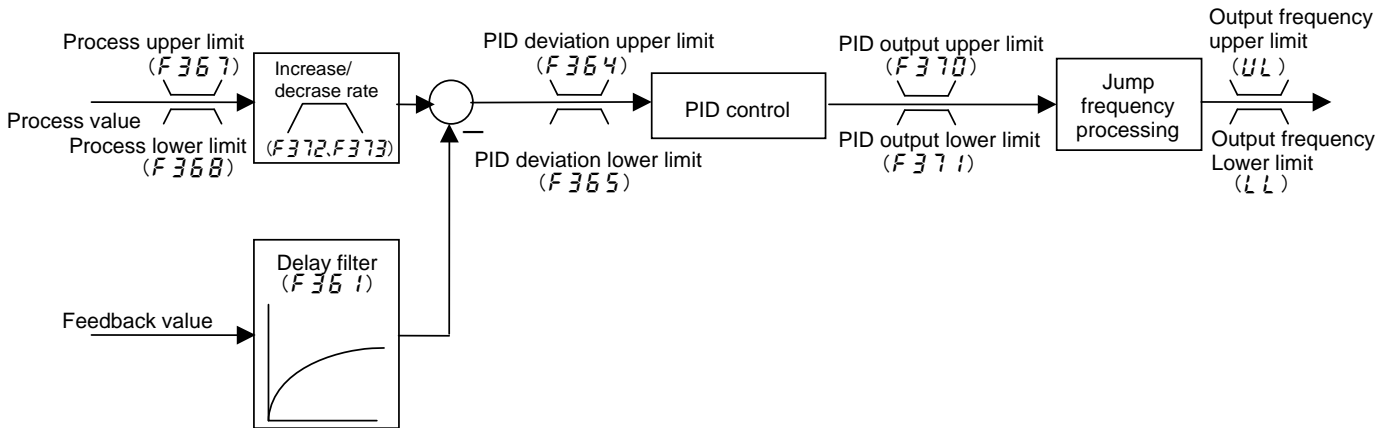
Item	Title	Function
Steady the PID control. (Limit the PID deviation)	<i>F364</i>	PID deviation upper limit
	<i>F365</i>	PID deviation lower limit
Start the PID control after the system become stable.	<i>F369</i>	PID control waiting time

2.2. Speed PID control

Speed PID control is selected for speed control of a winder, which is performed at high speed in response to change the speed.

[Speed PID control (F359=2)]

[Diagram]



[Parameter setting]

See the chapter 4 and 5 for detail of parameter setting.

- 1) Select the PID control type.

Title	Function	Setting
F359	PID control switching	2(speed PID control)

- 2) Select the input of process value and feedback value.

You need to convert tension level into frequency for setting.

Item	Title	Function
Process value	F004	Frequency setting mode selection 1
	F207	Frequency setting mode selection 2
Feedback value	F360	PID control feedback control signal selection

- a) Frequency free unit conversion function enables to set process value and feedback value easily
See the chapter 7 for detail.
- b) You can select the feedback signal by PG feedback.
*You need PG feedback option.
- c) You can add or multiply for process value by override function.

Item	Title	Function
Addition	F550	Override addition input selection
Multiplication	F551	Override multiplication input selection

- 3) Set the following parameters to suit the motor if necessary.

Title	Function
FH	Maximum frequency
UL	Upper limit frequency
LL	Lower limit frequency

<i>F270~F275</i>	Jump frequency 1 to 3
<i>F240</i>	Operation starting frequency
<i>F241</i>	Operation starting frequency hysteresis
<i>F243</i>	Stop frequency setting

4) Set the following parameters to suit the system.

Speed PID control set the acceleration time and the deceleration time to the smallest automatically in spite of parameter(*ACC,DEC*) setting.

The quick response is enabled by process increase and decrease rate separated from acceleration time and deceleration time.

Set the following parameters if necessary.

Item	Title	Function
Limit the input level of process value.	<i>F367</i>	Process upper limit
	<i>F368</i>	Process lower limit
Limit the PID output.	<i>F370</i>	PID output upper limit
	<i>F371</i>	PID output lower limit
Switc the PID forward /reverse characteristic.	Input terminal function: 54/55: PID forward/reverse switching	
Output of agreement signal between process value and feedback value. <VF-PS1 only>	<i>F374</i>	Frequency command agreement detection range
	Output terminal function: 144 to 149: Frequency command agreement signal	

5) Adjust the PID control gain.

See the section 5 for detail.

a) Fundamental adjustment

And adjust for stability and quick response.

Deviation means difference between process value and feedback value.

Item	Title	Function
PID control gain	<i>F362</i>	Proportional (P) gain
	<i>F363</i>	Integral (I) gain
	<i>F366</i>	Differential (D) gain
Steady the PID control (Feedback filter)	<i>F361</i>	Delay filter
Steady the PID control. (Limit the PID deviation)	<i>F364</i>	PID deviation upper limit
	<i>F365</i>	PID deviation lower limit
Adjust for quick response	<i>F372</i>	Process increasing rate (speed type PID control)
	<i>F373</i>	Process decreasing rate (speed type PID control)

b) Adjust the following parameters if necessary.

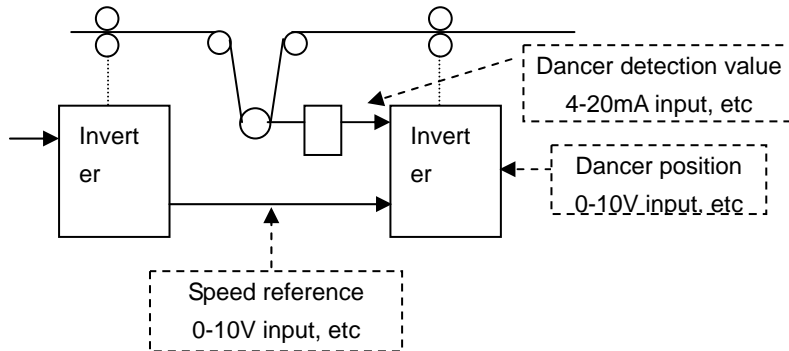
Item	Title	Function
Start the PID control after the system become stable.	<i>F369</i>	PID control waiting time

2.3. Dancer control

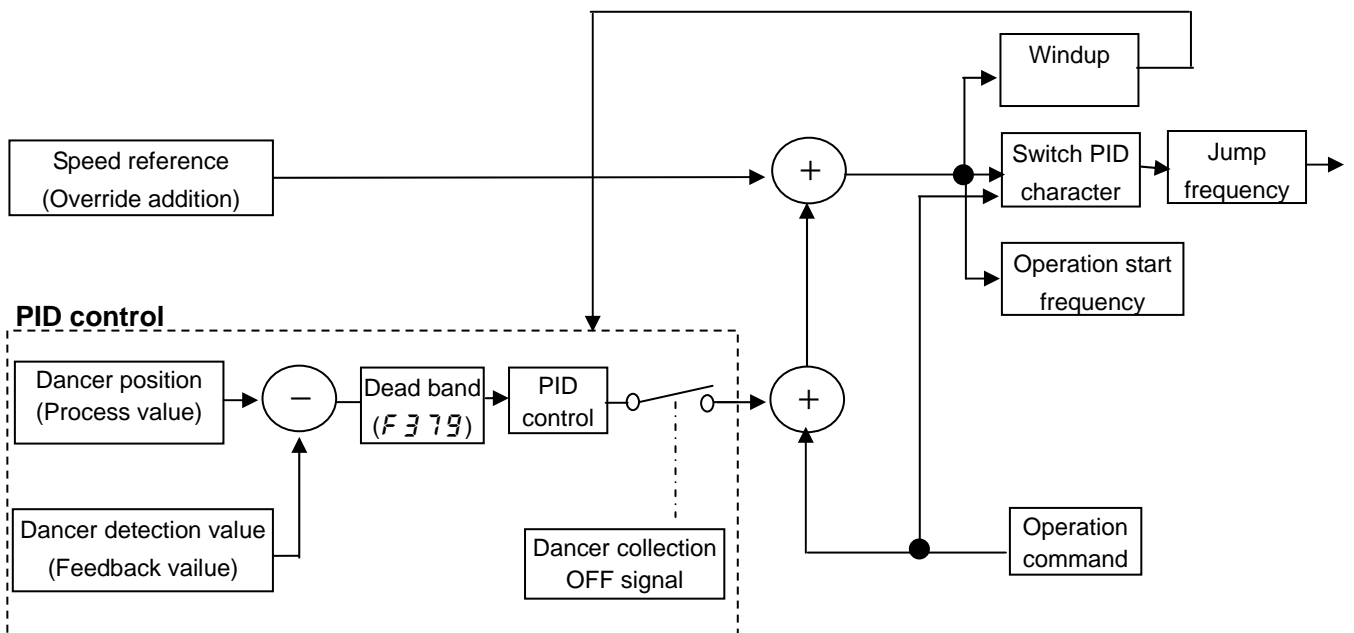
Dancer control is selected for dancer positioning control of winder system.

[Dancer control (F 3 5 9=4)]

[System image]



[Diagram]



[Dancer control operation]

- 1) Inverter operates by speed reference.
*Dancer control use override addition function for speed reference.
- 2) PID control: Process value; dancer position
Feedback value; dancer detection value
Correct speed reference by deviation of PID control for dancer.
Set the dead band (*F 3 7 9*) for the deviation if necessary.
- 3) Set the dancer correction OFF signal to input terminal if necessary.
In case the input terminal ON, the PID output is zero. The speed reference is override addition value.

Windup: If the value after override addition become following, inverter control stop the integration.

- (1) Upper limit (*U L*) or more
Maximum frequency (*F H*) or more
- (2) Lower limit (*L L*) or less
Clear the windup process by deviation value of PID control.

[Parameter setting]

See the chapter 4 and 5 for detail of parameter setting.

- 1) Select the PID control type.

Title	Function	Setting
<i>F 3 5 9</i>	PID control switching	4(dancer control)

- 2) Set the speed reference as override addition.

Item	Title	Function
Addition	<i>F 5 5 0</i>	Override addition input selection

*You can set override multiplication (*F 5 5 1*) instead of *F 5 5 0*, but it is difficult to set.
Use *F 5 5 0* please.

- 3) Select the input of process value (dancer position) and feedback value (dancer detection value).
Set each level converted into frequency for the setting.
Set the dead band for deviation of PID control if necessary.

Item	Title	Function
Process value	<i>F 0 0 4</i>	Frequency setting mode selection 1
	<i>F 2 0 7</i>	Frequency setting mode selection 2
Feedback value	<i>F 3 6 0</i>	PID control feedback control signal selection
PID output dead band	<i>F 3 7 9</i>	PID output dead band

*Frequency free unit coversion function enables to set process value and feedback value easily
See the chapter 7 for detail

- 4) Set the following parameters to suit the winder system if necessary.

Item	Title	Function
Operation by speed reference only (Dncer correction OFF)		Input terminal function: 94/95: Dancer correction OFF
Prohibit the reverse-run	<i>F 3 1 1</i>	Reverse- run prohibition selection

- 5) Set the following parameters to suit the motor if necessary.

Title	Function
<i>F H</i>	Maximum frequency
<i>U L</i>	Upper limit frequency
<i>L L</i>	Lower limit frequency
<i>F 2 7 0 ~ F 2 7 5</i>	Jump frequency 1 to 3
<i>F 2 4 0</i>	Operation starting frequency

<i>F241</i>	Operation starting frequency hysteresis
<i>F243</i>	Stop frequency setting

6) Set the following parameters to suit the system.

- a) Set the acceleration time and the deceleration time to small for quick response.
But too small setting cause inverter trip.

Title	Function
<i>ACC</i>	Acceleration time 1
<i>DEC</i>	Deceleration time 1

b) Set the following parameters if necessary.

Item	Title	Function
Limit the input level of process value.	<i>F367</i>	Process upper limit
	<i>F368</i>	Process lower limit
Limit the PID output.	<i>F370</i>	PID output upper limit
	<i>F371</i>	PID output lower limit
Switc the PID forward /reverse characteristic.	Input terminal function: 54/55: PID forward/reverse switching	
Output of agreement signal between process value and feedback value. <VF-PS1 only>	<i>F374</i>	Frequency command agreement detection range
	Output terminal function: 144 to 149: Frequency command agreement signal	

7) Adjust the PID control gain.

a) Fundamental adjustment

Item	Title	Function
PID control gain	<i>F362</i>	Proportional (P) gain
	<i>F363</i>	Integral (I) gain
	<i>F365</i>	Differential (D) gain

b) Adjust the following parameters if necessary.

Deviation means difference between process value and feedback value.

Item	Title	Function
Steady the PID control. (Limit the PID deviation)	<i>F364</i>	PID deviation upper limit
	<i>F365</i>	PID deviation lower limit
Start the PID control after the system become stable.	<i>F369</i>	PID control waiting time

3. PID control type and parameters

The following is parameters for PID control.

Valid parameters are different from each PID control types, Process PID control, Speed PID control and Dancer control.

* Override function of dancer control is different from the others.

Title	Function	PID control type ○: valid ×: invalid △: *1		
		Process type	Speed type	Dancer control
<i>F00d</i>	Frequency setting mode selection 1	○	○	○
<i>FH</i>	Maximum frequency	○	○	○
<i>UL</i>	Upper limit frequency	○	○	○
<i>LL</i>	Lower limit frequency	○	○	○
<i>ACC</i>	Acceleration time 1	○	×	○
<i>DEC</i>	Deceleration time 1	○	×	○
<i>F207</i>	Frequency setting mode selection 2	○	○	○
<i>F240</i>	Operation starting frequency	○	○	○
<i>F241</i>	Operation starting frequency hysteresis			
<i>F243</i>	Stop frequency setting	○	○	○
<i>F270</i>	Jump frequency 1	○	○	○
<i>F271</i>	Jump step 1	○	○	○
<i>F272</i>	Jump frequency 2	○	○	○
<i>F273</i>	Jump step 2	○	○	○
<i>F274</i>	Jump frequency 3	○	○	○
<i>F275</i>	Jump step 3	○	○	○
<i>F311</i>	Reverse- run prohibition selection	○	○	○
<i>F359</i>	PID control switching	○	○	○
<i>F360</i>	PID control feedback control signal selection	○	○	○
<i>F361</i>	Delay filter	×	○	×
<i>F362</i>	Proportional (P) gain	○	○	○
<i>F363</i>	Integral (I) gain	○	○	○
<i>F364</i>	PID deviation upper limit	○	○	○
<i>F365</i>	PID deviation lower limit	○	○	○
<i>F366</i>	Differential (D) gain	○	○	○
<i>F367</i>	Process upper limit	○	○	○
<i>F368</i>	Process lower limit	○	○	○
<i>F369</i>	PID control waiting time	○	○	○
<i>F370</i>	PID output upper limit	○	○	○
<i>F371</i>	PID output lower limit	○	○	○
<i>F372</i>	Process increasing rate (speed type PID control)	×	○	×
<i>F373</i>	Process decreasing rate (speed type PID control)	×	○	×
<i>F374</i>	Frequency command agreement detection range <VF-PS1 only>	○	○	○
<i>F379</i>	PID output dead band	×	×	○
<i>F660</i>	Override addition input selection	△	○ (Valid for process value)	○ (Speed reference)
<i>F661</i>	Override multiplication input selection	△		△

F 702	Frequency free unit display magnification	○	○	○
F 703	Frequency free unit conversion selection	○	○	○
F 729	Operation panel override multiplication gain <VF-AS1 only>	○	○	△

[Input/output terminal function]

Terminal	Function	PID control type ○: valid ×: invalid △: *1		
		Process type	Speed type	Dancer control
Input terminal	PID control OFF selection	○	○	○
	PID differentiation/integration reset	○	○	○
	PID forward/reverse switching	○	△	△
	Dancer correction OFF	×	×	○
Output terminal	PID deviation limit	○	○	○
	Frequency command agreement signal (RR/S4) *2	○	○	○
	Frequency command agreement signal (VI) *2	○	○	○
	Frequency command agreement signal (RX) *2	○	○	○

[FM/AM pulse output and monitor output function]

Function		PID control type ○: valid ×: invalid △: *1		
FM/AM/pulse output	Monitor output	Process type	Speed type	Dancer control
Frequency command value		○	○	○
Speed feedback (real time value)		○	○	○
Speed feedback (1-second filter)		○	○	○
PID feedback value		○	○	○
—	PID result frequency	○	○	○
—	Synchronous speed frequency command	×	×	○

*1: The functions are valid, but it is not used actually.

*2: VF-PS1 only

4. Setting for PID control

First, set the process value and feed back value. : 4.1
 Then, set other parameters to suit the motor and the system if necessary. : 4.2, 4.3

Note) It is necessary to convert the process value and feedback value into frequency for setting.
 Actual output frequency is different from setting frequency of PID control.

4.1. Fundamental setting

You need to set process value and feedback value.
 In case of process type PID control and dancer control, you need to set the acceleration time and the deceleration time to small for quick response.

4.1.1. Feedback value

Input the signal from detector as feedback signal.

1. Select the feedback input from *F 3 5 0*.

Description	PID control feedback control signal selection (<i>F 3 5 0</i>)
Deviation input (no feedback input)	0
VI/II (voltage/current input)	1
RR/R4 (potentiometer/voltage input)	2
RX (voltage input)	3
Option AI1 (differential current input)	4
Option AI2 (voltage/current input)	5
PG feedback option	6

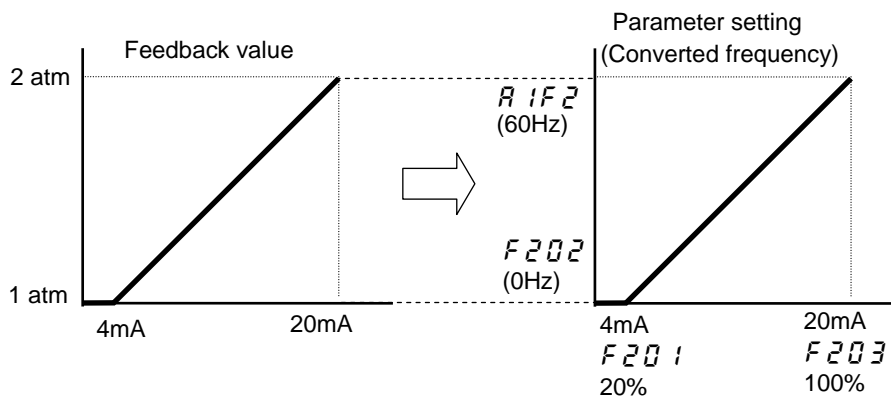
2. Convert the feedback input level into frequency, and set it.

- 1) Analog input
 See the chapter 6 for detail of analog input characteristic setting.

[Example of feedback setting]

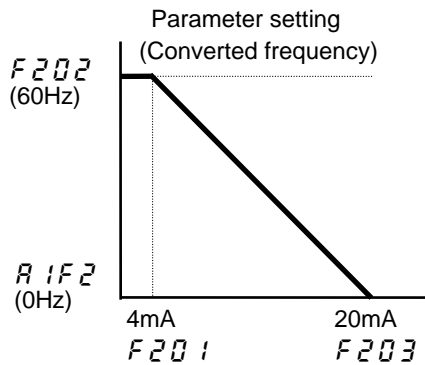
Condition: Pressure control as PID control

Input the feedback signal of 1 to 2 atm into VI/II terminal by 4 to 20mA signal.



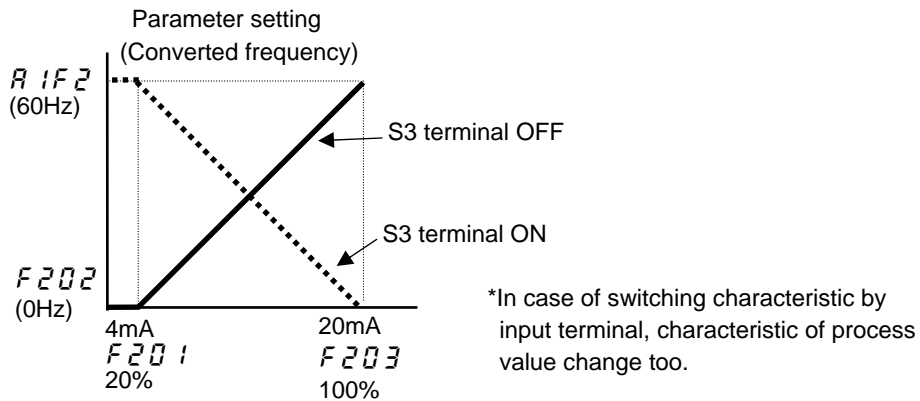
You can set the reverse characteristic or switch the characteristic.

a) Example of reverse characteristic setting



1

b) Example of switching characteristic by S3 input terminal (positive logic)



Title	Function	Example of setting
$R1F2$	VI/II input point 2 frequency	60(Hz)
$F117$	Input terminal function selection 7 (S3)	54: PID forward/reverse switching
$F201$	VI/II input point 1 setting	20(%)
$F202$	VI/II input point 1 frequency	0(Hz)
$F203$	VI/II input point 2 setting	100(%)

2) Optional terminal input

You can input the signal into optional terminals as same as analog input.

See the section 6 for detail of input characteristic setting.

AI1: differential current input

AI2: voltage / current input

3) PG feedback input

It is used in speed PID control mainly.

Input by single-phase pulse in case of PG feedback for PID control.

Set Pf (V/f control mode selection) except 7: PG feedback control and R : PG feedback vector control<VF-AS1 only>.

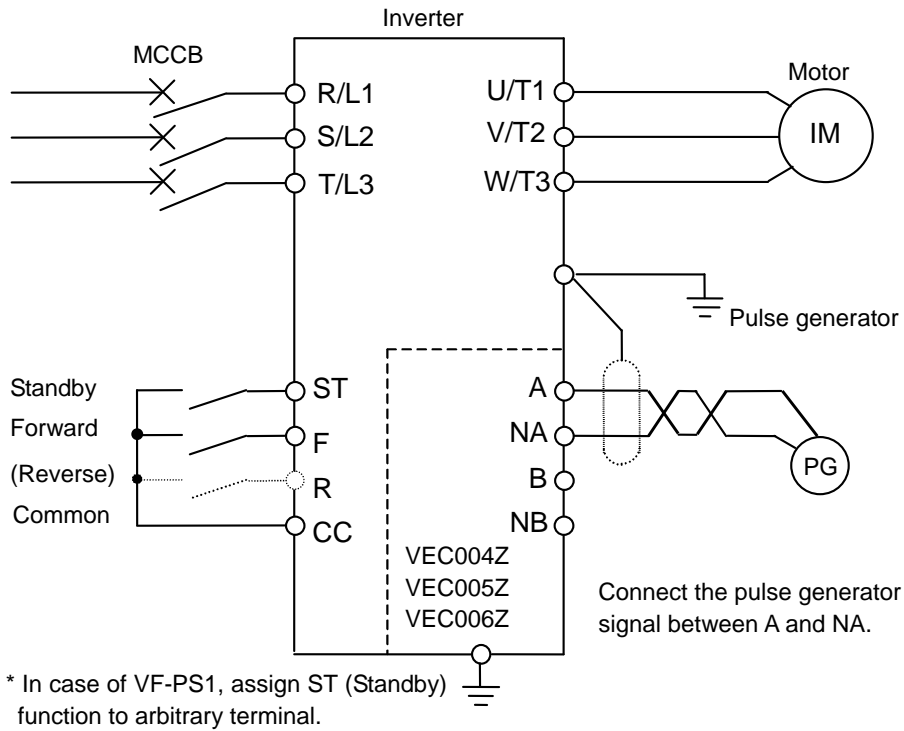
See the manual E6581319 for detail of PG feedback option.

E6581319: PG feedback board instruction manual

[Example of PG feedback input]

a) Connection example

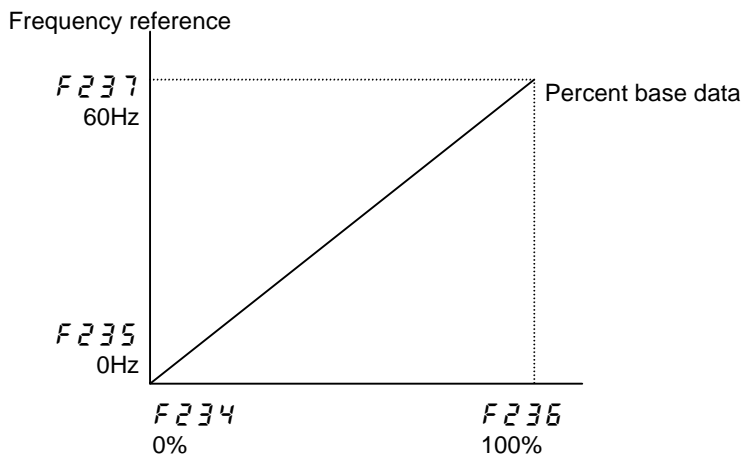
Connect single-phase pulse signal to A-NA terminals of PG feedback board option.



b) Parameter setting

Calculate the input pulse frequency to percent base data by the following.
Set the parameters of 2 input points.

$$\text{Percent base data} = \frac{\text{Input pulse frequency}}{\text{PG input pulse} \times \text{Maximum frequency}} \times 100(\%)$$



Title	Function	Adjustment range	Setting (Example)
<i>FH</i>	Maximum frequency	30.0~500.0	60.0 (Hz)
<i>F234</i>	RP/high speed pulse input point 1 setting	0 ~ 100	0(%)
<i>F235</i>	RP/high speed pulse input point 1 frequency	0.0 ~ <i>FH</i>	0.0(Hz)
<i>F236</i>	RP/high speed pulse input point 2 setting	0 ~ 100	100 (%)
<i>F237</i>	RP/high speed pulse input point 2 frequency	0.0 ~ <i>FH</i>	60.0(Hz)
<i>F375</i>	Number of PG input pulses	12 ~ 9999	500
<i>F376</i>	Selection of number of PG input phase	1: Single-phase input 2: Two-phase input 3: Two-phase input (Inversion of polarity)	1
<i>F377</i>	PG disconnection detection	1: Disabled 2: Enabled (with filter) 3: Enabled (Detection of momentary power failure)	1

Note) In case of using shaft built-in type PG, set the RP/high speed pulse input point 2 to a multiple number of "1/ (a half number of motor poles)".
For example, set *F236* =50(%) in case of using shaft built-in type PG with 4-poles motor.

c) Previous check

You can check frequency reference from pulse input by monitor function previously.

Set the monitor selection to 1: frequency command.

See the section 8 of inverter instruction manual for the detail of monitor function.

4.1.2. Process value

Input the target value against the feedback value as process value.

1. Select the process value input from parameter *F 00 d* or *F 20 7*.

Description	Frequency setting mode selection 1 (<i>F 00 d</i>) Frequency setting mode selection 2 (<i>F 20 7</i>)
VI/II (voltage/current input)	1
RR/S4 (potentiometer/voltage input)	2
RX (voltage input)	3
Operation panel input enabled (including LED/LCD panel option input)	4
Operation panel RS485 (2-wire) communication input	5
Internal RS485 (4-wire) communication input	6
Communications option input	7
Optional AI1 (differential current input)	8
Optional AI2 (voltage/current input)	9
UP/DOWN frequency	10
Optional RP pulse input	11
Optional High-speed pulse input	12
-	13

Speed type

You can add or multiply for process value by override function.

Note) Dancer control use override addition function for speed reference.

2. Convert the feedback input level into frequency, and set it.

<Note>

You need to input the process value less than maximum of feedback value.

If the process value is setted maximum of feedback value or more, the feedback value reaches maximum and the deviation becomes zero. The output frequency is fixed because the feedback value does not become high level anymore.

You can set upper limit of process value input by parameter *F 36 7*: Process upper limit.

- 1) Analog input

See the chapter 6 for detail of analog input characteristic setting.

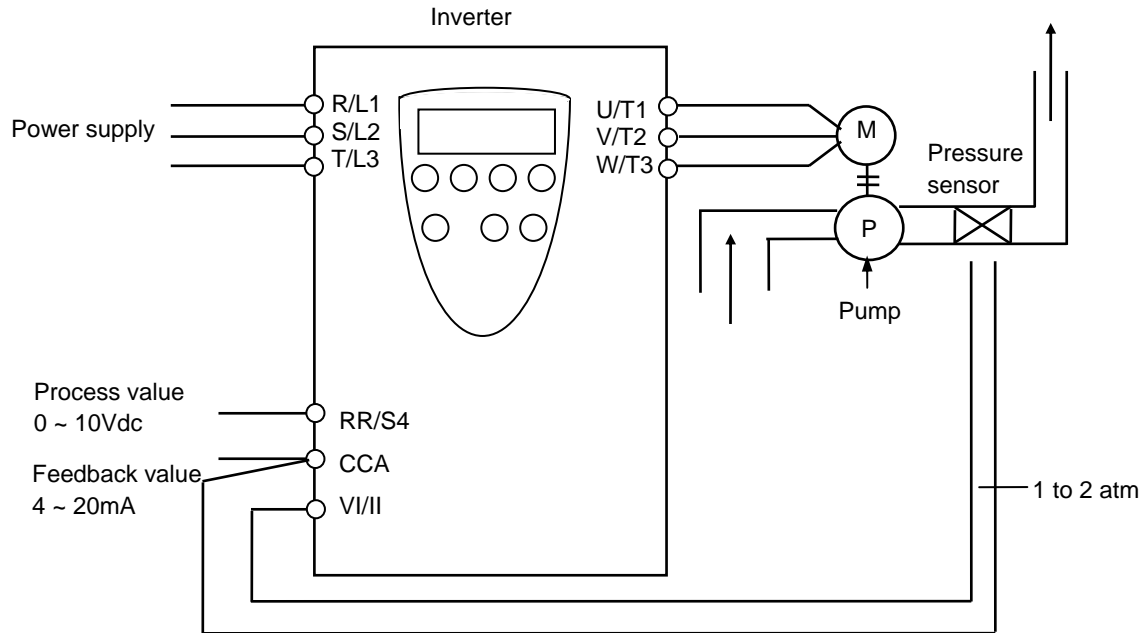
[Example of process value setting]

Condition: Pressure control as PID control

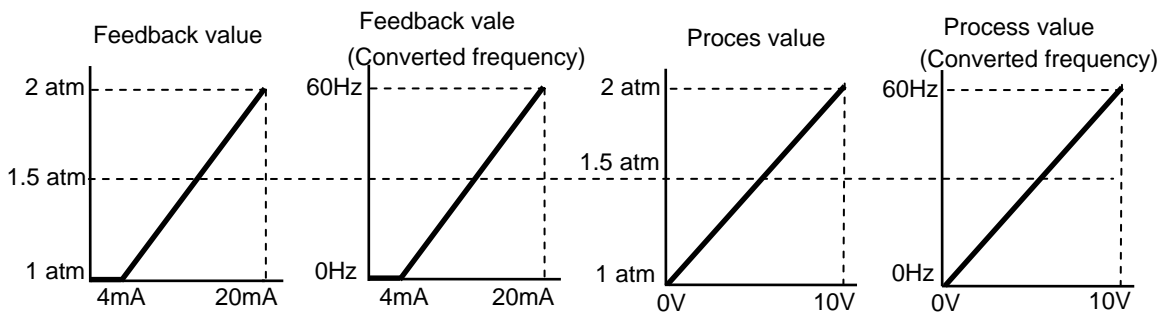
Input the feedback signal of 1 to 2 atm into VI/II terminal by 4 to 20mA signal.

Input the process value into RR/S4 terminal by 0 to 10V signal.

a) Example of system



b) Parameter setting



Pressure (atm)	Feedback value (4~20mA)	Process value (0~10V)	Converted frequency (Hz)
1	4	0	0
1.25	8	2.5	15
1.5	12	5.0	30
1.75	16	7.5	45
2	20	10	60

Convert the feedback value and process value to frequency, and set each level.

Actual output frequency is different from these setting frequencies.

Note)

You need to input the process value less than maximum of feedback value.

For example, if you input the process value as 2 atm=10V(60Hz), the feedback value reaches 2 atm=20mA(60Hz) and deviation becomes zero. The feedback value can not exceed 20mA(60Hz) even if the output becomes high level. Then output frequency is fixed.

Title	Function	Setting (Example)
<i>RvF2</i>	RR/S4 input point 2 frequency	60(Hz)
<i>R1F2</i>	VI/II input point 2 frequency	60(Hz)
<i>F108</i>	Analog iVI/II voltage/current switching	1:
<i>F201</i>	VI/II input point 1 setting	20(%)
<i>F202</i>	VI/II input point 1 frequency	0(Hz)
<i>F203</i>	VI/II input point 2 setting	100(%)
<i>F210</i>	RR/S4 input point 1 setting	0(%)
<i>F211</i>	RR/S4 input point 1 frequency	0(Hz)
<i>F212</i>	RR/S4 input point 2 setting	100(%)

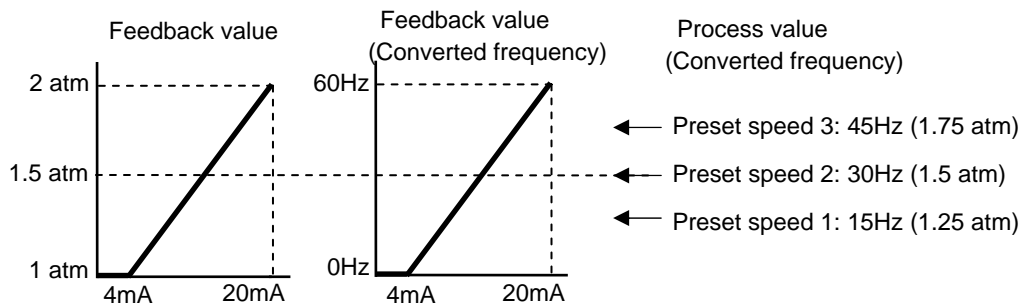
2) Preset speed

[Example of process value setting]

Condition: Pressure control as PID control

Input the feedback signal of 1 to 2 atm into VI/II terminal by 4 to 20mA signal.

Input the process value into S1 and S2 terminals by preset speed (3 preset speeds) setting.



Pressure (atm)	Feedback value (4~20mA)	Process value			Converted frequency (Hz)
		Preset speed 1 to 3	S1 terminal	S2 terminal	
1	4	-	-	-	0
1.25	8	1	ON	OFF	15
1.5	12	2	OFF	ON	30
1.75	16	3	ON	ON	45
2	20	-	-	-	60

Title	Function	Setting (Example)
<i>R1F2</i>	VI/II input point 2 frequency	60(Hz)
<i>Sr1</i>	Preset speed operation frequency 1	15(Hz)
<i>Sr2</i>	Preset speed operation frequency 2	30(Hz)
<i>Sr3</i>	Preset speed operation frequency 3	45(Hz)
<i>F108</i>	Analog iVI/II voltage/current switching	1: Current input
<i>F115</i>	Input terminal function selection 5 (S1)	10: Preset speed 1
<i>F116</i>	Input terminal function selection 6 (S2)	12: Preset speed 2
<i>F201</i>	VI/II input point 1 setting	20(%)
<i>F202</i>	VI/II input point 1 frequency	0(Hz)
<i>F203</i>	VI/II input point 2 setting	100(%)

Note) You need to input the process value less than maximum of feedback value.

4.1.3. Override function

Speed type

You can add or multiply for process value by override function (*F 660, F 661*).

<VF-AS1 only>

Multiplication gain is able to set by parameter *F 729*.

See the inverter instruction manual for the detail of the setting.

* The functions are valid for process type PID control, but it is not used actually.

Dancer control

Dancer control uses override addition function (*F 660*) for speed reference.

4.1.4. Acceleration and deceleration time

Process type

Dancer control

Set the acceleration time (*ACC*) and the deceleration time (*DEC*) to small for quick response.

But too small setting cause inverter trip.

Speed type

Speed PID control set the acceleration time and the deceleration time to the smallest automatically in spite of parameter(*ACC, DEC*) setting.

*Adjust each gain in case of inverter trip. If you need to set the acceleration time and the deceleration time larger, change the process type PID control.

4.2. Set to suit the motor

Set the following parameters to suit the motor if necessary.

These parameters are valid for actual output frequency (result of PID control).

Title	Function	Discription
<i>FH</i>	Maximum frequency	1) Set the maximum frequency of output frequency. 2) It is base of the acceleration time (<i>ACC</i>) and the deceleration time (<i>DEC</i>). Acceleration time (<i>ACC</i>) is from 0Hz to <i>FH</i> . Deceleration time (<i>DEC</i>) is from <i>FH</i> to 0Hz.
<i>UL</i>	Upper limit frequency	It is upper limit of output frequency.
<i>LL</i>	Lower limit frequency	It is lower limit of output frequency.
<i>F270~ F275</i>	Jump frequency 1 to 3	Set the jump frequency to avoid (jump) resonance frequency of machinery if necessary.
<i>F240</i>	Starting frequency setting	1) Inverter output the frequency setted by <i>F240</i> immediately. 2) It is useful for quick response of starting torque.
<i>F241</i>	Operation start frequency	Inverter operates RUN and STOP by <i>F241</i> setting frequency
<i>F243</i>	Stop frequency setting	The output frequency is dropped to 0Hz at the frequency setted by <i>F243</i> .

4.3. Set to suit the system

4.3.1. Set if necessary

Set the following parameters if necessary.

Title	Function	Discription
<i>F367</i>	Process upper limit	1) It is upper limit of process value. 2) It is necessary to input the process value less than maximum of feedback value. If the process value is setted maximum of feedvack value or more, the feedback value reaches maximum and the deviation becomes zero. The output frequency is fixed because the feedback value does not become high level anymore. Set the upper limit of process value input by this parameter if necessary.
<i>F368</i>	Process lower limit	It is lower limit of process value.
<i>F370</i>	PID output upper limit	It is upper limit of output frequency by PID control.
<i>F371</i>	PID output lower limit	It is lower limit of output frequency by PID control.

4.3.2. Switch PID characteristic

It is used in process PID control mainly.

You can switch the PID forward / reverse characteristic,for example cooler and heater.

[Input terminal function]

Positive logic	Negative logic	Function	Discription (Positiv logic)
54	55	PID forward/reverse switching	Switch the PID forward / reverse characteristic of process value and feedback value.

4.3.3. Agreement between process and feedback value

<VF-PS1 only>

Inverter can output agreement signal between the process value and the feedback value.

Select the output terminal function number for each input terminal (RR/S4,VI/II,RX) of feedback value.

Title	Function	Discription
<i>F374</i>	Frequency command agreement detection range	Set the PID frequency command agreement detection. range :0.0~ <i>FH</i> (Hz).

[Output teiminal function]

Positive logic	Negative logic	Function	Discription (Positiv logic)
144	145	Frequency command agreement signal (RR/S4)	Frequency command agreement between <i>FND</i> (or <i>F207</i>) and RR/S4 input.
146	147	Frequency command agreement signal (VI)	Frequency command agreement between <i>FND</i> (or <i>F207</i>) and VI input.
148	149	Frequency command agreement signal (RX)	Frequency command agreement between <i>FND</i> (or <i>F207</i>) and RX input.

4.3.4. Switch to frequency command operation

Process type Speed type

You can switch from PID control to frequency command operation (not PID control) by input terminal signal.

- a) Inverter operates with frequency reference setted by process value.
- b) The acceleration time and the deceleration time are setted small for quick response in case of process PID control.

You can set second acceleration time and deceleration time if necessary for frequency command operation.

[Input terminal function]

Positive logic	Negative logic	Function	Discription (Positiv logic)
36	37	PID control OFF selection	Switch to frequency command operation after PID control OFF

5. PID control adjustment

5.1. Outline of adjustment

If you have an aim of PID control gain, set each gain and check the working of your system. Adjust the gain only if necessary.

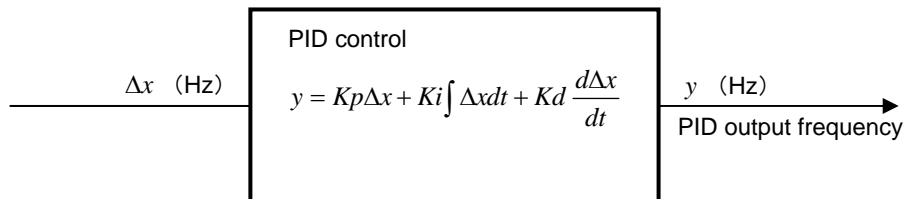
If you don't have an aim of PID control gain, adjust in order of the following.

- 1) First, operate in default setting and check the working of your system.
- 2) Adjust the fundamental adjustment.
 - a) Adjust the proportional (P) gain first if the response speed delay.
 - b) Adjust the integral (I) gain if the unstable situation continues.
 - c) Adjust the differential (D) gain if the unstable situation continues after adjustment of PI gains or the load fluctuates large continuously.
- 3) Adjust the applied adjustment for stability if necessary.

*Set the delay filter for stability of the speed PID control.

5.2. Fundamental adjustment (common)

Adjust the PID control fundamental gain.

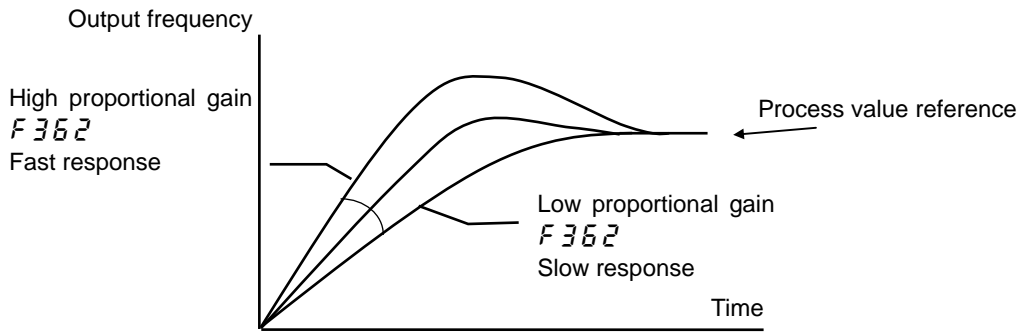


Symbol	Title	Function	Setting value
K_p	F 3 5 2	Proportional (P) gain	F 3 5 2=1.0: $K_p=1.0$
K_i	F 3 5 3	Integral(I) gain	F 3 5 3=1.0: $K_i=1.0$ (1/s)
K_d	F 3 5 6	Differential (D) gain	F 3 5 6=1.0: $K_d=1.0$ (s)

5.2.1. Proportional (P) gain

Set the proportional (P) gain of PID control by *F 362*.

The proportional (P) gain, a factor by which the deviation (difference between the process value and the feedback value) is multiplied, is used to perform control in such a way as to make a correction in proportion to the deviation. Although setting this gain high is effective in increasing the response speed, setting it excessively high may cause an unstable operation, such as vibration.

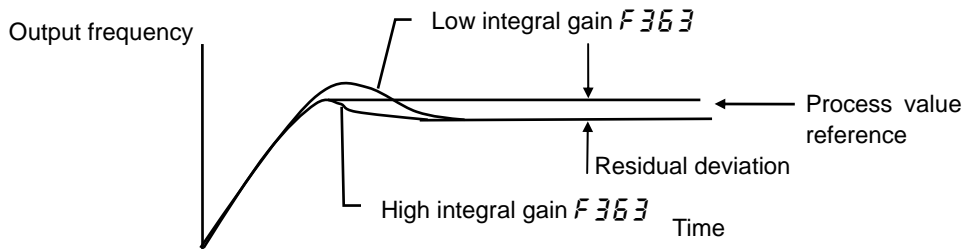


5.2.2. Integral (I) gain

Set the integral (I) gain of PID control by *F 363*.

The integral gain reduces the deviation remaining after proportional control to zero (offsetting of residual deviation).

Although setting this gain high is effective in reducing the residual deviation, setting it excessively high may cause an unstable operation, such as vibration.

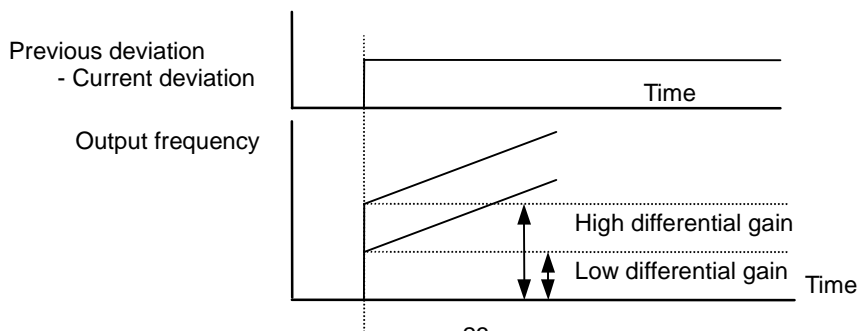


5.2.3. Differential (D) gain

Set the differential (D) gain of PID control by *F 365*.

The differential gain increases the speed of response to rapid changes in deviation.

If this gain is set excessively high, a phenomenon in which the output frequency greatly fluctuates may occur.



5.3. Applied adjustment (Common)

Adjust the following for stability if necessary.

5.3.1. PID deviation upper limit and lower limit

Limit the PID deviation momentarily for stability. (It is not necessary to change under normal conditions.)

Inverter can output the signal in case of the deviation level within the limit setting.

Title	Function	Discription
<i>F 364</i>	PID deviation upper limit	It is upper limit of deviation increase (+).
<i>F 365</i>	PID deviation lower limit	It is lower limit of deviation decrease (-).

[Output terminal function]

Positive logic	Negative logic	Function	Discription (Positiv logic)
38	39	PID deviation limit	In case of the PID deviation level between <i>F 364</i> and <i>F 365</i> .

5.3.2. PID differentiation / integration reset

You can reset the PID differentiation value and integration value by input terminal signal.

[Input terminal function]

Positive logic	Negative logic	Function	Discription (Positiv logic)
52	53	PID differentiation/ integration reset	Reset the PID differentiation value and integration value.

5.3.3. PID control waiting time

You can set the waiting time before PID control start.

It is useful in case the system is not steady at start, etc.

Title	Function	Discription
<i>F 369</i>	PID control waiting time	Inverter operates with frequency reference setted by process value within <i>F 369</i> setting time. After <i>F 369</i> setting time, switch the PID control mode.

5.4. Applied adjustment (for speed PID control)

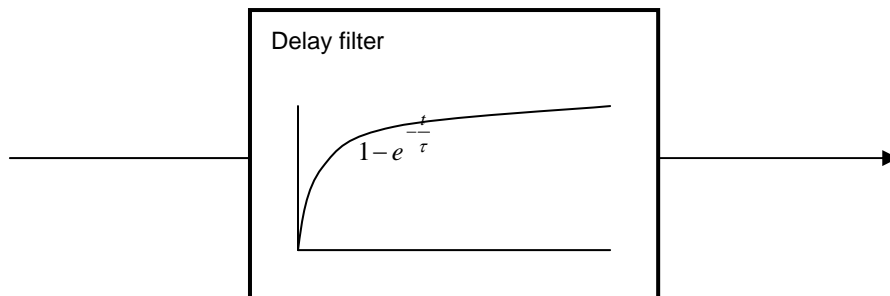
Adjust the following for stability of speed PID control if necessary.

5.4.1. Delay filter

The delay filter set with $F361$ moderates changes in deviation (primary delay control).

Large setting cause processing speed delay for stability of the control.

(It is not necessary to change under normal conditions.)

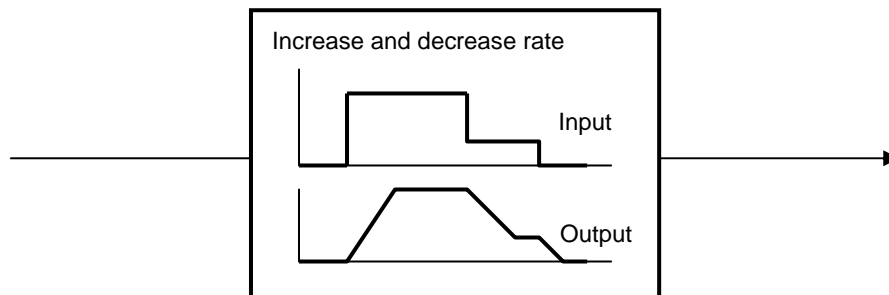


Symbol	Title	Function	Setting value
τ	$F361$	Delay filter	$F361=1.0: \tau=1.0$ (s)

5.4.2. Process increasing rate/ decreasing rate

Set the $F372$ and $F373$ to small for quick response if necessary.

It is effective for response of feedback value.

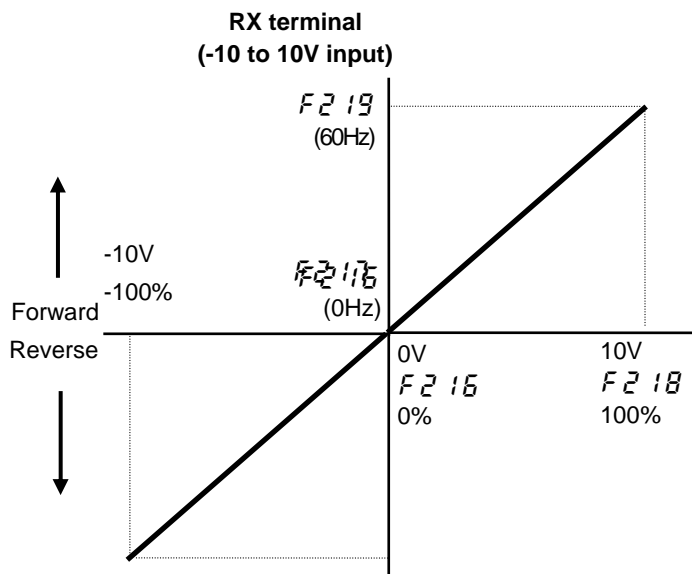
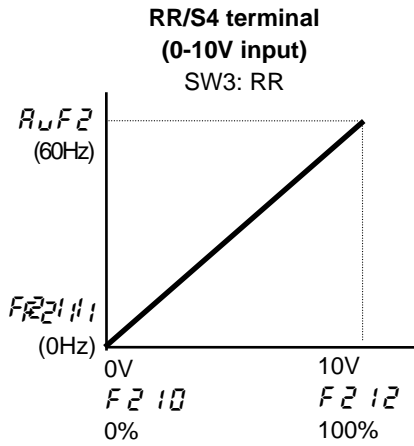
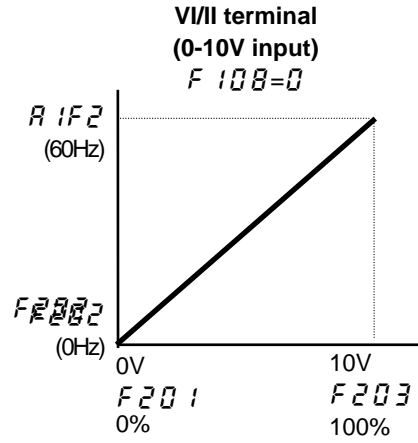
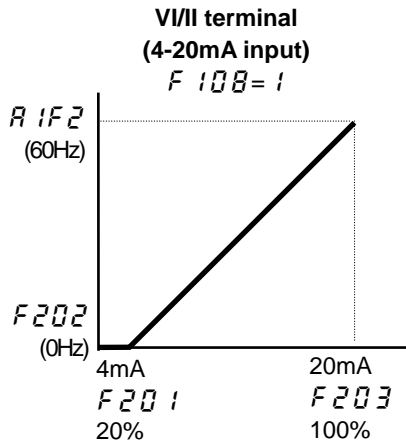


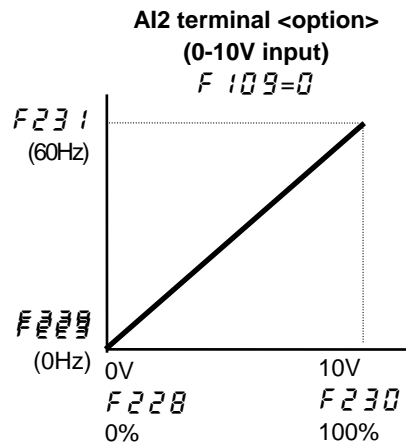
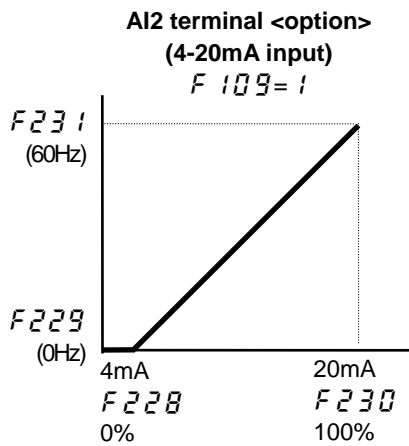
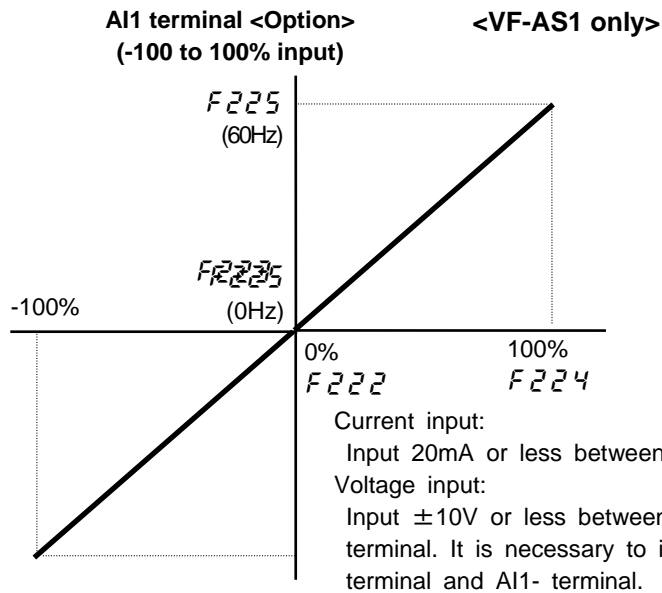
Symbol	Title	Setting value
$F372$	Process increasing rate (speed type PID control)	$F372=1.0$: Increase reference from 0Hz to FH (Maximum frequency) in 1.0 sec
$F373$	Process decreasing rate (speed type PID control)	$F373=1.0$: Decrease reference from FH (Maximum frequency) to 0Hz in 1.0 sec

6. Analog input characteristics

Set the analog input characteristics in case the feedback value and the process value input by the analog input terminals.

*The following examples are setting from 0 to 60Hz





7. Parameter list of PID control

Title	Function	Adjustment range	Default setting
<i>FNDd</i>	Frequency setting mode selection 1	1: VI/II (voltage/current input) 2: RR/S4 (potentiometer/voltage input) 3: RX (voltage input) 4: Operation panel input enabled (including LED/LCD panel option input) 5: Operation panel RS485 (2-wire) communications input 6: Internal RS485 (4-wire) communications input 7: Communications option input 8: Optional AI1 (differential current input) 9: Optional AI2 (voltage/current input) 10: UP/DOWN frequency 11: Optional RP pulse input 12: Optional High-speed pulse input 13: -	2
<i>FH</i>	Maximum frequency	30.0~500.0 (Hz)	80.0
<i>UL</i>	Upper limit frequency	0.0~ <i>FH</i> (Hz)	60.0
<i>LL</i>	Lower limit frequency	0.0~ <i>LL</i> (Hz)	0.0
<i>ACC</i>	Acceleration time 1	0.1~6000 (sec.)	Depends on the capacity
<i>DEC</i>	Deceleration time 1	0.1~6000 (sec.)	
<i>F207</i>	Frequency setting mode selection 2	Same as <i>FNDd</i> (1~13)	1
<i>F240</i>	Starting frequency setting	0.0~10.0 (Hz)	0.1
<i>F241</i>	Operation start frequency	0.0~ <i>FH</i> (Hz)	0.0
<i>F243</i>	Stop frequency setting	0.0~30.0 (Hz)	0.0
<i>F270</i>	Jump frequency 1	0.0~ <i>FH</i> (Hz)	0.0
<i>F271</i>	Jump step 1	0.0~30.0 (Hz)	0.0
<i>F272</i>	Jump frequency 2	0.0~ <i>FH</i> (Hz)	0.0
<i>F273</i>	Jump step 2	0.0~30.0 (Hz)	0.0
<i>F274</i>	Jump frequency 3	0.0~ <i>FH</i> (Hz)	0.0
<i>F275</i>	Jump step 3	0.0~30.0 (Hz)	0.0
<i>F311</i>	Reverse-run prohibition selection	0: Permit all 1: Prohibition reverse-run 2: Prohibition forward-run	0
<i>F359</i>	PID control switching	0: No PID 1: Process PID control (temperature, pressure, etc.) 2: Speed PID control (potentials etc.) 3: Stop holding P control 4: Dancer control	0
<i>F360</i>	PID control feedback control signal selection	0: Deviation input (no feedback input) 1: VI/II (voltage/current input) 2: RR/S4 (potentiometer/voltage input) 3: RX (voltage input) 4: Optional AI1 (differential current input) 5: Optional AI2 (voltage/current input) 6: PG feedback option	0
<i>F361</i>	Delay filter	0.0~25.0 (sec.)	0.1
<i>F362</i>	Proportional (P) gain	0.01~100.0	0.10
<i>F363</i>	Integral (I) gain	0.01~100.0 (1/sec.)	0.10
<i>F364</i>	PID deviation upper limit	<i>LL</i> ~ <i>UL</i> (Hz)	60 / 50
<i>F365</i>	PID deviation lower limit	<i>LL</i> ~ <i>UL</i> (Hz)	60 / 50
<i>F366</i>	Differential (D) gain	0.00~2.55	0.00

<i>F367</i>	Process upper limit	<i>LL~UL</i> (Hz)	60 / 50
<i>F368</i>	Process lower limit	<i>LL~UL</i> (Hz)	0.0
<i>F369</i>	PID control waiting time	0~2400 (sec.)	0
<i>F370</i>	PID output upper limit	<i>LL~UL</i> (Hz)	60 / 50
<i>F371</i>	PID output lower limit	<i>LL~UL</i> (Hz)	0.0
<i>F372</i>	Process increasing rate (speed type PID control)	0.1~600.0(s)	10.0
<i>F373</i>	Process decreasing rate (speed type PID control)	0.1~600.0(s)	10.0
<i>F374</i>	Frequency command agreement detection range <VF-PS1 only>	0.0~ <i>FH</i> (Hz)	2.5
<i>F379</i>	PID output dead band	0.0~100(%)	0
<i>F660</i>	Override addition input selection	0: Deselect 1: VI/II (voltage/current input) 2: RR/S4 (potentiometer/voltage input) 3: RX (voltage input) 4: Operation panel input enabled (including LED/LCD panel option input) 5: Operation panel RS485 (2-wire) communications input 6: Internal RS485 (4-wire) communication input 7: Communications option input 8: Optional AI1 (differential current input) 9: Optional AI2 (voltage/current input) 10: UP/DOWN frequency 11: Optional RP pulse input 12: Optional High-speed pulse input 13:-	0
<i>F661</i>	Override multiplication input selection	0: Deselect 1: VI/II 2: RR/S4 3: RX 4: <i>F729</i> <VF-AS1 only> 5: AI1	0
<i>F702</i>	Frequency free unit display magnification	0.00: OFF, 0.01~200.0	0.00
<i>F703</i>	Frequency free unit conversion selection	0: All frequencies display free unit selection 1: PID frequencies free unit selection	0
<i>F729</i>	Operation panel override multiplication gain <VF-AS1 only>	-100~100 (%)	0

*1 : See the manual E6581319 for detail of "Stop holding P control".
E6581319: PG feedback board instruction manual

[Input/output terminal function]

	Positive logic	Negative logic	Function
Input terminal	36	37	PID control OFF selection
	52	53	PID differentiation/integration reset
	54	55	PID forward/reverse switching
	94	95	Dancer correction OFF
Output terminal	38	39	PID deviation limit
	144	145	Frequency command agreement signal (RR/S4) *2
	146	147	Frequency command agreement signal (VI) *2
	148	149	Frequency command agreement signal (RX) *2

*2: VF-PS1 only

[FM/AM pulse output and monitor output function]

FM/AM pulse output		Monitor output		Function
Option No.	Communication No.	Option No.	Communication No.	
1	FD02	1	FE02	Frequency command value
6	FD16	6	FE16	Speed feedback (real time value)
7	FD17	7	FE17	Speed feedback (1-second filter)
13	FD22	13	FE22	PID feedback value
-	-	79	FD52	PID result frequency
-	-	80	FE84	Synchronous speed frequency command

You need to convert the process value and the feedback value into frequency for the PID control.

F 702 (free unit selection) and *F 703* (conversion item selection) enable to set process value and feedback value easily. It is possible to convert frequency display to temperature or pressure level by calculation.

$$\boxed{\text{Value displayed}} = \boxed{\text{Frequency displayed on the monitor or specified with a parameter}} \times \boxed{F 702}$$

F 703 = 0

Frequency on the monitor or specified with parameter display the value multiplied by *F 702*.

Note) This setting does not change automatically if it is switched from PID control to frequency command operation. Output frequency displays the value by *F 702*.

F 703 = 1

The following frequency with the parameters and the monitor display the value multiplied by *F 702*.

[Parameters]

Title	Function
<i>F 364</i>	PID deviation upper limit
<i>F 365</i>	PID deviation lower limit
<i>F 367</i>	Process upper limit
<i>F 368</i>	Process lower limit

[FM/AM pulse output and monitor display]

FM/AM pulse output		Monitor output		Function
Option No.	Communication No.	Option No.	Communication No.	
1	FD02	1	FE02	Operation frequency command value
13	FD22	13	FE22	PID feedback value