

Catalog Correction Notice

Catalog / Manual

Issue Date April 01, 2025

NRO

No. 2025003DE

The mistake of the print and the description is found in the catalog / manual that our company issued. We apologize.

[Name of catalog / manual]

"R88D-1SN[]-ECT-51 AC Servo System 1S Series with SS1/SLS Safety Sub-Functions Pamphlet" < Publication in December, 2024 > < Catalog number I927-E1-02>
"R88D-1SN[]-ECT-51 AC Servo System 1S-series with SS1/SLS Safety Sub-Functions Data Sheet" < Publication in July, 2024 > < Catalog number I928-E1-01 >
"AC Servomotors/Servo Drives EtherCAT® Communications and SS1/SLS Safety Sub-Functions User's Manual"
< Publication in August, 2024 > < Manual number I696-E1-01 >

[Page of publishing]

 "R88D-1SN[]-ECT-51 AC Servo System 1S Series with SS1/SLS Safety Sub-Functions Pamphlet" Page 6 1S Series Product Lineup
 "R88D-1SN[]-ECT-51 AC Servo System 1S-series with SS1/SLS Safety Sub-Functions Data Sheet" Page 10 Details about Safety Functions

"AC Servomotors/Servo Drives EtherCAT® Communications and SS1/SLS Safety Sub-Functions User's Manual"

Page 8-32Safely-limited Speed (SLS) FunctionPage A-175Error Descriptions

[Correction method]

We revise it at the time of a Catalog reprint on the next time.

[Content of correction]

Before								After												
Pamph 2-6											add the desc	-			e re	d ci	ircle	ed p	oart	•
	otability for ma	Power range	aret	(y		Safety F	unctions	1			ptability for ma	1	aret	y		Safety F	unctions	ŕ		
Product	15 Series	Power range	STO SIL2 PLd	<u>851</u>	SLS	852	\$05	SLP	SDI	SBC	18 Series	Power range	STO SIL2 PLd	SS1	SLS	SS2	SOS	SLP	SDI	SBO
P	1S Series with SS1/SLS Safety Sub-Functions	50 W to 15 kW	*1 SIL2 PLd *1	● SIL2 PLd *3	• SIL2 PLd *2*3						15 Series with SS1/SLS Safety Sub-Functions	50 W to 15 kW	*1 SIL2 PLd *1	● SIL2 PLd *3	● SIL2 PLd *2*3*4					
1	15 Series with Safety Functionality	200 W to 3 kW	• SIL3 PLe	• SIL3 PLe	• SIL3 PLe	• SIL3 PLe	• SIL3 PLe	• SIL3 PLe	e SIL3 PLe	• SIL3 PLe	1S Series with Safety Functionality	200 W to 3 kW	● SIL3 PLe	● SIL3 PLe	● SIL3 PLe	● SH.3 PLe	SIL3 PLe	● SiL3 PLe	● SIL3 PLe	SIL PL
Salely-Limited Spee Sub-Functions User	wing. for setting the SLS speed monitori (BLS Function" in the AC Services Mercul (Cat. Not60) for details haven (Cat. Not60) for details tot the safety functions is possible	otors/Servo Drives	15-series	with Built	-in Ether Co	AT* Comm	nunication	ra and SS1			wing: If or earting the SLS speed monitorie of (SLS) (uncloan [®] in the AD Serveme a Manual (CEL NextROB for details) on when a vertical ans, etc., is subject is, For axes to which this applies, use the	tors/Servo Drives	15 series	with Built esult in a f	in EtherO	AT [®] Comm	surication	s and SS1	/SLS Sefe	ity

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Data Sheet] 10	function at maximum are shown as the below table.	
Function	Achievable safety level EN61508/EN ISO 13849-1	
STO function via safety input signals	SIL3/PLe	
STO function via FSoE	SIL2/PLd	8
881 #1	SIL2/PLd	
SLS #2	SIL2/PLd	
method, you may need to change or After Servo ON, the SLS function sho Although SLS velocity limit can be se Motor Velocity. Therefore, at a monit monitoring velocity is not actually exc To use the SLS function, we recomm	reaching the monitoring velocity is not supported. If you use an existing user program modify it. cold be activated when the speed is stable. It to leas than 100 mins, 3step Present Motor Velocity may be displayed 100 min it to ring velocity of less than 100 mins, SLS Monitoring Limit Exceeded may occur ever evended. Set all appropriate monitoring speed after floworgh / decking the operation evend outprior appropriate monitoring in a faste detection of Monitoring Limit Exceeded may a vend during oreation events in a faste detection of Monitoring Limit Exceeded may and when during normal operation, resulting in a faste detection of Monitoring Limit Exceeded may an USA and the speed and the speed after floword monitoring the speed set of the speed may an USA and the speed may and the speed monitoring the speed mo	larger than Present n though the n. le longer than 20 m

(Cat. No. 1696) for details

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Precautions for Correct Use

- The method of activating SLS when reaching the monitoring velocity is not supported. If you
 use an existing user program based on this method, you may need to change or modify the
- use an existing user program based on this method, you may need to change or modify the user program.
 After Servo ON, activate the SLS function when the velocity is stable.
 Although SLS velocity limit can be set to less than 100 r/min, Safety Present Motor Velocity may be displayed 100 r/min larger than Present Motor Velocity. Therefore, at a monitoring velocity of less than 100 r/min, SLS Monitoring Limit Exceeded may occur even though the monitoring velocity is not actually exceeded. Set an appropriate monitoring speed after thoroughly checking the operation.
 To use the SLS function, we recommend to use an OMRON motor power cable of 20 m or less. Using a motor power cable longer than 20 m may cause the following phenomena even during normal operation, resulting in a false detection of Monitoring Limit Exceeded or Safety Present Motor Velocity Error 2. Set an appropriate monitoring speed after thoroughly checking the operation. In addition, using a noise filter on the power supply line may stabilize the Safety Present Motor Velocity an output chuc false detections. For the recommended noise filter thore were thore velocity and revealed filter thore were thore velocity and reduce false detections. For the recommended noise filter thore velocity and reduce false detections. Safety Present Motor Velocity and reduce false detections. For the recommended noise fil-ters, refer to 3-8 Noise Filter Specifications on page 3-145 and 4-7 Noise Filter Installation Conditions When the Total Wire Length Is Long on page 4-83.

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Event name	Safety Present N			Event code	68500000 hex			
Description	Safety Velocity	Detection - State	is (4F1A-82 hex) was disabled in SLS status. Or, the SLS com					
	was set to Activa	ate SLS with Safet	ty Velocity Detec	tion – Status (4F	1A-82 hex) disabled.			
Source	EtherCAT Maste	r Function Mod-	Source details	Slave	Detection tim- ing	During FSoE communica-		
	ule				mg	tions		
Error attrib-	Level	Minor fault	Recovery	Error reset (af-	Log category	System log		
utes				ter resetting slave errors)				
Effects	User program	Continues.	Operation	Power drive circ	uit is OFF			
Indicators	EtherCAT NET		EtherCAT NET I		EtherCAT LINK/ACT Name None			
	ON							
System-de-	Variable		Data type					
fined varia- bles	None		None					
Cause and	Assumed cause	9	Correction		Prevention			
correction	The acceleration	/deceleration	Correct the open	ation command	Perform a setting	g with consider		
	time for accelera		to increase the a		tion of precautio	ns.		
	eration in SLS st	atus is short.	deceleration time					
			Velocity Detect					
			(4F1A-82 hex) re					
			during acceleration		-			
	Motor power sta		Correct the open					
		or rotation in SLS	so that Motor po					
	status.		not turn OFF dur tion in SLS statu					
	The SLS comma		Set the SLS corr		-			
	Activate SLS wit		vate SLS with Sa					
	Velocity Detect		Detection – Sta					
	(4F1A-82 hex) d		hex) enabled.	103 (11 17-02				
	The motor powe		Use a motor p	ower cable of	1			
	Noise		the latest vers	ion.				
			 Take noise co 	untermeasures				
			such as using	a noise filter.				
	Hardware failure		If this error occu		None			
			even after the er					
			hardware is fault					
			Servomotor or S	ervo Drive	1			

ata Sheet』

Fu	nction	Achievable safety level EN61508/EN ISO 13849-1
STO function via si	afety input signals	SIL3/PL0
STO function via F	SoE	SIL2/PLd
SS1 #1		SIL2/PLd
SLS #2 #3		SIL2/PLd
to change or mo 2. The method of a method, you ma After Servo ON, Atthough SLS v	dify the user program activating SLS when r y need to change or the SLS function sho blocity limit can be se	motor stops is not supported. If you use an existing user program based on this method, you may neer n. eaching the monitoring velocity is not supported. If you use an existing user program based on this

After

ocity Error 2 even during normal operation. For axes to which this applies, use the 1S Series with Safety Functionality R88D-1SAN: Servo Drives 1S-series with Built-in B Refer to the AC Servomo

User's Manual P8-32

Precautions for Correct Use 内

- The method of activating SLS when reaching the monitoring velocity is not supported. If you use an existing user program based on this method, you may need to change or modify the user program.
- After Servo ON, activate the SLS function when the velocity is stable.
 Although SLS velocity limit can be set to less than 100 r/min, Safety Present Motor Velocity may be displayed 100 r/min larger than Present Motor Velocity. Therefore, at a monitoring velocity of less than 100 r/min, SLS Monitoring Limit Exceeded may occur even though the monitoring velocity is not actually exceeded. Set an appropriate monitoring speed after thor-

Using the SLS function when a vertical axis, etc., is subject to an unbalanced load may result in a false detection of Safety Present Motor Velocity Error 2 even during normal operation. For axes to which this applies, consider using the 1S-series with Safety Functionality R88D-1SAND

less. Using a motor power cable longer than 20 may cause the following phenomena even during normal operation, resulting in a false detection of Monitoring Limit Exceeded or Safety Present Motor Velocity Error 2. Set an appropriate monitoring speed after thoroughly check-ing the operation. In addition, using a noise filter on the power supply line may stabilize the Safety Present Motor Velocity and reduce false detections. For the recommended noise fil-ters, refer to 3-8 Noise Filter Specifications on page 3-145 and 4-7 Noise Filter Installation Canditions (Micro the Tatt) Wing Longer 1.0 and 2-9 A93. Conditions When the Total Wire Length Is Long on page 4-83.

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ule ing communications										
was set to Activate SLS with Safety Velocity Detection - Status (4F1A-82 hex) disabled. Source EtherCAT Master Function Module Source details Sawe Detection timely communications Error attributes Level Minor fault Recovery Error reset (af. Log category size errors) System log issue errors) Effects User program Continues. Operation Power drive circuit is OFF Indicators EtherCAT NET RUN EtherCAT INSTE ERR EtherCAT LINK/ACT ON System-de- Ined varia- bles None None None Cause and Correction Assumed cause Correction Prevention The acceleration/deceleration time for acceleration and decel- eration in SLS status is short. Correct the operation command to in SLS status. Perform a setting with consid to nof precautions. Motor power status was tured OFF during motor rotation in SLS status. Set the SLS command to Acti- vate SLS with Safety Velocity Detection - Status Fert SLS command to Acti- vate SLS with Safety Velocity Detection - Status Valiable External forces such as unbalanced loads are applied. Petace ensure that no external forces are applied to the motor. If the operation is intentional, please consider using the 1S Series with	Event name	Safety Present M	Notor Velocity Erro	r 2	Event code	68500000 hex				
Source EtherCAT Master Function Module Source details Slave Detection tim- ing During FSc ions Error attrib- utes Level Minor fault Recovery Error rest (af- ter resetting slave errors) Log category System log Effects User program Continues. Operation Power drive circuit is OFF Indicators EtherCAT NET RUN EtherCAT NET ERR EtherCAT LINK/ACT ON System-de- lined varia- bles None None None The acceleration/ideceleration time for acceleration and decel- eration in SLS status is short. Correction Prevention Motor power status was turned OFF during motor rotation in SLS status. Gerte the operation command is of that Motor power status dees not tum OFF during motor rota- tion in SLS status. Set the SLS command to Acti- vate SLS with Safety Velocity Detection – Status (4F1A-82 beak declard Ether SLS command was set to Activate SLS with Safety Velocity Detection – Status Fease ensure that no external forces are applied to the motor. If the operation is intentional, please consider unbalanced loads are applied. Prevention is intentional, please consider using the 1S Series with	Description	Safety Velocity	Detection – Statu	us (4F1A-82 hex)	was disabled in Sl					
ule ing communications Error attributes Level Minor fault Recovery Error reset (after resetting slave errors) System log Effects User program Continues. Operation Power drive circuit is OFF System log Indicators EtherCAT NET RUN EtherCAT NET ERR EtherCAT LINK/ACT ON System.dec Data type Name fined variables Data type Name correction The acceleration/doceleration Correct the operation command to increase the acceleration/ Prevention Correction The acceleration/doceleration Correct the operation command to increase the acceleration/ Perform a setting with conside during acceleration/doceleration. Motor power status was turned Ocrese the operation command to increase the acceleration. Perform a setting with conside during acceleration/doceleration. OFF during motor rotation in SLS status. Correct the operation command to active GLS with Safety Velocity Detection - Status does not turn OFF during motor rotation in SLS status. Set the SLS command to Active SLS with Safety Velocity Detection - Status does not turn OFF during motor rotation in SLS status. // Ether Cat action as unbalanced loads are applied. Pease ensure that no external forces are applied to the motor. If the operation is intentional, please consider using the 1S Series with		was set to Activa	ate SLS with Safet	y Velocity Detect	tion – Status (4F1					
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intentional, please consider using the 1S Series with		unbalanced load	is are applied.							
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R88D-1SANd.					· ·					
The motor power cable is long. • Use a motor power cable of		The motor powe	r cable is long.	 Use a motor p 	ower cable of					
Noise the latest version.		- · · ·								
 Take noise countermeasures 				 Take noise co 	untermeasures					
such as using a noise filter.				such as using	a noise filter.					
Hardware failure If this error occurs continuously None		Hardware failure		If this error occur	rs continuously	None				
even after the error is reset, the				even after the er	ror is reset, the					
hardware is faulty. Replace the				hardware is fault	y. Replace the					

Specifications in this product news are as of the issue date and are subject to change without notice. Only main changes in specifications are described in this document. Please be sure to read the relevant catalogs, datasheets, product specifications, instructions, and manuals for precautions and necessary information when using products.