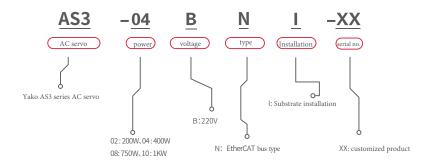
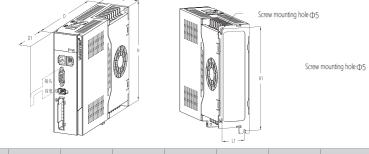
# Servo Drive Naming Rules



## Drive Specs and Dimensions



Model	L(mm)	) H(mm) D(mm		L1(mm)	H1(mm)	D1(mm)	screw hole	
AS3 Frame B	40	170	163	28	161	75	2-M4	
AS3 Frame C	50	170	173	37	161	75	2-M4	

Structure Size		SIZE B	SIZE C					
Drive Model	AS3-02BNI	AS3-04BNI	AS3-08BNI	AS3-10BNI 6.0 17				
Output Current Arms	1.6	2.8	5.0					
Maximum Output Current Arms	5.8	10	13.5					
Main Circuit Power Supply	Single-phase AC200V-240V							
Regenerative Loop Function	External brake resistor							
Control Circuit Power Supply	single-phase AC200V-240V,+10%~-10%,50/60Hz							

# Servo Drive Basic Specifications

$ \begin{array}{ c c c c } \medskip \meds$	<ul> <li>Basic Specific</li> </ul>	ations						
Working Environment         Image:         Storage: $-20^{\circ}$ C-70°C           Humidity $O \sim 90\%$ RH/L/T         Working Allitude         <1000 mabove sea level		Temperature	2	Operating: 0°C~+50°C (if it's in 45°C~55°C, the average load rate should <80%				
Working Environment         Working Allitude             Working Allitude         <1000m above sea level				Storage: -20°C~70°C				
Environment         Vibration/Shock         vibration : < 4.9m/s <sup>2</sup> impact: < 19.6m/s <sup>3</sup> IP Rating/Pollution degree         IP20/Pollution degree 2         IGBT PWM space vector control           Encoder         IGST PWM space vector control         Input           Input and output port         IOsignal         Input         5 (General)           Output         3 (General)         Output         3 (General)           Communication Function         RS232 (USS)         Connect with PC for debugging servo drive         ED display           Regenerative Loop Function         Regrementive Loop Function         Over current, overload, over voltage, low voltage, over speed, over temperat encoder abnormality, communication abnormality, eccessive position devia           Control mode         Smoothing Filter         Contour Position Mode (PP) ; Contour Speed Mode (PV) ; Contour Torque Mode (PT) ;           Position Command Format         EtherCAT bas digital         smoothing filter           Vibration Suppression Filter         Ina discharg upges actual guati interfere and span mosance fragment, to enser state operation of the discharg upges actual span format and span mosance fragment, to enser state operation of the discharg upges actual span format and span mosance fragment, to enser state operation of the discharg upges actual span format and span mosance fragment, to enser state operation of the discharg upges actual span format and span format actual span format and span forma task of the disginal           Speed		Humidity		0~90% RH以下				
Vibration/Shock         vibration : < 4.9m/S <sup>2</sup> impact: < 19.6m/S <sup>2</sup> IP Rating/Pollution degree         IP20/Pollution degree 2         IGBT PWM space vector control           Input and output port         IOsignal         Input         5 (General)           Input and output port         IOsignal         Input         5 (General)           Communication Function         RS232 (Connect with PC for debugging servo drive         IOUTput           Regenerative Loop Function         RS232 (Connect with PC for debugging servo drive         Output           Regenerative Loop Function         Bull-in braking resistor for > 1000W         Over current, overload, over voltage, low voltage, over speed, over temperat encoder abnormality, communication abnormality, excessive position devia           Protect Function         Position Command Format         EtherCAT bin digital           Position Control Mode         Smoothing Filter         Gondung perature due of the	Working	Working Alt	itude	<1000m above sea level				
	Environment	Vibration/Shock		vibration: $< 4.9 \text{m/s}^2$ impact: $< 19.6 \text{m/s}^2$				
Control Method         IGBT PWM space vector control           Encoder         17-bit incremental / 23-bit absolute           Input and output port         IOsignal         Input         3 (General)           Communication Function         PS232 (USB)         Connect with PC for debugging servo drive         LED display           Panel Operator         Bull-in braking resistor for > 1000W         Over current, overload, over voltage, low voltage, over speed, over temperat encoder abnormality, communication abnormality, excessive position devia           Protect Function         Control mode         Contur Position Mode (PP) ; Contour Speed Mode (PV) ; Contour Torque Mode (PT) ;           Control mode         Position Command Format         EtherCAT bus digital           Position Control Mode         Smoothing Filter         smoothing the pation command to make the moter not mone table           Vibration Suppression Filter         Vibration Suppression Filter         tran effectively supprese central signal interference and system resonance frequency, to more table operation of command to make the moter not mone table           Speed Control Mode         Speed Change Load Fluctuation         0.100% load : < 0.5% (Rated speed)		IP Rating/Po	llution degree	IP20/Pollution degree 2				
Input and output port	Con	Ū.	intuon degree	IGBT PWM space vector control				
$ \begin{array}{ c c c c } \medskip \meds$	En	coder		17-bit incremental / 23-bit absolute				
Communication       Function       RS232 (USB)       Connect with PC for debugging serve drive         Panel Operator       LED display         Regenerative Loop Function       Built-in braking resistor for >1000W         Protect Function       Over current, overload, over voltage, low voltage, over speed, over temperat encoder abnormality, communication abnormality, excessive position devia         Control mode       Contour Position Mode (PP) ; Contour Speed Mode (PV) ; Contour Torque Mode (PT) ;         Position Command Format       EtherCAT bas digital         Position Control Mode       Smoothing Filter         Smoothing Filter       Smoothing Filter         Notifications       Smoothing Filter         Vibration Suppression Filter Rate       Notification         Voltage Rate       Command Form         EtherCATbus digital       Voltage         Voltage Rate       Oltage         Speed Control Mode       Command Form         EtherCATbus digital       Voltage         Interpretation       Command Form         EtherCATbus digital       Temperature         Speed Control Mode       Command Form         EtherCATbus digital       Temperature         Internet to zero mode       Command Form         EtherCAT bus digital       Zero return method setting <tr< td=""><td></td><td></td><td>Input</td><td>5 (General)</td></tr<>			Input	5 (General)				
Communication Function         RS232 (USB)         Connect with PC for debugging serve drive           Panel Operator         LED display           Regenerative Loop Function         Built-in braking resistor for ≥ 1000W           Protect Function         Over current, overload, over voltage, low voltage, over speed, over temperat encoder abnormality, communication abnormality, excessive position devia           Control mode         Contour Position Mode (PP) ; Contour Speed Mode (PV) ; Contour Torque Mode (PT) ;           Position Command Format         EtherCAT bas digital           Position Control Mode         Smoothing Filter           Smoothing Filter         Smoothing the position command to make the motor run unother and more stable           Vibration Suppression Filter         Iten effectively suppresestent algand interference and yatem resonance frequency, to ensure stable operation of epidemic command to make the motor run unother and more stable           Speed Control Mode         Speed Change Load Fluctuation         Poly: 0.5% (Rated speed)           Rate         Voltage         Rate dvoltage±10%: 0.5% (Rated speed)           Torque Control Mode         Command Form         EtherCAT bus digital           Acceleration Develoration memory stange lange         0-10S           Torque Control Mode         Command Form         EtherCAT bus digital           Return to zero mode         Command Form         EtherCAT bus digital	Input and output port	IOsignal	-	3 (General)				
Commanded of National Vision Costs       U(SS)       LED display         Regenerative Loop Function       Built-in braking resistor for >1000W         Protect Function       Over current, overload, over voltage, low voltage, over speed, over temperat encoder abnormality, communication abnormality, excessive position devia         Control mode       Contour Position Mode (PP) ; Contour Speed Mode (PV) ; Contour Torque Mode (PT) ;         Position Command Format       EtherCAT bus digital         Position Control Mode       Smoothing Filter         Smoothing Filter       Smoothing the position command to make the motor run smoother and more stable         Vibration Suppression Filter       Iten effectively suppress external signal interformer and yotem resonance frequency. to ensure stable operation of equipments         Speed Control Mode       Speed Control Form       EtherCAT bus digital         Speed Control Mode       Speed Control Mode       Speed Control Mode         Speed Control Mode       Command Form       EtherCAT bus digital         Acceleration Decleration Setting Runge       0-10S         Torque Control Mode       Command Form       EtherCAT bus digital         Return to zero mode       Command Form       EtherCAT bus digital         Return to zero mode       Command Form       EtherCAT bus digital         Zero return method setting       Through the EtherCAT bus configuration,	Communication	n Function	RS232	Connect with PC for debugging servo drive				
Built-in braking resistor for $\geq 1000W$ Protect Function         Protect Function       Over current, overload, over voltage, low voltage, over speed, over temperat encoder abnormality, communication abnormality, excessive position devia encoder abnormality, communication abnormality, excessive position devia         Control mode       Contour Position Mode (PP) ; Contour Speed Mode (PV) ; Contour Torque Mode (PT) ;         Position Command Format       EtherCAT bus digital         Position Control Mode       Smoothing Filter       Smoothing the position command to make the motor run smoother and more stable         Vibration Suppression Filter       tr can effectively suppress external signal interference and system resonance frequency, to ensure stable operation of equation         Speed Control Mode       Command Form       EtherCAT bus digital         Speed Control Mode       Command Form       EtherCAT bus digital         Speed Control Mode       Command Form       EtherCAT bus digital         Command Form       EtherCAT bus digital         Rate       Command Form       EtherCAT bus digital         Control mode       Command Form       EtherCAT bus digital         Conder brodwak Bietronic Gar       EtherCAT bus digital         Zero return method setting       Through the EtherCAT bus configuration,         Return to zero mode       Self-tuning Function       suppo			(USB)					
Protect Function       Over current, overload, over voltage, low voltage, over speed, over temperat         Protect Function       Control mode       Contour Position Mode (PP); Contour Speed Mode (PV);         Control mode       Contour Position Mode (PP); Contour Speed Mode (PV);       Contour Torque Mode (PT);         Image: speed control Mode       Position Command Format       EtherCAT bus digital         Position Suppression Filter       Smoothing Filter       Smoothing the position command to make the motor run smoother and more stable         Vibration Suppression Filter       It can effectively suppress external signal interference and system resonance frequency, to ensure stable operation of eq         Speed Control Mode       Speed Change       Voltage         Rate       Voltage       Rated voltage ±10%: 0.5% (Rated speed)         Acceleration Deceleration Setting Range       0-10S         Torque Control Mode       Command Form       EtherCAT bus digital         Return to zero mode       Command Form       EtherCAT bus digital         Common       Gommand Form       EtherCAT bus digital         Zero return method setting       Through the EtherCAT bus configuration,         Self-tuning Function       support a variety of zero return mode Inertia         Incoder Readuad Electronic Coar       identification, rigidity tuning         Abnormal Information Record       Se		1	Function	Built-in braking resistor for ≥1000W				
encoder abnormality, communication abnormality, excessive position devia $ \begin{array}{c c c c c c c c c } \hline Control mode \\ \hline Contour Position Mode (PP) ; Contour Speed Mode (PV) ; Contour Torque Mode (PT) ; \\ \hline Contour Torque Mode (PT) ; \\\hline \hline Position Command Format \\ \hline Position Command Format \\ \hline Position Suppression Filter \\ \hline Vibration Suppression Filter \\ \hline tean effectively suppress external signal interference and system resonance frequency, to ensure stable operation of equation of equation for the ensure matched speed) \\ \hline Position Development \\ \hline Position Command Form \\ \hline Position Suppression Filter \\ \hline tean effectively suppress external signal interference and system resonance frequency, to ensure stable operation of equation for the ensure stable operation operation for the ensure stable operation operation for the ensure stable operation operation for the ensure stable operation operation for the ensure stable operation operation for the ensure stable operation operation for$	Keş	generative Loop	Function	C C				
Control mode       Contour Torque Mode (PT) ; <ul> <li>Functions Specifications</li> </ul> Position Control Mode <ul> <li>Smoothing Filter</li> <li>Smoothing Filter</li> <li>Smoothing the position command to make the motor run smoother and more stable</li> <li>Vibration Suppression Filter</li> <li>It can effectively suppress external signal interference and system resonance frequency, to ensure stable operation of exp</li> <li>Fluctuation</li> <li>Function Provided</li> <li>Voltage</li> <li>Fluctuation</li> <li>Position Control Mode</li> </ul> Speed Control Mode <ul> <li>Speed Control Mode</li> <li>Speed Change</li> <li>Coad Fluctuation 0-100% load: <ul> <li>0.5% (Rated speed)</li> <li>Temperature</li> <li>25±25°C: <ul> <li>0.5% (Rated speed)</li> <li< td=""><td>Pi</td><td>rotect Function</td><td></td><td colspan="3">encoder abnormality, communication abnormality, excessive position deviati</td></li<></ul></li></ul></li></ul></li></ul></li></ul></li></ul></li></ul></li></ul></li></ul></li></ul></li></ul>	Pi	rotect Function		encoder abnormality, communication abnormality, excessive position deviati				
$ \begin{array}{ c c c c } \hline \label{eq:position} \hline \begin{tabular}{ c c c } \hline \begin{tabular}{ c c c c } \hline \begin{tabular}{ c c c c } \hline \begin{tabular}{ c c c c } \hline \begin{tabular}{ c c c c c c } \hline \begin{tabular}{ c c c c c c c } \hline \begin{tabular}{ c c c c c c c c c c c c c c c c c c c$	Control mode							
Position Control Mode  Position Control Mode  Smoothing Filter Smoothing the position command to make the motor run smoother and more stable  Vibration Suppression Filter It can effectively suppress external signal interference and system resonance frequency, to ensure stable operation of equency is a stable operation operatin operation operation operating is a stable operat	Functions Sp	ecifications						
Position Control Mode         Smoothing Filter         smoothing the position command to make the motor run smoother and more stable           Vibration Suppression Filter         It can effectively suppress external signal interference and system resonance frequency, to ensure stable operation of equency for the position command to make the motor run smoother and more stable           Speed Control Mode         Command Form         EtherCATbus digital           Speed Control Mode         Speed Change         Voltage Fluctuation         Rated voltage±10%: 0.5% (Rated speed)           Rate         Load Fluctuation         0-100% load: < 0.5% (Rated speed)		Position Cor	nmand Format	EtherCAT hus divital				
Vibration Suppression Filter       In can effectively suppress external signal interference and system resonance frequency, to ensure stable operation of equation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency, to ensure stable operation of equation is a signal interference and system resonance frequency. The system is a signal interference and system resonance frequency is a signal interference and system resonance frequency. The system is a signal interference and system resonance frequency is a signal interference and system resonance frequency. The system is a signal interference and system resonance frequency is a signal interference and system resonance frequency. The system is a signal interference and system resonance frequency is a signal interference and system resonance frequency. The system is a signal interference and system resonance is a signal interference and system resonance is a signal interference and system resonance is a sinterm is a sintermatere in the system is a signal interference an	Position Control Mode							
Speed Control ModeCommand FormEtherCATbus digitalSpeed Control ModeSpeed Change FluctuationNated voltage±10%: 0.5% (Rated speed)RateLoad Fluctuation0-100% load: $\leq 0.5\%$ (Rated speed)RateCommand Form25±25°C: $\leq 0.5\%$ (Rated speed)Torque Control ModeCommand FormEtherCAT bus digitalReturn to zero modeCommand FormEtherCAT bus digitalZero return method settingThrough the EtherCAT bus configuration,Self-tuning Functionsupport a variety of zero return mode InertiaCommonEncoder Feedback Electronic Gearidentification, rigidity tuningAbnormal Information RecordSetting freely		Vibration Suppression Filter						
Speed Control Mode       Voltage Fluctuation       Rated voltage±10%: 0.5% (Rated speed)         Speed Change Rate       Load Fluctuation       0-100% load: $\leq 0.5\%$ (Rated speed)         Temperature       25±25°C: $\leq 0.5\%$ (Rated speed)         Acceleration Deceleration Setting Range       0-10S         Torque Control Mode       Command Form       EtherCAT bus digital         Return to zero mode       Command Form       EtherCAT bus digital         Zero return method setting       Through the EtherCAT bus configuration,         Self-tuning Function       support a variety of zero return mode Inertia         Encoder Feedback Electronic Gear       identification, rigidity tuning         Abnormal Information Record       Setting freely								
Speed Control Mode       Speed Change       Load Fluctuation       0-100% load: $\leq$ 0.5%(Rated speed)         Acceleration Deceleration Setting Range       0-100% load: $\leq$ 0.5%(Rated speed)         Acceleration Deceleration Setting Range       0-10S         Torque Control Mode       Command Form       EtherCAT bus digital         Return to zero mode       Command Form       EtherCAT bus digital         Zero return method setting       Through the EtherCAT bus configuration,         Self-tuning Function       support a variety of zero return mode Inertia         Encoder Feesback Electronic Gear       identification, rigidity tuning         Abnormal Information Record       Setting freely         8 groups of historical information zecords			Voltage	· · · · · · · · · · · · · · · · · · ·				
$\frac{P_{ate}}{P_{ate}} = \frac{P_{ate}}{P_{exp}} \frac{P_{ate}}{P_{exp}} = \frac{P_{ate}}{P_{exp}} $	Speed Control Mode							
Acceleration Deceleration Setting Range         0-10S           Torque Control Mode         Command Form         EtherCAT bus digital           Return to zero mode         Command Form         EtherCAT bus digital           Zero return method setting         Through the EtherCAT bus configuration,           Self-tuning Function         support a variety of zero return mode Inertia           Encoder Feedback Electronic Gear         identification, rigidity tuning           Abnormal Information Record         Setting freely								
Torque Control Mode         Command Form         EtherCAT bus digital           Return to zero mode         Command Form         EtherCAT bus digital           Zero return method setting         Through the EtherCAT bus configuration,           Self-tuning Function         support a variety of zero return mode Inertia           Encoder Feedback Electronic Gear         identification, rigidity tuning           Abnormal Information Record         Setting freely		Acceleration Deceleration Setting Range						
Command Form         EtherCAT bus digital           Zero return method setting         Through the EtherCAT bus configuration,           Self-tuning Function         support a variety of zero return mode Inertia           Encoder Feedback Electronic Gear         identification, rigidity tuning           Abnormal Information Record         Setting freely           8 groups of historical information records	Torque Control Mode	Command I	Form					
Return to zero mode         Zero return method setting         Through the EtherCAT bus configuration,           Common         Self-tuning Function         support a variety of zero return mode Inertia           Encoder Feedback Electronic Gear         identification, rigidity tuning           Abnormal Information Record         Setting freely           8 groups of historical information records		Command Form						
Self-tuning Function         support a variety of zero return mode Inertia           Encoder Feedback Electronic Gear         identification, rigidity tuning           Abnormal Information Record         Setting freely           8 groups of bistorical information records	Return to zero mode							
Common Encoder Feedback Electronic Gear identification, rigidity tuning Abnormal Information Record Setting freely								
Common Abnormal Information Record Setting freely		~						
8 groups of historical information records	Common	Abnormal Infor	mation Record					
dynamic braking	-	dum anai a bual-tu u						
		dyna	umic braking	e group of motorical mornadon records				

### Servo Drive Connection to Peripheral Devices



### Servo Drive Terminal Definition

Function

Home switch

Probe 2

Probe 1

Forward drive forbidden

Backward drive forbidden

Internal 24V power supply, voltage range

No definition; For the motor with

brake, the function code P02.23

should set as 11 for the brake output

internal 24V ground; open collector pulse input ground

Power input, 12~24V

Servo ready

Position reached

+20~28V, Maximum output current 200mA

CN1 Control Terminal - General Input and Output Signal

Definition PIN

10

9

8

7

11

15

14

13

1 S-RDY+

6 S-RDY-

3

2

5

4

P-OT

N-OT

Home

Switch

Touch

Probe2

Touch

Probe1

COIN+

COIN-

DI1

DI2

DI3

DI4

DI5

+24

COM\_24

IN\_COM

DO1+

D01-

DO2+

D02-

DO3+

DO3-

#### CN2 Encoder Cable Servo Driver Side Terminal Pin Distribution

PIN	Encoder Signal	Function
1	+5V	+5V Power Output
2	GND	power GND output
5	SD+	
6	SD-	Encoder Signal
Shell	PE	

#### CN3 and CN4 - Industrial Bus Communication Port Uses

PIN	Color Signal	Name	Direction
1	white/orange	TxData+	Output
2	orange	TxData-	Output
3	white/green	RecvData+	Input
4	blue	Unused	Unused
5	white/blue	Unused	Unused
6	green	RecvData-	Input
7	white/brown	Unused	Unused
8	brown	Unused	Unused

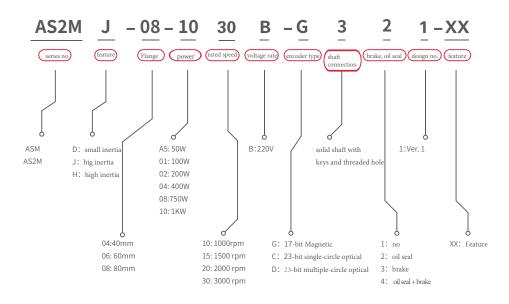
#### Main Circuit Terminal Definition

Name	Terminal Mark	Function Specification						
Control Power Input Terminal	L1,L2	Control circuit power input terminal						
External Regenerative Resistor Connection Terminal	P.D.C	For the IKw molds, P and D are short commeted by default, and the buffs in resistor has been connected. When the braking capacity is issufficient, please context the external brake resistance between P and C (to use the external resistance, remove the short wiring and keep P and D open). For 400W models, P and C are equipped with external brake resistance, so D terminal is unavailable.						
Common DC Bus Terminal	P、N	Common bus connection when multiple units are connected in parallel						
Servo Motor Connection Terminal	U,V,W	Servo motor connection terminal, connected to U, V, W.						
Ground Terminal	PE	Two grounding terminals are connected to the power grounding terminal and the motor grounding terminal. Be sure to ground the entire system.						

## Servo System Configuration Table

	Single	220V	
	F		
	Size B		Size C
AS3-02BNI	AS3-04BNI	AS3-08BNI	AS3-10BNI
ASMD-04-A530B AS2MD-04-0130B AS2MJ-06-0230B	AS2MJ-06-0430B	AS2MJ-08-0830B	AS2MJ-08-0830B AS2MJ-08-1030B

# Motor Naming Rules



## Motor Parameters

	1				1 1					
Parameters	Rated Output	Rated Torque	Maximum Torque	Rated Current	Maximum Current	Rated Speed	Maximum Speed	Rotor Inertia	Voltage	Matched Drive Mod
model	(KW)	(Nm)	(Nm)	(Arms)	(Arms)	(rpm)	(rpm)	(10 <sup>-4</sup> Kgm <sup>2</sup> )	(Kg)	
			17-bit B	Encoder M	otor Parame	ters				
				<b>40</b> Fla	ange					
ASMD-04-A530B-G311	0.05	0.159	0.477	0.67	2.01	3000	5000	0.025	0.4	AS3-02BNI
AS2MD-04-0130B-G321	0.1	0.318	0.954	1.26	3.78	3000	5000	0.043	0.45	AS3-02BNI
				60 Fla	ange					
AS2MJ-06-0230B-G321	0.2	0.64	1.92	1.67	5.1	3000	5000	0.32	0.93	AS3-02BN
AS2MJ-06-0430B-G321	0.4	1.27	3.81	2.5	7.5	3000	5000	0.57	1.26	AS3-04BNI
				<b>80</b> Fla	ange					
AS2MJ-08-0830B-G321	0.75	2.39	7.17	4.8	14.4	3000	5000	1.69	2.8	AS3-08BN AS3-10BN
AS2MJ-08-1030B-G321	1.0	3.18	9.52	6.3	18.9	3000	5000	2.1	2.9	AS3-10BN
			23-bit	Encoder M	otor Parame	eters				
				<b>40</b> Fla	ange					
AS2MD-04-0130B-D321	0.1	0.318	0.954	1.26	3.78	3000	7000	0.043	0.45	AS3-02BNI
				60 Fla	inge					
AS2MJ-06-0230B-D321	0.2	0.64	1.92	1.67	5.1	3000	7000	0.32	0.93	AS3-02BNI
AS2MJ-06-0430B-C321	0.4	1.27	3.81	2.5	7.5	3000	7000	0.57	1.26	AS3-04BNI
AS2MJ-06-0430B-D321	0.4	1.27	3.81	2.5	7.5	3000	7000	0.57	1.26	AS3-04BNI
				80 Fla	ange					
AS2MJ-08-0830B-C321	0.75	2.39	7.17	4.8	14.4	3000	6500	1.69	2.8	AS3-08BNI AS3-10BNI
AS2MJ-08-0830B-D321	0.75	2.39	7.17	4.8	14.4	3000	6500	1.69	2.8	AS3-08BNI AS3-10BNI
AS2MJ-08-1030B-D321	1.0	3.18	9.52	6.3	18.9	3000	6500	2.1	2.9	AS3-10BNI