

Absolute multi-turn hollow shaft encoder

BOMH – *Digitalizer*

SSI

features

- high resolution multi-turn encoder up to
 - 18 bit single-turn
 - 18 bit multi-turn
- SSI interface programmable
- permanent self-test
- reference point programmable



general data

voltage supply	5 VDC (05C) 10 - 30 VDC (24C)
supply current no load	typ. 120 mA (at 5 VDC) (05C) typ. 50 mA (at 24 VDC) (24C)
output circuit	SSI, complementary RS 422 binary or Gray code
max. resolution single-turn	18 bit (1 step = 5")
multi-turn	18 bit (262'144 revolutions)
max. clock frequency	1.1 MHz
repeatability	0,012°
direction of rotation	looking at the flange, position counts up as the shaft rotates clockwise (CW), programmable

mechanical data

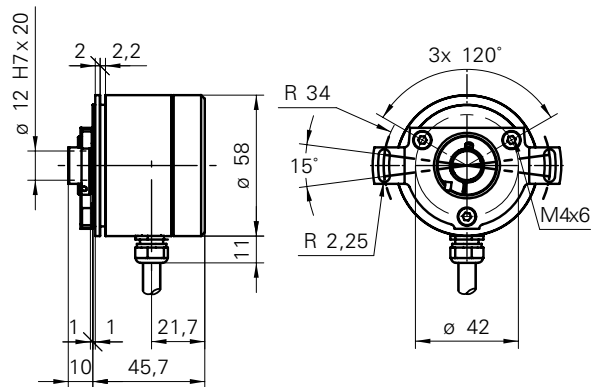
max. revolutions	mech. 6'000 rpm electr. 6'000 rpm
moment of inertia	typ. $18,4 \times 10^{-7} \text{ kgm}^2$
torque	typ. 1,75 cNm (3'000 rpm / 20 °C / IP 42)
product life	depending on ambient conditions (typ. 10^9 revolutions)
max. protection class	IP 65
material	housing: aluminum
weight	approx. 370 g

ambient conditions

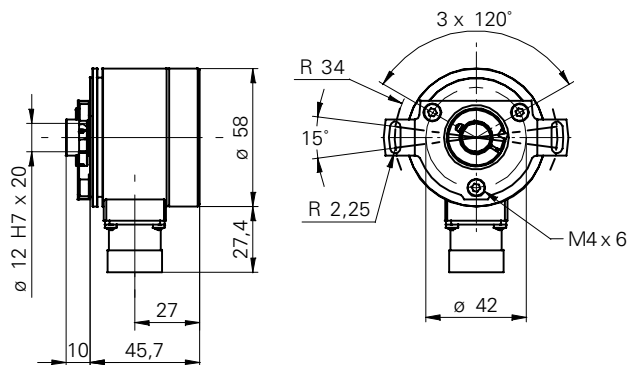
temperature range	-20...+85 °C
relative humidity	max. 95% non condensing
vibration (sine)	IEC 60068-2-6 ($\leq 100 \text{ m/s}^2$ / 10 - 2'000 Hz) 150 min per axis
vibration (random)	IEC 60068-2-64 ($\leq 0,1 \text{ g}^2/\text{Hz}$ / 20 - 1'000 Hz) 30 min per axis
shock	IEC 60068-2-27 ($\leq 500 \text{ m/s}^2$ / 11 ms) 10 pulses per axis and direction
noise immunity	EN 61000-6-2
emitted interference	EN 61000-6-3

dimensions and connection dimensions

-5



-A



Note

Mounting drawings see end of chapter.

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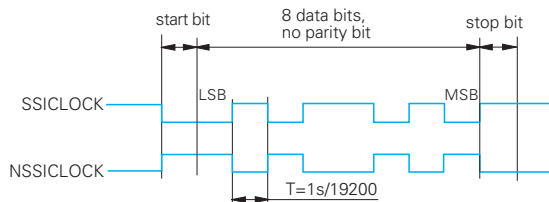
commands to encoder and setting of parameters

Multibyte commands* and parameters can be sent by asynchronous protocol with parameterized baud rate.

The multibyte protocol consists of length byte, address byte, command byte, data bytes and LRC byte.

length	slave address	command	(memory address), (data)	checksum LRC
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The 8 data bits have are embedded between a start bit (LOW) and a stop bit (HIGH).



Setting of parameters

It is always possible to set parameter over the SSI interface, even if the encoder is in operation.

For example:

- SSI bit format (position resolution)
- direction of rotation CW/CCW
- monoflop time
- interface mode
- compensation of propagation time
- baud rate for parameter setting and programming
- signal code (binary, Gray)

Additional features:

- efficient error handling
- memory for operating time
- incremental totalisator (number of rotations)
- preset function

The response on commands (data/ „acknowledge“ / „negative acknowledge“) has to be read out at the SSI interface before reading the next position value.

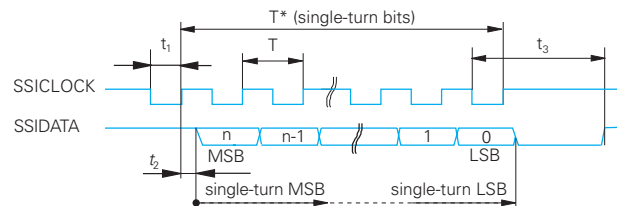
Reading out of position values and programmable of *Digitalizer* is also possible via PCI-board.

See chapter accessories.

* With end shaft mounting, commands and parameter setting by singlebyte protocol. Description on request.

read out of position values

The SSI interface can be used especially for real time signal processing. It is possible to precisely scan the angle information with the first negative clock.



Important: The SSI protocol does not start with zeros. NSSICLOCK and NSSIDATA are not symbolized.

$$T = 0,9 \text{ to } 14 \mu\text{s} \quad t_2 \geq 0,6 \mu\text{s}$$

$$0,45 \mu\text{s} < t_1 < t_3 \quad t_3 = 2, 5, 10 \text{ or } 20 \mu\text{s}$$

The monoflop-time (t_3) is programmable (Default 20 μs). Please keep the condition $t_3 \geq 1,4 \cdot T$.

I/O description

V/R* Input to set direction of rotation. Input is normally HIGH. V/R*-HIGH corresponds to increasing position values while looking at flange and shaft rotation in clockwise direction (CW). V/R*-LOW corresponds to increasing position values while looking at flange and shaft rotation in counter-clockwise direction (CCW). Read-in of V/R* voltage occurs during encoder power-on.

ZERO Input to set position to zero. Input is normally LOW. Zero setting procedure is initiated by a HIGH-pulse (pulse length $\geq 100 \text{ ms}$). For maximum disturbance immunity, connect input to 0 V.

DV* Output for error (data valid). Output is LOW-active, it indicates an error with LOW-voltage.

inputs and outputs

Control signals to V/R* and ZERO

Level HIGH $> 0,8 \cdot +V_s$

Level LOW $< 0,2 \cdot +V_s$

Connection V/R*-input with 15 kOhms against $+V_s$, ZERO-input with 15 kOhms against 0 V

Output signal from DV* and DVMT*

Connection DV*-output push-pull max. 30 mA

DVMT*-output push-pull max. 30mA

