Nano Module EtherCAT AFS NES

DIGITAL SERVO DRIVE FOR BRUSH & BRUSHLESS MOTORS

Advanced Feature Set

- 32-bit floating point filters
- Multiple advanced filters
- Frequency analysis tools

Control Modes

- Cyclic Synchronous Position-Velocity-Torque (CSP, CSV, CST)
- Cyclic Synchronous Torque with Commutation Angle (CSTCA)
- Profile Position-Velocity-Torque
- Interpolated Position, Homing
- Indexer, Point-to-Point, PVT
- Camming, Gearing

Command Interface

- CANopen application protocol over EtherCAT (CoE)
- ASCII, Serial Binary, and discrete I/O
- Stepper or Quad A/B position commands
- PWM Velocity-Torque command
- Master encoder (Gearing, Camming)
- ±10 V Position-Velocity-Torque

Communications

- EtherCAT
- RS-232

Feedback

- Primary Absolute
  BiSS-C Unidirectional
  SSI Absolute or Incremental
- Primary & Secondary Incremental
  Digital Quad A/B/X
- Digital Halls

I/O

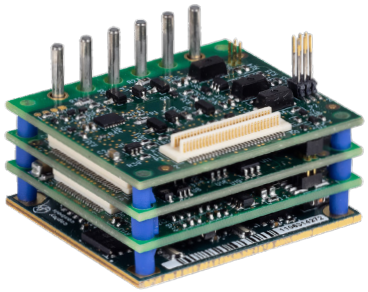
- 1 Analog input ±10V, 12-bit
- 5 High-speed digital inputs
- 1 Motor overtemp input
- 4 High-speed digital outputs

Safe Torque Off (STO)

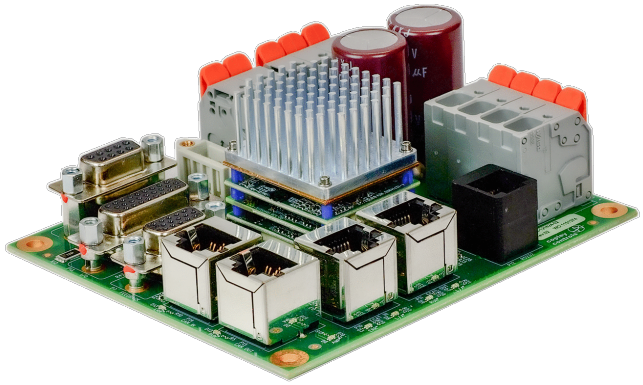
- SIL 3, Category 3, PL e

Dimensions

- 35 x 30 x 21.6 mm [1.38 x 1.18 x 0.85 in]
- 0.8 oz [0.023 kg]



Model	Ic	Ip	Vdc
NES-090-10	5	10	9~90
NES-090-70	35	70	9~90
NES-180-10	5	10	20~180
NES-180-30	15	30	20~180



Model	Ic	Ip	Vdc
NES-090-10-D	5	10	9~90
NES-090-70-D	35	70	9~90
NES-180-10-D	5	10	20~180
NES-180-30-D	15	30	20~180

Nano is the smallest servo drive that Copley offers and can be mounted directly on the motor or within robotic joints. It can satisfy requirements of the robotics, AGV, industrial machinery, medical/life-sciences and aerospace industries.

It mounts to user PC boards using connectors, or can be soldered in. An optional interface board provides connectors which facilitate easy integration into customer applications. The Nano has a third party approved STO feature. Opto-isolators provide connections to user wiring and controls.

DIGITAL SERVO DRIVE FOR BRUSH & BRUSHLESS MOTORS

GENERAL SPECIFICATIONS

Test conditions: Load = Wye connected load: 1 mH+ 1Ω line-line. Ambient temperature = 25 °C. +HV = HVmax

MODEL	NES-090-10 NES-090-10-D	NES-090-70 NES-090-70-D	NES-180-10 NES-180-10-D	NES-180-30 NES-180-30-D	
OUTPUT POWER…					
Peak Current	10 (7.07)	70 (49.5)	10 (7.07)	30 (21.2)	Adc (Arms, sinusoidal)
Peak time	1	1	1	1	Sec
Continuous current	5 (3.54)	35 (24.8)	5 (3.54)	15 (10.6)	Adc (Arms, sinusoidal)
Peak Output Power	0.9	6.3	1.8	5.4	kW
Continuous Output Power	0.45	3.15	0.9	1.8	kW
INPUT POWER					
HVmin to HVmax	+9 to +90	+9 to +90	+20 to +180	+20 to +180	Vdc, transformer-isolated
Ipeak	10	70	10	30	Adc (1 sec) peak
Icont	5	35	5	15	Adc continuous
VLOGIC	+9 to +60	+9 to +60	+9 to +60	+9 to +60	Vdc, transformer-isolated
VLOGIC Power	3 W with no encoder, 6 W with encoder +5V @ 500 mA				
PWM OUTPUTS					
Type	MOSFET 3-phase inverter, 16 kHz center-weighted PWM carrier, space-vector modulation				
PWM ripple frequency	32 kHz				

BANDWIDTH		
Current loop, small signal	2.5 kHz typical, bandwidth will vary with tuning & load inductance	
HV Compensation	Changes in HV do not affect bandwidth	
Current loop update rate	16 kHz (62.5 µs)	
Position & Velocity loop update rate	4 kHz (250 µs)	
COMMAND INPUTS		
EtherCAT:	CANopen application protocol over EtherCAT (CoE): Cyclic Synchronous Position/Velocity/Torque Profile Position/Velocity/Torque, Interpolated Position (PVT), Homing Cyclic Synchronous Torque with Commutation Angle (CSTCA)	
Stand-alone mode		
Digital position reference	Pulse/Direction, CW/CCW	Stepper commands (2 MHz maximum rate)
	Quad A/B Encoder	2 M line/sec, 8 Mcount/sec (after quadrature)
Digital torque & velocity reference	PWM , Polarity	PWM = 0% - 100%, Polarity = 1/0
	PWM 50%	PWM = 50% ±50%, no polarity signal required
	PWM frequency range	1 kHz minimum, 100 kHz maximum
	PWM minimum pulse width	220 ns
Indexing	Up to 32 sequences can be launched from inputs or ASCII commands	
Camming	Up to 10 CAM tables can be stored in flash memory	
ASCII	RS-232, 9600~230,400 Baud, 3-wire	
DIGITAL INPUTS		
Number	6	
IN1~5	General purpose inputs LV CMOS 3.3V Schmitt trigger, 100 ns RC filter, max input voltage = +12 Vdc, 10 kΩ pull-up to +5 Vdc 2.2 Vdc min positive threshold, 0.6 Vdc max negative theshold RC time-constant assumes active drive on inputs and does not include 10 kΩ pull-ups	
IN1~3 on DEV Board	HV CMOS 5.0V Schmitt trigger, no RC filter, 0~24 Vdc compatible, 10 kΩ pull-up to +5 Vdc 2.2 Vdc min positive threshold, +0.6 Vdc max negative threshold	
IN6	Motor overtemperature, LV CMOS 3.3V Schmitt trigger, 33 µS RC filter, max input voltage = +12 Vdc 4.99 kΩ pull-up to +5 Vdc, 2.2 Vdc min positive threshold, 0.6 Vdc max negative theshold	
ANALOG INPUT		
Number	1	
Type	Differential, ±10 Vdc range, 5.5 kΩ input impedance, 12 bits, single-pole 1934 Hz input filter	
Function	Torque, velocity, or position command. Or, as general purpose analog input	
DIGITAL OUTPUTS		
Number	4	
OUT1~4	74HCT14 5 V CMOS Schmitt trigger, functions programmable, +5 Vcc Source -4 mA @ VOH = 4.18 Vdc, Sink 4 mA @ VOL = 0.26 Vdc	
OUT4 (DEV board)	Brake control, programmable release time followed by programmable PWM duty-cycle for holding current	
SERIAL COMMUNICATION PORT		
Signals	RxD, TxD, SGND RxD input is 74LVC14 3.3 V Schmitt trigger with 10 kΩ pull-up to +5V TxD output is 74HCT14 5 V Schmitt trigger	
Mode	Full-duplex, DTE serial communication port for drive setup and control, 9,600 to 230,400 Baud	
Protocol	ASCII or Binary format	
Isolation	Non-isolated. Referenced to Signal Ground	
ETHERCAT PORT		
Format	100BASE-TX	
Protocol	EtherCAT, CANopen Application Protocol over EtherCAT (CoE)	
Isolation	External magnetics required. Max voltage with respect to grounds: 32 Vdc	

DC POWER OUTPUT

+5 Vdc	500 mA maximum. Protected for overload or shorts. Shared by dual encoders.

SAFE TORQUE OFF (STO)

Function	PWM outputs are inactive and current to the motor will not be possible when the STO function is active
Safety Integrity Level	SIL 3, Category 3, Performance level d
Inputs	2 two-terminal: STO-IN1, STO-COM1, STO-IN2, STO-COM2
Type	Opto-isolators, 5V compatible
Disabling	Connecting both STO inputs to +5V will deactivate the STO function

PROTECTIONS

HV Overvoltage	+HV > +95 ±1 Vdc	Drive outputs turn off until +HV is < +95 ±1 Vdc (90 V model)
	+HV > +185 ±1 Vdc	Drive outputs turn off until +HV is < +185 ±1 Vdc (180 V models)
HV Undervoltage	+HV < +8.5 ±0.5 Vdc	Drive outputs turn off until +HV > +8.5 Vdc ±0.5 Vdc (90 V models)
	+HV < +19.5 ±0.5 Vdc	Drive outputs turn off until +HV > +19.5 Vdc ±0.5 Vdc (180 V models)
Drive over temperature	PC Board > 90 °C +3/-0 ºC	Programmable as latching or temporary fault
Short circuits	Output to output, output to ground, internal PWM bridge faults	
I^2T Current limiting	Programmable: continuous current, peak current, peak time for drive and motor	
Latching / Non-Latching	Programmable response to errors	

MECHANICAL & ENVIRONMENTAL

Size	35 x 30 x 21.6 mm [1.38 x 1.18 x 0.85 in]
Weight	0.8 oz [0.023 kg]
Ambient temperature	0 to +45 °C operating, -40 to +85 °C storage
Humidity	0 to 95%, non-condensing
Altitude	≤ 2000 m (6,562 ft)
Vibration	2 *g* peak, 10~500 Hz (Sine)
Shock	10 *g*, 10 ms, half-Sine pulse
Contaminants	Pollution degree 2

AGENCY STANDARDS CONFORMANCE

Standards and Directives

Functional Safety

IEC 61508-1, IEC 61508-2, IEC 61508-3, IEC 61508-4 (SIL 3)

Directive 2006/42/EC (Machinery)

ISO 13849-1 (Cat 3, PL e)

IEC 61800-5-2 (SIL3)

Product Safety

Directive 2014/35/EU (Low Voltage)

IEC 61800-5-1

EMC

Directive 2014/30/EU (EMC)

IEC 61800-3

IEC 61800-5-2

Restriction of the Use of Certain Hazardous Substances (RoHS)

Directive 2011/65/EU (RoHS II)

Approvals

UL and cUL recognized component to:

UL 61800-5-1, UL 61800-5-2

IEC 61800-5-1, IEC 61800-5-2

FUNCTIONAL SAFETY

ISO 13849-1
Up to PL e (Cat.3)
IEC 61800-5-2
Up to SIL 3

All of the agency standards are pending at this time.

MOTOR CONNECTIONS

Motor U,V,W	Drive outputs to 3-phase brushless motor, Wye or delta connected For DC brush motor use outputs U & V Minimum inductance: 200 µH line-line
Encoder	Digital encoders, incremental and absolute (see FEEDBACK below)
Halls	Digital U/V/W
Motemp	Input is programmable to disable the drive if motor sensor drives input HI or LO

FEEDBACK

Incremental encoders:	
Digital Incremental Encoder	Quadrature signals, (A, /A, B, /B, X, /X), differential (X, /X Index signals not required) RS-422 line receivers, 5 MHz maximum line frequency (20 M counts/sec), 74HCT thresholds
Absolute encoders:	
BiSS-C Unidirectional, SSI	MA+, MA- (X, /X), SL+, SL- (A, /A) signals, clock output from drive, data returned from encoder
Terminators	All encoder data inputs and clock outputs are differential and require external terminators
Commutation:	Hall signals (U,V,W), 15 kΩ pull-up to +5V, 15 kΩ/100 pF RC to 74LVC3G14 Schmitt trigger at +5 Vcc

HALLS

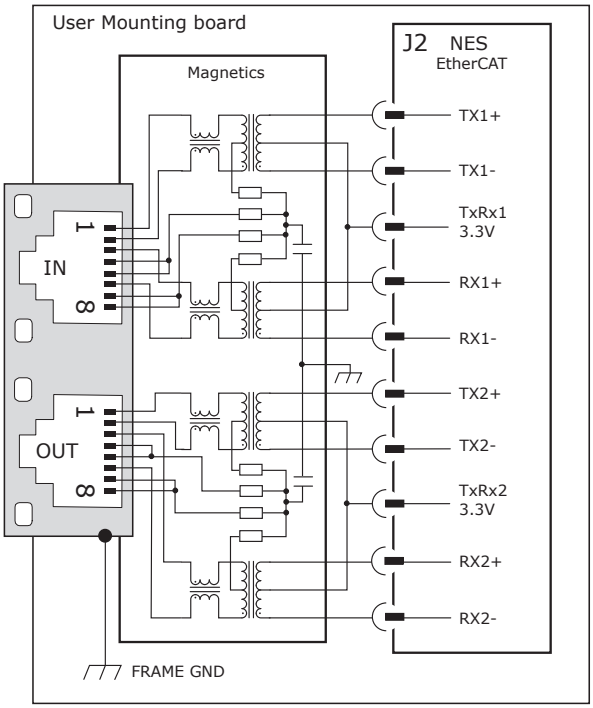
U, V, W:	Single-ended, 120° electrical phase difference Schmitt trigger, 1.0 µs RC filter from active HI/LO sources, 5 Vdc compatible 15 kΩ pull-up to +5 Vdc, 74LVC, 3.3 V thresholds

5V OUTPUT

Number	1
Rating	+5 Vdc @ 500 mA thermal and overload protected, shared by two encoders

ETHERCAT COMMUNICATIONS

EtherCAT is the open, real-time Ethernet network developed by Beckhoff based on the widely used 100BASE-TX cabling system. EtherCAT enables high-speed control of multiple axes while maintaining tight synchronization of clocks in the nodes.
Data protocol is CANopen application protocol over EtherCAT (CoE) based on CiA 402 for motion control devices.
More information on EtherCAT can be found on this web-site: *http://ethercat.org/default.htm*



Network RJ-45

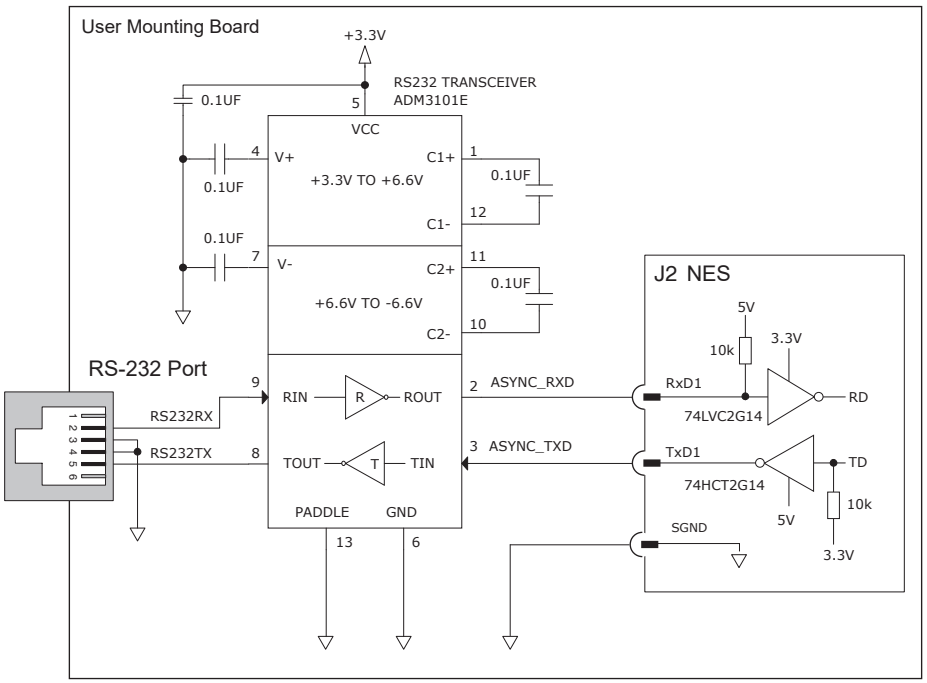
IN Name	Pin	OUT Name
Ecat TX1+	1	Ecat TX2+
Ecat TX1-	2	Ecat TX2-
Ecat RX1+	3	Ecat RX2+
R/C	4	R/C
	5	
Ecat RX1-	6	Ecat RX2-
R/C	7	R/C
	8	

R/C refers to the 75 Ω & 1000 pF components shown.

Drive J2

Name	Pin
(TX1+) TXPA	24
(TX1-) TXNA	26
+3.3V_TXRX1	19
(RX1+) RXPA	20
(RX1-) RXNA	22
(Tx2+) TXPB	25
(Tx2-) TXNB	23
+3.3V_TXRX2	21
(Rx2+) RXPB	29
(Rx2-) RXNB	27

RS-232 COMMUNICATIONS



The serial port is a full-duplex, three-wire (RxD, TxD, SGND) type that operates from 9,600 to 230,400 Baud.
It can be used by CME for drive configuration and setup or by external equipment sending ASCII commands.

The circuit shown here is used on the DEV board and is recommended for user's PC boards. It converts the single-ended TTL signals levels in the NES into the ANSI RS-232 levels which are the standard for serial communications and computer COMM ports.

RS-232 Port

Name	Pins
RS232RX	2
RS232TX	5
SGND	3,4

Drive J2

Name	Pins
RxD1	30
TxD1	32
SGND	34

SAFE TORQUE OFF (STO)

The Safe Torque Off (STO) function is defined in IEC 61800-5-2. Two channels are provided which, when de-energized, prevent the upper and lower devices in the PWM outputs from producing torque in the motor.

This provides a positive OFF capability that cannot be overridden by the control firmware, or associated hardware components. When the opto-couplers are energized (current is flowing in the input diodes), the control core will be able to control the on/off state of the PWM outputs to produce torque in the motor.

INSTALLATION

DANGER	***Refer to the 16-121699 Nano Micro Modules NES & NPS USER GUIDE***
	The information provided in the *16-121699 Nano Micro Modules NES & NPS USER GUIDE* must be considered for any application using the drive's STO feature. ***FAILURE TO HEED THIS WARNING CAN CAUSE EQUIPMENT DAMAGE, INJURY, OR DEATH.***

STO DISABLE

In order for the PWM outputs of the NES to be activated, current must be flowing through the opto-couplers that are connected to the STO-IN1 and STO-IN2 terminals and the drive must be in an ENABLED state. When either of the opto-couplers are OFF, the drive is in a Safe Torque Off (STO) state and the PWM outputs cannot be activated by the control core to drive a motor.

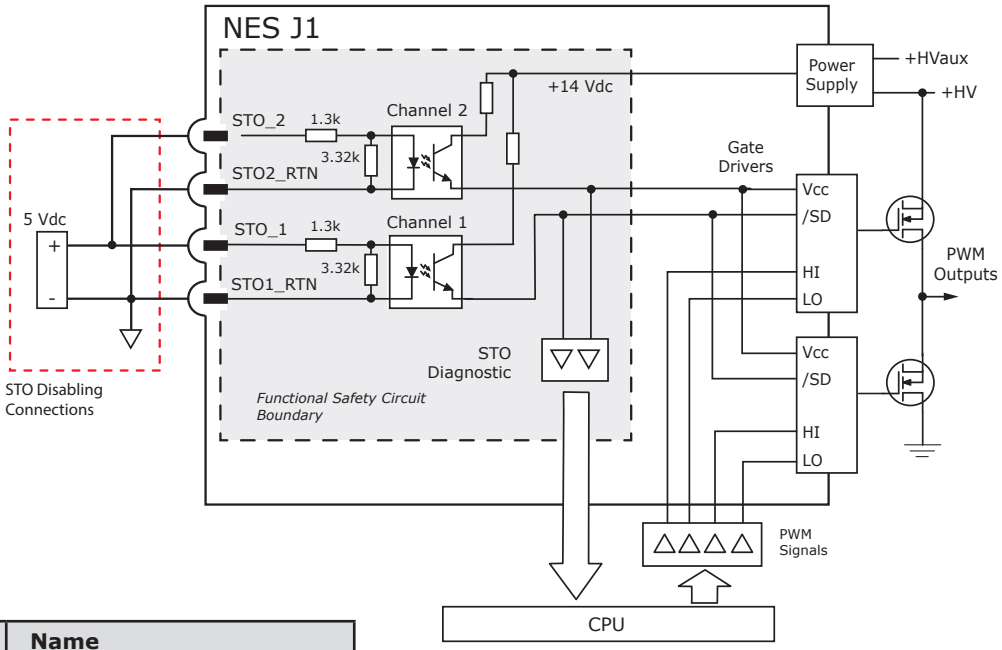
This diagram shows connections that will energize both opto-couplers from a +5V source. When this is done the STO feature is disabled and control of the output PWM stage is under control of the digital control core.

If not using the STO feature, these connections must be made in order for the drive to be enabled.

DEV BOARD STO DISABLE CONNECTIONS

Current must flow through all of the opto-couplers before the drive can be enabled

FUNCTIONAL DIAGRAM



J1 STO

Name	Pin		Name
STO_IN1	1	2	STO_IN1_RTN
STO_IN2	3	4	STO_IN2_RTN
STO_STATUS_OUTPUT	5	6	STO_STATUS_OUTPUT_RTN

STO OPERATION

STO Input Voltage	STO State
STO1_IN *AND* STO2_IN ≥ 3.3 Vdc	STO Inactive. Drive can be enabled to produce torque
STO1_IN *OR* STO2_IN ≤ 2.0 Vdc	STO Active. Drive cannot be enabled to produce torque

Note: Voltages in the STO Operation table are referenced between STO_INx and STO_INx_RTN in J1
E.g. V(STO1_IN) = V(STO_IN1) - V(STO_IN1_RTN)

DIGITAL COMMAND INPUTS: POSITION

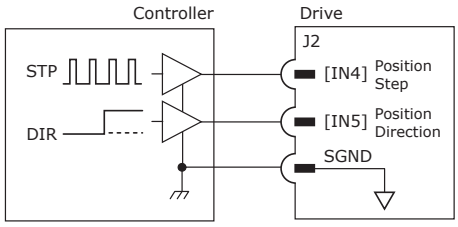
STAND-ALONE MODE DIGITAL POSITION-CONTROL INPUTS

NES works with motion controllers that output pulses to command Position.
These formats are supported:

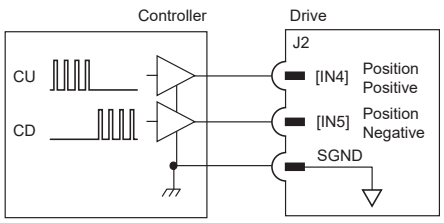
Step/Direction
Count-Up/Count-Down (CU/CD)
A/B Quadrature Encoder

In Step/Direction mode, a pulse-train controls motor Position, and the Direction is controlled by a DC level at the Direction input. CU/CD (Count-Up/Count-Down) signals command the motor to move CW or CCW depending on which input the pulse-train is directed to. The motor can also be operated in an electronic gearing mode by connecting the inputs to a quadrature encoder on another motor. In all cases the ratio between input pulses and motor revolutions is programmable.

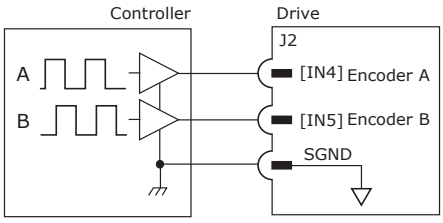
STEP/DIRECTION INPUTS



COUNT-UP/COUNT-DOWN INPUTS



QUAD A/B ENCODER INPUTS



Command Options	Name	J2 Pins
Step, Count Up, Encoder A	IN4	8
Direction, Count Down, Encoder B	IN5	9

J2 SGND Pins
3,4,11,12,33,34,49,50

DIGITAL COMMAND INPUTS: VELOCITY, TORQUE

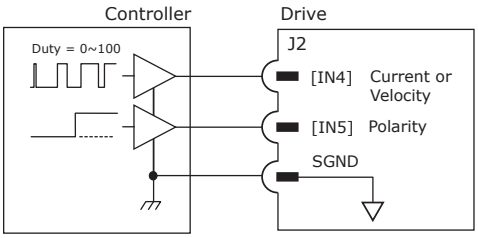
STAND-ALONE MODE DIGITAL VELOCITY-TORQUE INPUTS

NES works with motion controllers that output pulses to command Velocity or Torque.
These formats are supported:

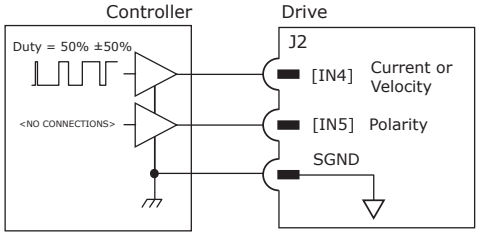
Pulse/Direction
PWM 50%

In Pulse/Direction mode, a pulse-train with variable duty cycle on IN4 controls Velocity or Torque from 0~100%.
IN5 HI or LO controls the direction of the Velocity or polarity of the Torque.
In 50% PWM mode, a single signal of 50% duty cycle commands 0% Velocity/Torque.
Increasing the duty cycle to 100% commands positive Velocity/Torque.
Decreasing the duty cycle to 0% commands negative Velocity/Torque.

PWM & DIRECTION



50% PWM



Command Options	Name	J2 Pins
PWM Vel/Trk, PWM Vel/Trk & Direction	IN4	8
PWM/Dir Polarity, (none)	IN5	9

HIGH SPEED INPUTS: IN1, IN2, IN3, IN4, IN5

The six digital inputs to the NES are programmable to a selection of functions.
All have 100 ns RC filters when driven by active sources (CMOS, TTL, etc.) and all have 10 kΩ pull-up resistors to +5 Vdc.
In addition to the selection of functions, the active level for each input is individually programmable.
Input *level* functions have programmable HI or LO to activate the function.
Input *transition* functions are programmable to activate on LO -> HI, or HI -> LO transitions.

INPUT LEVEL FUNCTIONS

- Drive Enable, Enable with Clear Faults, Enable with Reset
- PWM Sync
- Positive Limit Switch
- Negative Limit Switch
- Home Switch
- Encoder Fault
- Motor Temperature Sensor Input
- Motion Abort
- High-Resolution Analog Divide

INPUT TRANSITION FUNCTIONS

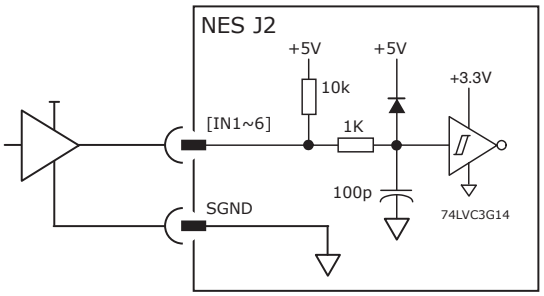
- Clear Faults and Event Latch
- Drive Reset
- PWM Sync Input
- Trajectory Update
- Count Input Edges, Save to Register
- High-Speed Position Capture
- Simulated Absolute Encoder Burst
- Abort Move if > N Counts From Destination in Register

SPECIFICATIONS

Input	Data	Notes
Input Voltages	HI	V_T+ = 1.42~2.38 Vdc
	LO	V_T+ = 0.68~1.6 Vdc
	Hys	V_H = 0.44~1.26
	Max	+6 Vdc
	Min	0 Vdc
Pull-up	R1	10 kΩ
Low pass filter	R2	1 kΩ
	C1	100 pF
	RC	IN1~5: 0.1 µs IN6: 33 us

CONNECTIONS

Name	J2 Pins
IN1	5
IN2	6
IN3	7
IN4	8
IN5	9



** IN7 is the SLI-MISO signal when the SLI Port is in use.*

J2 SGND Pins
3,4,11,12,33,34,49,50

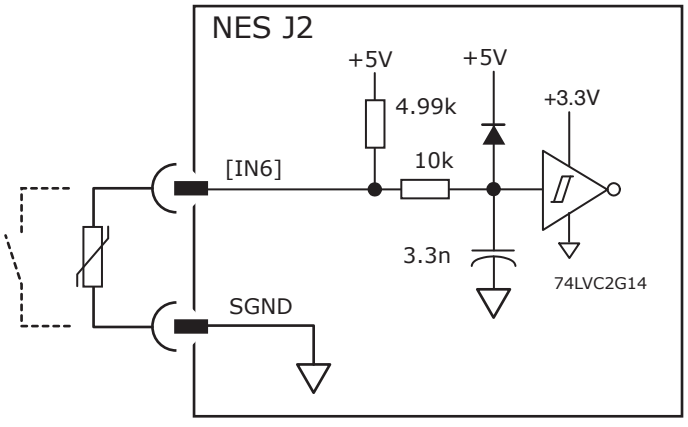
Inputs IN1~5 have 100 nanosecond rise time RC filters, each with a 10K pullup resistor to +5 VDC.
12 Vdc compatible, 2.2V minimum HI threshold voltage, 0.6V max LO threshold voltage
IN1~6 are +3.3V logic, IN7 is +5V logic.

MOTOR OVERTEMP INPUT: IN6

Input IN6 has a 49 microsecond rise time RC filter, with a 4.99 kΩ pullup resistor to +5 VDC. Input IN6 is designed to interface with an industry standard PTC thermistor IAW BS 49990111(1987) for built-in thermal protection of the motor as a default.
If not used for the Motemp function, IN6 can be re-programmed for other input functions.

CONNECTIONS

Name	J2 Pins
IN6	10



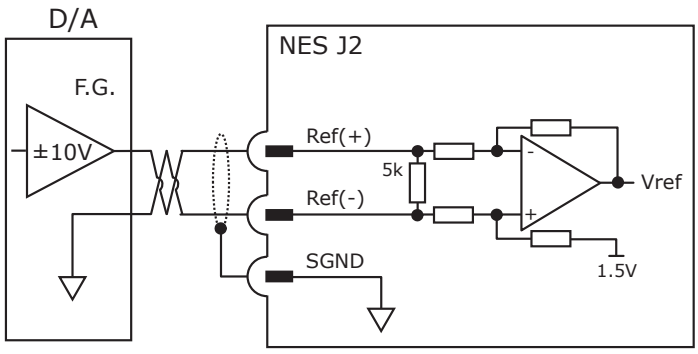
ANALOG INPUT: AIN1

As a reference input it takes Position/Velocity/Torque commands from a controller.
If not used as a command input, it can be used as general-purpose analog input.

SPECIFICATIONS

Spec	Data	Notes
Input Voltage	Vref	±10 Vdc
Input Resistance	Rin	5.0 kΩ

Name	J2 Pins
Ref(+)	2
Ref(-)	1



DIGITAL OUTPUTS: OUT1~OUT4

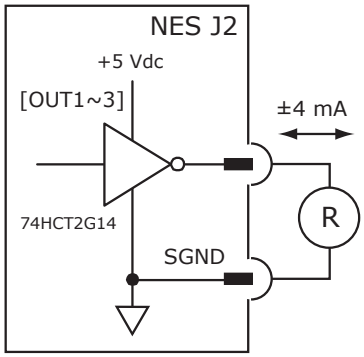
Digital outputs [OUT1~4] are CMOS inverters. They operate from +5V and can source/sink 4 mAdc.
The output functions shown below are programmable to turn the output ON (HI) or OFF (LO) when active.

OUTPUT FUNCTIONS

- Fault
- Custom event
- PWM Sync
- Custom Trajectory status
- Custom position-triggered output
- Program control
- Brake control (see below)

Name	J2 Pins
OUT1	13
OUT2	14
OUT3	15
OUT4	16

J2 SGND Pins
3,4,11,12,33,34,49,50



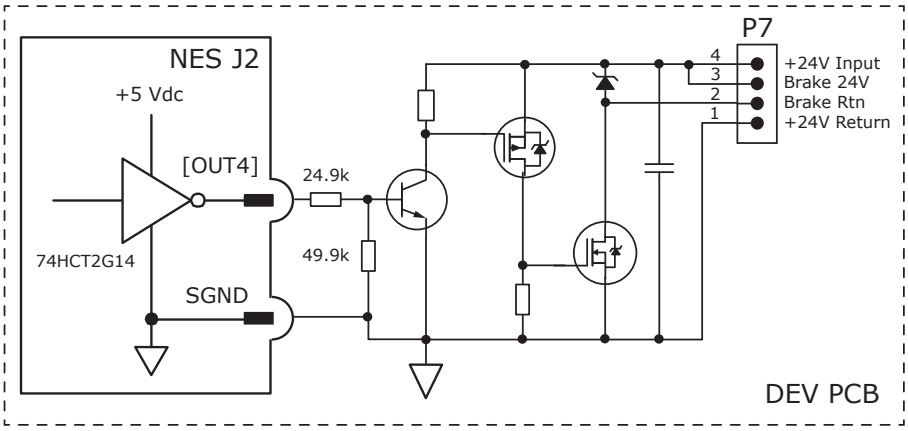
BRAKE OUTPUT: OUT4

The default function of OUT4 is control of a motor holding brake using the DEV board that has components to sink the higher current of the brake. If not used for brake control it can be programmed as a logic output.

OUTPUT FUNCTION

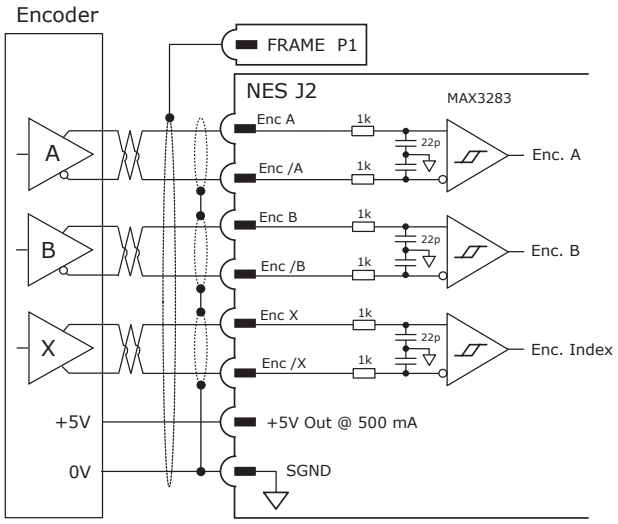
- Motor holding brake when NES is mounted to an DEV PCB.
- Same functions as OUT1~OUT3 if drive is used without DEV PCB

Name	J2 Pins
OUT4	16



ENCODER 1 (PRIMARY FEEDBACK)

QUAD ENCODER WITH INDEX



A/B/X SIGNALS

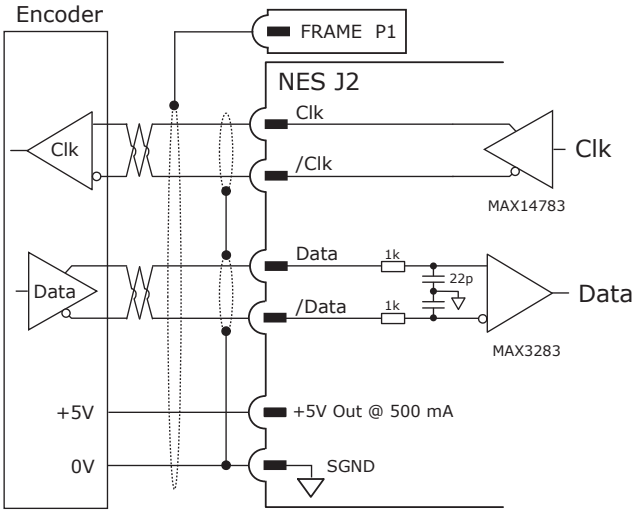
Name	J2 Pins
Enc A	43
Enc /A	44
Enc B	45
Enc /B	46
Enc X	47
Enc /X	48
+5V	57,59

FRAME GROUND
P1

J2 SGND Pins
3,4,11,12,33,34,49,50

SSI ABSOLUTE ENCODER

The SSI (Synchronous Serial Interface) is an interface used to connect an absolute position encoder to a motion controller or control system. The NES drive provides a train of clock signals in differential format to the encoder which initiates the transmission of the position data on the subsequent clock pulses. The number of encoder data bits and counts per motor revolution are programmable.
The hardware bus consists of two signals: SCLK and SDATA. The SCLK signal is only active during transfers. Data is clocked in on the falling edge of the clock signal.



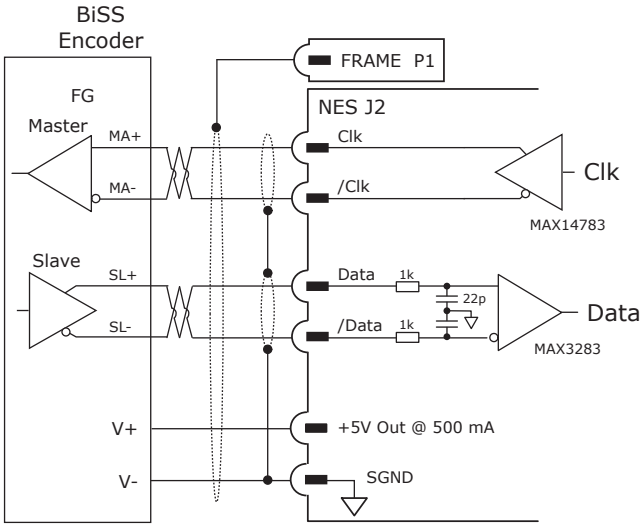
SSI, BiSS SIGNALS

SSI	BiSS	J2 Pins
Clk	MA+	47
/Clk	MA-	48
Data	SL+	43
/Data	SL-	44
+5V		57,58

BiSS-C ABSOLUTE ENCODER

BiSS-C is an - Open Source - digital interface for sensors and actuators. BiSS-C refers to principles of well known industrial standards for Serial Synchronous Interfaces like SSI, AS-Interface® and Interbus® with additional options.

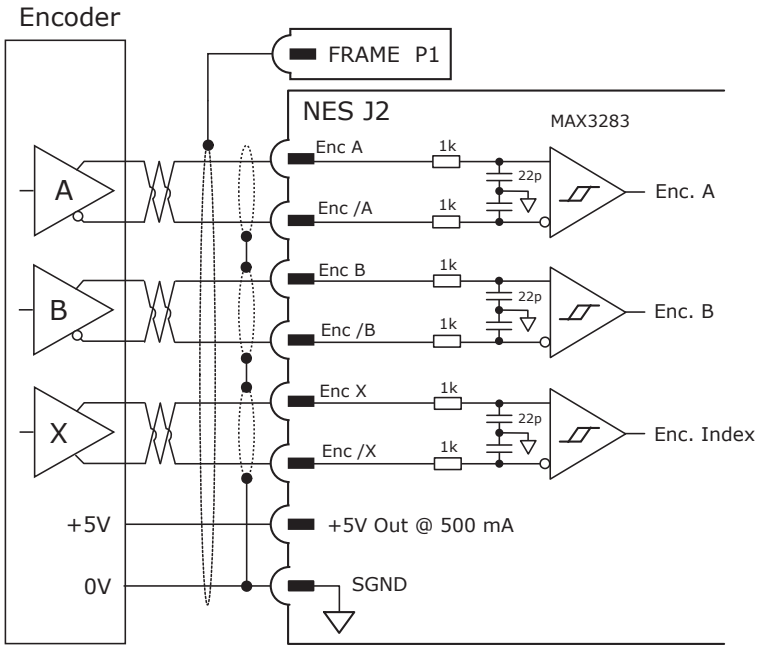
Serial Synchronous Data Communication
- Cyclic at high speed
- 2 unidirectional lines Clock and Data
  - Line delay compensation for high speed data transfer
  - Request for data generation at slaves
  - Safety capable: CRC, Errors, Warnings
  - Bus capability incl. actuators
- Bidirectional
  - BiSS C-protocol: Continuous mode



Note: Single (outer) shields should be connected at the drive end. Inner shields should only be connected to Signal Ground on the drive.

ENCODER 2: SECONDARY FEEDBACK

QUAD ENCODER WITH INDEX



A/B/X SIGNALS

Name	J2 Pins
Enc A	51
Enc /A	52
Enc B	53
Enc /B	54
Enc X	55
Enc /X	56
+5V	57,59

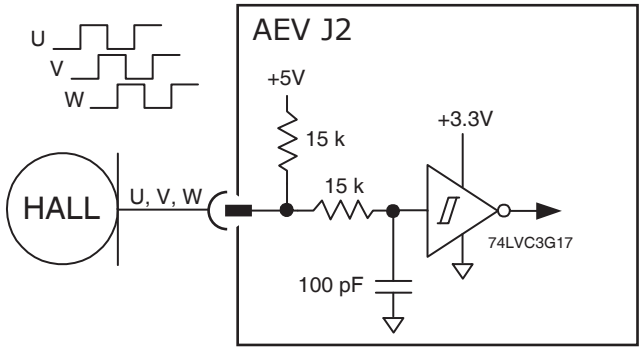
FRAME GROUND
P1

J2 SGND Pins
3,4,11,12,33,34,49,50

OTHER MOTOR CONNECTIONS

HALLS

Hall sensors in a brushless motor are produced from the magnetic field in the motor and provide commutation feedback without an encoder. When used with incremental encoders, they enable the motor to operate without a phase-finding cycle.

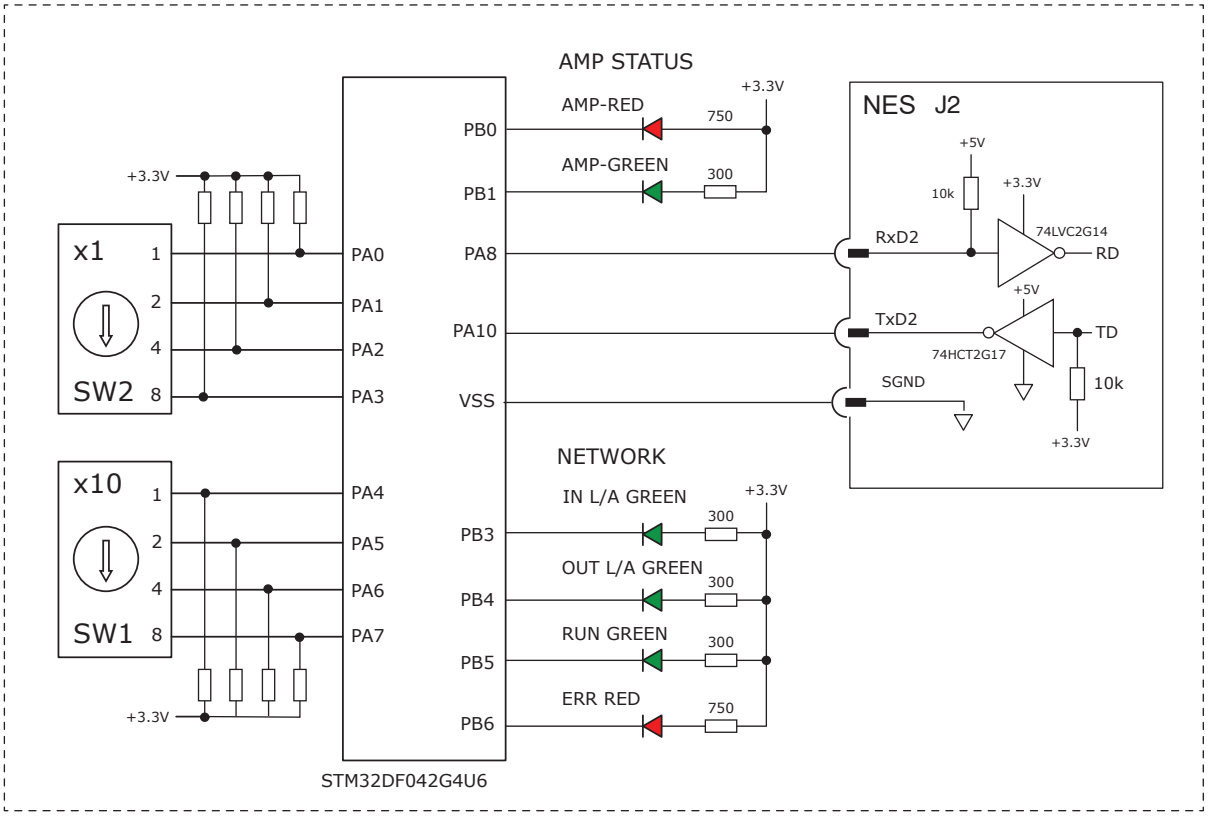


HALL SIGNALS

Name	J2 Pins
Hall U	39
Hall V	40
Hall W	41

SECONDARY SERIAL PORT

This serial port is is used in combination with the DEV board driving the LEDs and reading the address switches for the EtherCAT device ID (Station Alias).



SERIAL SIGNALS

Name	J1 Pins
ASYNC_RxD2	35
ASYNC_TxD2	37
SGND	33

J2 SGND Pins
3,4,11,12,33,34,49,50

+HV CONNECTIONS

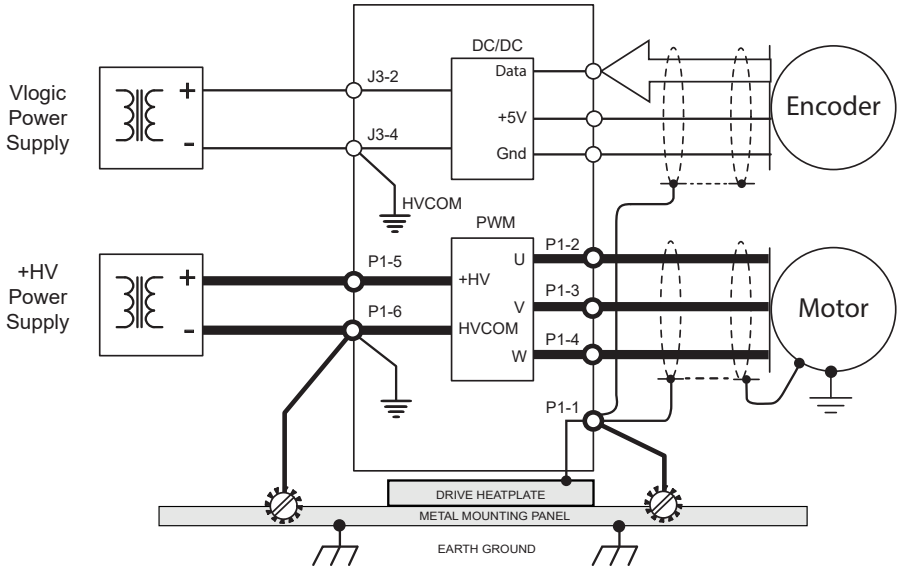
POWER SUPPLIES

The drive main power, +HV, is typically supplied by unregulated DC power supplies. These must be isolated from the mains, and all circuits should be grounded to earth at some point. The +HV supply connects to P5 and P6. For good wiring practice, the +HV wires should be twisted together for noise suppression, and the power supply should not be grounded. Doing this ensures that the higher currents flowing in these conductors will not flow through any circuit grounds where they might induce noise.

During deceleration, mechanical energy in the motor and load is converted back into electrical energy that must be dissipated as the motor comes to a stop. While some of this is converted to heat in the motor windings, the rest of it will flow through the drive into the power supply. An external storage capacitor should be used if the load has appreciable inertia, and this should be sized such that adding the undissipated energy from the motor will not raise the voltage beyond the point at which the drive shuts down. When this is not possible, an external 'dumper', or regenerative energy dissipater must be used which acts as a shunt regulator across the +HV and Gnd terminals.

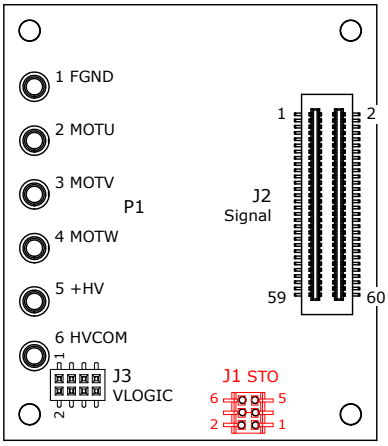
GROUNDING

A P1-6 connection to ground keeps the +HV power source stable at the drive while the voltage at the power supply (-) varies due to the cable resistance and the +HV current. Grounding at P1-1 provides a PE (Protective Earth) connection as well as a point to ground the motor cable shields.



P1~P6

Name	Pins
Chassis	P1
MOTU	P2
MOTV	P3
MOTW	P4
+HV	P5
HVCOM	P6



VLOGIC CONNECTIONS

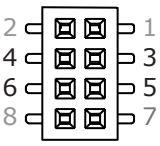
DESCRIPTION

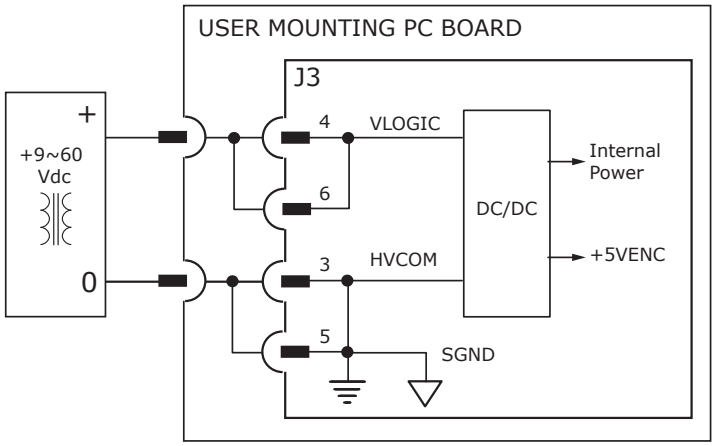
VLOGIC is required for operation of the drive. It powers the internal logic and control circuits. Encoder +5V is derived from VLOGIC. When using the STO feature, VLOGIC must be produced by power supplies with transformer isolation from the mains and PELV or SELV ratings and a maximum output voltage of 60 Vdc.

If the motor can operate from voltages of 60 Vdc or less, the +HV and VLOGIC can be driven from a single power supply.

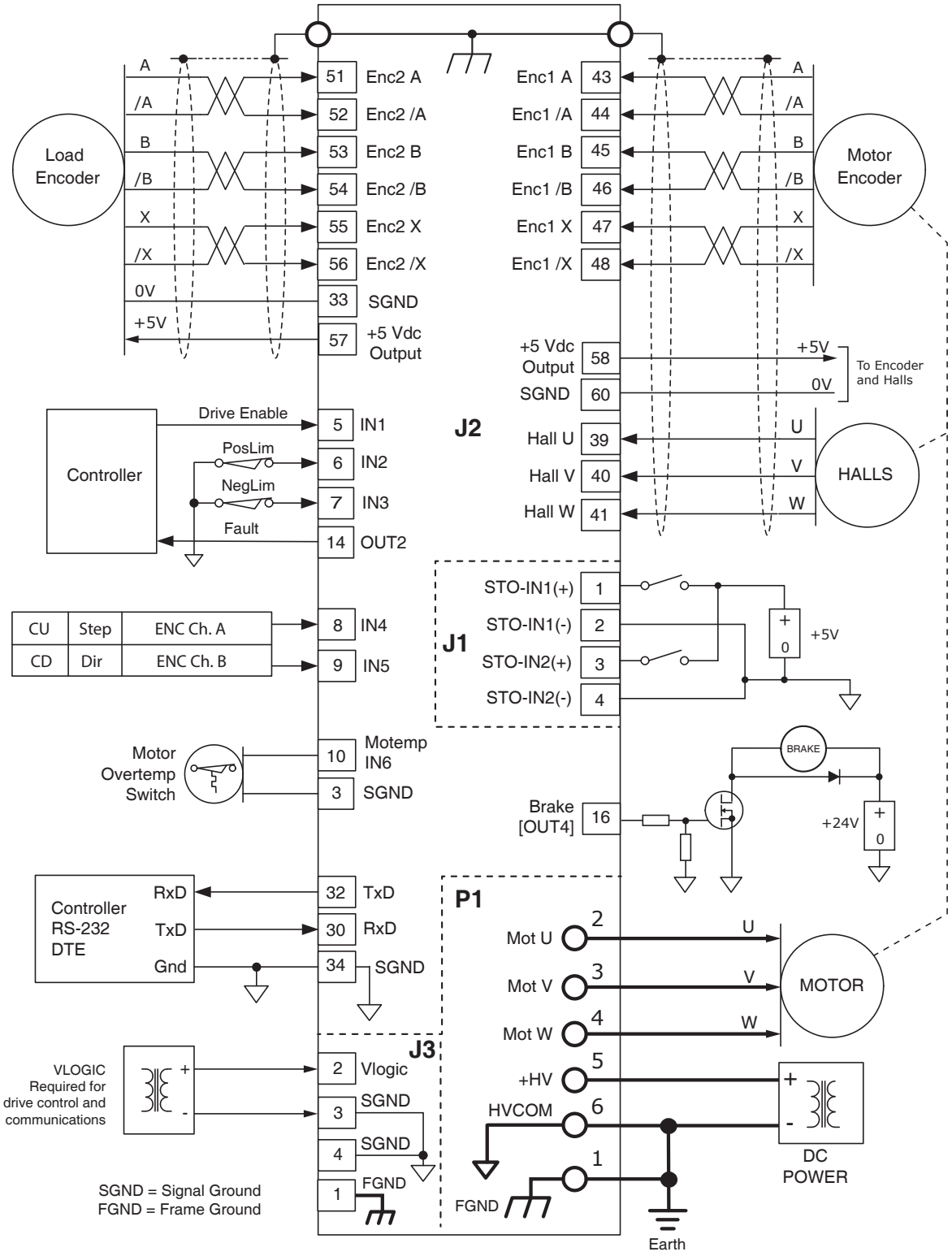
J3 VLOGIC

Name	Pin		Name
n.c.	2	1	n.c.
VLOGIC	4	3	HVCOM
VLOGIC	6	5	HVCOM
n.c.	8	7	n.c.





NES TYPICAL CONNECTIONS

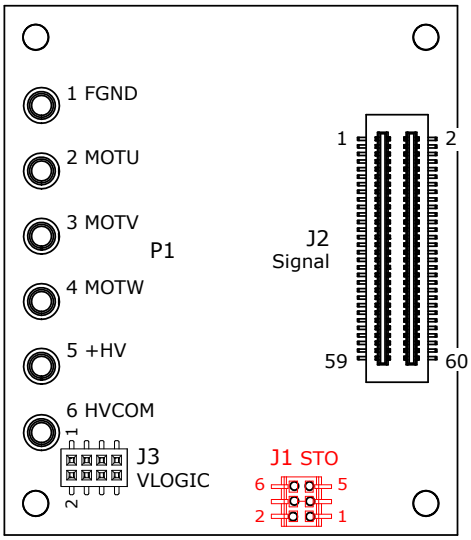


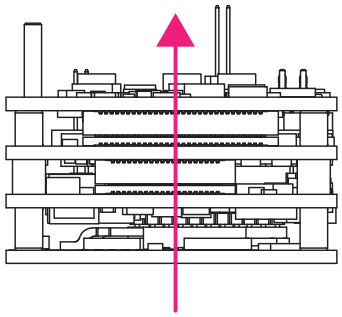
PC BOARD CONNECTIONS

P1 MOTOR & +HV

Name	Pin
FGND	1
Mot U	2
Mot V	3
Mot W	4
+HV	5
HVCOM	6

This page shows the pins and signals looking down on a user PC board.





J2 SIGNAL

Name	Pin		Name
REFIN1-	1	2	REFIN1+
SGND	3	4	SGND
(ENABLE) IN1	5	6	IN2
IN3	7	8	IN4
IN5	9	10	IN6
SGND	11	12	SGND
DOUT1	13	14	DOUT2
DOUT3	15	16	DOUT4 (BRAKE)
SGND	17	18	SGND
+3.3V_TXRX1	19	20	RXPA (RX1+)
+3.3V_TXRX2	21	22	RXNA (RX1-)
(TX2-) TXNB	23	24	TXPA (TX1+)
(TX2+) TXPB	25	26	TXNA (TX1-)
(RX2-) RXNB	27	28	SGND
(RX2+) RXPB	29	30	ASYNC_RXD1
SGND	31	32	ASYNC_TXD1
SGND	33	34	SGND
ASYNC_RXD2	35	36	CANTX
ASYNC_TXD2	37	38	CANRX
HALLU	39	40	HALLV
HALLW	41	42	+3.3V
ENCA1_UBC_DAT	43	44	/ENCA1_UBC_DAT
ENCB1	45	46	/ENCB1
ENCX1_UBC_CLK	47	48	/ENCX1_UBC_CLK
SGND	49	50	SGND
ENCA2	51	52	/ENCA2
ENCB2	53	54	/ENCB2
ENCX2	55	56	/ENCX2
+5VENC	57	58	+5V
+5VENC	59	60	+3.3V

J3 VLOGIC

Name	Pin		Name
N.C.	2	1	N.C.
VLOGIC	4	3	HVCOM
	6	5	
N.C.	8	7	N.C.

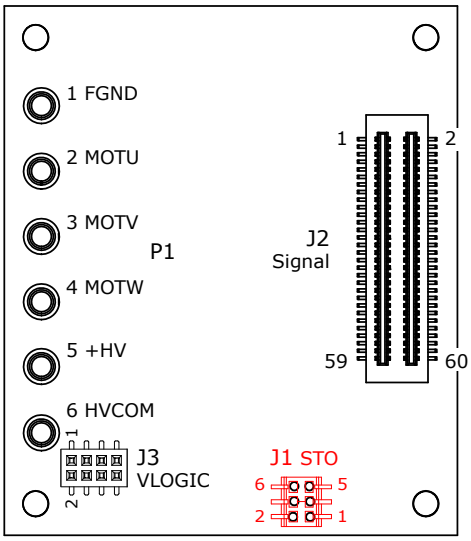
J1 STO

Name	Pin		Name
STO_STATUS_OUTPUT_RTN	6	5	STO_STATUS_OUTPUT
STO2_RTN	4	3	STO2
STO1_RTN	2	1	STO1

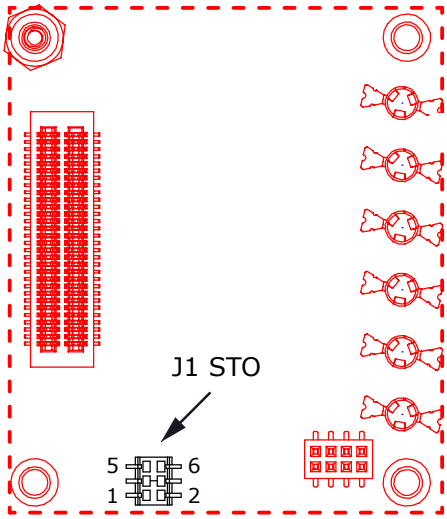
NOTE:
THE STO CONNECTOR J2 IS MOUNTED ON THE BOTTOM SIDE OF THE PCB

PC BOARD CONNECTORS

The pin sockets P1~P6 are rated for 6 A continuous.
For operation at higher currents the drive pins should be soldered to the PCB etched copper.



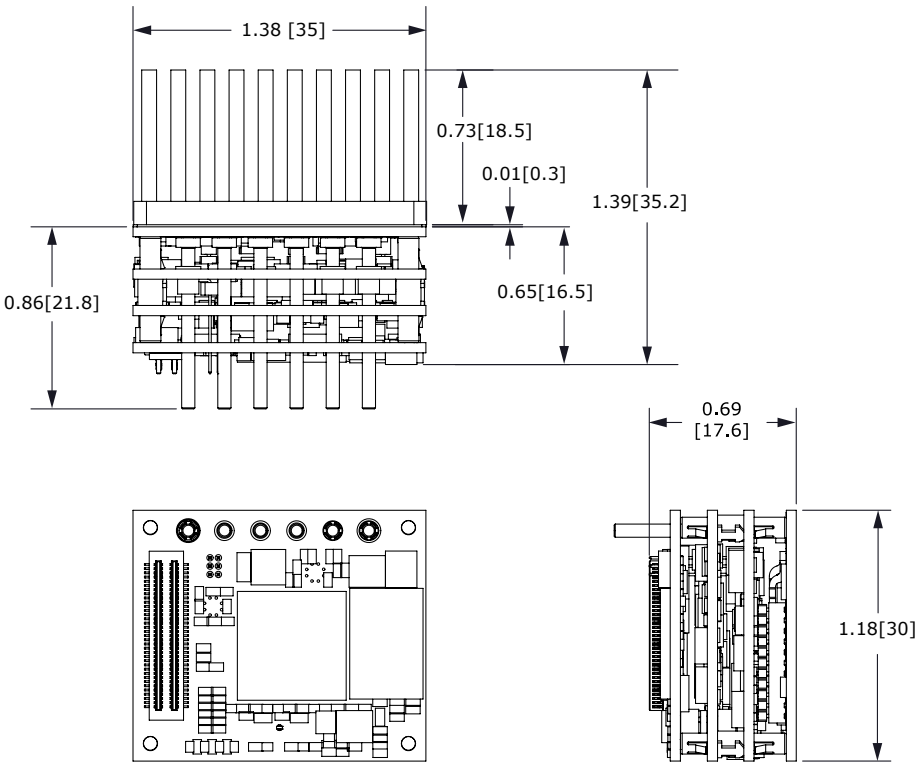
PC Board
TOP VIEW



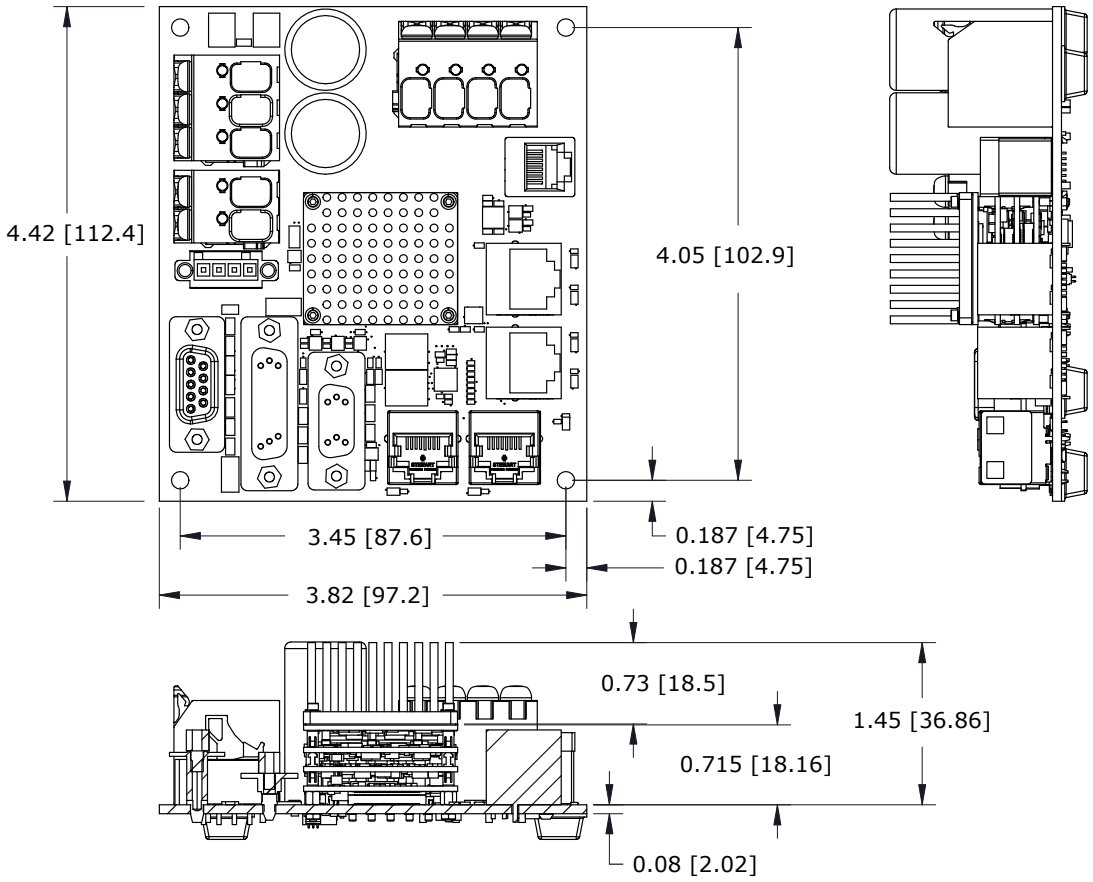
PC Board
BOTTOM VIEW

Ref Des	Label	Mfgr	Part Number	Description
J1	STO	Samtec	CLM-103-02-L-D-BE	Header, 6 pos, 1 mm pitch
J2	Signal	Kunshan WCON	3620-S060-022G202	Header, 60 pos, 0.5 mm pitch
J3	VLOGIC	WCON	2521-202MG3CUNR1	Header, 4 pos, 1 mm pitch
P1~P6	+HV, Motor	Harwin	S9121-45R	Socket, 2 mm diam

DIMENSIONS

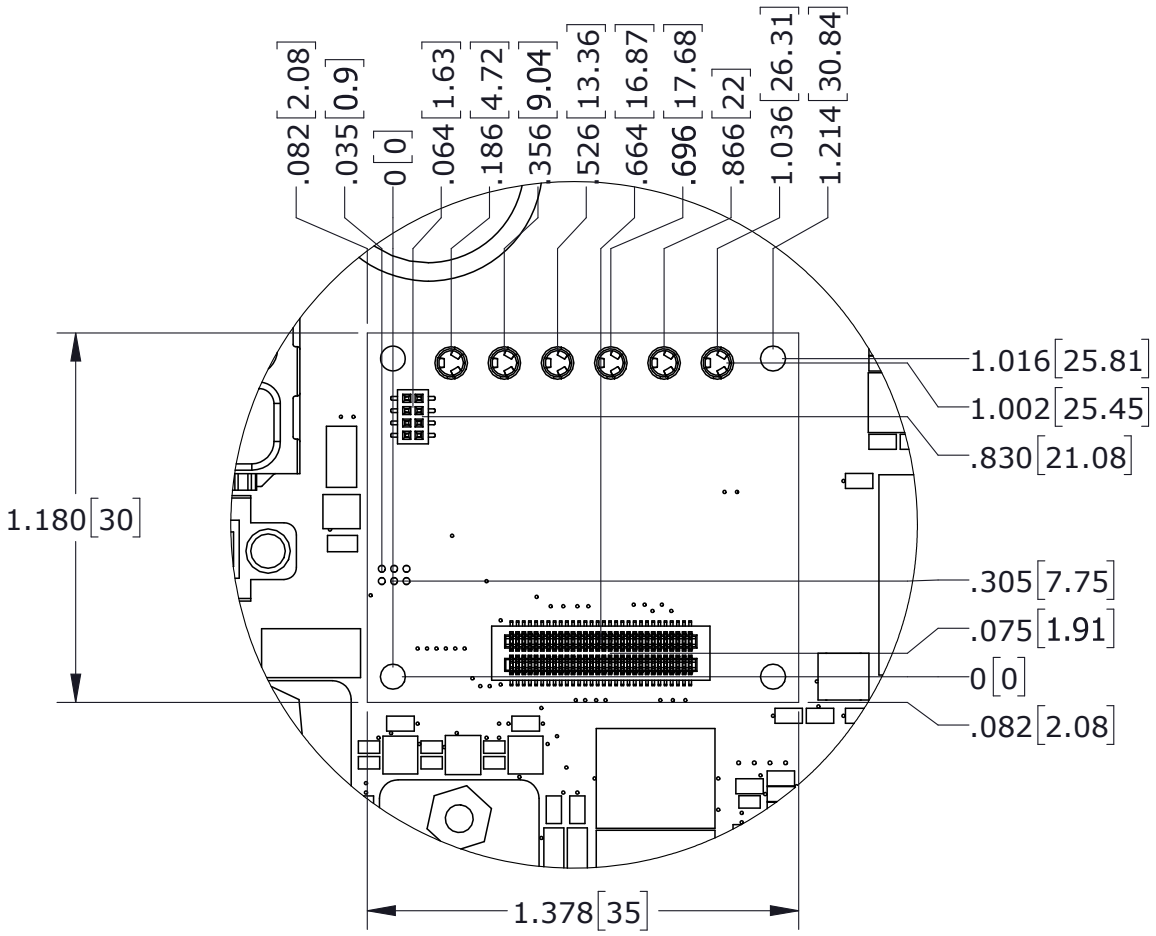


Dimensions are in inches [mm]



PC BOARD MOUNTING DIMENSIONS

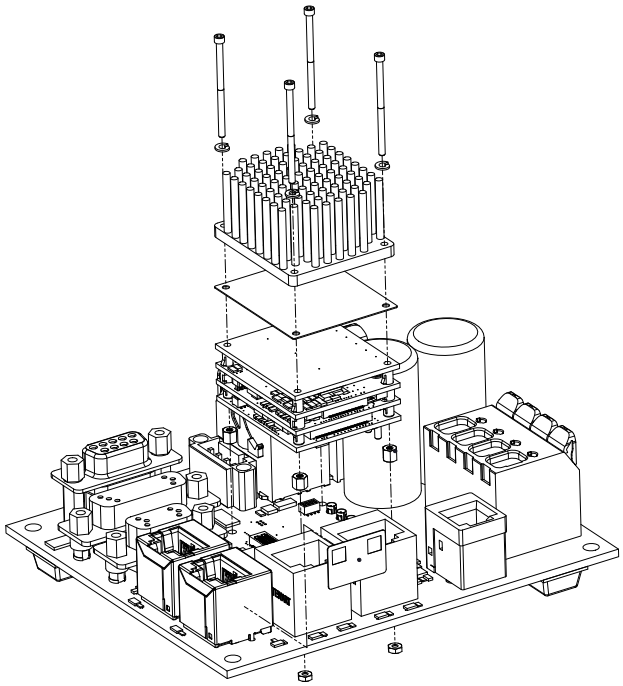
Looking down on the mounting PC board for the drive. The STO connector is mounted on the underside of the PC board.

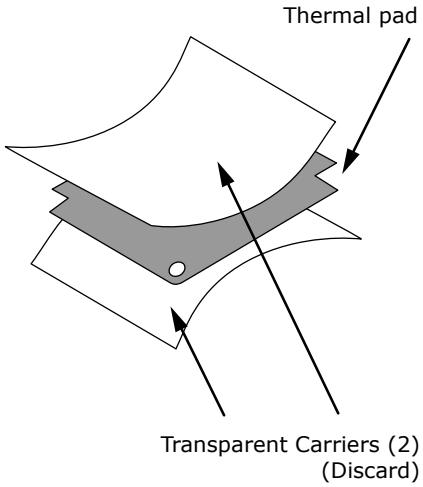


DEV KIT HEATSINK MOUNTING

A thermal pad is used in place of heatsink grease. The pad is die-cut to shape and has notches for the heat sink mounting screws. There are two protective sheets, blue on one side and clear on the other. Both must be removed when the interface pad is installed.

1: Remove the blue protective sheet from one side of the pad.
2: Place the interface pad on the drive, taking care to center the pad holes over the heatplate mounting holes.
3 Remove the clear protective sheet from the pad.
4 Mount the heatsink onto the drive taking care to see that the holes in the heatsink, interface pad, and drive all line up.
5 Torque the _#0-80 mounting screws to 4 in-lb, 64 in-oz, 0.45 Nm.



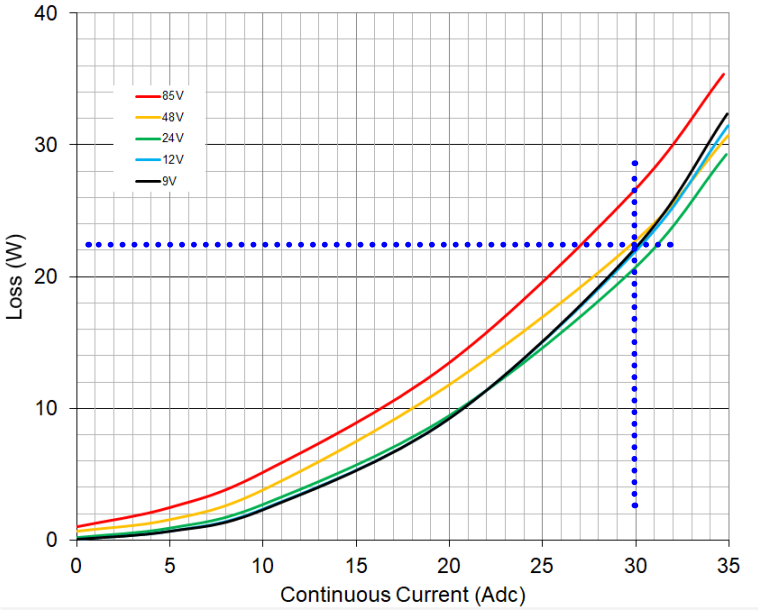


N-HK Heatsink Kit

Item	Description	Quantity
1	Screw, #0-80, hex, socket cap screw, 1 in [25.4 mm]. stainless steel	4
2	Heatsink, NES/NPS, 0.728 [18.49] tall, pins	1
3	Thermal pad, NES/NPS	1
4	Spacer, hex, 0.125 in [3.18 mm], 0-80 UNC 2B thread, 0.120 in [3.05 mm] tall, AL	4
6	Washer, medium split lock, #0, 18-8, stainless steel,	4
7	Nut, #0-80, fine thread, stainless steel	4
5	Ifixit Opening Tool	1

THERMALS: PWM OUTPUTS DISSIPATION

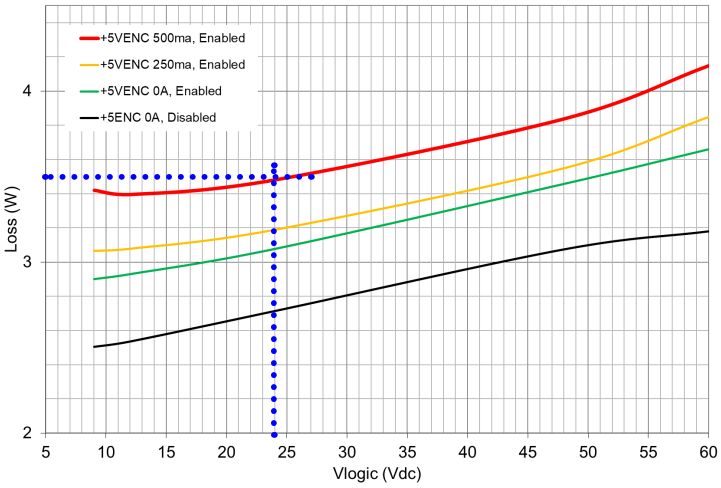
NES-090-70



This chart shows the power dissipation in the drive when the PWM outputs are driving a motor. Adding the PWM dissipation to the Vlogic dissipation will yield the total dissipation in Watts for the drive. The dotted lines in the chart show a dissipation of 22 W. at a continuous current of 30 Adc and +HV = 48 Vdc.

THERMALS: VLOGIC & ENCODER +5V OUTPUT DISSIPATION

NES All Models



This chart shows the power dissipation in the Vlogic circuits that power the drives control circuits and external encoders. Adding the PWM dissipation to the Vlogic dissipation will yield the total dissipation in Watts for the drive.
The dotted lines in the chart show a dissipation of 3.5 W. at Vlogic = 24 Vdc when the drive is in an Enabled state and outputting 250 mA for an encoder.

THERMALS: HEASINK COOLING

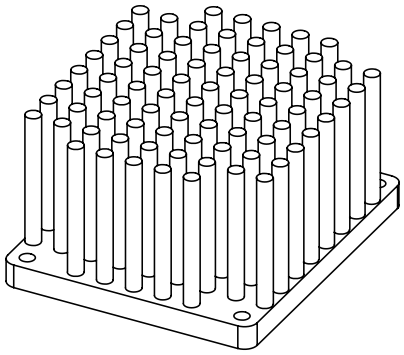
Thermal resistance Rth is a measure of the way the drive resists the flow of heat produced internally to the environment. The lower the resistance the more freely the heat can be dissipated. Thermal resistance Rth is in units of degrees-Centigrade per Watt (C/W). Lowering Rth can be done with heatsinks that increase the area that is exposed to the environment and by moving air over the surfaces with fans. The flow of fan forced air is measured in Linear-Feet-per-Minute (LFM).

No Heatsink

LFM	0	100	200	300
Rth				

Pins Heatsink Forced-Air

LFM	0	100	200	300
Rth	1.57			



Pins Heatsink

DEV BOARD

J4 MOTOR

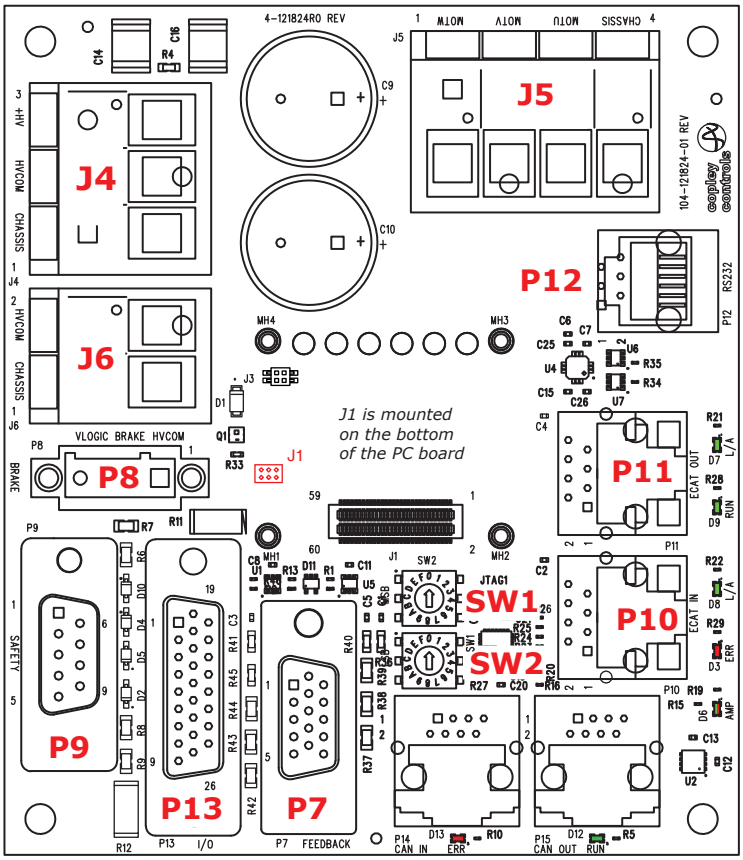
Signal	Pin
+HV	3
HVCOM	2
FGND	1

J6 FGND/ HVCOM

Signal	Pin
HVCOM	2
FGND	1

P8 BRAKE

Signal	Pin
HVCOM	1
Brake	2
VLOGIC	3
VLOGIC	4



J5 MOTOR

Pin	Signal
1	MOTW
2	MOTV
3	MOTU
4	FGND

P12 RS-232

Pin	Signal
6	n.c.
5	TxD
4	SGND
3	SGND
2	RxD
1	n.c.

P10 ECAT IN

Pin	Name
8	FGND
7	n.c.
6	Rx1-
5	TxRx1
4	Rx1+
3	Tx1-
2	TxRx1
1	Tx1+

P11 ECAT OUT

Pin	Name
8	FGND
7	n.c.
6	Rx2-
5	TxRx2
4	Rx2+
3	Tx2-
2	TxRx2
1	Tx2+

P9 STO

Signal	Pin		Signal
FGND	1	6	STO_STATUS_OUTPUT
STO1_24V_IN	2	7	STO_STATUS_OUTPUT_RTN
STO1_RTN	3	8	SGND
STO2_24V_IN	4	9	VLOGIC +24V
STO2_RTN	5		

P7 ENCODER 1

Pin	Signal	Pin	Signal	Pin	Signal
1	FGND	6	Hall V	11	Enc1 /B
2	+5 V	7	Enc1 /X	12	Enc1 B
3	Hall U	8	Enc1 X	13	Enc1 /A
4	+5 V	9	Hall W	14	Enc1 A
5	SGND	10	Fault (IN6)	15	SGND

P13 I/O & ENCODER 2

Pin	Signal	Pin	Signal	Pin	Signal
1	FGND	10	IN5 12V	19	SGND
2	Aref-	11	n.c.	20	+5 V
3	Aref+	12	n.c.	21	Enc2 /X
4	IN1 24V	13	n.c.	22	Enc2 X
5	IN2 24V	14	n.c.	23	Enc2 /B
6	IN3 24V	15	SGND	24	Enc2 B
7	IN4 12V	16	OUT1	25	Enc2 /A
8	n.c.	17	OUT2	26	Enc2 A
9	n.c.	18	OUT3		

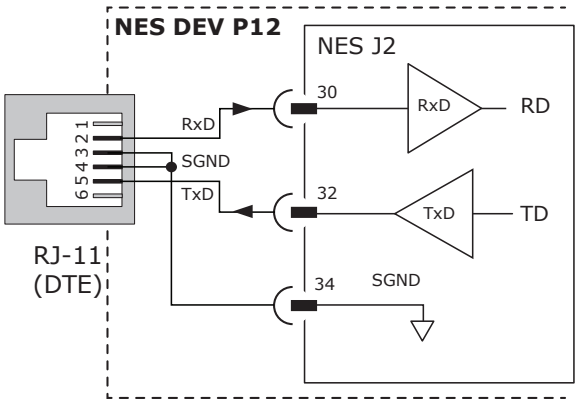
DEV BOARD

RS-232 CONNECTION

The RS-232 port is used to configure the drive for stand-alone applications, or for configuration before it is installed into an EtherCAT network. CME software communicates with the drive over this link and is then used for complete drive setup. The EtherCAT Device ID that is set by the rotary switches can be monitored, and a Device ID programmed as well.
The RS-232 connector, P12, is a modular RJ-11 type that uses a 6-position plug, four wires of which are used for RS-232. A connector kit is available (SER-CK) that includes the modular cable, and an adaptor to interface this cable with a 9-pin RS-232 port on a computer.

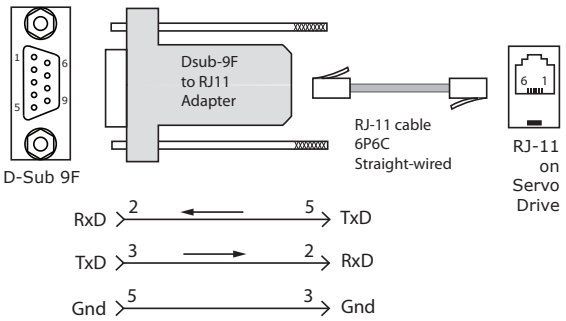
P12 DEV RS-232

Pin	Signal
2	RxD
3,4	SGND
5	TxD



SER-CK SERIAL CABLE KIT

The SER-CK provides connectivity between a D-Sub 9 male connector and the RJ-11 connector P12 on the DEV board. It includes an adapter that plugs into the COM1 (or other) port of a PC and uses a straight-through modular cable to connect to the NES. The connections are shown in the diagram below.



SER-USB-RJ11

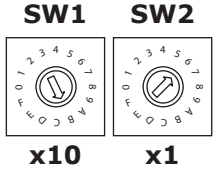
This provides connectivity between a USB connector and the RJ-11 connector P12 on the DEV board.

Don't forget to order a SER-USB-RJ11 when placing your order for an NES drive with the DEV board.

EtherCAT Device ID

In an EtherCAT network, slaves are automatically assigned fixed addresses based on their position on the bus. When a device must have a positive identification that is independent of cabling, a Device ID is needed. In the DEV board this is provided by two 16-position rotary switches with hexadecimal encoding. These can set the Device ID of the drive from 0x01~0xFF (1~255 decimal). The chart shows the decimal values of the hex settings of each switch.
Example 1: Find the switch settings for decimal Device ID 107:

1) Find the highest number under SW1 that is less than 107 and set SW1 to the hex value in the same row: 96 < 107 and 112 > 107, so SW1 = 96 = Hex 6
2) Subtract 96 from the desired Device ID to get the decimal value of switch SW2 and set SW2 to the Hex value in the same row: SW2 = (107 - 96) = 11 = Hex B



EtherCAT Device ID Switch Decimal values

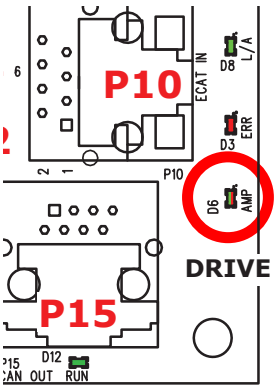
	SW1	SW2
HEX	DEC	
0	0	0
1	16	1
2	32	2
3	48	3
4	64	4
5	80	5
6	96	6
7	112	7
8	128	8
9	144	9
A	160	10
B	176	11
C	192	12
D	208	13
E	224	14
F	240	15

DEV BOARD

DRIVE STATUS LED (AMP)

A bi-color LED gives the state of the drive. Colors do not alternate, and can be solid ON or blinking. If multiple conditions occur, only the top-most condition will be displayed. When that condition is cleared the next one below will shown.

Red/Blinking	=	Latching fault. Operation can not resume until drive is Reset.
Red/Solid	=	Transient fault condition. Drive can resume operation when the condition causing the fault is removed.
Green/Slow-Blinking	=	Drive OK but NOT-enabled. Can run when enabled.
Green/Fast-Blinking	=	Positive or Negative limit switch active. Drive can only move in direction not inhibited by limit switch.
Green/Solid	=	Drive OK and enabled. Can run in response to reference inputs or EtherCAT commands.



LATCHING FAULTS

DEFAULT	OPTIONAL (PROGRAMMABLE)
Short circuit (Internal or external)	Over-voltage
Drive over-temperature	Under-voltage
Motor over-temperature	Motor Phasing Error
Feedback Error	Command Input Lost
Following Error	Motor Wiring Disconnected
	Over Current (latched)

ETHERCAT COMMUNICATIONS

EtherCAT is the open, real-time Ethernet network developed by Beckhoff based on the widely used 100BASE-TX cabling system. EtherCAT enables high-speed control of multiple axes while maintaining tight synchronization of clocks in the nodes.

Data protocol is CANopen application protocol over EtherCAT (CoE) based on DSP-402 for motion control devices.
More information on EtherCAT can be found on this web-site:
http://ethercat.org/default.htm

ETHERCAT CONNECTIONS

Dual RJ-45 sockets accept standard Ethernet cables. The IN port connects to a master, or to the OUT port of a device that is 'upstream', between the Accelnet and the master.

The OUT port connects to 'downstream' nodes.
If the drive is the last node on a network, only the IN port is used. No terminator is required on the OUT port.

ETHERCAT LEDS

RUN Green: Shows the state of the ESM (EtherCAT State Machine)

Off	=	Init
Blinking	=	Pre-operational
Single-flash	=	Safe-operational
On	=	Operational

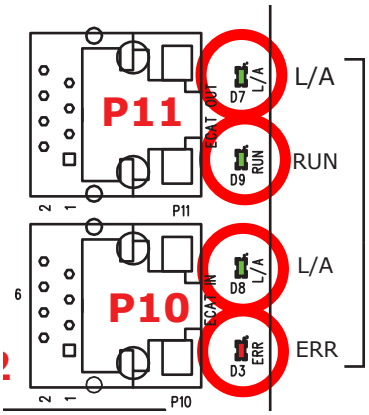
ERR Red: Shows errors such as watchdog timeouts and unsolicited state changes in the drive due to local errors.

Off	=	EtherCAT communications are working correctly
Blinking	=	Invalid configuration, general configuration error
Single Flash	=	Local error, slave has changed EtherCAT state autonomously
Double Flash	=	PDO or EtherCAT watchdog timeout, or an application watchdog timeout has occurred

L/A Green: Shows the state of the physical link and activity on the link.
A green LED indicates the state of the EtherCAT network:

LED	Link	Activity	Condition
ON	Yes	No	Port Open
Flickering	Yes	Yes	Port Open with activity
Off	No	(N/A)	Port Closed

P10~11
EtherCAT PORTS
RJ-45 receptacles, 8 position



DEV BOARD ETHERCAT CONNECTORS

ETHERCAT CONNECTORS

Dual RJ-45 connectors that accept standard Ethernet CAT-5 cables are provided for EtherCAT connectivity.

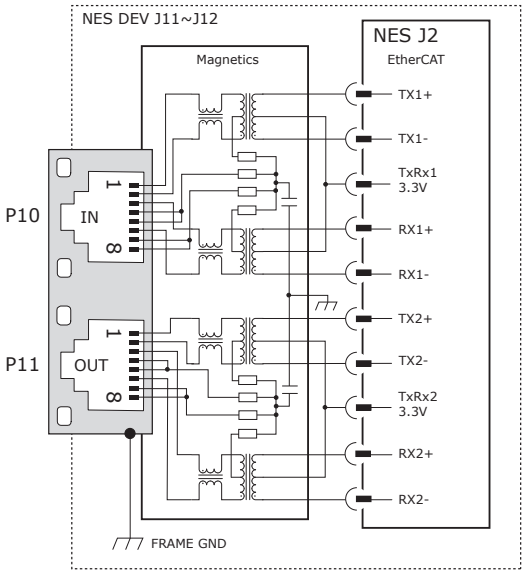
P10 ECAT-IN

Pin	Signal
1	TX1+
2	TX1-
3	RX1+
4	n.c.
5	n.c.
6	RX1-
7	n.c.
8	n.c.

P11 ECAT-OUT

Pin	Signal
1	TX2+
2	TX2-
3	RX2+
4	n.c.
5	n.c.
6	RX2-
7	n.c.
8	n.c.

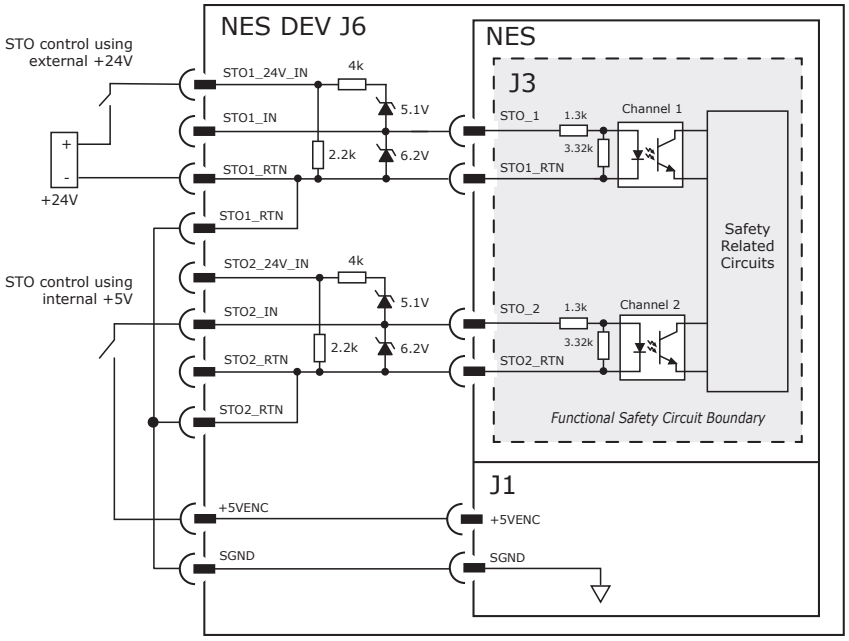
* This connects to R/C that isside the ECAT connector.



DEV BOARD SAFE TORQUE OFF (STO)

DESCRIPTION

This shows the use of external 24V to energize the STO inputs. Both STO inputs must be energized in order to enable the drive. IN1, the hardware Enable input is for use with an immediate contact relay to bring the motor to a stop before a delayed contact relay de-energizes the STO inputs and prevents torque production in the motor.



J6 STO

Signal	Pin		Signal
FGND	1	6	STAT(+)
STO1-IN-24V	2	7	STAT(-)
STO1-RTN	3	8	SGND
STO2-IN-24V	4	9	VLOGIC
STO2-RTN	5		

STAT-OUT Operation

STO1	0	1	0	1
STO2	0	0	1	1
STAT	0	0	0	1

In this table, STO1 & STO2 rows, 1 = 24V has been applied between the IN-24V and RTN. 0 = open-circuit.
In the STAT row, 1 = the optocoupler is ON, 0 = the optocoupler is OFF.
STAT output is ON (True) when both STO1 & STO2 are energized, allowing the drive to be enabled and to produce torque.

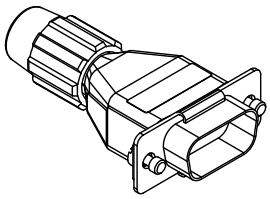
STO OPERATION

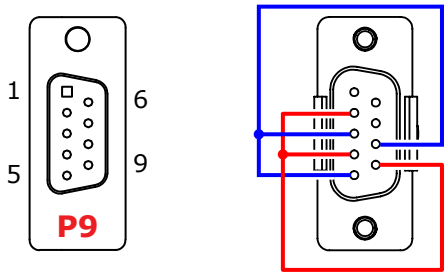
STO Input Voltage	STO State
STO1-IN-24V *AND* STO2-IN-24V ≥ 16 Vdc	STO Inactive. Drive can be enabled to produce torque
STO1-IN-24V *OR* STO2-IN-24V < 16 Vdc	STO Active. Drive cannot be enabled to produce torque
STO1-IN *OR* STO2-IN Open	

Note: Voltages in the table above are referenced between an STOx-IN and an STOx-RTN in P2
E.g. V(STO1-IN) = V(STO1-24V-IN1) - V(STO1-RTN)

DEV BOARD SAFE TORQUE OFF BYPASS JUMPER: STO-CK-04

The graphic below shows the STO Bypass plug. The switches are read after the drive is reset, or powered-on. When changing the settings of the switches, be sure to either reset the drive, or to power it off-on.





Jumper 1 carries +24V from P8 (Brake release)
Jumper 2 connects to SGND.
The STO bypass has no connections to any other circuits and is designed to be powered by +24V.

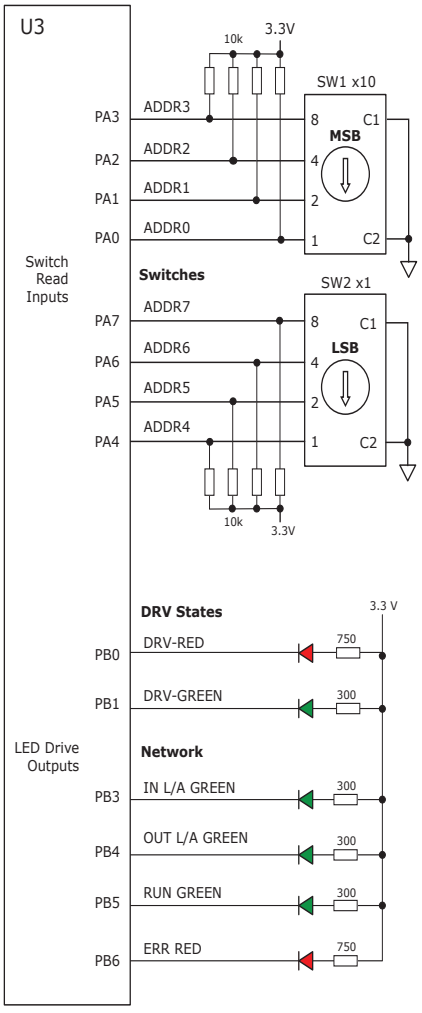
J6 STO

Signal	Pin		Signal
No connection	1	6	No connection
Jumper 1	2	7	No connection
Jumper 2	3	8	Jumper 2
Jumper 1	4	9	Jumper 1
Jumper 2	5		

DEV BOARD SWITCHES & LEDS

ETHERCAT DEVICE ID (STATION ALIAS) SWITCH CONNECTIONS & LEDS

The graphic below shows the connections to the EtherCAT Device ID switches and status LEDs. The switches are read after the drive is reset, or powered-on. When changing the settings of the switches, be sure to either reset the drive, or to power it off-on.



DEV BOARD +HV, VLOGIC, & MOTOR CONNECTIONS

J4 +HV

The +HV power supply outputs connect to J4 pins 2 & 3. The shield shown is optional and is primarily for reduction of RF emissions from the drive. As shown is connects to the case of the power supply. Note that the minus terminal is not grounded externally. This is because currents in the cables produce voltage drops. Grounding the supply at the drive ensures that such voltage drops do not appear in the drive circuits.

J5 MOTOR

Pins 1~3 are for the motor windings. Pin 4 is for a cable shield. It connects to the drive heatplate on one end and should connect to the motor frame on the other. This provides a return path for currents produced by the PWM outputs and the capacitance between the cable conductors, motor windings, and motor frame. While the frame is commonly grounded by mounting to equipment, without the shield connections the PWM shield current could flow into external devices.

P8 VLOGIC

Powers the internal logic and control circuits in the drive. When using the STO feature, it must be produced by power supplies with transformer isolation from the mains and PELV or SELV ratings and a maximum output voltage of 60 Vdc. If the motor can operate from voltages of 60 Vdc or less, the +HV and VLOGIC can be driven from a single power supply.
P8 also is the connection point for a motor holding brake. These connect to pins 2 & 3 and is not shown here because it is not part of the power & motor connections.

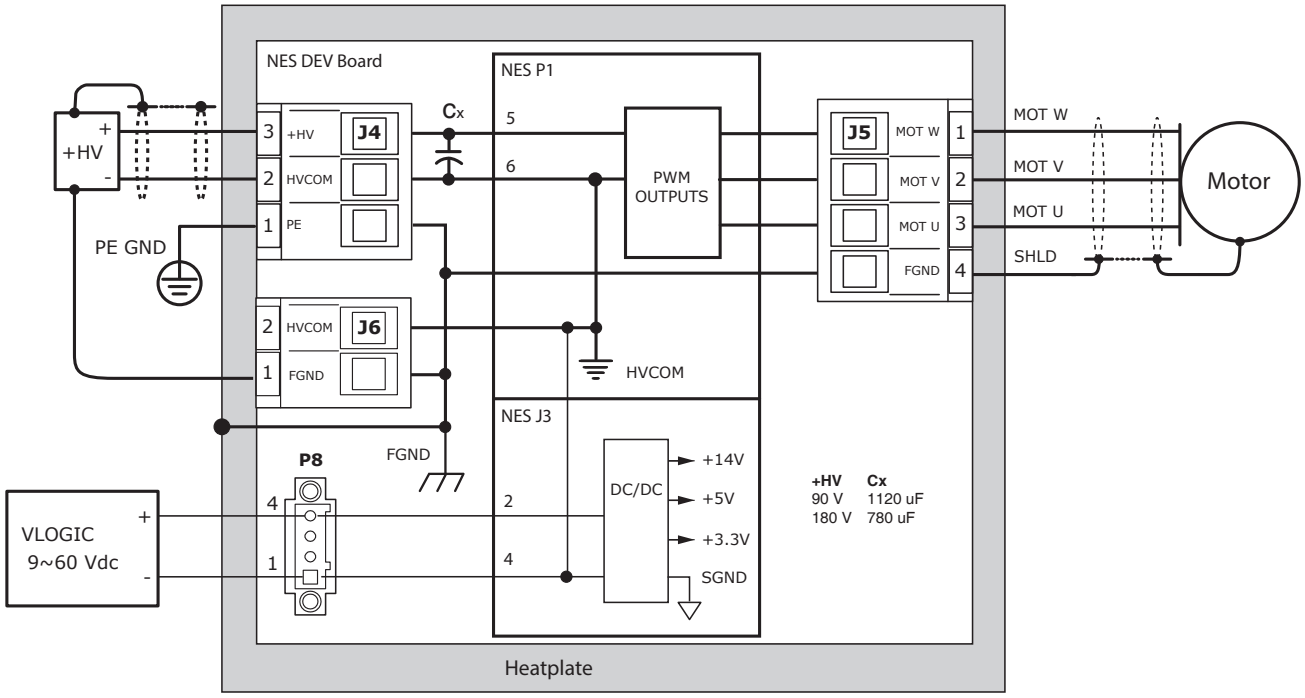
GROUNDING

PE GND is a Protective Earth ground which is the zero-volt reference for voltages used in the drive and is also the connection point for fault currents that might flow from any failures in the drive that could expose a user to an electric shock.

FGND, Frame Ground is referenced to the drive heatplate and has no connections to any circuits in the drive. Internal connections from the heatplate to J4, J5, and J6 enable cabling for grounding and shielding.

HVCOM, High-Voltage-Common is the 0V or 'ground' circuit for the high voltage circuits that drive the motor.

SGND, Signal Ground is the 0V circuit for low power control and interface circuits. It is connected to HVCOM internally so that all internal circuits have a common "0V" connection.



J4 +HV

Pin	Signal
3	+HV
2	HVCOM
1	FGND

J6 GROUNDS

Pin	Signal
2	HVCOM
1	FGND

P8 VLOGIC & BRAKE

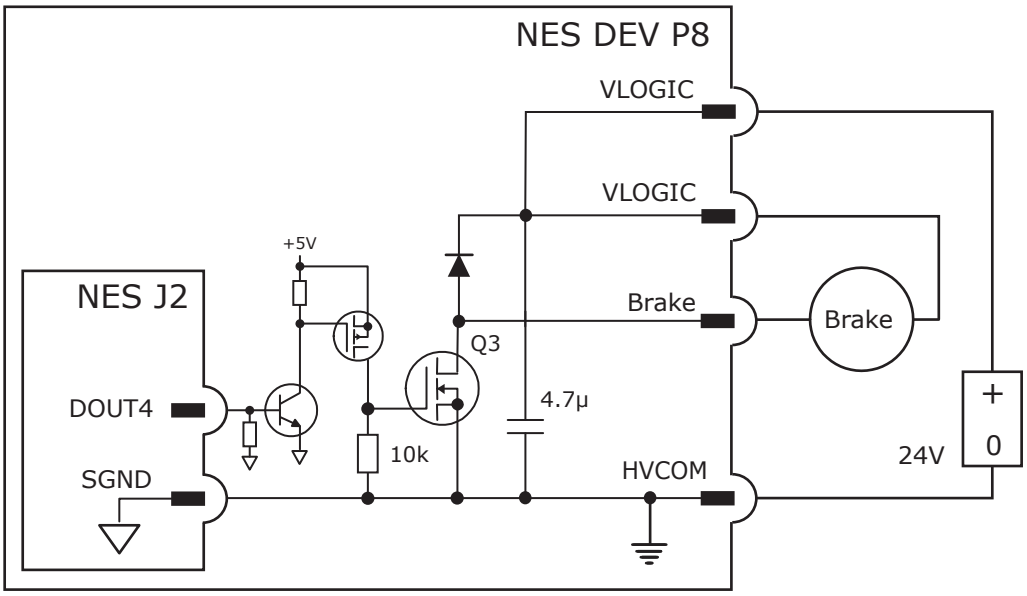
Pin	Signal
4	VLOGIC
3	VLOGIC
2	Brake
1	HVCOM

J5 MOTOR

Pin	Signal
1	MOT W
2	MOT V
3	MOT U
4	FGND

DEV BOARD VLOGIC & BRAKE

The brake circuit on the DEV board is a MOSFET driven by OUT4 of the NES



Specifications

Output	Data	Notes
Voltage Range	Max	+30 Vdc
Output Current	Ids	1.0 Adc

P8 BRAKE

Signal	Pins
VLOGIC	4
VLOGIC	3
Brake	2
HVCOM	1

HI/LO definitions: outputs

Input	State	Condition
BRAKE [OUT4]	LO	Output MOSFET Q3 is OFF Brake is un-powered and locks motor Motor cannot move Brake state is Active
	HI	Output MOSFET Q3 is ON Brake is powered, releasing motor Motor is free to move Brake state is NOT-Active

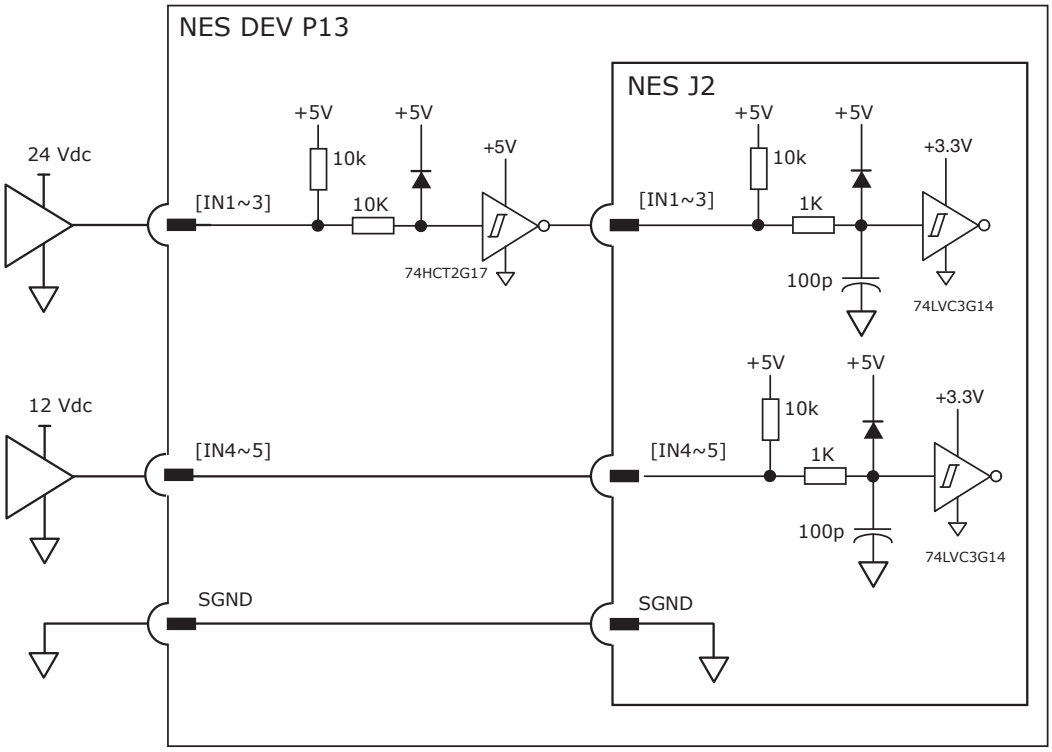
CME Default Setting for Brake Output [OUT4] is "Brake - Active Low"
Active = Brake is holding motor shaft (i.e. the *Brake is Active*)
Motor cannot move
No current flows in coil of brake
CME I/O Line States shows [OUT4] as LO
BRK Output voltage is HI (24V), MOSFET Q3 is OFF
Servo drive output current is zero
Servo drive is disabled, PWM outputs are off
Inactive = Brake is not holding motor shaft (i.e. the *Brake is Inactive*)
Motor can move
Current flows in coil of brake
CME I/O Line States shows [OUT4] as HI
BRK output voltage is LO (~0V), MOSFET Q3 is ON
Servo drive is enabled, PWM outputs are on
Servo drive output current is flowing

DEV BOARD INPUTS & OUTPUTS

P13 LOGIC INPUTS

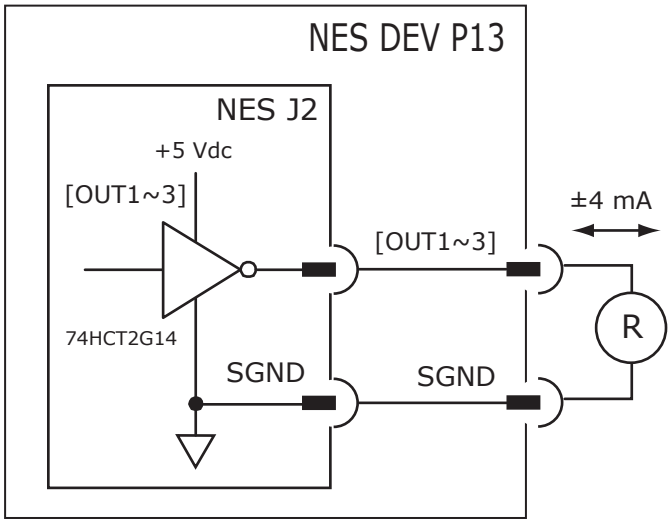
Signal	Pins
IN1 24V Enable	4
IN2 24V	5
IN3 24V	6
IN4 12V	7
IN5 12V	10
SGND	15,19

IN1~3 on the DEV board are 24V compatible.
IN4~5 are 12V tolerant.



P13 LOGIC OUTPUTS

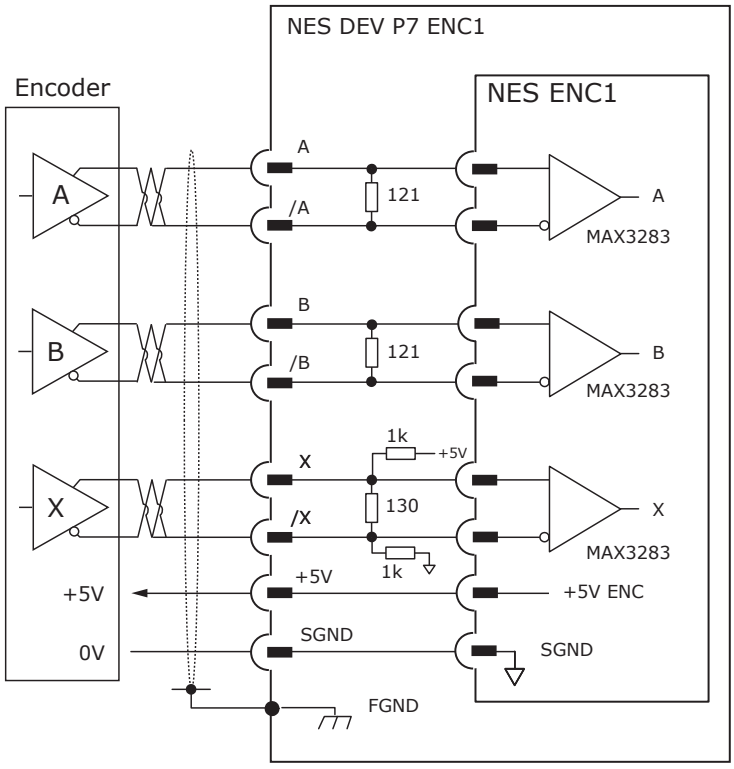
Signal	Pins
OUT1	16
OUT2	17
OUT3	18
SGND	15,19



P7 ENC1 INPUTS

Signal	Pins
ENC1 A	14
ENC1 /A	13
ENC1 B	12
ENC1 /B	11
ENC1 X	8
ENC1 /X	7
Fault IN6	10
+5 V	2,4
SGND	5,15

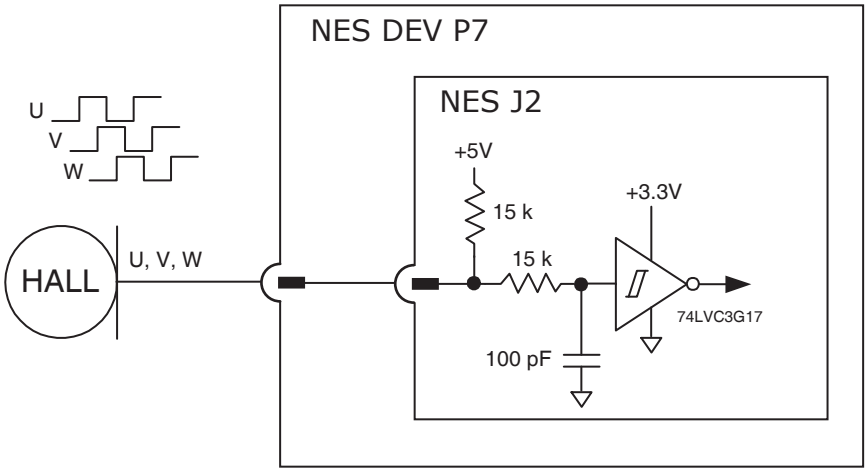
ENC1 is the Motor encoder and should be used in single-encoder applications.
In dual-encoder applications, it can be assigned as Primary or Secondary using CME.



FGND connects to the connector shells which connect to the etch around the four mounting holes of the DEV board. The mounting screws and metal standoffs provide a connection to the equipment chassis which has a connection to earth.

P7 HALL INPUTS

Signal	Pins
Hall U	3
Hall V	6
Hall W	9

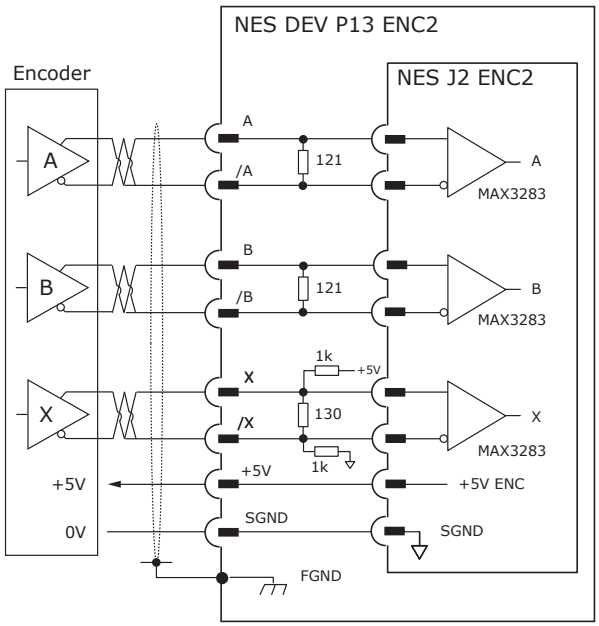


DEV BOARD SECONDARY FEEDBACK ENCODER

P13 ENC2 INPUTS

Signal	Pins
ENC2 A	26
ENC2 /A	25
ENC2 B	24
ENC2 /B	23
ENC2 X	22
ENC2 /X	21
Fault IN5	10
+5 V	20
SGND	15,19
FGND	1

ENC2 is the Load encoder and typically is feedback from a load driven by the motor and is used in dual-encoder applications. In dual-encoder applications, it can be assigned as Primary or Secondary using CME.



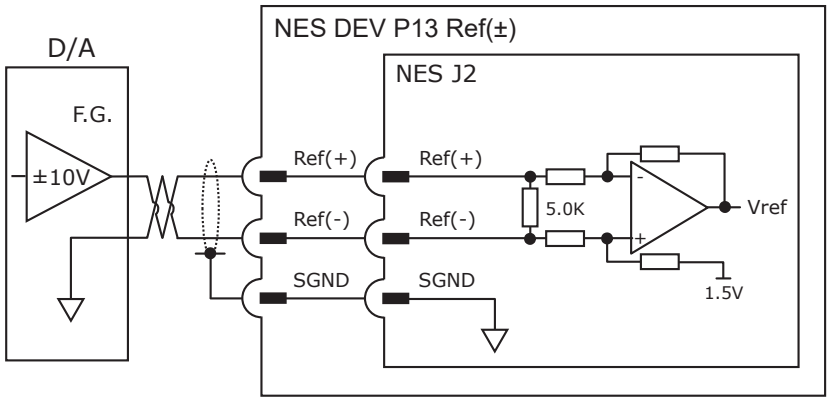
DEV BOARD ANALOG INPUT: AIN1

As a reference input it takes Position/Velocity/Torque commands from a controller. If not used as a command input, it can be used as general-purpose analog input.

SPECIFICATIONS

Spec	Data	Notes
Input Voltage	Vref	±10 Vdc
Input Resistance	Rin	5 kΩ

Signal	J2 Pins
Ref(+)	2
Ref(-)	1
Sgnd	3



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ORDERING GUIDE

NANO

NES-090-10	*Nano Micro Module EtherCAT* NES servo drive, 5/10 A, 90 Vdc
NES-090-70	*Nano Micro Module EtherCAT* NES servo drive, 35/70 A, 90 Vdc
NES-180-10	*Nano Micro Module EtherCAT* NES servo drive, 5/10 A, 180 Vdc
NES-180-30	*Nano Micro Module EtherCAT* NES servo drive, 15/30 A, 180 Vdc
NES-090-10-D	Nano Micro Module with DEV board, not soldered, no heat sink
NES-090-70-D	Nano Micro Module with DEV board, soldered, with heat sink
NES-180-10-D	Nano Micro Module with DEV board, not soldered, no heat sink
NES-180-30-D	Nano Micro Module with DEV board, not soldered, with heat sink

ACCESSORIES FOR NANO MICRO MODULES

NS-D-CK	DEV Board Connector Kit
N-HK	Heat Sink Kit
SER-CK	Serial Cable Kit: 9-Pin Dsub receptacle to 6-pin modular adapter, plus modular cable for DEV board
SER-USB-RJ11	USB to 6-pin modular adapter
NES-NC-01	Ethernet network cable, 1 ft (0.3 m)
NES-NC-10	Ethernet network cable, 10 ft (3 m)

16-121736 Document Revision History

Revision	Date	Remarks
00	October 11, 2019	Initial released version
01	November 12, 2019	DEV board info added
02	November 22, 2019	NES-090-10 added
03	Decemter 6, 2019	Corrections to diagram on page 15.
04	March 20, 2020	Update module photo on page 1, update ordering guide
05	May 20, 2020	Added thermals
06	February 25, 2021	ECAT connections updated, DEV board only

Note: Specifications subject to change without notice