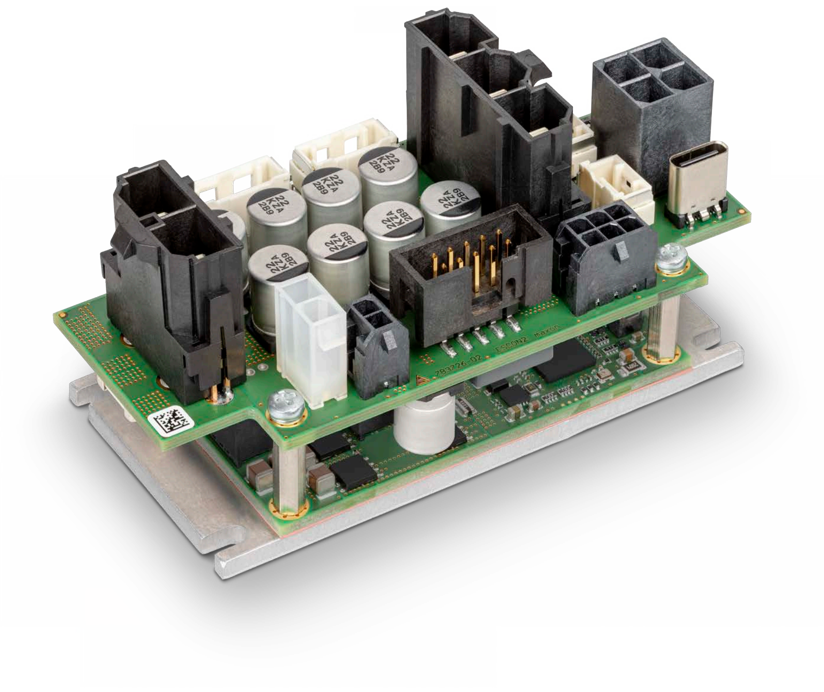
maxon

Servo Controller

ESCON2 Compact 60/30

Hardware Reference



CANopen
I/O

escon.maxongroup.com

ESCON2 Compact 60/30 Servo Controller | P/N 783734
Hardware Reference
CCMC | Edition 2024-12 | DocID rel12453

TABLE OF CONTENTS

READ THIS FIRST

These instructions are intended for qualified technical personnel. Prior commencing with any activities*…*

- *you must carefully read and understand this manual and*
- *you must follow the instructions given therein.*

***The ESCON2 Compact** is considered as partly completed machinery according to EU Directive 2006/42/EC, Article 2, Clause (g) and **are intended to be incorporated into or assembled with other machinery or other partly completed machinery or equipment**.*
Therefore, you must not put the device into service*,…*

- *unless you have made completely sure that the other machinery fully complies with the EU directive's requirements!*
- *unless the other machinery fulfills all relevant health and safety aspects!*
- *unless all respective interfaces have been established and fulfill the herein stated requirements!*

••page intentionally left blank••

1 ABOUT

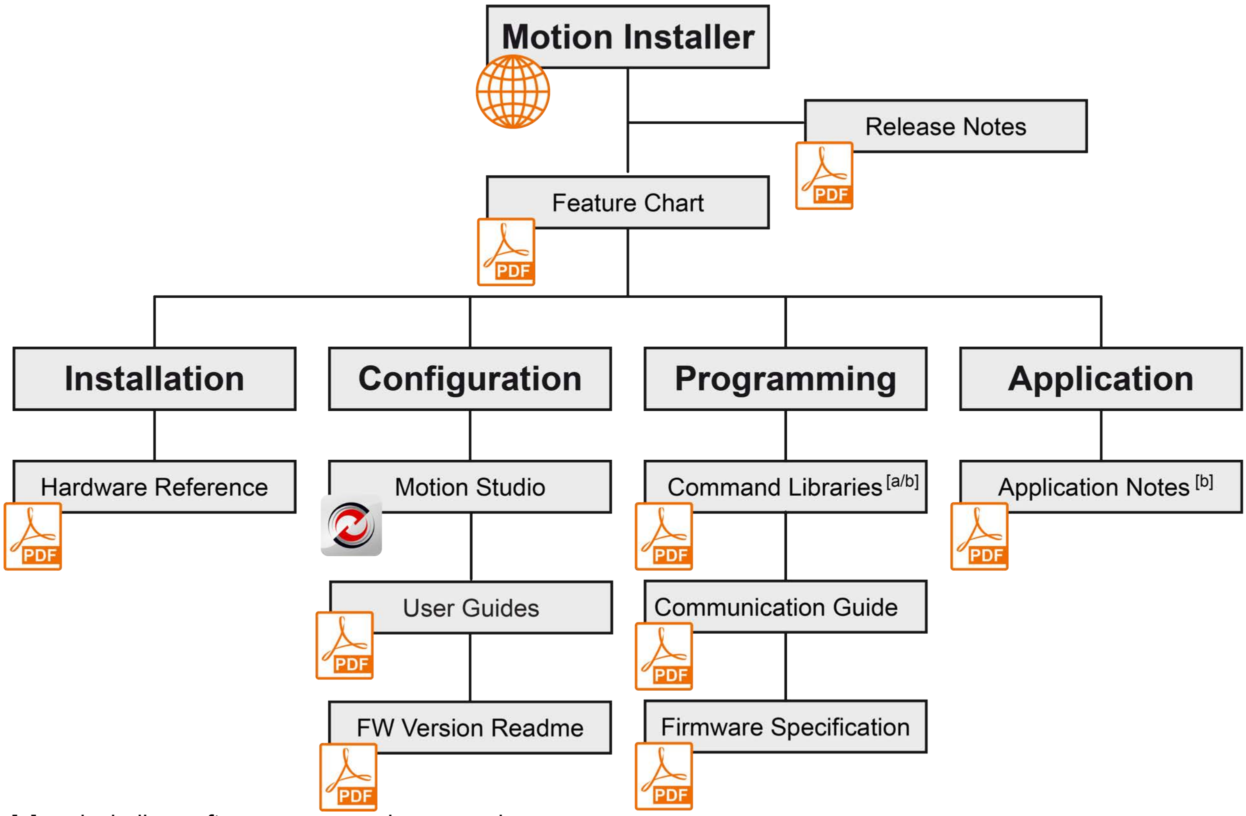
1.1 About this document

1.1.1 Intended purpose

The purpose of the present document is to familiarize you with the ESCON2 Compact 60/30 Servo Controller. It will highlight the tasks for safe and adequate installation and/or commissioning. Follow the described instructions.

- to avoid dangerous situations,
- to keep installation and/or commissioning time at a minimum,
- to increase reliability and service life of the described equipment.

The present document is part of a documentation set and contains performance data and specifications, information on fulfilled standards, details on connections and pin assignment, and wiring examples. The below overview shows the documentation hierarchy and the interrelationship of its individual parts:



[a] including software programming examples
[b] will be available with upcoming release

Figure 1-1 Documentation structure

Find the latest edition of the present document as well as additional documentation and software for ESCON2 servo controllers on the Internet: http://escon.maxongroup.com

1.1.2 Target audience

The present document is intended for trained and skilled personnel. It conveys information on how to understand and fulfill the respective work and duties.

1.1.3 How to use

Follow these notations and codes throughout the document.

Notation	Meaning
ESCON2	stands for «ESCON2 Servo Controller»
«Abcd»	indicating a title or a name (such as of document, product, mode, etc.)
(n)	refers to an item (such as a part number, list items, etc.)
*	refers to an internal value
➔	denotes “check”, “see”, “see also”, “take note of” or “go to”

Table 1-1 Notations used in this document

1.1.4 Symbols & signs

This document uses the following symbols and signs:

Type	Symbol	Meaning
Safety alert DANGER		Indicates an **imminent hazardous situation**. If not avoided, it **will result in death or serious injury.**
WARNING		Indicates a **potential hazardous situation**. If not avoided, it **can result in death or serious injury.**
CAUTION		Indicates a **probable hazardous situation** or calls the attention to unsafe practices. If not avoided, it **may result in injury.**
Prohibited action	 (typical)	Indicates a dangerous action. Hence, **you must not!**
Mandatory action	 (typical)	Indicates a mandatory action. Hence, **you must!**
Requirement, Note, Remark		Indicates an activity you must perform prior to continuing, or gives information on a particular point that must be observed.
Best practice		Indicates an advice or recommendation on the easiest and best way to further proceed.
Material Damage		Indicates information particular to possible damage of the equipment.

Table 1-2 Symbols and signs

1.1.5 Trademarks and brand names

For easier legibility, registered brand names are listed below and will not be further tagged with their respective trademark. It must be understood that the brands (the list below is not necessarily concluding) are protected by copyright and/or other intellectual property rights, even if their legal trademarks are omitted in the later course of this document.

Brand Name	Trademark Owner
Adobe® Reader®	© Adobe Systems Incorporated, San Jose, California, United States
BiSS	© iC-Haus GmbH, Bodenheim, Germany
CANopen® CiA®	© CiA CAN in Automation e.V, Nuremberg, Germany
Windows®	© Microsoft Corporation, Redmond, Washington, United States

Table 1-3 Brand names and trademark owners

1.1.6 Copyright

CCMC | ESCON2 Compact 60/30 Hardware Reference | Edition 2024-12 | DocID rel12453

1.2 About the device

The ESCON2 Compact 60/30 is a small-sized, powerful 4-quadrant PWM servo controller. Its high power density allows flexible use for brushed DC motors and brushless EC (BLDC) motors up to approximately 1’800 Watts with various feedback options, such as Hall sensors, incremental encoders as well as absolute sensors in a multitude of drive applications.

The device is specially designed to be commanded and controlled by analog and digital set values, as well as a slave node in a CANopen network. Additionally, the unit can be operated via any USB port of a Windows workstation. It also features extensive analog and digital I/O functionality.

Latest technology, such as field-oriented control (FOC), acceleration/velocity feed forward, in combination with highest control cycle rates allow sophisticated, ease-of-use motion control.

The compact servo controller is a fully integrated and ready-to-connect device for easy and quick installation.

1.3 About the safety precautions

- Make sure that you have read and understood the note ➔«READ THIS FIRST»!
- Do not engage with any work unless you possess the stated skills (➔Chapter "1.1.2 Target audience" on page 1-5)!
- Refer to ➔Chapter "1.1.4 Symbols & signs" on page 1-6 to understand the subsequently used indicators!
- You must observe any regulation applicable in the country and/or at the site of implementation with regard to health and safety/accident prevention and/or environmental protection!

DANGER

High voltage and/or electrical shock
Touching live wires causes death or serious injuries!

- *Consider any power cable as connected to live power, unless having proven the opposite!*
- *Make sure that neither end of cable is connected to live power!*
- *Make sure that power source cannot be engaged while work is in process!*
- *Obey lock-out/tag-out procedures!*
- *Make sure to securely lock any power engaging equipment against unintentional engagement and tag it with your name!*

Requirements

- *Make sure that all associated devices and components are installed according to local regulations.*
- *Be aware that, by principle, an electronic apparatus can not be considered fail-safe. Therefore, you must make sure that any machine/apparatus has been fitted with independent monitoring and safety equipment. If the machine/apparatus should break down, if it is operated incorrectly, if the control unit breaks down or if the cables break or get disconnected, etc., the complete drive system must return – and be kept – in a safe operating mode.*
- *Be aware that you are not entitled to perform any repair on components supplied by maxon.*

Electrostatic sensitive device (ESD)

- *Wear working cloth and use equipment in compliance with ESD protective measures.*
- *Handle device with extra care.*
- *Be aware that you are not entitled to perform any repair on components supplied by maxon.*

2 SPECIFICATIONS

2.1 Technical data

ESCON2 Compact 60/30 (P/N 783734)		
Electrical data	Nominal power supply voltage V_{CC}	10…60 VDC
	Nominal logic supply voltage V_C	10…60 VDC
	Absolute supply voltage V_{min} / V_{max}	8 VDC / 62 VDC
	Output voltage (max.)	0.95 × V_{CC}
	Output current I_{cont} / I_{max} (< 4 s)	30 A / 60 A
	Pulse Width Modulation (PWM) frequency	50 kHz
	Sampling rate PI current controller	50 kHz
	Sampling rate PI speed controller	10 kHz
	Sampling rate analog input	50 kHz
	Max. efficiency	98.5 % ➔Figure 2-4
	Max. speed DC motor	limited by max. permissible motor speed and max. output voltage (controller)
	Max. speed EC motor (FOC)	120'000 rpm (1 pole pair)
	Built-in motor choke per phase	470 nH / 30 A
Inputs & outputs	Sensor 1 Digital Hall sensor H1, H2, H3	0...24 VDC (internal pull-up)
	Sensor 2 (choice between multiple functions): • Digital incremental encoder • SSI absolute encoder [a] • BISS C unidirectional absolute encoder [a] • High-speed digital inputs 1…2 • High-speed digital inputs 3…4 • High-speed digital output 1	 2-channel, EIA/RS422, max. 6.67 MHz 0.1...2 MHz (single-ended, configurable) 0.1...4 MHz (single-ended, configurable) EIA/RS422, max. 6.67 MHz Logic: 0...12 VDC, max. 6.25 MHz 3.3 VDC / I_L ≤ 24 mA / R_i = 75 Ω
	Digital Inputs 1...4	Logic: 0…25 VDC, inputs 1…2 PWM capable
	Digital Outputs 1...2	max. 30 VDC / I_L ≤ 500 mA (open drain with internal pull-up)
	Analog Inputs 1...2	Resolution 12-bit, ± 10 VDC (differential), 10 kHz
	Analog Outputs 1...2	Resolution 12-bit, ± 4 VDC (referenced to GND), 25 kHz
	Motor temperature sensor [a]	Resolution 12-bit, 0...3.3 VDC (internal pull-up)
Voltage outputs	Sensor supply voltage V_{Sensor}	5 VDC / I_L ≤ 145 mA
	Peripheral supply voltage $V_{Peripheral}$	-
Motor connections	DC motor	+ Motor, − Motor
	EC motor	Motor winding 1, Motor winding 2, Motor winding 3

Continued on next page.

ESCON2 Compact 60/30 (P/N 783734)			
Communi-cation interfaces	CAN		Max. 1 Mbit/s
	RS232		-
	USB		12 Mbit/s (Full Speed)
Status indicators	Device status		Operation (green) Warning/Error (red)
Mechanical data	Dimensions (L × W × H)		93.5 × 46 × 41 mm
	Weight (approx.)		128 g
	Mounting		M3 screws
Environmen-tal conditions	Temperature	Operation	−30…+25 °C
		Extended range [b]	+25…+75 °C Derating: approx. -0.506 A/°C ➔Figure 2-2 with additional heatsink: ➔Figure 2-3
		Storage	−40…+85 °C
	Altitude [c]	Operation	0…500 m MSL
		Extended range [b]	500...10'000 m MSL Derating ➔Figure 2-2
	Humidity		5…90 % (condensation not permitted)

[a] The functionality will be available with a future firmware release.
[b] Operation within the extended range is permitted. However, a respective derating (declination of output current I_{cont}) as to the stated values will apply.
[c] Operating altitude in meters above Mean Sea Level, MSL.

Table 2-4 Technical data

2.2 Thermal data

Mandatory operation within the specified limits

- *Operation within the stated thermal specifications is mandatory.*
- *Exceeding ambient temperatures beyond the specified limits can lead to thermal overload even at low output currents.*

2.2.1 Test setup for data collection

Unless otherwise stated, the thermal data has been generated with the unit in an upright position (connections facing to the top) and placed on thermally poorly conductive holders (floating in air).

2.2.2 Derating of output current (operation without additional heat sink)

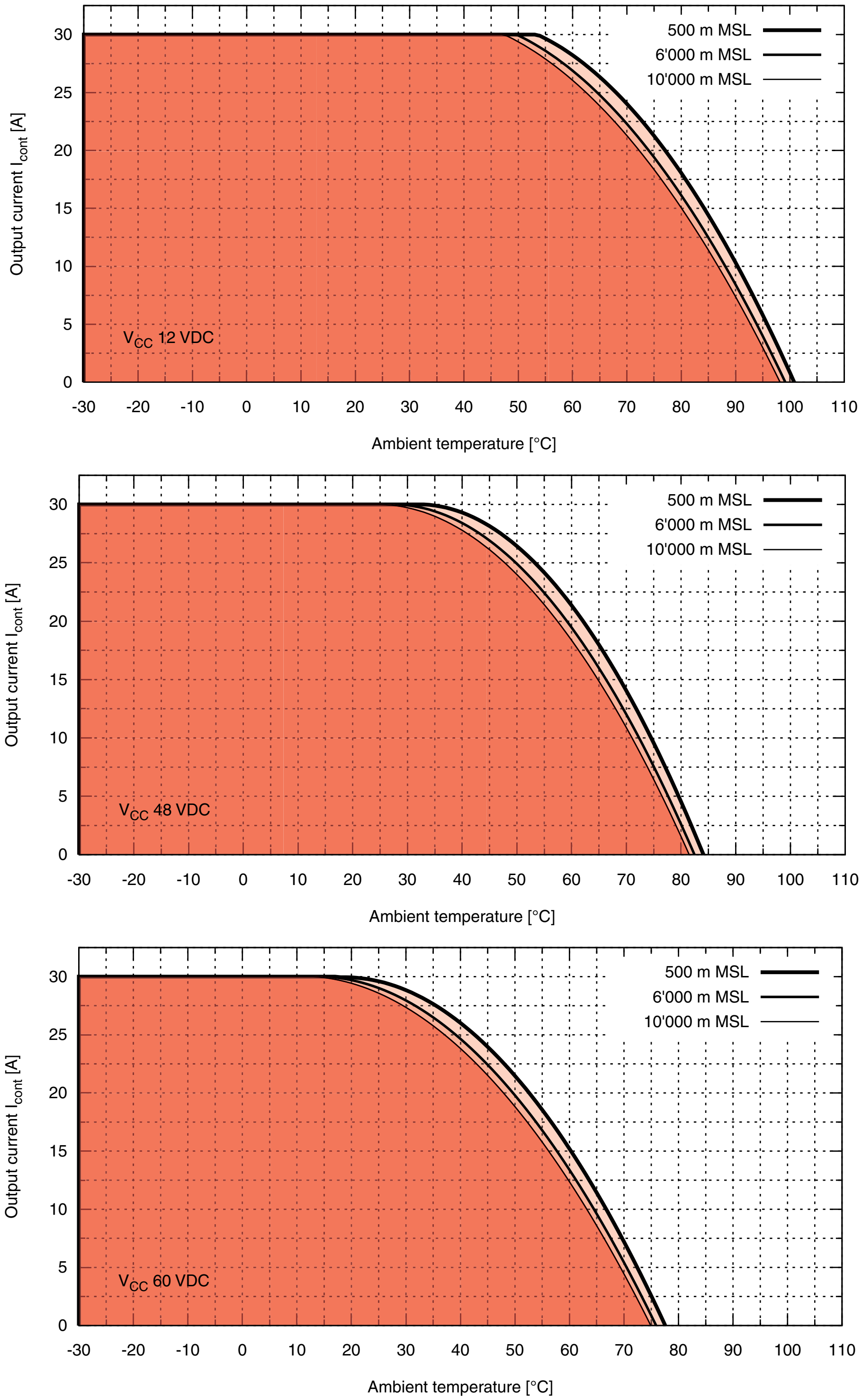


Figure 2-2 Derating of output current (operation without additional heatsink)

2.2.3 Operation with additional heatsink

In the process of data collection within this chapter, the unit was placed on its side. This positioning facilitates the upward flow of heat from the additional heatsink, thereby promoting effective passive cooling at the top.

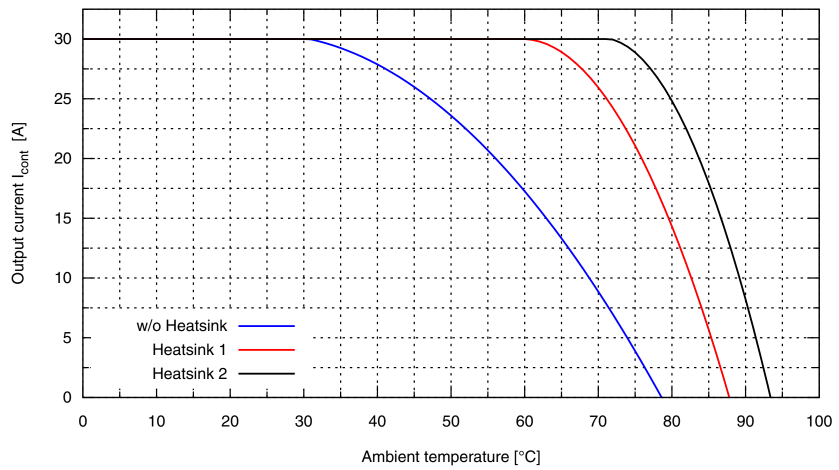


Figure 2-3 Extended operation @ V_{CC} 60 VDC with additional heatsink

Heatsink	Manufacturer	Type	Dimensions [mm]	Thermal resistance R_{th} [K/W]
1	Fischer Elektronik GmbH	SK 81 50 SA	50 × 100 × 15	3
2	Fischer Elektronik GmbH	SK 92 50 AL	50 × 100 × 40	1.75

Table 2-5 Heatsink – tested components

2.2.4 Power dissipation and efficiency

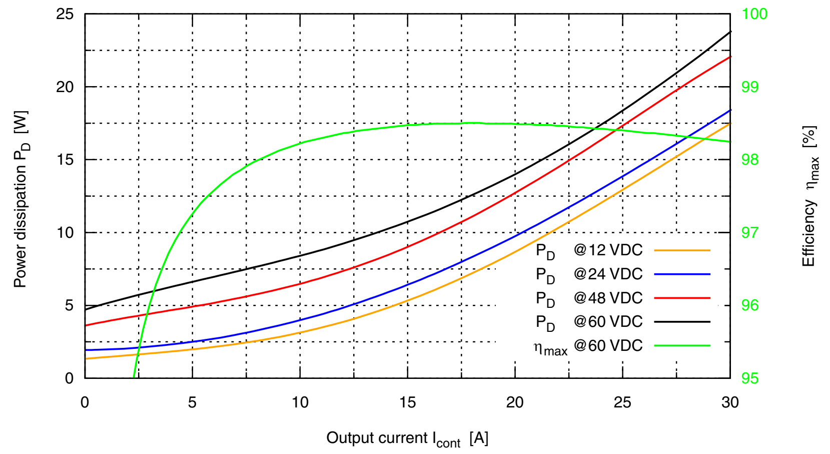


Figure 2-4 Power dissipation and efficiency

2.3 Limitations and protections

Functionality		Switch-off threshold	Recovery threshold
Undervoltage		7.5 VDC	7.75 VDC
Overvoltage		65 VDC	64 VDC
Thermal overload	logic	108 °C	98 °C
	power stage	110 °C	—

Table 2-6 Limitations and protections

Additionally, the device features a configurable output current limit and an overcurrent protection function that protects the controller in the event of a short circuit in a motor winding or a damaged power stage. The undervoltage, overvoltage and the thermal overload power stage protection limits are configurable. Further information can be found in the «ESCON2 Firmware Specification».

2.4 Dimensional drawing

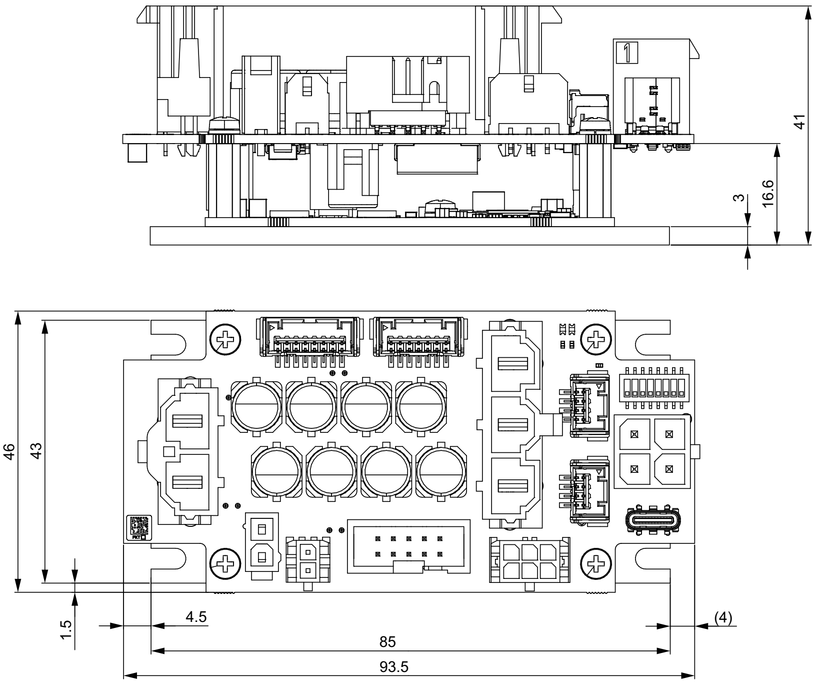


Figure 2-5 Dimensional drawing [mm]

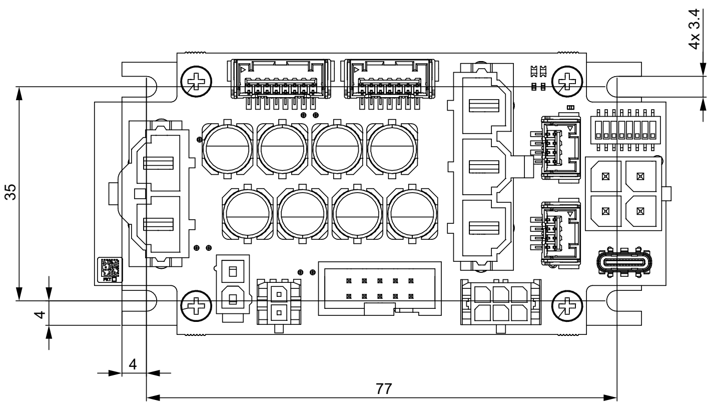


Figure 2-6 Dimensional drawing – Attachment points [mm]

2.5 Standards

The described device has been successfully tested for compliance with the below listed standards. In practical terms, only the complete system (the fully operational equipment comprising all individual components, such as motor, servo controller, power supply unit, EMC filter, cabling etc.) can undergo an EMC test to ensure interference-free operation.

Important Notice
The device's compliance with the mentioned standards does not imply its compliance within the final, ready to operate setup. In order to achieve compliance of your operational system, you must perform EMC testing of the involved equipment as a whole.

Electromagnetic compatibility		
Generic	IEC/EN 61000-6-2	Immunity for industrial environments
	IEC/EN 61000-6-3	Emission standard for residential, commercial and light-industrial environments
Applied	IEC/EN 55022 (CISPR32)	Radio disturbance characteristics / radio interference
	IEC/EN 61000-4-3	Radiated, radio-frequency, electromagnetic field immunity test >10 V/m
	IEC/EN 61000-4-4	Electrical fast transient/burst immunity test ±2 kV
	IEC/EN 61000-4-6	Immunity to conducted disturbances, induced by radio-frequency fields 10 Vrms

Others		
Environment	IEC/EN 60068-2-6	Environmental testing – Test Fc: Vibration (sinusoidal, 10…500 Hz, 20 m/s^2)
	MIL-STD-810F	Random transport (10…500 Hz up to 2.53 g_{rms})
Safety	UL File Number	Unassembled printed circuit boards: E207844
Reliability	MIL-HDBK-217F [a]	Reliability prediction of electronic equipment Environment: Ground, benign (GB) Ambient temperature: 298 K (25 °C) Component stress: In accordance with circuit diagram and nominal power Mean Time Between Failures (MTBF): 225'850 hours

[a] The reliability calculation is based on MIL-HDBK-217F. Since component manufacturer data is more accurate, it has been used whenever possible.

Table 2-7 Standards

3 SETUP

IMPORTANT NOTICE: PREREQUISITES FOR PERMISSION TO COMMENCE INSTALLATION

The ESCON2 Compact is considered as partly completed machinery according to EU Directive 2006/42/EC, Article 2, Clause (g) and **are intended to be incorporated into or assembled with other machinery or other partly completed machinery or equipment**.

WARNING

Risk of injury
Operating the device without the full compliance of the surrounding system with the EU Directive 2006/42/EC may cause serious injuries!

- *Do not operate the device, unless you have made completely sure that the other machinery fully complies with the EU directive's requirements!*
- *Do not operate the device, unless the other machinery fulfills all relevant health and safety aspects!*
- *Do not operate the device, unless all respective interfaces have been established and fulfill the requirements stated in this document!*

CAUTION

Burn hazard
Hot surfaces can cause burns.

- *During operation, some parts of the device become very hot. Contact with these parts can burn your skin.*
- *Disconnect the power supply and secure it. Wait for the surface to cool before you do maintenance.*

3.1 Generally applicable rules

Maximum permitted supply voltage

- *Make sure that supply power is between 10…60 VDC.*
- *Supply voltages above 65 VDC, or wrong polarity will destroy the unit.*
- *Note that the necessary output current is depending on the load torque. Yet, the output current limits are as follows:*
  – continuous max. 30 A
  – short-time (acceleration) max. 60 A (< 4 s)

Hot plugging the USB interface may cause hardware damage

If the USB interface is being hot-plugged (connecting while the power supply is on), the possibly high potential differences of the two power supplies of controller and PC/Notebook can lead to damaged hardware.

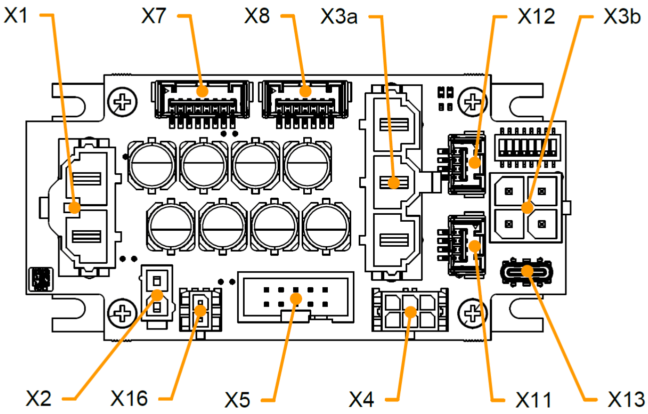
- *Avoid potential differences between the power supply of controller and PC/Notebook or, if possible, balance them.*
- *Insert the USB connector first, then switch on the power supply of the controller.*

Best practice

Keep the motor mechanically disconnected during the setup and adjustment phase.

3.2 Connections

For in-depth details on connections ➔Chapter “3.3 Connection specifications” on page 3-18.



X1	Power supply ➔page 3-18
X2	Logic supply ➔page 3-20
X3a/b	Motor ➔page 3-20
X4	Sensor 1 Hall sensor ➔page 3-22
X5	Sensor 2 ➔page 3-24
X7	Digital I/Os ➔page 3-31
X8	Analog I/Os ➔page 3-35
X11	CAN 1 ➔page 3-37
X12	CAN 2 ➔page 3-37
X13	USB ➔page 3-38
X16	Motor temperature sensor ➔page 3-39

Figure 3-7 Connections

3.2.1 Cabling

PLUG&PLAY

Take advantage of maxon’s prefab cable assemblies. They come as ready-to-use parts and will help to reduce commissioning time to a minimum.

a) Check the following table and find the part number of the cable assembly that matches the setup you will be using.

b) Follow the cross-reference to get the cable’s pin assignment.

Prefab cable assembly			
Connector	**Designation**	**Part Number**	**➔Page**
X1	Power cable highest current **Mandatory for supply of power stage!**	838459	3-19
X2	Power cable **Optional for separate logic supply!**	275829	3-20
X3a	Motor cable highest current	838460	3-21
X3b	Motor cable high current	520851	3-22
X4	Sensor 1 Hall sensor cable	275878	3-23
X5	Encoder cable	275934	3-25
X7	Signal cable 8core	520853	3-32
X8	Signal cable 7core	520854	3-35
X11	CAN-CAN cable CAN-COM cable	520858 520857	3-37 3-38
X12	CAN-CAN cable CAN-COM cable	520858 520857	3-37 3-38
X13	USB Type C – Type C cable USB Type A – Type C cable	845854 838461	3-39 3-39
X16	NTC cable	847301	3-40

Table 3-8 Prefab maxon cables

MAKE&BAKE YOUR OWN

If you decide not to employ maxon's prefab cable assemblies, you might wish to use the prepackaged kit that contains all connectors required to make up your own cabling.

Motion connector set highest current (P/N 846645)		
Connector	**Specification**	**Quantity**
Connectors		
X1	Molex Mini-Fit Sr., 2 poles (428160212)	1
X2	Molex Mini-Fit, 2 poles (39012020)	1
X3a	Molex Mini-Fit Sr., 3 poles (428160312)	1
X3b	Molex Mega-Fit, 4 poles (1700010104 / 1716920104)	1
X4	Molex Micro-Fit 3.0, 6 poles (430250600)	1
X7	Molex CLIK-Mate, 8 poles (5025780800)	1
X8	Molex CLIK-Mate, 7 poles (5025780700)	1
X11 / X12	Molex CLIK-Mate, 4 poles (5025780400)	2
X16	Molex Micro-Fit 3.0, 2 poles (430250200)	1
Crimp Terminals		
X1 / X3a	Molex Mini-Fit Sr., AWG10-12 (428150114)	5
X2	Molex Mini-Fit, AWG16 (457503112 / 457503111)	2
X3b	Molex Mega-Fit, AWG14-16 (1720630311)	4
X4 / X16	Molex Micro-Fit 3.0, AWG26-30 (430300010 / 430300004)	8
X7 / X8 / X11 / X12	Molex CLIK-Mate, AWG24-28 (5025790100 / 5025790000)	25

Table 3-9 Motion connector set highest current – Content

TOOLS

Tool	Manufacturer	Part Number
Hand crimper for Mini-Fit Sr. crimp terminals	Molex	2002188600
Hand crimper for Mini-Fit crimp terminals	Molex	2002182200
Hand crimper for Mega-Fit crimp terminals	Molex	2238631200
Hand crimper for Micro-Fit 3.0 crimp terminals	Molex	0638190000
Hand crimper for CLIK-Mate crimp terminals	Molex	2002187400

Table 3-10 Recommended tools

3.3 Connection specifications

The actual connection will depend on the overall configuration of your drive system and the type of motor you will be using. Follow the description in given order and choose the wiring diagram (➔see page 4-45) that best suits the components you are using.

How to read pin assignment tables
In the subsequent sections of the document, you will come across tables outlining the pin assignments. These tables provide information about the hardware connectors, their corresponding wired signals, the assigned pins, and details regarding the prefab cables that are available.
- *The initial column provides the pin numbers for the connectors.*
- *The second column specifies the pin numbers for the corresponding end (Head A) of the prefab cable.*
- *The third column describes the core color of the prefab cable.*
- *The fourth column indicates the pin numbers for the other end (Head B) of the prefab cable.*

3.3.1 Power supply (X1)

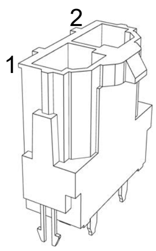


Figure 3-8 Power supply connector X1

X1 Pin	Prefab cable Head A Pin	Cable color	Head B Pin	Signal	Description
1	1	black	–	GND	Ground
2	2	black	+	V_{CC}	Power supply voltage input (10...60 VDC)

Table 3-11 Power supply connector X1 – Pin assignment

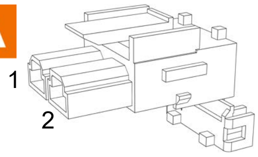
Power cable highest current (P/N 838459)		
A 		B
Cross-section	2 × 4 mm^2, grey	
Length	3 m	
Head A	Plug	Molex Mini-Fit Sr., 2 poles (428160212)
	Contacts	Molex Mini-Fit Sr. female crimp terminals (428150114)
Head B	Wire end sleeves 4 mm^2	

Table 3-12 Power cable highest current

Power supply requirements	
Nominal output voltage V_{CC}	10…60 VDC
Absolute output voltage V_{CC}	min. 8 VDC / max. 62 VDC
Output current	Depending on load • continuous max. 30 A • short-time (acceleration) max. 60 A (< 4 s)

Table 3-13 Power supply requirements

1) Use the formula below to calculate the required voltage under load.
2) Choose a power supply according to the calculated voltage. Thereby consider:
   a) During braking of the load, the power supply must be capable of buffering the recovered kinetic energy (for example, in a capacitor).
   b) If you are using an electronically stabilized power supply, make sure that the over current protection circuit is configured inoperative within the operating range.

The formula already takes the following into account:
- *Maximum PWM duty cycle of 95 %*
- *Controller's max. voltage drop of 1 V @ 30 A*

KNOWN VALUES:

- Operating torque M [mNm]
- Operating speed n [rpm]
- Nominal motor voltage U_N [Volt]
- Motor no-load speed at U_N; n_O [rpm]
- Speed/torque gradient of the motor $\Delta n/\Delta M$ [rpm/mNm]

SOUGHT VALUE:

- Supply voltage V_{CC} [Volt]

SOLUTION:

$$V_{CC} \geq \left[\frac{U_N}{n_O} \cdot \left(n + \frac{\Delta n}{\Delta M} \cdot M\right) \cdot \frac{1}{0.95}\right] + 1\,[V]$$

3.3.2 Logic supply (X2)

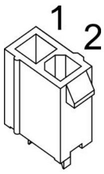


Figure 3-9 Logic supply connector X2

X2	Prefab cable			Signal	Description
Pin	Head A Pin	Cable color	Head B Pin		
1	1	black	–	GND	Ground
2	2	black	+	V_C	Logic supply voltage input (10...60 VDC)

Table 3-14 Logic supply connector X2 – Pin assignment

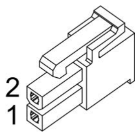
Power cable (P/N 275829)		
A 		B
Cross-section	2 × 0.75 mm², grey	
Length	3 m	
Head A	Plug	Molex Mini-Fit Jr., 2 poles (39012020)
	Contacts	Molex Mini-Fit Jr. female crimp terminals (457501112)
Head B	Wire end sleeves 0.75 mm²	

Table 3-15 Power cable

Logic supply requirements	
Nominal output voltage V_C	10…60 VDC
Absolute output voltage V_C	min. 8 VDC / max. 62 VDC
Min. output power	P_C min. 3 W

Table 3-16 Logic supply requirements

3.3.3 Motor (X3)

The controller is set to drive either maxon EC motor (BLDC, brushless DC motor) or maxon DC motor (brushed DC motor) with separated motor/encoder cable.

3.3.3.1 Motor highest current (X3a)

Motor connector X3a must be used for motors that require a continuous current greater 20 A.

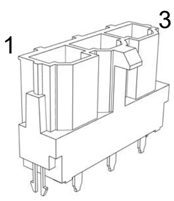


Figure 3-10 Motor connector X3a

Best practice
Keep the motor mechanically disconnected during the setup and adjustment phase.

X3a Pin	Prefab cable: Head A Pin	Prefab cable: Cable color	Prefab cable: Head B Pin	Signal	Description
1	1	black		Motor winding 1	EC motor: Winding 1
				Motor (+M)	DC motor: Motor +
2	2	black		Motor winding 2	EC motor: Winding 2
				Motor (-M)	DC motor: Motor -
3	3	black		Motor winding 3	EC motor: Winding 3
				-	DC motor: DO NOT CONNECT
-		black		Motor shield	Cable shield

Table 3-17 Motor connector X3a – Pin assignment for maxon EC & DC motor

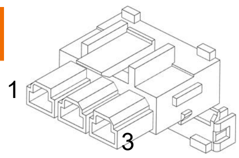
Motor cable highest current for X3a (P/N 838460)		
A  B		
Cross-section	3 × 4 mm^2, shielded, grey	
Length	3 m	
Head A	Plug	Molex Mini-Fit Sr., 3 poles (428160312)
	Contacts	Molex Mini-Fit Sr. female crimp terminals (428150114)
	1 × cable lug 4 mm^2 for M4 screws	
Head B	Wire end sleeves 4 mm^2	

Table 3-18 Motor cable highest current

3.3.3.2 Motor high current (X3b)

Motor connector X3b can be used for motors that require a continuous current of up to 20 A.

Maximum permitted current
The connector is designed for the following output current:
- *X3b:* $I_{cont} \leq 20$ *A*

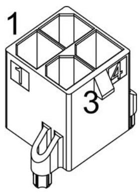


Figure 3-11 Motor connector X3b

Best practice
Keep the motor mechanically disconnected during the setup and adjustment phase.

X3b Pin	Prefab cable Head A Pin	Prefab cable Cable color	Prefab cable Head B Pin	Signal	Description
1	1	black		Motor winding 1	EC motor: Winding 1
				Motor (+M)	DC motor: Motor +
2	2	black		Motor winding 2	EC motor: Winding 2
				Motor (-M)	DC motor: Motor -
3	3	black		Motor winding 3	EC motor: Winding 3
				-	DC motor: DO NOT CONNECT
4	4	black		Motor shield	Cable schield

Table 3-19 Motor connector X3b – Pin assignment for maxon EC & DC motor

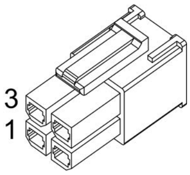
Motor cable high current for X3b (P/N 520851)		
A 		B
Cross-section	3 × 2.5 mm², shielded, grey	
Length	3 m	
Head A	Plug	Molex Mega-Fit, 4 poles (1716920104)
	Contacts	Molex Mega-Fit female crimp terminals (1720630311)
Head B	Wire end sleeves 2.5 mm²	

Table 3-20 Motor cable high current

3.3.4 Sensor 1 Hall sensor (X4)

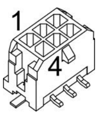


Figure 3-12 Sensor 1 Hall sensor connector X4

X4 Pin	Prefab cable Head A Pin	Cable color	Head B Pin	Signal	Description
1	1	green		Hall sensor 1	Hall sensor 1 input
2	2	brown		Hall sensor 2	Hall sensor 2 input
3	3	white		Hall sensor 3	Hall sensor 3 input
4	4	yellow		GND	Ground
5	5	grey		V_{Sensor}	Sensor supply voltage output (5 VDC / $I_L \leq$ 145 mA)
6	6	black		Hall shield	Cable schield

Table 3-21 Sensor 1 Hall sensor connector X4 – Pin assignment

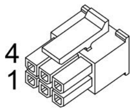
Hall sensor cable (P/N 275878)		
A 		B
Cross-section	5 × 0.14 mm^2, shielded, grey	
Length	3 m	
Head A	Plug	Molex Micro-Fit 3.0, 6 poles (430250600)
	Contacts	Molex Micro-Fit 3.0 female crimp terminals (430300010)
Head B	Wire end sleeves 0.14 mm^2	

Table 3-22 Sensor 1 Hall sensor cable

Important Notice

The maximum supply current of the sensor supply voltage output V_{Sensor} is in total 145 mA. It can be used for:

- *Hall sensors ➔Chapter “3.3.4 Sensor 1 Hall sensor (X4)” on page 3-22*
- *Incremental encoders ➔Chapter “3.3.5.1 Incremental encoder” on page 3-26*
- *SSI / BiSS C encoders ➔Chapter “3.3.5.2 SSI / BISS C unidirectional absolute encoder (future release)” on page 3-27*
- *High-speed digital I/Os ➔Chapter “3.3.6 Digital I/Os (X7)” on page 3-31*
- *Digital I/Os ➔Chapter “3.3.6 Digital I/Os (X7)” on page 3-31*
- *Other peripherals which need a 5 VDC supply.*

All currents resulting from parts connected to the sensor supply voltage output V_{Sensor} must not exceed 145 mA in total.

Hall sensor	
Sensor supply voltage output V_{Sensor}	5 VDC
Max. Hall sensor supply current	145 mA (➔refer to Important Notice)
Input voltage	0…24 VDC
Max. input voltage	24 VDC
Low-level input voltage	< 0.8 VDC
High-level input voltage	> 2.0 VDC
Internal pull-up resistor	2.7 kΩ (referenced to 5.45 VDC - 0.6 VDC)

Table 3-23 Sensor 1 Hall sensor specification

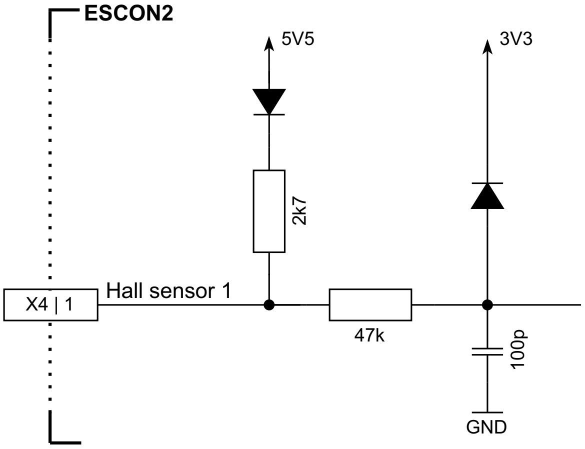


Figure 3-13 Sensor 1 Hall sensor input circuit (analogously valid for Hall sensors 2 & 3)

3.3.5 Sensor 2 Encoder / I/Os (X5)

Additional sensors, both incremental and serial encoders, or digital inputs and outputs can be connected. Only one sensor/function can be used at a time, i.e. either an incremental encoder, or an absolute encoder, or high-speed digital I/Os.

Best practice
For best performance and good resistance against electrical interference, ***we recommend using encoders with a line driver (differential scheme).*** *Otherwise, limitations may apply due to slow switching edges. Nevertheless, the controller supports both schemes – differential and single-ended (unsymmetrical).*

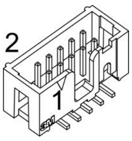


Figure 3-14 Sensor 2 connector X5

X5	Prefab cable			Signal	Description
Pin	Head A Pin	Cable color	Head B Pin		
1	1	brown	1	Data	Data (SSI, BiSS C)
				HsDigIN4	High-speed digital input 4
2	2	white	2	V_{Sensor}	Sensor supply voltage output (5 VDC / $I_L \leq$ 145 mA)
3	3	red	3	GND	Ground
4	4	white	4	Clock	Clock (SSI, BiSS C)
				HsDigOUT1	High-speed digital output 1
5	5	orange	5	Channel A\	Digital incremental encoder channel A complement
				HsDigIN1\	High-speed digital input 1 complement
6	6	white	6	Channel A	Digital incremental encoder channel A
				HsDigIN1	High-speed digital input 1
7	7	yellow	7	Channel B\	Digital incremental encoder channel B complement
				HsDigIN2\	High-speed digital input 2 complement
8	8	white	8	Channel B	Digital incremental encoder channel B
				HsDigIN2	High-speed digital input 2
9	9	green	9	–	not connected
10	10	white	10	HsDigIN3	High-speed digital input 3

Table 3-24 Sensor 2 connector X5 – Pin assignment

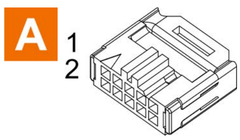
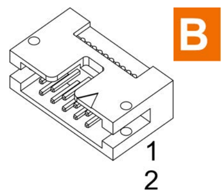
Encoder cable (P/N 275934)	
	
Cross-section	10 × AWG28, round-jacket, flat cable, pitch 1.27 mm
Length	3 m
Head A	DIN 41651 female, pitch 2.54 mm, 10 poles, with strain relief
Head B	DIN 41651 plug, pitch 2.54 mm, 10 poles, with strain relief

Table 3-25 Encoder cable

Important Notice
The maximum supply current of the sensor supply voltage output V_{Sensor} is in total 145 mA. It can be used for:
- *Hall sensors ➔Chapter "3.3.4 Sensor 1 Hall sensor (X4)" on page 3-22*
- *Incremental encoders ➔Chapter "3.3.5.1 Incremental encoder" on page 3-26*
- *SSI / BiSS C encoders ➔Chapter "3.3.5.2 SSI / BISS C unidirectional absolute encoder (future release)" on page 3-27*
- *High-speed digital I/Os ➔Chapter "3.3.6 Digital I/Os (X7)" on page 3-31*
- *Digital I/Os ➔Chapter "3.3.6 Digital I/Os (X7)" on page 3-31*
- *Other peripherals which need a 5 VDC supply.*

All currents resulting from parts connected to the sensor supply voltage output V_{Sensor} must not exceed 145 mA in total.

3.3.5.1 Incremental encoder

Digital incremental encoder (differential)	
Sensor supply voltage output V_{Sensor}	5 VDC
Max. sensor supply current	≤ 145 mA (➔refer to Important Notice)
Min. differential input voltage	± 200 mV
Max. input voltage	± 12 VDC
Line receiver (internal)	EIA/RS422 standard
Max. input frequency	6.67 MHz

Table 3-26 Differential digital incremental encoder specification

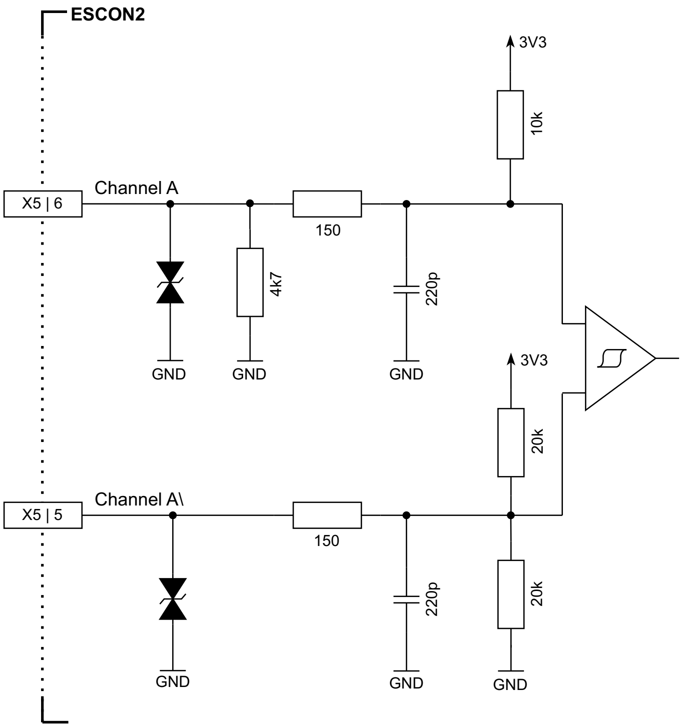


Figure 3-15 Digital incremental encoder input circuit Ch A “differential” (analogously valid for Ch B)

Digital incremental encoder (single-ended)		
Sensor supply voltage output V_{Sensor}		5 VDC
Max. sensor supply current		≤ 145 mA (➔refer to Important Notice)
Input voltage		0...5 VDC
Max. input voltage		± 12 VDC
Low-level input voltage		< 1 VDC
High-level input voltage		> 2.4 VDC
Input high current		I_{IH} = typically 1.3 mA @ 5 VDC
Input low current		I_{IL} = typically -0.36 mA @ 0 VDC
Max. input frequency	Push-pull	6.25 MHz
	Open collector	100 kHz (additional external 3k3 pull-up)

Table 3-27 Single-ended digital incremental encoder specification

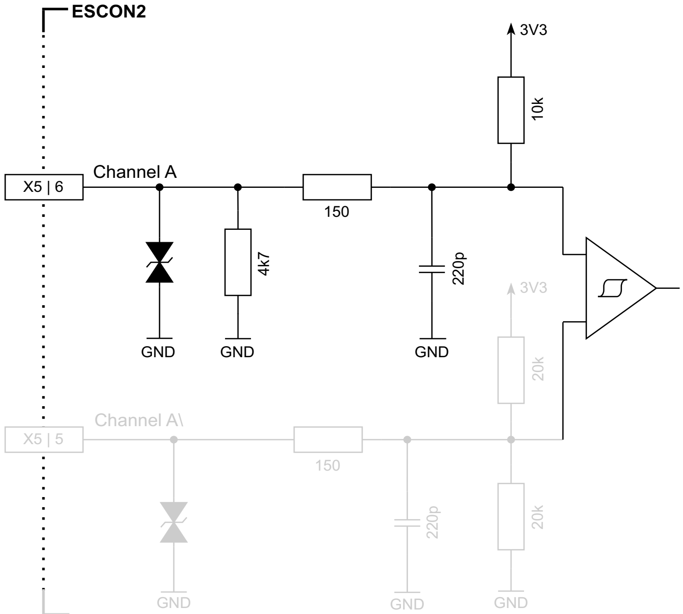


Figure 3-16 Digital incremental encoder input circuit Ch A “single-ended” (analogously valid for Ch B)

3.3.5.2 SSI / BISS C unidirectional absolute encoder (future release)

The functionality will only be available with a future firmware release.

SSI / BiSS C unidirectional absolute encoder (single-ended)		
Sensor supply voltage output V_{Sensor}		5 VDC
Max. sensor supply current		≤ 145 mA (➔refer to Important Notice)
Clock frequency	SSI	0.1...2 MHz
	BiSS C	0.1...4 MHz

Table 3-28 SSI / BISS C unidirectional absolute encoder specification

SSI / BiSS C unidirectional absolute encoder data channel	
Input voltage	0…5 VDC
Max. input voltage	± 12 VDC
Low-level input voltage	< 1.0 VDC
High-level input voltage	> 2.4 VDC
Input high current	I_{IH} = typically 0.34 mA @ 5 VDC (➔refer to Important Notice)
Input low current	I_{IL} = typically 0 mA @ 0 VDC (➔refer to Important Notice)
Max. input frequency	6.25 MHz
Total reaction time	< 1.5 ms

Table 3-29 Single-ended SSI / BISS C unidirectional absolute encoder data channel specification

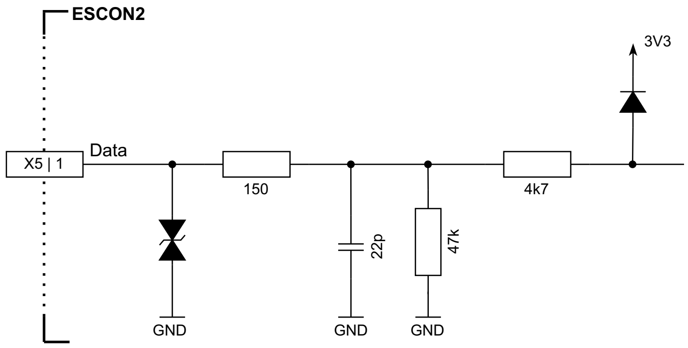


Figure 3-17 SSI absolute encoder data input (analogously valid for BiSS C)

SSI / BISS C unidirectional absolute encoder clock channel		
Output voltage		3.3 VDC
Output resistance		47 Ω
Max. output current		24 mA
Clock frequency	SSI	0.1...2 MHz
	BiSS C	0.1...4 MHz

Table 3-30 Single-ended SSI / BISS C unidirectional absolute encoder clock channel specification

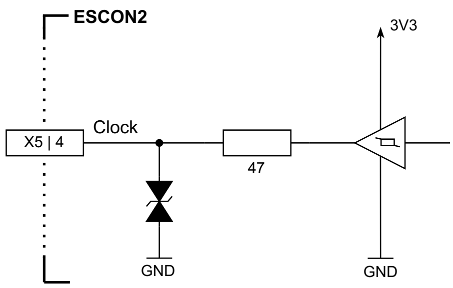


Figure 3-18 SSI absolute encoder clock output (analogously valid for BiSS C)

3.3.5.3 High-speed digital I/Os

Alternatively, the sensor interface can be used for high-speed digital I/O operation.

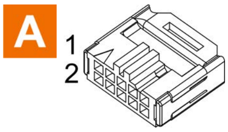
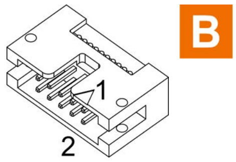
Encoder cable (P/N 275934)	
	
Cross-section	10 × AWG28, round-jacket, flat cable, pitch 1.27 mm
Length	3 m
Head A	DIN 41651 female, pitch 2.54 mm, 10 poles, with strain relief
Head B	DIN 41651 plug, pitch 2.54 mm, 10 poles, with strain relief

Table 3-31 Encoder cable

High-speed digital input 1…2 (differential)	
Max. input voltage	± 12 VDC
Min. differential input voltage	± 200 mV
Line receiver (internal)	EIA/RS422 standard
Max. input frequency	6.67 MHz
Total reaction time	< 1.5 ms

Table 3-32 Differential high-speed digital input specification

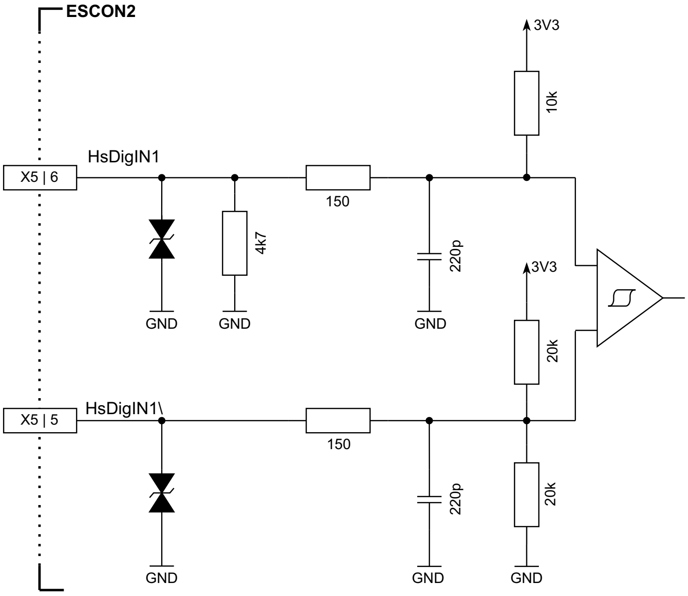


Figure 3-19 HsDigIN1 circuit “differential” (analogously valid for HsDigIN2)

High-speed digital input 1…4 (single-ended)		
Input voltage		0…5 VDC
Max. input voltage		± 12 VDC
Low-level input voltage		< 1.0 VDC
High-level input voltage		> 2.4 VDC
Input high current	HsDigIN1…3	I_{IH} = typically 1.3 mA @ 5 VDC (➔refer to Important Notice)
	HsDigIN4	I_{IH} = typically 0.34 mA @ 5 VDC (➔refer to Important Notice)
Input low current	HsDigIN1…3	I_{IL} = typically −0.36 mA @ 0 VDC (➔refer to Important Notice)
	HsDigIN4	I_{IL} = typically 0 mA @ 0 VDC (➔refer to Important Notice)
Max. input frequency		6.25 MHz
Total reaction time		< 1.5 ms

Table 3-33 Single-ended high-speed digital input specification

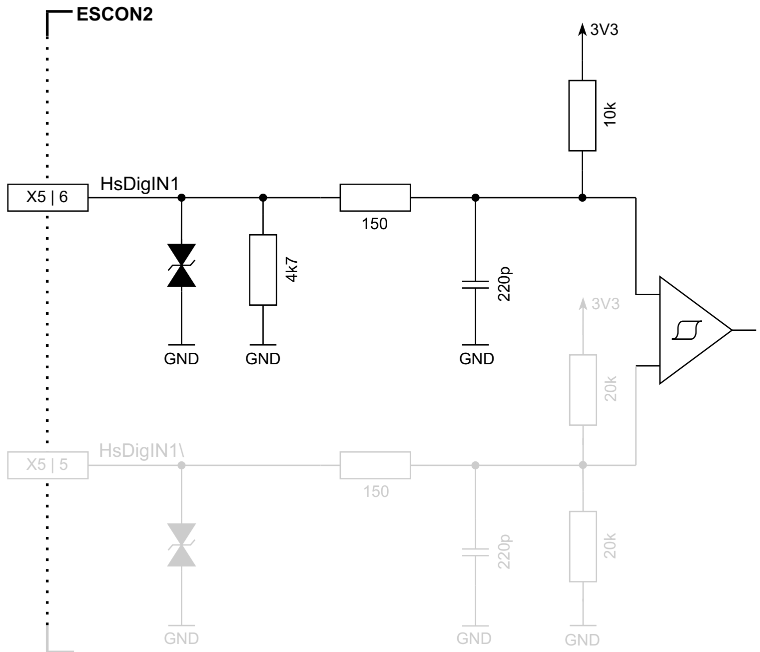


Figure 3-20 HsDigIN1 circuit “single-ended” (analogously valid for HsDigIN2…3)

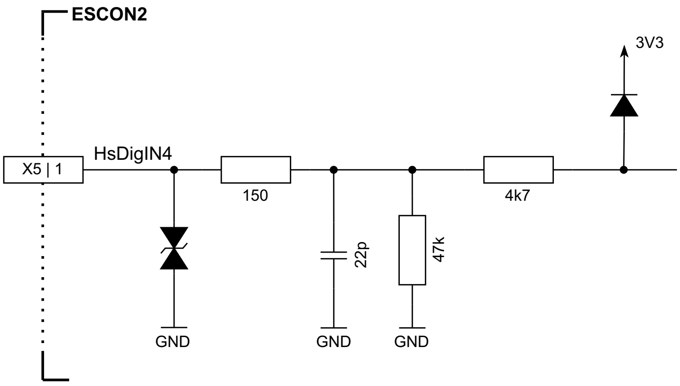


Figure 3-21 HsDigIN4 circuit “single-ended”

High-speed digital output 1	
Output voltage	3.3 VDC
Output resistance	47 Ω
Max. output current	24 mA
Max. output frequency	25 kHz

Table 3-34 High-speed digital output specification

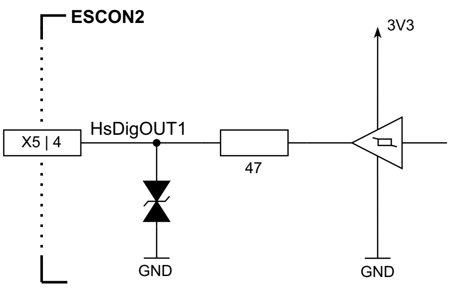


Figure 3-22 HsDigOUT1 circuit

3.3.6 Digital I/Os (X7)

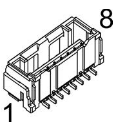


Figure 3-23 Digital I/Os connector X7

X7 Pin	Prefab cable Head A Pin	Prefab cable Cable color	Prefab cable Head B Pin	Signal	Description
1	1	white		DigIN1	Digital input 1
2	2	brown		DigIN2	Digital input 2
3	3	green		DigIN3	Digital input 3
4	4	yellow		DigIN4	Digital input 4
5	5	grey		DigOUT1	Digital output 1
6	6	pink		DigOUT2	Digital output 2
7	7	blue		GND	Ground
8	8	red		$V_{I/O}$	$V_{I/O}$ = 5 VDC - 0.75 VDC = 4.25 VDC

Table 3-35 Digital I/Os connector X7 – Pin assignment

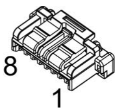
Signal cable 8core (P/N 520853)		
A 		B
Cross-section	8 × 0.14 mm^2, grey	
Length	3 m	
Head A	Plug	Molex CLIK-Mate, single row, 8 poles (5025780800)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)
Head B	Wire end sleeves 0.14 mm^2	

Table 3-36 Signal cable 8core

Digital inputs 1…2	
Input voltage	0…25 VDC
Max. input voltage	±25 VDC
Low-level input voltage	< 0.8 VDC
High-level input voltage	> 2.1 VDC
Input resistance	typically 47 kΩ < 3.3 VDC typically 37 kΩ @ 5 VDC typically 25 kΩ @ 24 VDC
Input current at logic 1	typically 135 µA @ 5 VDC
Hardware switching delay	< 6 µs
Total reaction time	< 2.3 ms
PWM duty cycle (resolution)	10...90 % (0.1 %)
PWM frequency	50 Hz...10 kHz
PWM accuracy	typically +0.1 % absolute @ 50 Hz / 5 VDC typically +1.5 % absolute @ 10 kHz / 5 VDC

Table 3-37 Digital inputs 1...2 specification

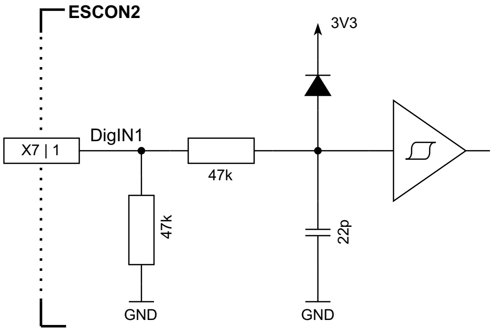


Figure 3-24 DigIN1 circuit (analogously valid for DigIN2)

Digital inputs 3…4	
Input voltage	0…25 VDC
Max. input voltage	±25 VDC
Low-level input voltage	< 0.8 VDC
High-level input voltage	> 2.1 VDC
Input resistance	typically 47 kΩ < 3.3 VDC typically 37 kΩ @ 5 VDC typically 25 kΩ @ 24 VDC
Input current at logic 1	typically 135 μA @ 5 VDC
Hardware switching delay	< 300 μs
Total reaction time	< 2.3 ms

Table 3-38 Digital inputs 3...4 specification

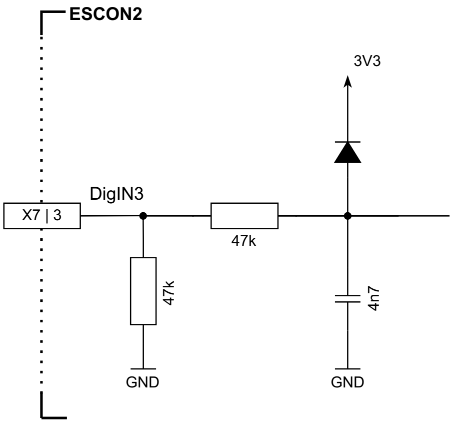


Figure 3-25 DigIN3 circuit (analogously valid for DigIN4)

Digital outputs 1...2 “sink”	
Max. input voltage	36 VDC
Max. load current	500 mA
Max. voltage drop	0.25 VDC @ 500 mA
Max. load inductance	100 mH @ 24 VDC; 500 mA with internal clamping typically 45 VDC
Max. output frequency	25 kHz

Table 3-39 Digital outputs specification – Sinks

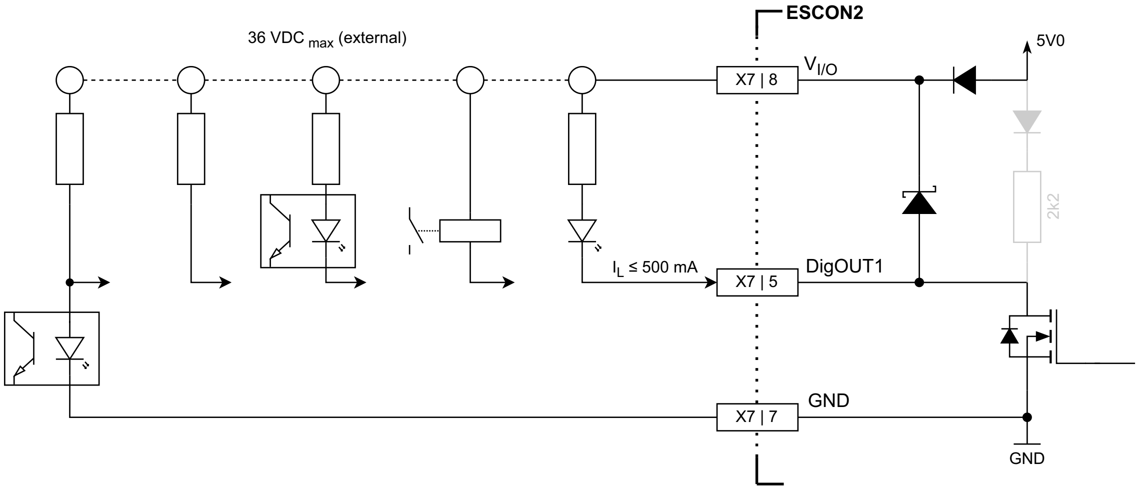


Figure 3-26 DigOUT1 “sinks” (analogously valid for DigOUT2)

Freewheeling diode for inductive loads
When utilizing the digital output load switch for the operation of inductive loads, such as relays, and $V_{I/O}$ is not used, it is essential to confirm the presence of a freewheeling diode to prevent potential harm to the hardware. If possible, install the freewheeling diode at the load.

Digital outputs 1...2 “source”	
Output voltage	V_{Out} = 5 VDC − 0.75 VDC − (I_L × 2´200 Ω)
Max. load current	$I_L \leq$ 2 mA

Table 3-40 Digital outputs specification – Sources

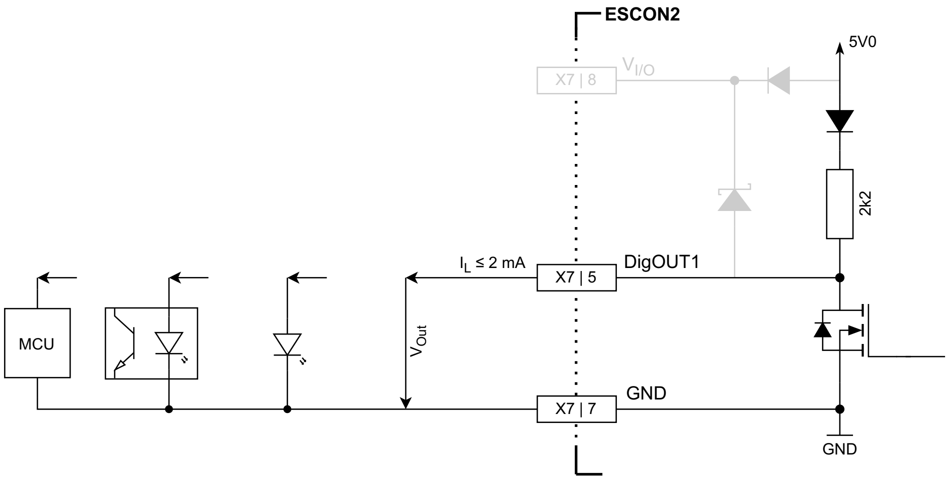


Figure 3-27 DigOUT1 “source” (analogously valid for DigOUT2)

3.3.7 Analog I/Os (X8)

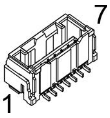


Figure 3-28 Analog I/Os connector X8

X8 Pin	Prefab cable			Signal	Description
	Head A Pin	Cable color	Head B Pin		
1	1	white		AnIN1+	Analog input 1 positive signal
2	2	brown		AnIN1−	Analog input 1 negative signal
3	3	green		AnIN2+	Analog input 2 positive signal
4	4	yellow		AnIN2−	Analog input 2 negative signal
5	5	grey		AnOUT1	Analog output 1
6	6	pink		AnOUT2	Analog output 2
7	7	blue		GND	Ground

Table 3-41 Analog I/Os connector X8 – Pin assignment

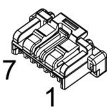
Signal cable 7core (P/N 520854)		
A  7 1		B
Cross-section	7 × 0.14 mm², grey	
Length	3 m	
Head A	Plug	Molex CLIK-Mate, single row, 7 poles (5025780700)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)
Head B	Wire end sleeves 0.14 mm²	

Table 3-42 Signal cable 7core

Analog inputs 1…2		
Input voltage		±10 VDC (differential)
Max. input voltage		±24 VDC
Common mode voltage		−5…+10 VDC (referenced to GND)
Input resistance	differential	80 kΩ
	referenced to GND	65 kΩ
A/D converter		12-bit
Resolution		5.64 mV
Bandwidth		10 kHz

Table 3-43 Analog input specification

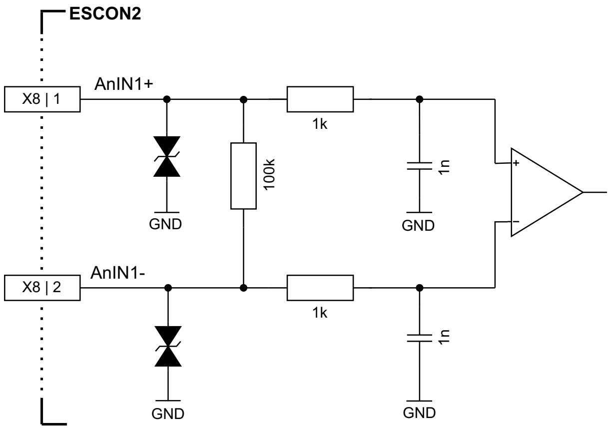


Figure 3-29 AnIN1 circuit (analogously valid for AnIN2)

Analog outputs 1…2	
Output voltage	±4 VDC
D/A converter	12-bit
Resolution	2.42 mV
Refresh rate	50 kHz
Analog bandwidth of output amplifier	25 kHz
Max. capacitive load	300 nF ***Note:*** *The increase rate is limited in proportion to the capacitive load (e.g. 5 V/ms @ 300 nF)*
Max. output current limit	1 mA

Table 3-44 Analog output specification

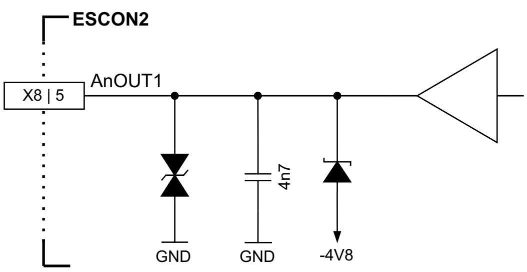


Figure 3-30 AnOUT1 circuit (analogously valid for AnOUT2)

3.3.8 CAN 1 (X11) & CAN 2 (X12)

The ESCON2 is specially designed being commanded and controlled via a Controller Area Network (CAN), a highly efficient data bus very common in all fields of automation and motion control. It is preferably used as a slave node in the CANopen network.

For the CAN configuration check ➔Chapter “3.4 DIP switch configuration (SW1)” on page 3-41.

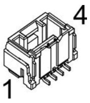
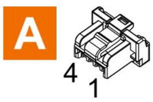


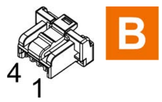
Figure 3-31 CAN 1 connector X11/CAN 2 connector X12

X11/12 Pin	Prefab cable				Signal	Description
	Head A Pin	Cable color	P/N 520858 Head B Pin	P/N 520857 Head B Pin		
1	1	white	1	7	CAN high	CAN bus high line
2	2	brown	2	2	CAN low	CAN bus low line
3	3	green	3	3	GND	Ground
4	4	yellow	4	5	CAN shield	Cable shield

Table 3-45 CAN 1 connector X11/CAN 2 connector X12 – Pin assignment

CAN-CAN cable (P/N 520858)

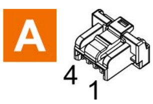


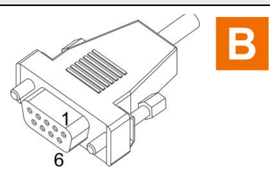


Cross-section	2 × 2 × 0.14 mm², twisted pair, shielded	
Length	3 m	
Head A	Plug	Molex CLIK-Mate, single row, 4 poles (5025780400)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)
Head B	Plug	Molex CLIK-Mate, single row, 4 poles (5025780400)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)

Table 3-46 CAN-CAN cable

CAN-COM cable (P/N 520857)





Cross-section	2 × 2 × 0.14 mm², twisted pair, shielded	
Length	3 m	
Head A	Plug	Molex CLIK-Mate, single row, 4 poles (5025780400)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)
Head B	Female D-Sub connector DIN 41652 9 poles, with mounting screws	

Table 3-47 CAN-COM cable

CAN interface	
Standard	ISO 11898-2:2003
Max. bit rate	1 Mbit/s
Max. number of CAN nodes	31/127 (via hardware/software setting)
Protocol	CiA 301 version 4.2.0
Node-ID setting	By DIP switch or software

Table 3-48 CAN interface specification

Note
- *Consider the CAN master’s maximal bit rate.*
- *The standard bit rate setting (factory setting) is 1 Mbit/s.*
- *Use 120 Ω termination resistor at both ends of the CAN bus.*
- *For detailed CAN information see separate document ➔«ESCON2 Communication Guide».*

3.3.9 USB (X13)

Hot plugging the USB interface may cause hardware damage
If the USB interface is being hot-plugged (connecting while the power supply is on), the possibly high potential differences of the two power supplies of controller and PC/Notebook can lead to damaged hardware.
- *Avoid potential differences between the power supply of controller and PC/Notebook or, if possible, balance them.*
- *Insert the USB connector first, then switch on the power supply of the controller.*

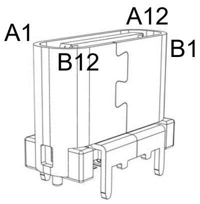


Figure 3-32 USB connector X13

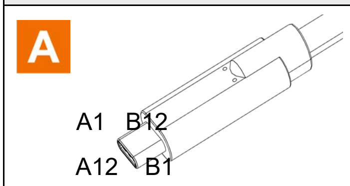
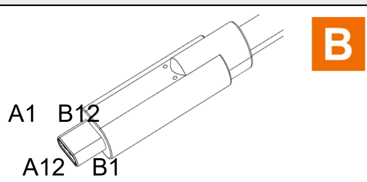
USB Type C - Type C cable (P/N 845854)	
	
USB standard	USB 3.2
Length	1.5 m
Head A	USB Type C
Head B	USB Type C

Table 3-49 USB Type C – Type C cable

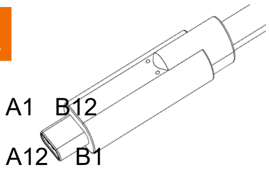
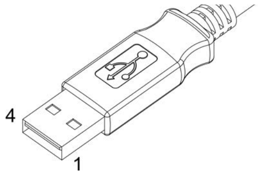
USB Type A - Type C cable (P/N 838461)	
A 	 B
USB standard	USB 2.0 / USB 3.0
Length	1.5 m
Head A	USB Type C
Head B	USB Type A

Table 3-50 USB Type A – Type C cable

USB	
Data signaling rate	12 Mbit/s (Full speed)
Max. bus supply voltage V_{Bus}	5.25 VDC
Max. DC data input voltage	−0.3…+3.8 VDC

Table 3-51 USB interface specification

3.3.10 Motor temperature sensor (X16) (future release)

The functionality will only be available with a future firmware release.

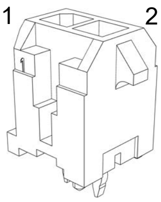
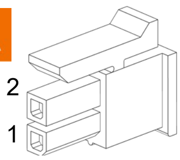


Figure 3-33 Motor temperature sensor connector X16

X16 Pin	Prefab cable			Signal	Description
	Head A Pin	Cable color	Head B Pin		
1	1	black		GND	Ground
2	2	red		MotorTemp	Motor temperature sensor input

Table 3-52 Motor temperature sensor connector X16 – Pin assignment

NTC cable (P/N 847301)	
A 	B
Cross-section	2 × 0.5 mm^2, grey
Length	3 m

NTC cable (P/N 847301)		
Head A	Plug	Molex Micro-Fit 3.0, 2 poles (430250200)
	Contacts	Molex Micro-Fit 3.0 female crimp terminals (0430300001)
Head B	Wire end sleeves 0.5 mm^2	

Table 3-53 NTC cable

Motor temperature sensor input	
Input voltage	0...3.3 VDC
Max. input voltage	+24 VDC
A/D converter	12-bit
Internal pull-up resistor	3.3 kΩ (referenced to 3.3 VDC)

Table 3-54 Motor temperature sensor – specifications

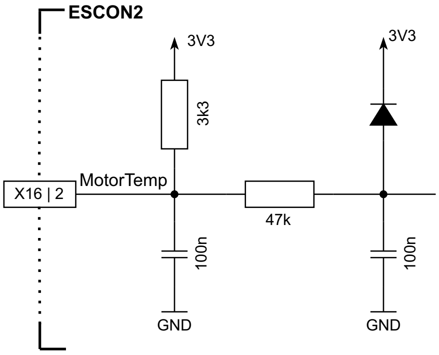


Figure 3-34 Motor temperature circuit

3.4 DIP switch configuration (SW1)

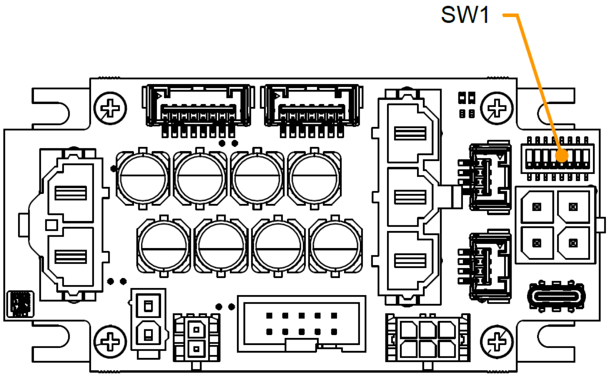


Figure 3-35 DIP switch SW1

DIP switch 8 has no functionality assigned and is not connected.

3.4.1 CAN ID (Node-ID)

The device’s identification (subsequently called “ID”) can be set by means of DIP switches 1...5 or software using binary code.

Setting the ID by DIP switch SW1

- *DIP switches 6…8 do not have any impact on the ID.*

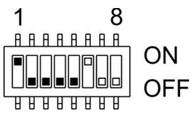
<table>
<tr><th>Setting</th><th>Switch</th><th>Binary Code</th><th>Valence</th></tr>
<tr><td rowspan="5">(factory setting)</td><td>1</td><td>2^0</td><td>1</td></tr>
<tr><td>2</td><td>2^1</td><td>2</td></tr>
<tr><td>3</td><td>2^2</td><td>4</td></tr>
<tr><td>4</td><td>2^3</td><td>8</td></tr>
<tr><td>5</td><td>2^4</td><td>16</td></tr>
</table>

Table 3-55 DIP switch SW1 – Binary code values

Continued on next page.

The set ID can be observed by adding the valence of all activated switches. Use the following table as a (non-concluding) guide:

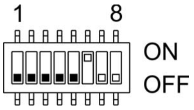
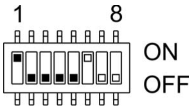
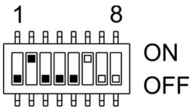
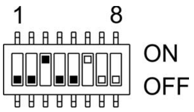
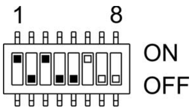
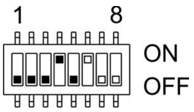
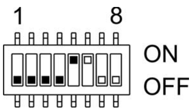
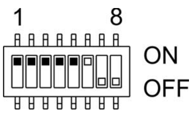
Setting	Switch 1	2	3	4	5	ID
	0	0	0	0	0	–
	**1**	0	0	0	0	1
	0	**1**	0	0	0	2
	0	0	**1**	0	0	4
	**1**	0	**1**	0	0	5
	0	0	0	**1**	0	8
	0	0	0	0	**1**	16
	**1**	**1**	**1**	**1**	**1**	31
0 = Switch "OFF" 1 = Switch "ON"						

Table 3-56 DIP switch SW1 – Examples

SETTING THE ID BY MEANS OF «MOTION STUDIO»

- The ID may be set by software (changing object 0x2000 «Node-ID», range 1…127).
- The ID set by software is valid if the ID is set to "0" (DIP switches 1...5 set to OFF).

3.4.2 CAN automatic bit rate detection

With this function, the CANopen interface can be put in a “listen only” mode. For further details see separate document ➔«ESCON2 Firmware Specification». Automatic bit rate detection is activated with DIP switch 6.

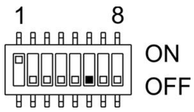
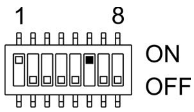
Switch	OFF	ON
6	 Automatic bit rate detection deactivated	 Automatic bit rate detection activated (factory setting)

Table 3-57 DIP switch SW1 – CAN automatic bit rate detection

3.4.3 CAN bus termination

A 120 Ω termination resistor can be "activated" with DIP switch 7.

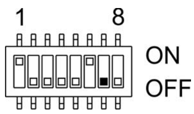
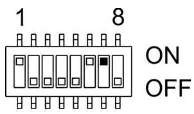
Switch	OFF	ON
7	 Without bus termination (factory setting)	 Bus termination with 120 Ω

Table 3-58 DIP switch SW1 – CAN bus termination

3.5 Status indicators

The ESCON2 features a set of LED indicators to display the device condition.

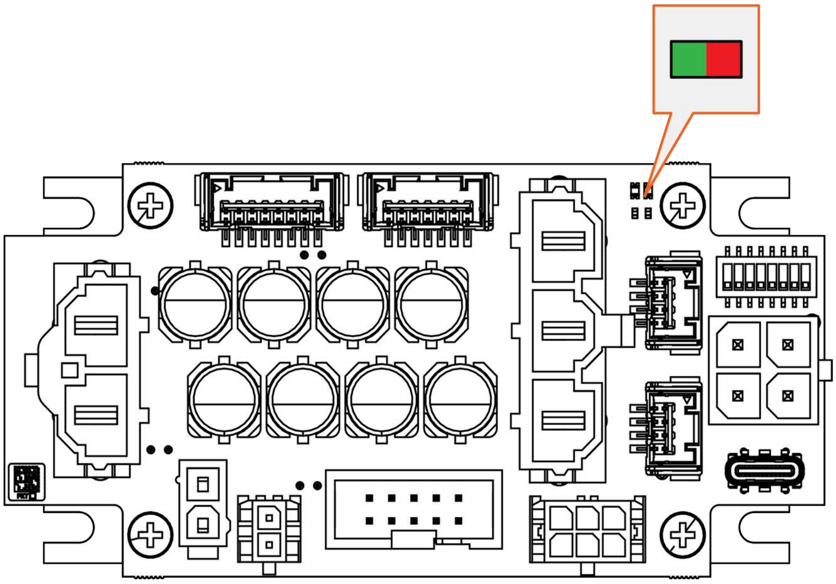


Figure 3-36 LEDs – Location

The LEDs display the actual status and possible warnings and errors of the ESCON2:

- Green LED shows the operation status
- Red LED indicates warnings and errors

<table>
<tr><th colspan="2">LED</th><th rowspan="2">Warning / Error</th><th rowspan="2">Description</th></tr>
<tr><th>Green</th><th>Red</th></tr>
<tr><td>Slow</td><td>OFF</td><td>No warning/error active.</td><td rowspan="2">Power stage is disabled. The ESCON2 is in status
• Switch on disabled
• Ready to switch on
• Switched on</td></tr>
<tr><td>Slow</td><td>Slow</td><td>At least one warning is active.</td></tr>
<tr><td>ON</td><td>OFF</td><td>No warning/error active.</td><td rowspan="2">Power stage is enabled. The ESCON2 is in status
• Operation enabled
• Quick stop active</td></tr>
<tr><td>ON</td><td>Slow</td><td>At least one warning is active.</td></tr>
<tr><td>ON</td><td>ON</td><td>At least one error has occurred.</td><td>Power stage is enabled. The ESCON2 is in temporary status
• Fault reaction active</td></tr>
<tr><td>OFF</td><td>ON</td><td>At least one error has occurred.</td><td>Power stage is disabled. The ESCON2 is in status
• Fault</td></tr>
<tr><td>Flash</td><td>ON</td><td>n/a</td><td>Firmware update in progress or invalid application</td></tr>
<tr><td colspan="4">Slow = LED is slowly blinking (0.5 s OFF, 0.5 s ON)
Flash = LED is flashing (0.9 s OFF, 0.1 s ON)</td></tr>
</table>

Table 3-59 Device status LEDs

4 WIRING

In this section you will find the wiring information for the setup you are using. You can either use the consolidated wiring diagrams (see ➔Figure 4-38) featuring the full scope of interconnectivity and pin assignment. Or you may wish to use the connection overviews for either DC motor or EC (BLDC) motor that will assist you in determining the wiring for your particular motor type and the appropriate feedback signals.

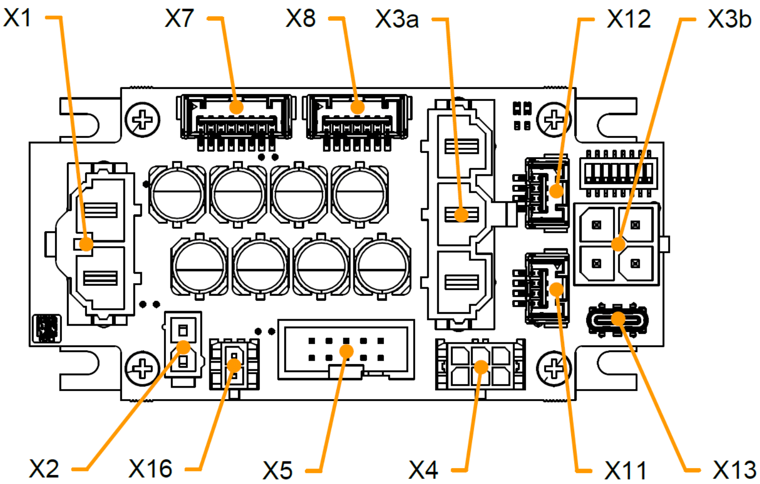


Figure 4-37 Interfaces – Designations and location

Signs and abbreviations used
The subsequent diagrams feature these signs and abbreviations:

- *«EC motor» stands for brushless EC motor (BLDC).*
- ⏚ *Ground safety earth connection (optional).*

4.1 Possible combinations to connect a motor

The following tables show feasible ways on how to connect the motor with its respective feedback signals or possible combinations thereof. To find the wiring that best suits your setup, proceed as follows:

1) Decide on the type of motor you are using and go to the respective subsection;
For DC motor, see ➔Chapter “4.1.1 DC motor” on page 4-46 or
For EC (BLDC) motor, see ➔Chapter “4.1.2 EC (BLDC) motor” on page 4-46.
2) Connect the power supply and the logic supply as shown in the referenced figure.
3) Check-out the listing for the combination that best suits your setup. Pick the wiring method # and go to the respective table;
For DC motor see ➔Table 4-60,
For EC (BLDC) motor see ➔Table 4-61.
4) Pick the row with the corresponding wiring method # and refer to the listed figure(s) to find the relevant wiring information.

maxon

4.1.1 DC motor

Power supply

Power supply and optional logic supply . . . . Figure 4-39 / Figure 4-40

Motor & feedback signals

Without sensor . . . . Method # DC1 [a]

Digital incremental encoder . . . . Method # DC2

SSI / BISS C unidirectional absolute encoder . . . . Method # DC3 [b]

Method #	Sensor 2		➔Figure(s)
	Digital incremental encoder	SSI / BISS C unidirectional absolute encoder [b]	
DC1 [a]			4-41
DC2	✓		4-41 4-44
DC3 [b]		✓	4-41 4-45

[a] For method # DC1, only the operating mode current control can be used.
[b] The functionality will be available with a future firmware release.

Table 4-60 Possible combinations of feedback signals for DC motor

4.1.2 EC (BLDC) motor

Power supply

Power supply and optional logic supply . . . . Figure 4-39 / Figure 4-40

Motor & feedback signals

Hall sensors . . . . Method # EC1

Hall sensors & Digital incremental encoder . . . . Method # EC2

Hall sensors & SSI / BISS C unidirectional absolute encoder . . . . Method # EC3 [a]

SSI / BISS C unidirectional absolute encoder . . . . Method # EC4 [a]

Method #	Sensor 1	Sensor 2		➔Figure(s)
	Hall sensors	Digital incremental encoder	SSI / BISS C unidirectional absolute encoder [a]	
EC1	✓			4-42 4-43
EC2	✓	✓		4-42 4-43 4-44
EC3 [a]	✓		✓	4-42 4-43 4-45
EC4 [a]			✓	4-42 4-45

[a] The functionality will be available with a future firmware release.

Table 4-61 Possible combinations of feedback signals for EC (BLDC) motor

4.2 Main wiring diagram

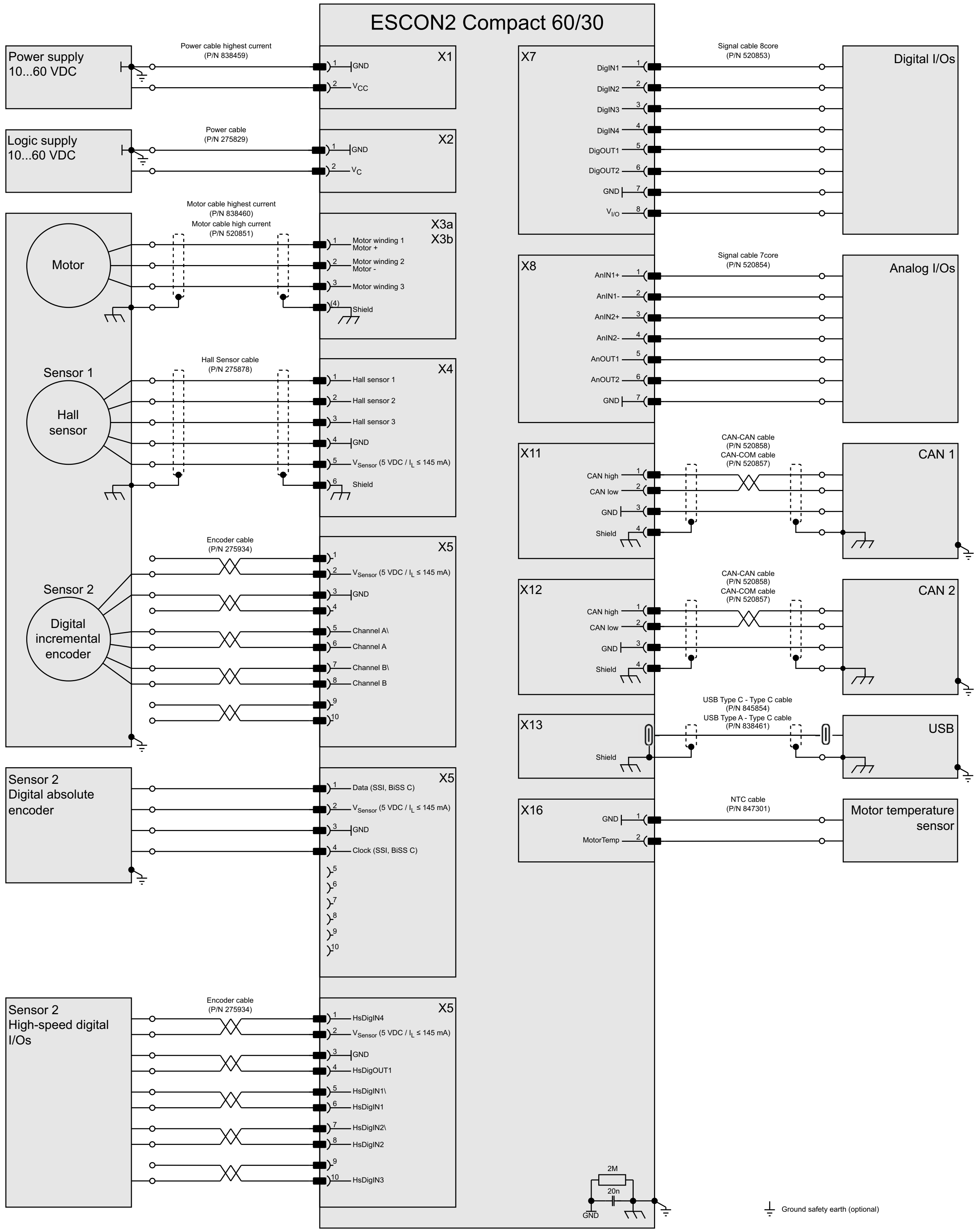


Figure 4-38 Main wiring diagram

4.3 Excerpts

4.3.1 Power supply

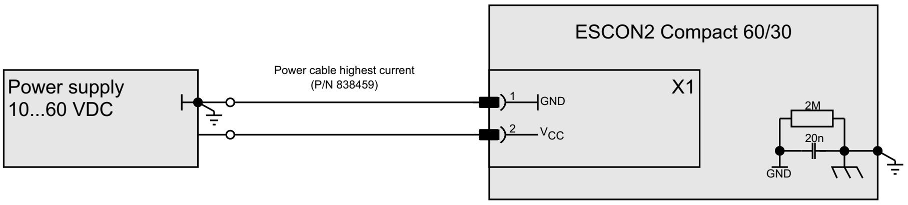


Figure 4-39 Power supply

4.3.2 Logic supply

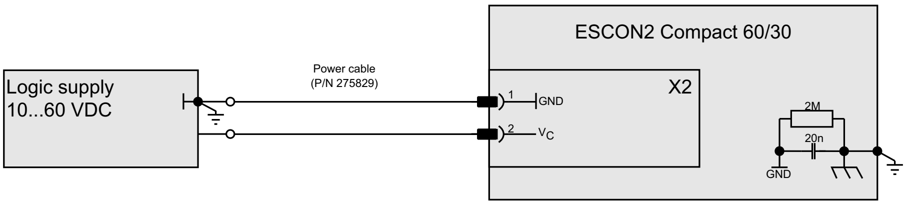


Figure 4-40 Logic supply

4.3.3 DC motor

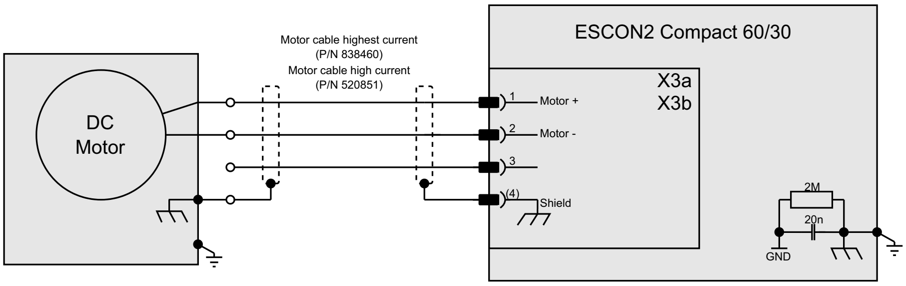


Figure 4-41 DC motor

The "Motor cable high current" (P/N 520851) can be used for currents up to 20 A. For higher currents, the "Motor cable highest current" (P/N 838460) must be used.

4.3.4 EC (BLDC) motor

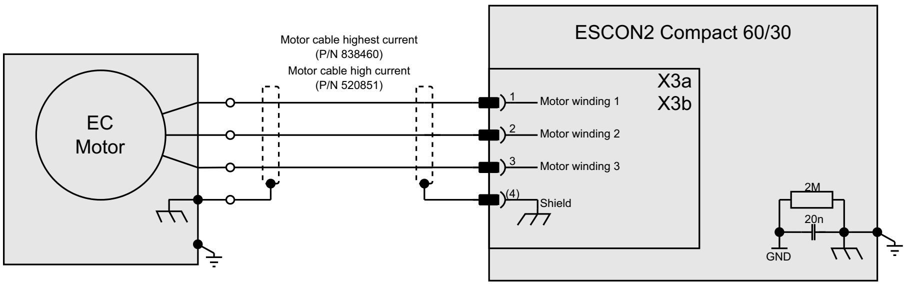


Figure 4-42 EC (BLDC) motor

The "Motor cable high current" (P/N 520851) can be used for currents up to 20 A. For higher currents, the "Motor cable highest current" (P/N 838460) must be used.

4.3.5 Sensor 1 Hall sensor

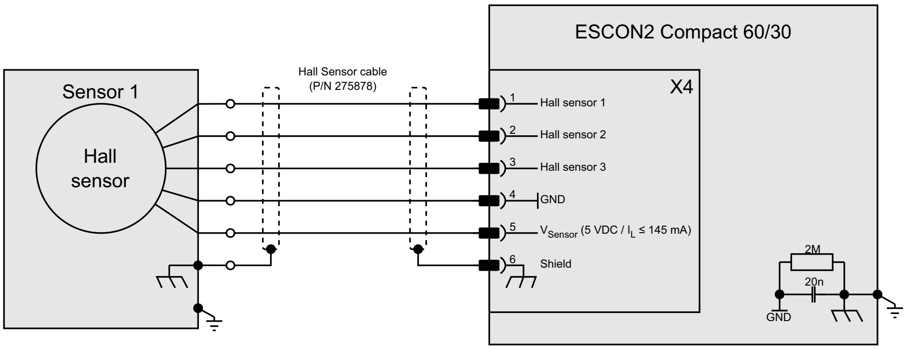


Figure 4-43 Sensor 1 Hall sensor

4.3.6 Sensor 2 Encoder / I/Os

4.3.6.1 Digital incremental encoder

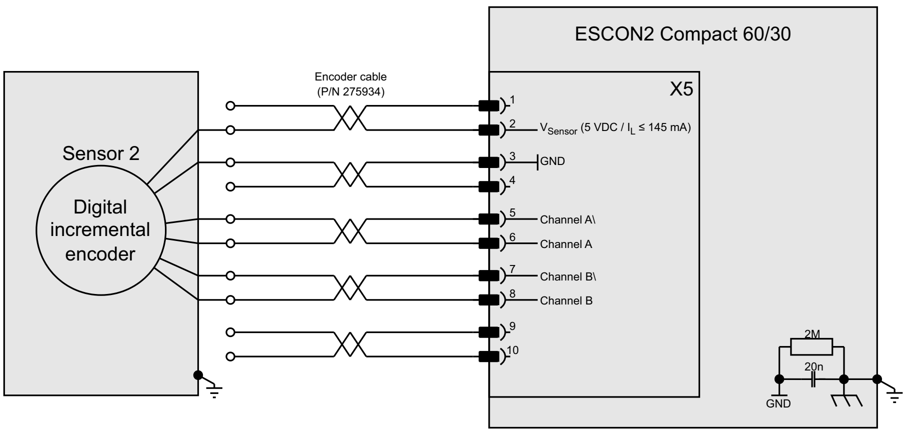


Figure 4-44 Digital incremental encoder

This interface can handle a digital incremental encoder, an SSI / BiSS C digital unidirectional absolute encoder or high-speed digital I/O's. Only one out of these three functions can be used at the same time.

4.3.6.2 SSI / BISS C unidirectional absolute encoder (future release)

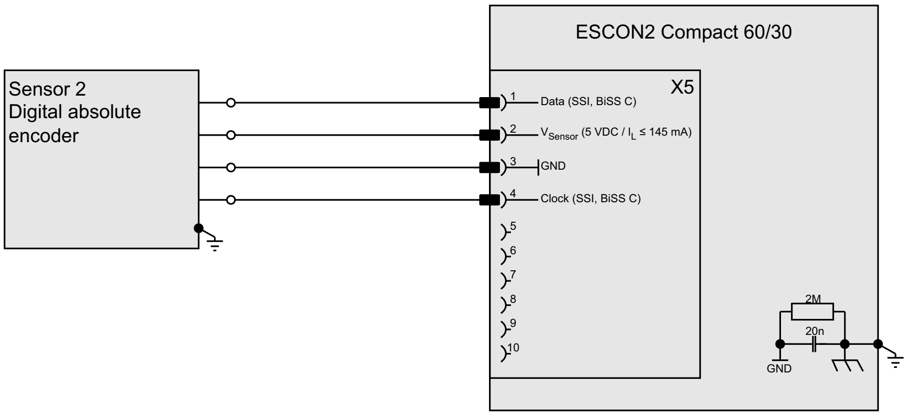


Figure 4-45 SSI / BISS C unidirectional absolute encoder

This interface can handle a digital incremental encoder, an SSI / BiSS C digital unidirectional absolute encoder or high-speed digital I/O's. Only one out of these three functions can be used at the same time.

4.3.6.3 High-speed digital I/Os

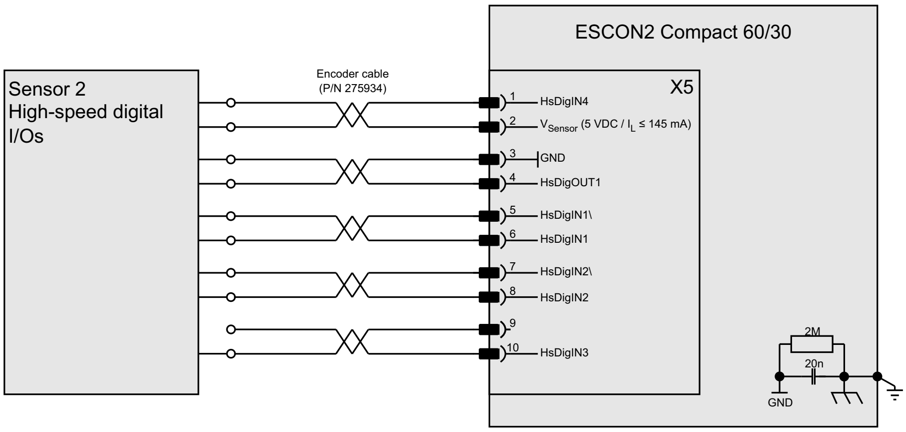


Figure 4-46 High-speed digital I/Os

This interface can handle a digital incremental encoder, an SSI / BiSS C digital unidirectional absolute encoder or high-speed digital I/O's. Only one out of these three functions can be used at the same time.

4.3.7 Digital I/Os

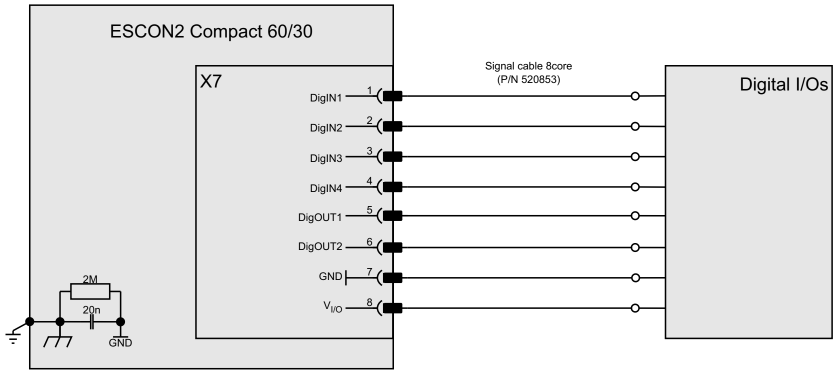


Figure 4-47 Digital I/Os

4.3.8 Analog I/Os

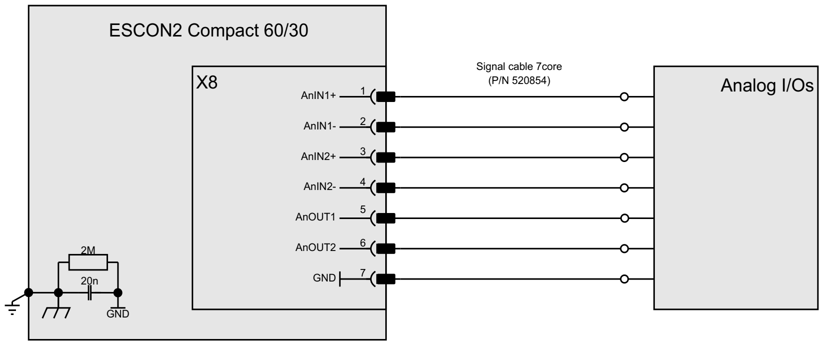


Figure 4-48 Analog I/Os

4.3.9 CAN

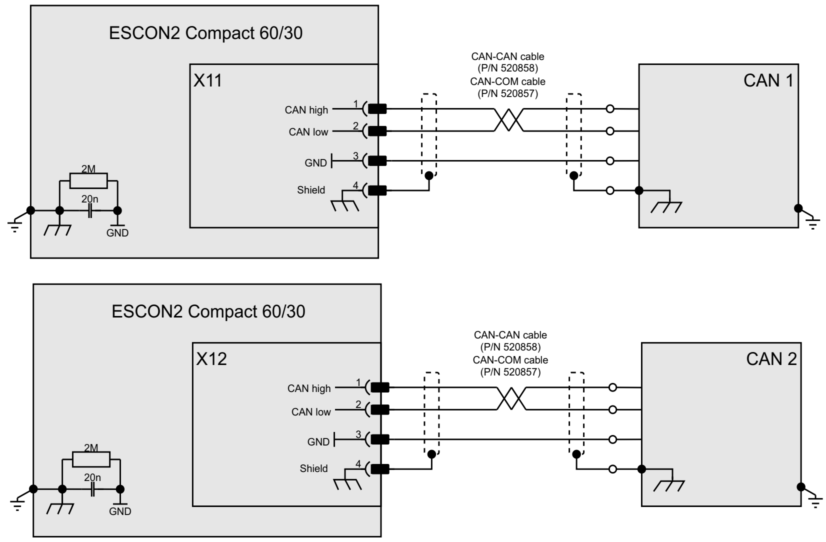


Figure 4-49 CAN

Depending on the preferred interface, one of the two prefab CAN cables can be used.

4.3.10 USB

4.3.10.1 USB-C

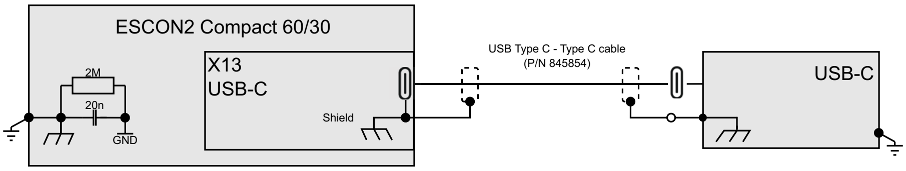


Figure 4-50 USB-C

4.3.10.2 USB-A

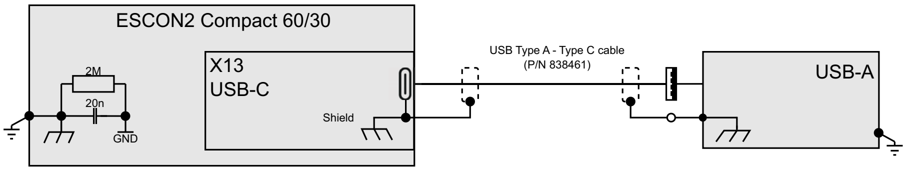


Figure 4-51 USB-A

4.3.11 Motor temperature sensor (future release)

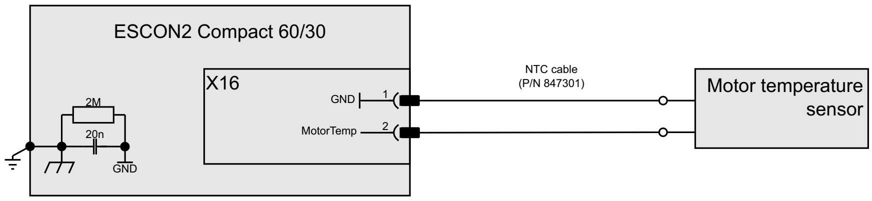


Figure 4-52 Motor temperature sensor

LIST OF FIGURES

LIST OF TABLES

INDEX

maxon

••page intentionally left blank••

CCMC | ESCON2 Compact 60/30 Hardware Reference | Edition 2024-12 | DocID rel12453