

iPOS360X MX -CAN/ -CAT

Intelligent Servo Drive for
Step, DC, Brushless DC and
AC Motors



T E C H N O S O F T

Intelligent Servo Drives



Technical Reference

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Read This First

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About This Manual

This book is a technical reference manual for:

Product Name	Part Number	Firmware	Description
iPOS3602 MX-CAN	P028.001.E101	F509x	Standard version, CAN
iPOS3602 MX-CAN	P028.001.E101	F524x	Linear Hall version, CAN
iPOS3604 MX-CAN	P028.002.E101	F508x	Standard version, CAN
iPOS3604 MX-CAN	P028.002.E101	F524x	Linear Hall version, CAN
iPOS3602 MX-CAT	P028.001.E121	F508x	Standard version, CAN
iPOS3602 MX-CAT	P028.001.E121	F523x	Linear Hall version, CAN
iPOS3604 MX-CAT	P028.002.E121	F508x	Standard version, CAN
iPOS3604 MX-CAT	P028.002.E121	F523x	Linear Hall version, CAN

In order to operate the **iPOS360X** drives, you need to pass through 3 steps:

- ☐ **Step 1 Hardware installation**
- ☐ **Step 2 Drive setup** using Technosoft **EasySetUp** software for drive commissioning
- ☐ **Step 3 Motion programming** using one of the options:
 - ☐ A **CANopen master**¹ or an **EtherCAT**² master
 - ☐ The drives **built-in motion controller** executing a Technosoft Motion Language (**TML**) program developed using Technosoft **EasyMotion Studio** software
 - ☐ A **TML_LIB motion library for PCs** (Windows or Linux)³
 - ☐ A **TML_LIB motion library for PLCs**³
 - ☐ A **distributed control** approach which combines the above options, like for example a host calling motion functions programmed on the drives in TML

This manual covers **Step 1** in detail. It describes the **iPOS360X** hardware including the technical data, the connectors and the wiring diagrams needed for installation.

For Step 2 and 3, please consult the document **iPOS Single Loop drives Software reference**

(**091.028.SL.Software.xxxx**). It also includes the scaling factors between the real SI units and the drive internal units. For detailed information regarding the next steps, refer to the related documentation.

Notational Conventions

This document uses the following conventions:

- **iPOS360X** – all products described in this manual
- **IU units** – Internal units of the drive
- **SI units** – International standard units (meter for length, seconds for time, etc.)
- **STO** – Safe Torque Off
- **TML** – Technosoft Motion Language
- **CANopen** – Standard communication protocol that uses 11-bit message identifiers over CAN-bus
- **TMLCAN** – Technosoft communication protocol for exchanging TML commands via CAN-bus, using 29bit message identifiers
- **CoE** – CAN application protocol over EtherCAT®

¹ when the iPOS360x MX-CAN is set in CANopen mode

² available only for CAT versions

³ available only for CAN versions

iPOS3602 MX-CAN Datasheet (P028.001.E101.DSH)

– describes the hardware connections of the iPOS3602 MX CAN intelligent servo drive including the technical data and connectors.

iPOS3604 MX-CAN Datasheet (P028.002.E101.DSH)

– describes the hardware connections of the iPOS3604 MX CAN intelligent servo drive including the technical data and connectors.

iPOS3602 MX-CAT Datasheet (P028.001.E121.DSH)

– describes the hardware connections of the iPOS3602 MX CAT intelligent servo drive including the technical data and connectors.

iPOS3604 MX-CAT Datasheet (P028.002.E121.DSH)

– describes the hardware connections of the iPOS3604 MX CAT intelligent servo drive including the technical data and connectors.

ECAT–VX EtherCAT Interface Datasheet (P038.022.E022.DSH)

– describes the hardware connections of the ECAT–VX EtherCAT Interface including the technical data and connectors.

EasyMotion Studio – Quick Setup and Programming Guide (P091.034.ESM-Quick.Setup.and.Programming.Guide.UM.xxxx) – describes the compatible software installation, drive software setup commissioning, introduction to TML motion programming and motion evaluation tools.

Help of the EasySetUp software – describes how to use **EasySetUp** to quickly setup any Technosoft drive for your application using only 2 dialogues. The output of EasySetUp is a set of setup data that can be downloaded into the drive EEPROM or saved on a PC file. At power-on, the drive is initialized with the setup data read from its EEPROM. With EasySetUp it is also possible to retrieve the complete setup information from a drive previously programmed. **EasySetUp can be downloaded free of charge from Technosoft web page**

iPOS CANopen Programming (part no. P091.063.iPOS.UM.xxxx) – explains how to program the iPOS family of intelligent drives using **CANopen** protocol and describes the associated object dictionary for **CiA 301 v.4.2** application layer and communication profile and **CiA DSP 402_2 v4.1** device profile for drives and motion control now included in IEC 61800-7-1 Annex A, IEC 61800-7-201 and IEC 61800-7-301 standards

61800-7-1 Annex A, IEC 61800-7-201 and IEC 61800-7-301 standards

CoE Programming (part no. P091.064.UM.xxxx) – explains how to program the Technosoft intelligent drives using **CAN application protocol over EtherCAT®** and describes the associated object dictionary.

Motion Programming using EasyMotion Studio (part no. P091.034.ESM.UM.xxxx) – describes how to use the EasyMotion Studio to create motion programs using in Technosoft Motion Language (TML). EasyMotion Studio platform includes **EasySetUp** for the drive/motor setup, and a **Motion Wizard** for the motion programming. The Motion Wizard provides a simple, graphical way of creating motion programs and automatically generates all the TML instructions. *With EasyMotion Studio you can fully benefit from a key advantage of Technosoft drives – their capability to execute complex motions without requiring an external motion controller, thanks to their built-in motion controller.* **A demo version of EasyMotion Studio (with EasySetUp part fully functional) can be downloaded free of charge from the Technosoft web page**

TML_LIB v2.0 (part no. P091.040.v20.UM.xxxx) – explains how to program in **C, C++, C#, Visual Basic or Delphi Pascal** a motion application for the Technosoft intelligent drives using TML_LIB v2.0 motion control library for PCs. The TML_lib includes ready-to-run examples that can be executed on **Windows** or **Linux** (x86 and x64).

TML_LIB_LabVIEW v2.0 (part no. P091.040.LABVIEW.v20.UM.xxxx) – explains how to program in **LabVIEW** a motion application for the Technosoft intelligent drives using TML_LIB_Labview v2.0 motion control library for PCs. The TML_Lib_LabVIEW includes over 40 ready-to-run examples.

TML_LIB_S7 (part no. P091.040.S7.UM.xxxx) – explains how to program in a PLC **Siemens series S7-300 or S7-400** a motion application for the Technosoft intelligent drives using TML_LIB_S7 motion control library. The TML_LIB_S7 library is **IEC61131-3 compatible**.

TML_LIB_CJ1 (part no. P091.040.CJ1.UM.xxxx) – explains how to program in a PLC **Omron series CJ1** a motion application for the Technosoft intelligent drives using TML_LIB_CJ1 motion control library for PLCs. The TML_LIB_CJ1 library is **IEC61131-3 compatible**.

TML_LIB_X20 (part no. P091.040.X20.UM.xxxx) – explains how to program in a PLC **B&R series X20** a motion application for the Technosoft intelligent drives using TML_LIB_X20 motion control library for PLCs. The TML_LIB_X20 library is **IEC61131-3 compatible**.

TechnoCAN (part no. P091.063.TechnoCAN.UM.xxxx) – presents TechnoCAN protocol – an extension of the CANopen communication profile used for TML commands

IO-iPOS360X (part no. P091.028.IO-iPOS360X.UM.xxxx) – describes the IO iPOS360x I/O extension board included in the **iPOS360X Starter Kits**.

If you Need Assistance ...

If you want to ...	Contact Technosoft at ...
Visit Technosoft online	World Wide Web: http://www.technosoftmotion.com/
Receive general information or assistance (see Note)	World Wide Web: http://www.technosoftmotion.com/ Email: sales@technosoftmotion.com
Ask questions about product operation or report suspected problems (see Note)	Tel: +41 (0)32 732 5500 Email: support@technosoftmotion.com
Make suggestions about, or report errors in documentation.	Mail: Technosoft SA Avenue des Alpes 20 CH-2000 Neuchatel, NE Switzerland

1 Safety information

Read carefully the information presented in this chapter before carrying out the drive installation and setup! It is imperative to implement the safety instructions listed hereunder.

This information is intended to protect you, the drive and the accompanying equipment during the product operation. Incorrect handling of the drive can lead to personal injury or material damage.

The following safety symbols are used in this manual:



WARNING! *SIGNALS A DANGER TO THE OPERATOR WHICH MIGHT CAUSE BODILY INJURY. MAY INCLUDE INSTRUCTIONS TO PREVENT THIS SITUATION*



CAUTION! *SIGNALS A DANGER FOR THE DRIVE WHICH MIGHT DAMAGE THE PRODUCT OR OTHER EQUIPMENT. MAY INCLUDE INSTRUCTIONS TO AVOID THIS SITUATION*



CAUTION! *Indicates areas SENSITIVE TO electrostatic discharges (ESD) WHICH REQUIRE HANDLING IN AN ESD PROTECTED ENVIRONMENT*

1.1 Warnings



WARNING! *THE VOLTAGE USED IN THE DRIVE MIGHT CAUSE ELECTRICAL SHOCKS. DO NOT TOUCH LIVE PARTS WHILE THE POWER SUPPLIES ARE ON*



WARNING! *TO AVOID ELECTRIC ARCING AND HAZARDS, NEVER CONNECT / DISCONNECT WIRES FROM THE DRIVE WHILE THE POWER SUPPLIES ARE ON*



WARNING! *THE DRIVE MAY HAVE HOT SURFACES DURING OPERATION.*



WARNING! *DURING DRIVE OPERATION, THE CONTROLLED MOTOR WILL MOVE. KEEP AWAY FROM ALL MOVING PARTS TO AVOID INJURY*

1.2 Cautions



CAUTION! *THE POWER SUPPLIES CONNECTED TO THE DRIVE MUST COMPLY WITH THE PARAMETERS SPECIFIED IN THIS DOCUMENT*



CAUTION! *TROUBLESHOOTING AND SERVICING ARE PERMITTED ONLY FOR PERSONNEL AUTHORISED BY TECHNOSOFT*



CAUTION! *THE DRIVE CONTAINS ELECTROSTATICALLY SENSITIVE COMPONENTS WHICH MAY BE DAMAGED BY INCORRECT HANDLING. THEREFORE THE DRIVE SHALL BE REMOVED FROM ITS ORIGINAL PACKAGE ONLY IN AN ESD PROTECTED ENVIRONMENT*

To prevent electrostatic damage, avoid contact with insulating materials, such as synthetic fabrics or plastic surfaces. In order to discharge static electricity build-up, place the drive on a grounded conductive surface and also ground yourself.

1.3 Quality system, conformance and certifications



IQNet and Quality Austria certification about the implementation and maintenance of the Quality Management System which fulfills the requirements of Standard **ISO 9001:2015**. **Quality Austria Certificate** about the application and further development of an effective Quality Management System complying with the requirements of Standard **ISO 9001:2015**

REACH Compliance - **TECHNOSOFT** hereby confirms that this product comply with the legal obligations regarding Article 33 of the European REACH Regulation 1907/2006 (Registration, Evaluation, Authorization and Restriction of Chemicals), which came into force on 01.06.2007.

RoHS Compliance - **Technosoft SA** here with declares that this product is manufactured in compliance with the RoHS directive 2002/95/EC on the restriction of the use of certain hazardous substances in electrical and electronic equipment (RoHS)

Technosoft SA hereby declares that this product conforms to the following European applicable directives:

2014/30/EU Electromagnetic Compatibility (EMC) Directive
2014/35/EU Low Voltage Directive (LVD)
93/68/EEC CE Marking Directive

Conflict minerals statement - **Technosoft** declares that the company does not purchase 3T&G (tin, tantalum, tungsten & gold) directly from mines or smelters...

We have no indication that Technosoft products contain minerals from conflict mines or smelters in and around the DRC.

For other certifications visit: <https://technosoftmotion.com/en/quality/>

2 Product Overview

2.1 Introduction

The **iPOS360X** is a family of fully digital intelligent servo drives, based on the latest DSP technology and they offer unprecedented drive performance combined with an embedded motion controller.

Suitable for control of brushless DC, brushless AC (vector control), DC brushed motors and step motors, the iPOS360X drives accept as position feedback quadrature incremental encoders and digital Hall signals.

All drives perform position, speed or torque control and work in single, multi-axis or stand-alone configurations. Thanks to the embedded motion controller, the iPOS360X drives combine controller, drive and PLC functionality in a single compact unit and are capable to execute complex motions without requiring intervention of an external motion controller. Using the high-level Technosoft Motion Language (**TML**) the following operations can be executed directly at drive level:

- ☐ Setting various motion modes (profiles, PVT, PT, electronic gearing¹ or camming¹, etc.)
- ☐ Changing the motion modes and/or the motion parameters
- ☐ Executing homing sequences
- ☐ Controlling the program flow through:
 - Conditional jumps and calls of TML functions
 - TML interrupts generated on pre-defined or programmable conditions (protections triggered, transitions on limit switch or capture inputs, etc.)
 - Waits for programmed events to occur
- ☐ Handling of digital I/O and analogue input signals
- ☐ Executing arithmetic and logic operations
- ☐ Performing data transfers between axes
- ☐ Controlling motion of an axis from another one via motion commands sent between axes²
- ☐ Sending commands to a group of axes (multicast). This includes the possibility to start simultaneously motion sequences on all the axes from the group²
- ☐ Synchronizing all the axis in a network

By implementing motion sequences directly at drive level you can really distribute the intelligence between the master and the drives in complex multi-axis applications, reducing both the development time and the overall communication requirements. For example, instead of trying to command each movement of an axis, you can program the drives using TML to execute complex motion tasks and inform the master when these tasks are done. Thus, for each axis control the master job may be reduced at: calling TML functions stored in the drive EEPROM and waiting for a message, which confirms the TML functions execution completion.

All iPOS360X CAN drives are equipped with a serial RS232 and a CAN 2.0B interface that can be set by hardware pins to operate in 2 communication protocol modes:

- ☐ **CANopen**
- ☐ **TMLCAN**

When **CANopen** mode is selected, the iPOS360X conforms to **CiA 301 v4.2** application layer communication profile and **CiA DSP 402_2 v4.1** device profile for drives and motion control, now included in IEC 61800-7-1 Annex A, IEC 61800-7-201 and IEC 61800-7-301 standards. In this mode, the iPOS360X may be controlled via a CANopen master. The iPOS drive offers the possibility for a CANopen master to call motion sequences/ functions, written in TML and stored in the drive EEPROM, using manufacturer specific objects. Also, the drives can communicate separately between each other by using non reserved 11 bit identifiers.

When **TMLCAN** mode is selected, the iPOS360X behaves as standard Technosoft intelligent drive and conforms to Technosoft protocol for exchanging TML commands via CAN-bus. When TMLCAN protocol is used, it is not mandatory to have a master. Any iPOS360X can be set to operate standalone, and may play the role of a master to coordinate both the network communication/synchronization and the motion application via TML commands sent directly to the other drives.

When higher level coordination is needed, apart from a CANopen master, the iPOS360X drives can also be controlled via a PC or a PLC using one of the **TML_LIB** motion libraries.

For iPOS360X commissioning **EasySetup** or **EasyMotion Studio** PC applications may be used.

¹ Available if the master axis sends its position via a communication channel, or by using the secondary encoder input

² Available only for CAN drives

EasySetUp is a subset of EasyMotion Studio, including only the drive setup part. The output of EasySetUp is a set of setup data that can be downloaded into the drive EEPROM or saved on a PC file. At power-on, the drive is initialized with the setup data read from its EEPROM. With EasySetUp it is also possible to retrieve the complete setup information from a drive previously programmed. EasySetUp shall be used for drive setup in all cases where the motion commands are sent exclusively from a master. Hence neither the iPOS360X TML programming capability nor the drive camming mode are used. **EasySetUp can be downloaded free of charge from Technosoft web page.**

EasyMotion Studio platform includes EasySetUp for the drive setup, and a **Motion Wizard** for the motion programming. The Motion Wizard provides a simple, graphical way of creating motion programs and automatically generates all the TML instructions. *With EasyMotion Studio you can execute complex motions, thanks to their built-in motion controllers.* EasyMotion Studio, may be used to program motion sequences in TML. This is the iPOS360X typical CAN operation mode when TMLCAN protocol is selected. EasyMotion Studio can also be used with the CANopen protocol, if the user wants to call TML functions stored in the drive EEPROM or to use the camming mode. With camming mode, EasyMotion Studio offers the possibility to quickly download and test a cam profile and also to create a .sw file with the cam data. The .sw file can be afterwards stored in a master and downloaded to the drive, wherever needed. **A demo version of EasyMotion Studio (with EasySetUp part fully functional) can be downloaded free of charge from Technosoft web page.**

2.2 Product Features

- Fully digital servo drive suitable for the control of rotary or linear brushless, DC brush, and step motors
- Very compact design
- Standard PCIe 4x mating connector
- Sinusoidal (FOC) or trapezoidal (Hall-based) control of brushless motors
- Open or closed-loop control of 2 and 3-phase steppers
- Various modes of operation, including: torque, speed or position control; position or speed profiles, Cyclic Synchronous Position (CSP) for CANopen mode, external reference mode (analogue or encoder feedback) or sent via a communication bus
- Technosoft Motion Language (TML) instruction set for the definition and execution of motion sequences
- Standalone operation with stored motion sequences
- Motor supply: 9-36V
- Logic supply: 7-36V
- Output current:
 - iPOS3602 MX -CAN/ -CAT: 2A² continuous; 3.2A peak
 - iPOS3604 MX-- CAN/ -CAT: 4A³ continuous; 10A peak
- PWM switching frequency up to 120kHz
- Communication:
 - RS-232 serial up to 115kbits/s
 - CAN-bus 2.0B up to 1Mbit/s (for CAN drives)
- Digital and analog I/Os:
 - 5 digital inputs: 5-24 V, sourcing/NPN : 2 Limit switches, Enable and 2 general-purpose
 - 3 digital outputs : 5-36V, 0.5A, NPN open-collector: Ready, Error, 1 general-purpose
 - 2 analogue inputs: 12-bit, 0-5V (Reference, Feedback) or general-purpose
- Electro-Mechanical brake support: software configurable digital output to control motor brake
- Feedback devices:
 - Incremental encoder interface (single ended or differential)
 - Digital Hall sensor interface (single-ended and open collector)
 - Linear Hall sensor interface
 - Analogue Sin/Cos encoder interface (differential 1V_{pp})
- Various motion programming modes:
 - Position profiles with trapezoidal or S-curve speed shape
 - Position, Velocity, Time (PVT) 3rd order interpolation
 - Position, Time (PT) 1st order interpolation

² 2A cont. with DC, step and BLDC motors (trapezoidal), 2A amplitude (1.41A_{RMS}) for PMSM (sinusoidal)

³ 4A cont. with DC, step and BLDC motors (trapezoidal), 4A amplitude (2.82A_{RMS}) for PMSM (sinusoidal)

- Cyclic Synchronous Position (CSP) for CANopen mode.
- Electronic gearing and camming
- 35 Homing modes
- Software CAN selectable addresses
- Two CAN operation modes selectable by HW pin (only for CAN drives):
 - **CANopen** – conforming with **CiA 301 v4.2** and **CiA DSP 402_2 v4.1**
 - **TMLCAN** – intelligent drive conforming with Technosoft protocol for exchanging TML commands via CAN-bus
- EtherCAT® supported protocols for for CAT drives:
 - **CoE** - CAN application protocol over EtherCAT
 - **EoE** – Ethernet over EtherCAT – for Easy Motion studio communication over EtherCAT
- 2K × 16 internal SRAM memory for data acquisition
- 4K × 16 E²ROM to store TML motion programs, cam tables and other user data
- Operating ambient temperature:
 - 0-70°C – iPOS360X MX -CAN/ -CAT
- Protections:
 - Short-circuit between motor phases
 - Short-circuit from motor phases to ground
 - Over-voltage
 - Under-voltage
 - Over-current
 - Communication error
 - Control error
 - Over-temperature
- Firmware on drive:
 - F509M+ or F524E+ for iPSO3602 MX-CAN
 - F508M+ or F523E+ for iPSO3604 MX-CAN
 - F511M+ for iPSO3602 MX-CAT
 - F511M+ for iPSO3604 MX-CAT

2.3 Identification Labels

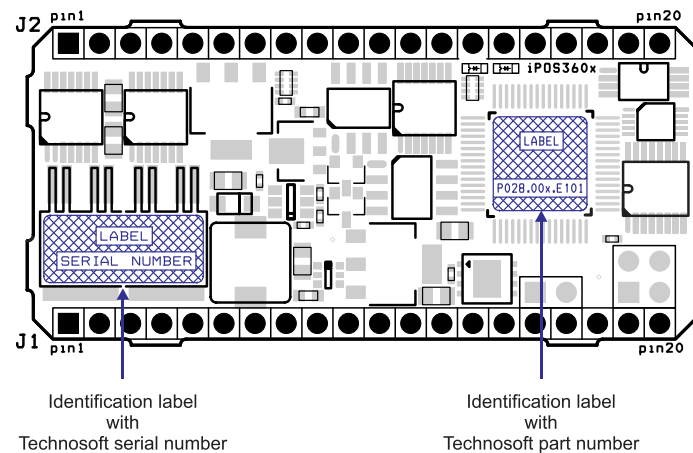


Figure 2.3.1. iPOS360X MX identification labels

The iPOS360X MX can has the following part number and name on the identification label:

Product Name	Part Number	Firmware	Description
iPOS3602 MX-CAN	P028.001.E101	F509x	Standard version, CAN
iPOS3602 MX-CAN	P028.001.E101	F524x	Linear Hall version, CAN
iPOS3604 MX-CAN	P028.002.E101	F508x	Standard version, CAN
iPOS3604 MX-CAN	P028.002.E101	F524x	Linear Hall version, CAN
iPOS3602 MX-CAT	P028.001.E121	F511x	Standard version, EtherCAT
iPOS3604 MX-CAT	P028.002.E121	F511x	Standard version, EtherCAT

2.4 Supported Motor-Sensor Configurations

The position and/or speed are controlled using one feedback sensor.

Sensor type \ Motor	Brushless PMSM	Brushless BLDC	DC Brush	Stepper 2 phase	Stepper 3 phase
Incr. encoder	Yes	-	Yes	Yes	-
Incr. encoder + Digital Hall	Yes	Yes	-	-	-
Sin-Cos encoder	Yes	-	-	-	-
Digital halls only	Yes	-	-	-	-
Linear Halls	Yes	-	-	-	-
Tacho	-	-	Yes	-	-
Open-loop (no sensor)	-	-	-	Yes	Yes
Open-loop (with step loss detection using incr. Encoder)	-	-	-	Yes	Yes
Open-loop with incr. encoder on load	-	-	-	Yes	Yes

2.5 iPOS360X I/O Evaluation board

A circuit board is available for evaluating the iPOS3602 or 3604 MX. It comes with multiple types of connectors for easy access to the iPOS360x features.



Figure 2.5.1. iPOS360X MX-CAN mounted on the I/O iPOS360X extension board

2.5.1 Starter Kit ordering information

Part number	Description
P091.084.IO-iPOS360x.UM.xxxx	Evaluation board User Manual (available for download on our website)
P028.002.E881	I/O board for iPOS360x MX (includes MX2VX adapter) – no drive
P028.600.E101	iPOS360x MX2VX adapter
P038.022.E022	ECAT-VX EtherCAT Interface
P028.001.E803	iPOS3602 MX-CAN Starter kit without motor (I/O, MX2VX adapter, drive)
P028.001.E804	iPOS3602 MX-CAN Starter kit with brushless motor
P028.001.E805	iPOS3602 MX-CAN Starter kit with stepper motor
P028.002.E803	iPOS3604 MX-CAN Starter kit without motor (I/O, MX2VX adapter, drive)
P028.002.E804	iPOS3604 MX-CAN Starter kit with brushless motor
P028.002.E805	iPOS3604 MX-CAN Starter kit with stepper motor

3 Hardware Installation

3.1 iPOS360X MX -CAN/ -CAT Board Dimensions

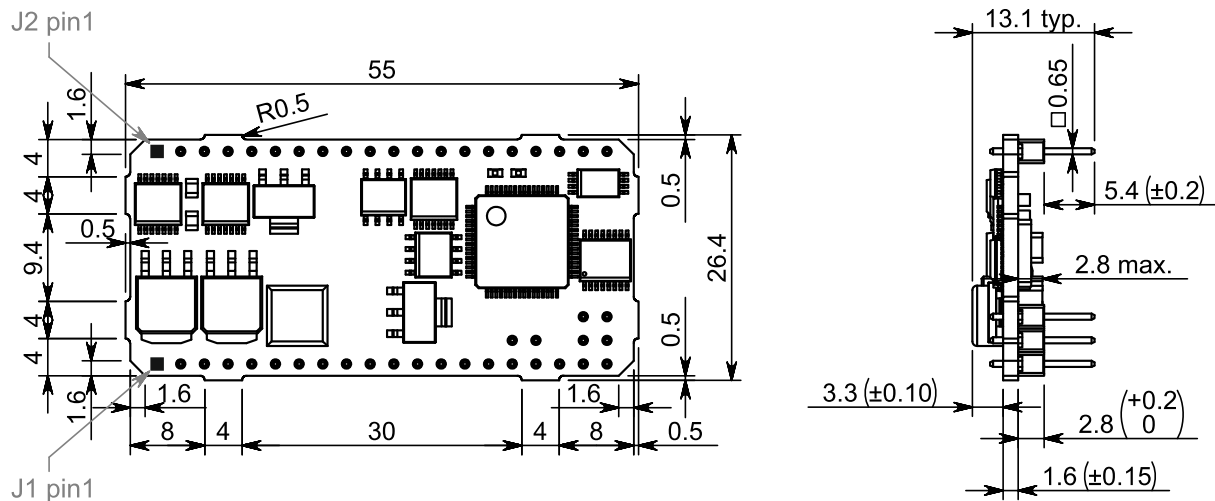


Figure 3.1.1. iPOS360X MX -CAN / -CAT drive dimensions

All dimensions are in mm. The drawings are not to scale.

Remark: The six pins located at the end of J1 are not installed in the standard configuration of the iPOS360x MX-CAN drive. These specific pins are designated for customized purposes and CAT versions of the drive. Their placement is illustrated in Fig. 3.1. When using the drive in its standard CAN configuration, there is no requirement to include these holes on the motherboard.

3.2 Mechanical Mounting

The iPOS360X drive is intended to be mounted horizontally on a motherboard equipped with the recommended mating connectors, as specified in chapter [0](#)

J1

Name	Type	Description	Pin
B / A-	O	Phase B for 3-ph motors, A- for 2-ph steppers, Motor- for DC brush motors	1-2
CR / B-	O	Chopping resistor / Phase B- for step motors	3-4
+V _{MOT}	I	Positive terminal of the motor supply: 9 to 36V _{DC}	5-6
+V _{LOG}	I	Positive terminal of the logic supply: 7 to 36V _{DC}	7
OUT3 / Ready	O	5-36V 0.5A drive ready output, active low, NPN open-collector/TTL pull-up. Also drives the green LED.	8
OUT2 / Error	O	5-36V 0.5A drive error output, active low, NPN open-collector/TTL pull-up. Also drives the red LED	9
Hall 1	I	Digital input Hall 1 sensor	10
Hall 2	I	Digital input Hall 2 sensor	11
Hall 3	I	Digital input Hall 3 sensor	12
OUT0	O	5-36V 0.5A general-purpose digital output, NPN open-collector / TTL pull-up	13
REF	I	Analogue input, 12-bit, 0-5V. Used to read an analog position, speed or torque reference, or used as general-purpose analogue input	14
Z / Z+	I	Incr. encoder Z (index) single-ended, or Z+ diff. input	15
Z- / LH3	I	Incr. encoder Z- differential input, or linear Hall 3 input	16
A / A+ / Sin+	I	Incr. encoder A single-ended, or A+ diff. input, or analogue encoder Sin+ diff. input	17
A- / Sin- / LH1	I	Incr. encoder A- diff. input, or analogue encoder Sin- diff. input, or linear Hall 1 input	18
B / B+ / Cos+	I	Incr. encoder B single-ended, or B+ diff. input, or analogue encoder Cos+ diff. input	19
B- / Cos- / LH2	I	Incr. encoder B- diff. input, or analogue encoder Cos- diff. input, or linear Hall 2 input	20

J4

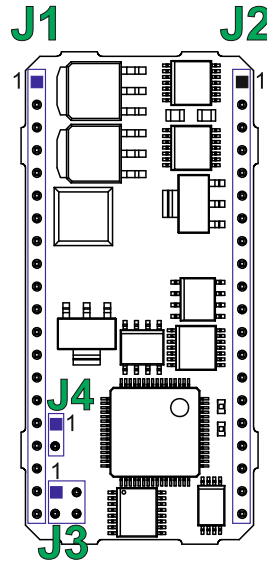
Pin	Name	Description
1	OUT1	5-36V 0.5A general-purpose digital output, NPN open-collector / TTL pull-up
2	Reserved	Reserved. Do not connect.

J2

Pin	Name	Type	Description
1-2	A / A+	O	Phase A for 3-ph motors, A+ for 2-ph steppers, Motor+ for DC brush motors
3-4	C / B+	O	Phase C for 3-ph motors, B+ for 2-ph steppers
5-6	GND	-	Negative return (ground) of the motor supply
7	IN0	I	5-36V digital input General-purpose
8	IN1	I	5-36V digital input
9	IN2 / LSP	I	5-36V digital input Positive limit switch input
10	IN3 / LSN	I	5-36V digital input Negative limit switch input
11	IN4 / Enable	I	5-36V digital input Drive enable input
12	GND	-	Return ground
13	+5V _{OUT}	O	5V output supply
14	Sync	I	3.3V digital input; for ECAT interface board
15	ECAT Ready	I	3.3V digital input; for ECAT interface board
16	Interrupt	I	3.3V digital input; for ECAT interface board
17	Reserved	I/O	Reserved. Do not connect.
18	Reserved	I/O	Reserved. Do not connect.
19	232TX	O	RS-232 Data Transmission
20	232RX	I	RS-232 Data Reception

J3

Pin	Name	Description
1	Data In	3.3V digital output; for ECAT interface board
2	Chip Select	3.3V digital output; for ECAT interface board
3	Data Out	3.3V digital input; for ECAT interface board
4	Clock	3.3V digital output; for ECAT interface board



To enable the EtherCAT communication functionality, the connections between the EtherCAT signals, specifically J2 pins 14, 15, 16, and J3 pins 1, 2, 3, 4, to P038.022.E0 - ECAT-VX EtherCAT Interface must be done according to the guidelines provided in the iPOS360x MX-CAT connection diagram.

Mating Connectors. Several drives can be hosted by a single motherboard.

For thermal calculations, the iPOS3604 MX-CAN drive can be assumed to generate 1 Watt (= 3.4 BTU/hour) at idle, and up to 3 Watt (= 10 BTU/hour) worst case while driving a motor.

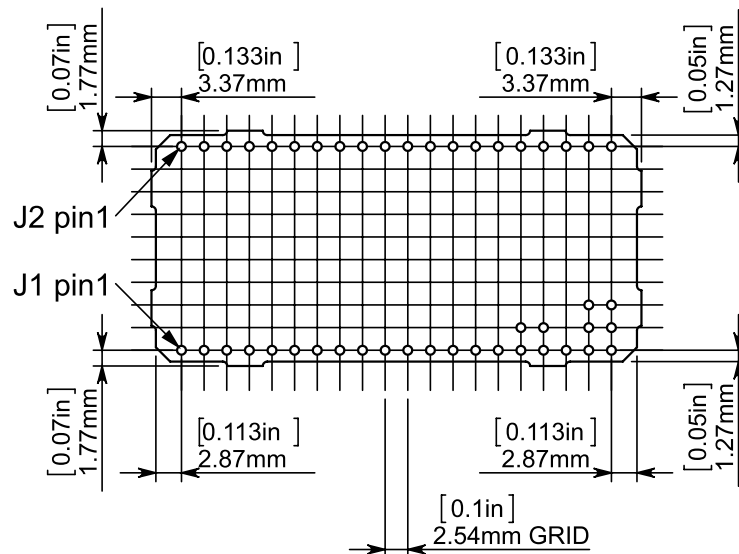


Figure 3.2.1. iPOS360X MX – CAN/ -CAT PCB Footprint

Remark: The six pins located at the end of J1 are not installed in the standard configuration of the iPOS360x MX-CAN drive. These specific pins are designated for customized purposes and CAT versions of the drive. Their placement is illustrated in Fig. 3.1. When using the drive in its standard CAN configuration, there is no requirement to include these holes on the motherboard.

3.3 Motherboard PCB Design

It is recommended to use a multi-layer PCB for the motherboard, in order to have enough room for routing all 40 pins of the iPOS360x. Using a 2-layer PCB is possible when some of the iPOS360x pins remain un-connected.

Below is a list of recommendations for the PCB design of the motherboard:

- Motor supply and motor outputs: use islands / areas of copper to escape connector area; this will maximize current capability. When using simple tracks, use at least 100mil cross section (75mil track width for 1oz/ft² copper thickness) – for iPOS3604. Halve these values for the iPOS3602.
- Motor supply and ground return tracks between iPOS360X and the nearby V_{MOT} decoupling capacitor are to be considered as EMI sources, and kept to a minimum length.
- Place the decoupling capacitors on V_{MOT} and V_{LOG} (see also 3.6.8 Power Supply Connection) as close as physically possible to the iPOS360X, to minimize EM radiated emissions. For un-shielded applications (no metallic box) and typical EMC regulations, the spacing between iPOS360X and capacitors must be less than 3 centimeters.
- In multi-axis applications (multiple iPOS360X drives on the same motherboard), it is preferable to have a separate decoupling capacitor for each drive's V_{MOT} . For V_{LOG} it is acceptable to share one decoupling capacitor for two drives.
- For stringent EMI requirements, it may be necessary to add common-mode filtering on the motor and/or logic supply inputs. Be sure to use 3-phase EMC filters, not 2-phase filters, in order to fulfill the basic requirement of zero common-mode current through the filter. This is necessary because the ground negative return is shared between V_{MOT} and V_{LOG} .
- Motor outputs shall be routed with parallel traces, and minimizing the loop area between these tracks. Avoid placing components above or below the motor output tracks, as these components may become effective antennas radiating EMI. If possible, route all 4 motor outputs in strip-line configuration (above or below a ground plane).
- For stringent EMI requirements, it may be necessary to add common-mode inductors on the motor outputs. Place these filters near the iPOS360X, not near the external connector, to reduce radiation from the PCB tracks.
- Motor outputs must be separated from any nearby track (on the same layer) by a guard ring / track / area connected to ground. It is recommended to use the same guarding precaution also for tracks on nearby layers, i.e. use intermediate guard layer(s) connected to ground. The motor outputs must be treated as first source of noise on the motherboard. Second source of noise is the current flow between each iPOS360X and its decoupling V_{MOT} capacitor.
- For best EMC performance, it is strongly recommended to provide an un-interrupted ground plane on one of the inner layers.
- All GND pins of the iPOS360X are galvanically connected together on-board the iPOS360X. If the motherboard provides an uninterrupted ground plane, it is recommended to connect all GND pins to the ground plane, and use the ground plane to distribute GND wherever needed. If the motherboard does not provide an uninterrupted ground plane, it is best to distribute GND connections evenly across the 3 pins. This will create local "star point" ground connection on-board each iPOS360X. For a multi-axis motherboard with one common power supply for all motors, each motor power supply return track shall be routed separately for each iPOS360X, and star-point connected at the power supply terminal.
- The following signal pairs must be routed differentially, i.e. using parallel tracks with minimal loop area: A1+, A1-; B1+, B1-; Z1+, Z1-; CAN-Hi, CAN-Lo.
- CAN-Bus tracks must be routed with a bus topology, without branches / bifurcations, in a daisy-chain fashion. The bus ends must be at the termination resistor(s) and/or external connectors.
- When using +5V_{OUT} as supply for external devices (like encoders, Hall sensors, etc.) provide extra filtering and protection: use series resettable (PTC) fuses to add short-circuit protection; use transient absorbers to protect against ESD and over-voltage; add high-frequency filtering to protect against external noise injected on +5V_{OUT}.
- The outer box / case / cabinet must be connected to the motherboard ground either galvanically (directly) or through high-frequency decoupling capacitors, rated at an appropriate voltage.



CAUTION!

WHEN THE iPOS360X IS SET IN TMLCAN MODE, IT STARTS TO EXECUTE AUTOMATICALLY AT POWER ON THE TML APPLICATION FROM ITS EEPROM. ADD ON THE MOTHERBOARD THE POSSIBILITY TO DISABLE THIS FEATURE AS SHOWN PAR. 3.6.11. THIS MIGHT BE NEEDED DURING DEVELOPMENT PHASE IN CASE THE EEPROM CONTENT IS ACCIDENTALLY CORRUPTED.



CAUTION!

THE iPOS360X IS AN ELECTROSTATICALLY SENSITIVE DEVICE, WHICH WILL BE DAMAGED BY INCORRECT HANDLING. THEREFORE THE DRIVE SHALL BE REMOVED FROM ITS ORIGINAL PACKAGE ONLY IN AN ESD PROTECTED ENVIRONMENT!

3.4 EMC recommendations

The drive is compliant to the requirements of the following European directives, when installed as described in this User Manual:

- 93/68/EEC CE Marking Directive
- 2014/30/EU Electromagnetic Compatibility (EMC) Directive
- EN 61800-3:2012 Adjustable speed electrical power drive systems, Part3: EMC
- product standard

The drive shall be installed as shown in the Figure below, in order to meet the above EMC requirements:

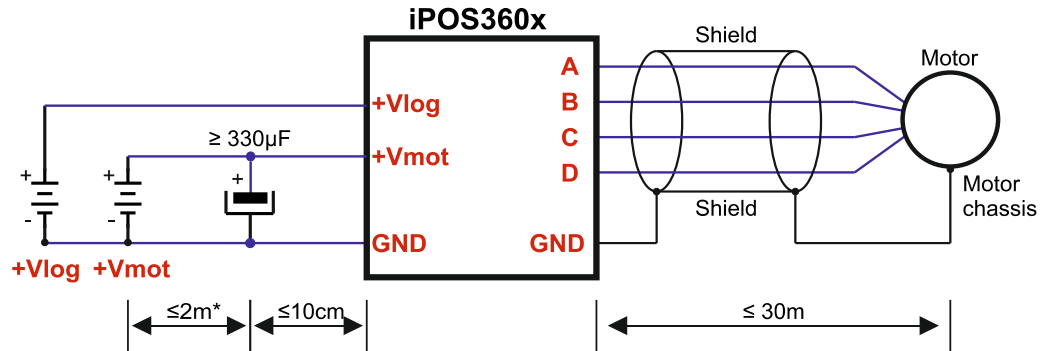


Figure 3.2 EMC recommended connections

* if +Vmot to capacitor wire length $\geq 2m$, use twisted wires for the supply and ground return (Vmot and GND)

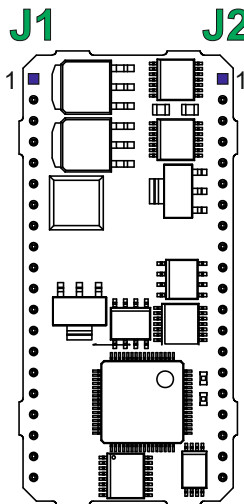
* if +Vmot to capacitor wire length $\geq 20m$, the capacitor value must be $\geq 2200 \mu F$.

3.5 Connectors and Pinouts

3.5.1 Pinouts for iPOS360X MX-CAN

J1

Name	Type	Description	Pin
B / A-	O	Phase B for 3-ph motors, A- for 2-ph steppers, Motor- for DC brush motors	1-2
CR / B-	O	Chopping resistor / Phase B- for step motors	3-4
+V _{MOT}	I	Positive terminal of the motor supply: 9 to 36V _{DC}	5-6
+V _{LOG}	I	Positive terminal of the logic supply: 7 to 36V _{DC}	7
OUT3 / Ready	O	5-36V 0.5A drive ready output, active low, NPN open-collector/TTL pull-up. Also drives the green LED.	8
OUT2 / Error	O	5-36V 0.5A drive error output, active low, NPN open-collector/TTL pull-up. Also drives the red LED	9
Hall 1	I	Digital input Hall 1 sensor	10
Hall 2	I	Digital input Hall 2 sensor	11
Hall 3	I	Digital input Hall 3 sensor	12
OUT0	O	5-36V 0.5A general-purpose digital output, NPN open-collector / TTL pull-up	13
REF	I	Analogue input, 12-bit, 0-5V. Used to read an analog position, speed or torque reference, or used as general-purpose analogue input	14
Z / Z+	I	Incr. encoder Z (index) single-ended, or Z+ diff. input	15
Z- / LH3	I	Incr. encoder Z- differential input, or linear Hall 3 input	16
A / A+ / Sin+	I	Incr. encoder A single-ended, or A+ diff. input, or analogue encoder Sin+ diff. input	17
A- / Sin- / LH1	I	Incr. encoder A- diff. input, or analogue encoder Sin- diff. input, or linear Hall 1 input	18
B / B+ / Cos+	I	Incr. encoder B single-ended, or B+ diff. input, or analogue encoder Cos+ diff. input	19
B- / Cos- / LH2	I	Incr. encoder B- diff. input, or analogue encoder Cos- diff. input, or linear Hall 2 input	20



J2

Pin	Name	Type	Description
1-2	A / A+	O	Phase A for 3-ph motors, A+ for 2-ph steppers, Motor+ for DC brush motors
3-4	C / B+	O	Phase C for 3-ph motors, B+ for 2-ph steppers
5-6	GND	-	Negative return (ground) of the motor supply
7	IN0	I	5-36V digital input General-purpose
8	IN1	I	5-36V digital input
9	IN2 / LSP	I	5-36V digital input Positive limit switch input
10	IN3 / LSN	I	5-36V digital input Negative limit switch input
11	IN4 / Enable	I	5-36V digital input Drive enable input
12	GND	-	Return ground
13	+5V _{OUT}	O	5V output supply
14	AxisID 2	I	Axis ID/Address input. 7 states: floating, strap to GND or +5V, resistor 4K7 or 22K to GND or +5V
15	AxisID 1	I	Axis ID/Address input. 7 states: floating, strap to GND or +5V, resistor 4K7 or 22K to GND or +5V
16	AxisID 0	I	Axis ID/Address input. 7 states: floating, strap to GND or +5V, resistor 4K7 or 22K to GND or +5V
17	Can-Lo	I/O	CAN-Bus negative line (dominant low)
18	Can-Hi	I/O	CAN-Bus positive line (dominant high)
19	232TX	O	RS-232 Data Transmission
20	232RX	I	RS-232 Data Reception

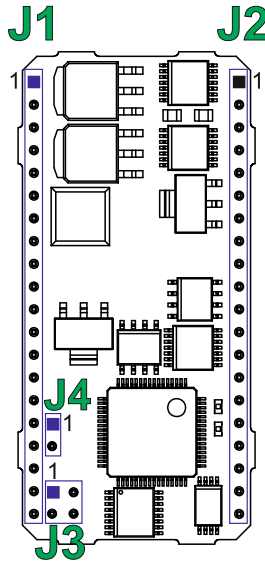
3.5.2 Pinouts for iPOS360X MX-CAT

J1

Name	Type	Description	Pin
B / A-	O	Phase B for 3-ph motors, A- for 2-ph steppers, Motor- for DC brush motors	1-2
CR / B-	O	Chopping resistor / Phase B- for step motors	3-4
+VMOT	I	Positive terminal of the motor supply: 9 to 36V _{DC}	5-6
+VLOG	I	Positive terminal of the logic supply: 7 to 36V _{DC}	7
OUT3 / Ready	O	5-36V 0.5A drive ready output, active low, NPN open-collector/TTL pull-up. Also drives the green LED.	8
OUT2 / Error	O	5-36V 0.5A drive error output, active low, NPN open-collector/TTL pull-up. Also drives the red LED	9
Hall 1	I	Digital input Hall 1 sensor	10
Hall 2	I	Digital input Hall 2 sensor	11
Hall 3	I	Digital input Hall 3 sensor	12
OUT0	O	5-36V 0.5A general-purpose digital output, NPN open-collector / TTL pull-up	13
REF	I	Analogue input, 12-bit, 0-5V. Used to read an analog position, speed or torque reference, or used as general-purpose analogue input	14
Z / Z+	I	Incr. encoder Z (index) single-ended, or Z+ diff. input	15
Z- / LH3	I	Incr. encoder Z- differential input, or linear Hall 3 input	16
A / A+ / Sin+	I	Incr. encoder A single-ended, or A+ diff. input, or analogue encoder Sin+ diff. input	17
A- / Sin- / LH1	I	Incr. encoder A- diff. input, or analogue encoder Sin- diff. input, or linear Hall 1 input	18
B / B+ / Cos+	I	Incr. encoder B single-ended, or B+ diff. input, or analogue encoder Cos+ diff. input	19
B- / Cos- / LH2	I	Incr. encoder B- diff. input, or analogue encoder Cos- diff. input, or linear Hall 2 input	20

J4

Pin	Name	Description
1	OUT1	5-36V 0.5A general-purpose digital output, NPN open-collector / TTL pull-up
2	Reserved	Reserved. Do not connect.



J2


Pin	Name	Type	Description
1-2	A / A+	O	Phase A for 3-ph motors, A+ for 2-ph steppers, Motor+ for DC brush motors
3-4	C / B+	O	Phase C for 3-ph motors, B+ for 2-ph steppers
5-6	GND	-	Negative return (ground) of the motor supply
7	IN0	I	5-36V digital input General-purpose
8	IN1	I	5-36V digital input
9	IN2 / LSP	I	5-36V digital input Positive limit switch input
10	IN3 / LSN	I	5-36V digital input Negative limit switch input
11	IN4 / Enable	I	5-36V digital input Drive enable input
12	GND	-	Return ground
13	+5V _{OUT}	O	5V output supply
14	Sync	I	3.3V digital input; for ECAT interface board
15	ECAT Ready	I	3.3V digital input; for ECAT interface board
16	Interrupt	I	3.3V digital input; for ECAT interface board
17	Reserved	I/O	Reserved. Do not connect.
18	Reserved	I/O	Reserved. Do not connect.
19	232TX	O	RS-232 Data Transmission
20	232RX	I	RS-232 Data Reception

J3

Pin	Name	Description
1	Data In	3.3V digital output; for ECAT interface board
2	Chip Select	3.3V digital output; for ECAT interface board
3	Data Out	3.3V digital input; for ECAT interface board
4	Clock	3.3V digital output; for ECAT interface board

To enable the EtherCAT communication functionality, the connections between the EtherCAT signals, specifically J2 pins 14, 15, 16, and J3 pins 1, 2, 3, 4, to P038.022.E0 - ECAT-VX EtherCAT Interface must be done according to the guidelines provided in the iPOS360x MX-CAT connection diagram.

3.5.3 Mating Connectors for iPOS360X MX

Ref	Producer	Part Number		
J1, J2	Fischer Elektronik	On-board connector	Mating connector	
		SL 11 112 020 G	BL 5 20	
J1, J2, J3, J4*	Standard socket for square pin 0.635 x 0.635 mm; 2.54 mm pitch; 20 poles			
	*Available only for EtherCAT executions			

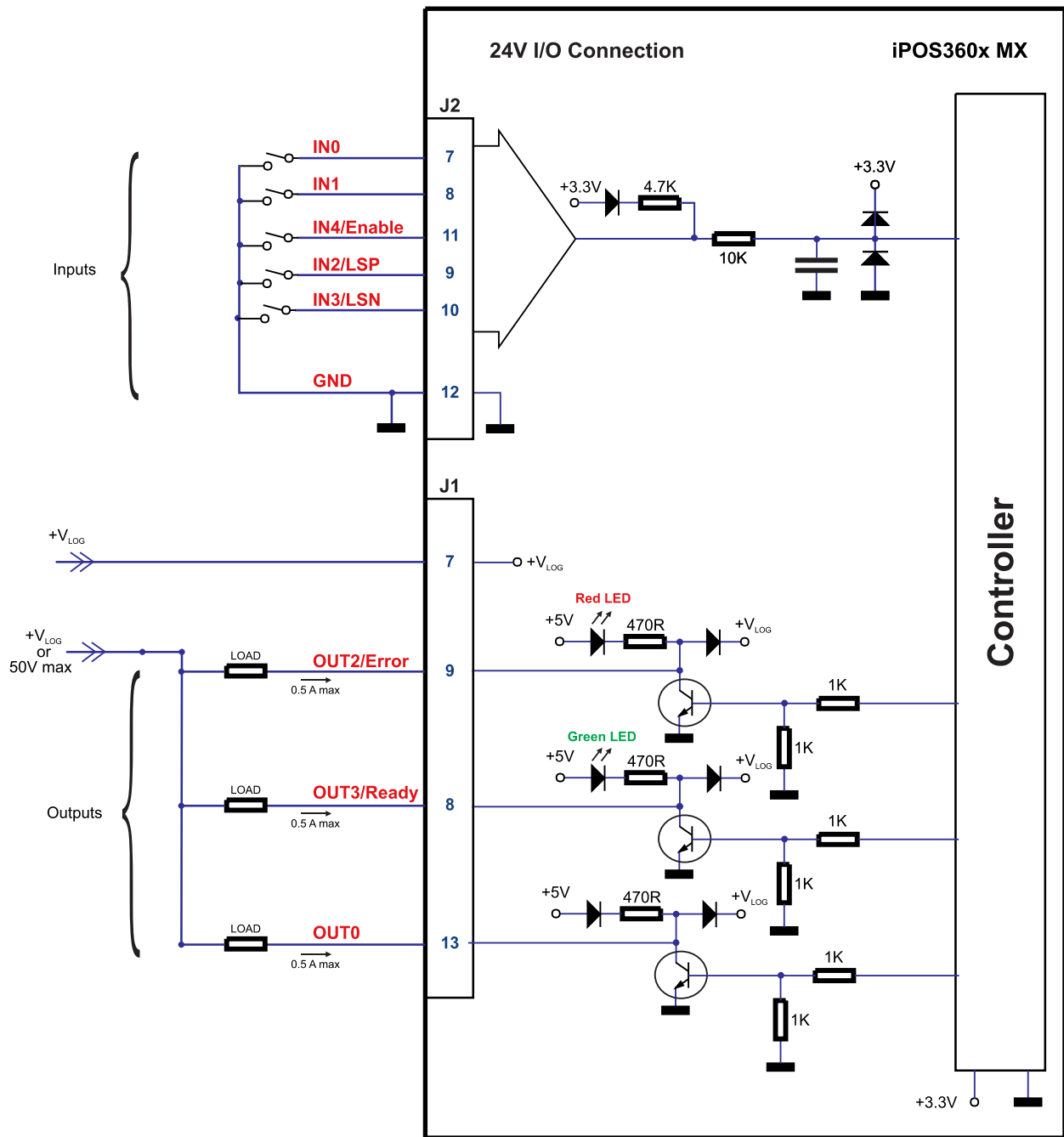


Figure 3.5. 24V Digital NPN Inputs connection

Remarks:

1. The inputs are compatible with NPN type outputs (input must be pulled to GND to change its default state)
2. The length of the cables must be up to 30m, reducing the exposure to voltage surges in industrial environment.
3. The outputs are compatible with NPN type inputs (load is tied to common +V_{LOG}, output pulls to GND when active and is floating when inactive)
4. The maximum sink current is 0.5A continuous, up to 1A pulsed for less than 5 seconds

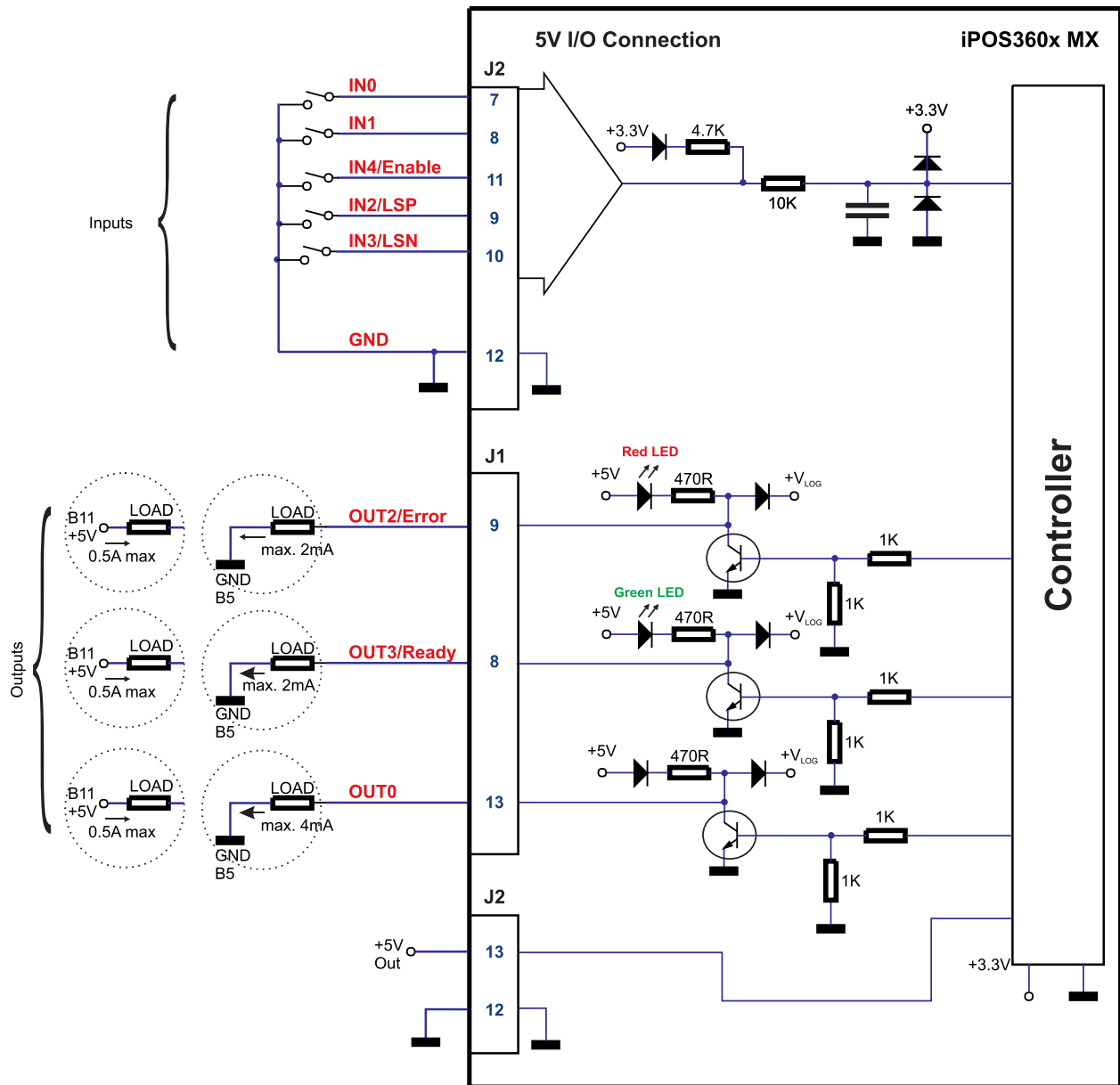


Figure 3.6. 5V Digital I/O connection

Remarks:

1. The inputs are compatible with TTL(5V), LVTTTL(3.3V), CMOS and open collector outputs
2. The outputs are compatible with TTL (5V) and CMOS (5V) inputs
3. The output loads can be individually and independently connected to +5V or to GND.
4. The length of the cables must be up to 30m, reducing the exposure to voltage surges in industrial environment.

3.6.5 Analog Inputs Connection

3.6.5.1 0-5V Input Range

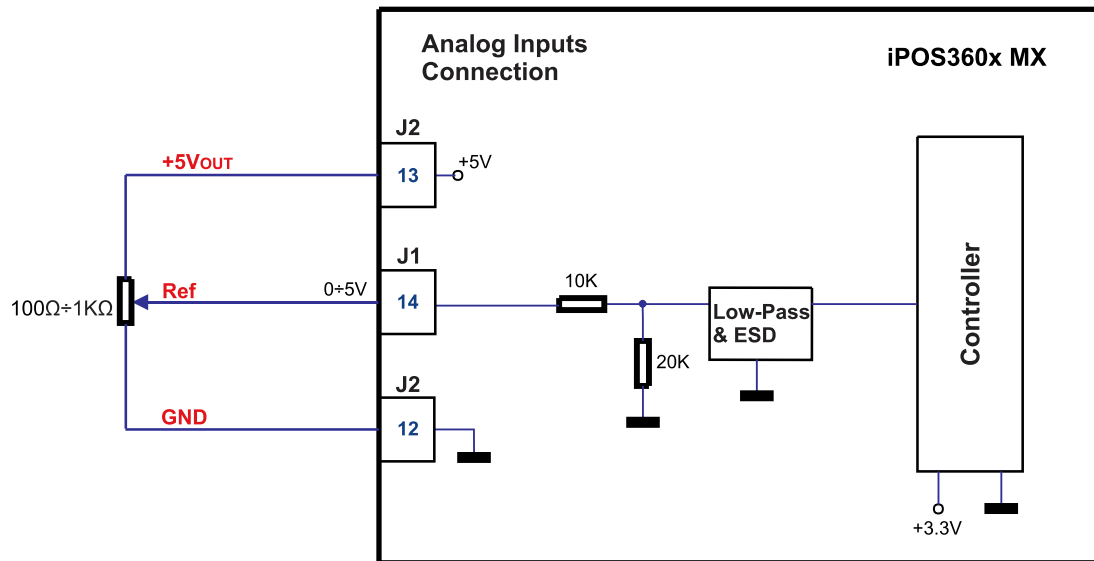


Figure 3.7. 0-5V Analog inputs connection

Remarks:

1. The length of the cables must be up to 30m, reducing the exposure to voltage surges in industrial environment.
2. Default input range for analog inputs is 0÷5 V for REF and FBDK. For a +/-10 V range, see [Figure 3.8](#).

3.6.5.2 +/-10V to 0-5V Input Range Adapter

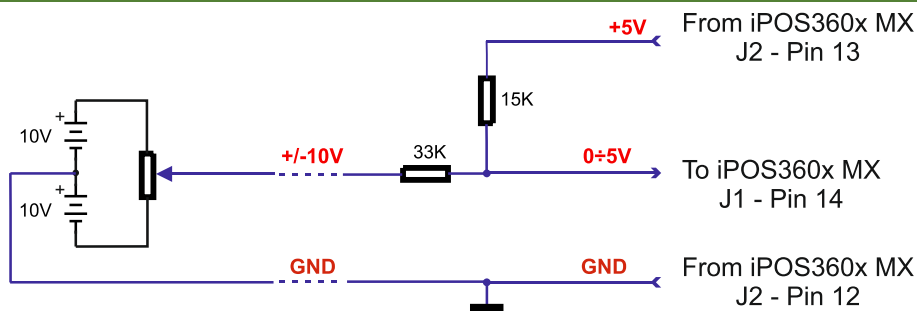


Figure 3.8. +/-10V to 0-5V adapter

Equivalent input impedance is 43Kohm. Floating input voltage is 3.3V. For best TML conversion, use the following parameters: RFOFSSET=0xC00 (3072); RFGAIN=0x8839 (34873) in your project file.

3.6.5.3 Recommendation for wiring

- a) If the analogue signal source is single-ended, use a 2-wire twisted shielded cable as follows: 1st wire connects the live signal to the drive input; 2nd wire connects the source ground to the drive ground; shield will be connected to the drive ground terminal.
- b) If the analogue signal source is differential and the signal source ground is isolated from the drive GND, use a 2-wire twisted shielded cable as follows: 1st wire connects the source plus (positive, in-phase) to the drive analogue input; 2nd wire connects the source minus (negative, out-of-phase) to the drive ground (GND). Shield is connected only at the drive side, to the drive GND, and is left unconnected at the source side.
- c) If the analogue signal source is differential and the signal source ground is common with the drive GND, use a 2-wire shielded cable as follows: 1st wire connects the source plus (positive, in-phase) to the drive analogue input; 2nd wire connects the source ground to the drive ground (GND); shield is connected only at the drive side, to the drive GND, and is left unconnected at the source side. The source minus (negative, out-of-phase) output remains unconnected.

3.6.6 Motor connections

3.6.6.1 Brushless Motor connection

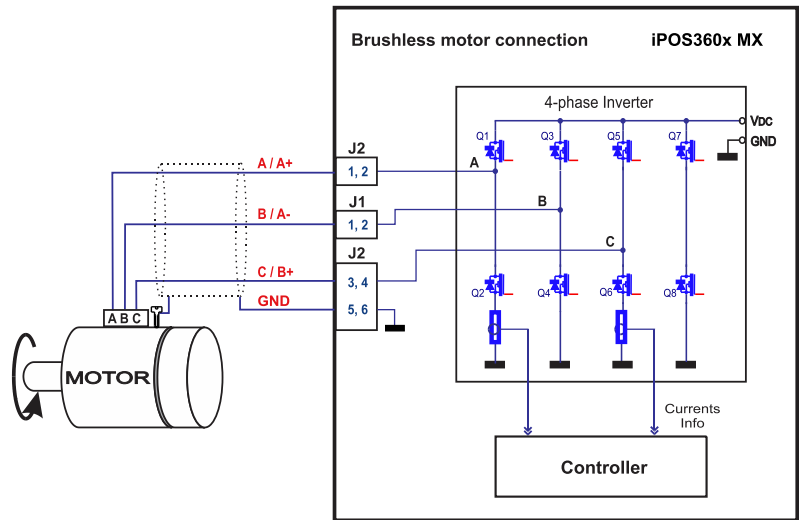


Figure 3.9. Brushless motor connection

3.6.6.2 2-phase Step Motor connection

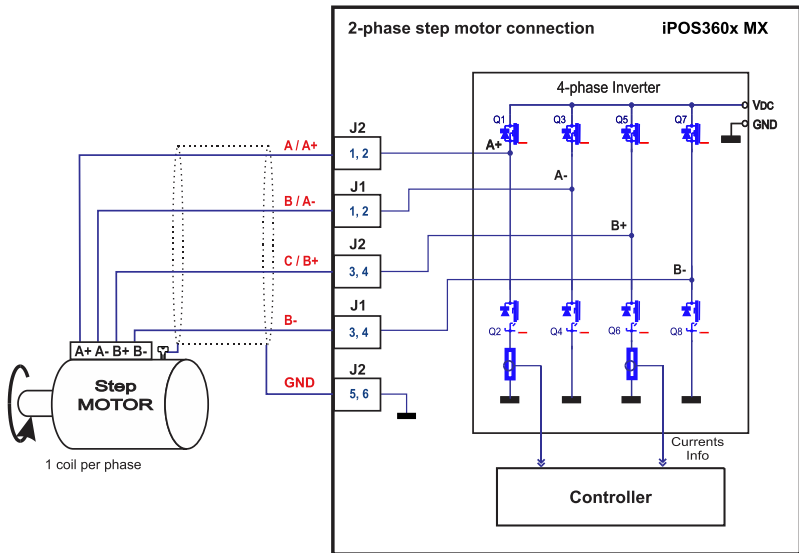


Figure 3.10. 2-phase step motor connection, one coil per phase

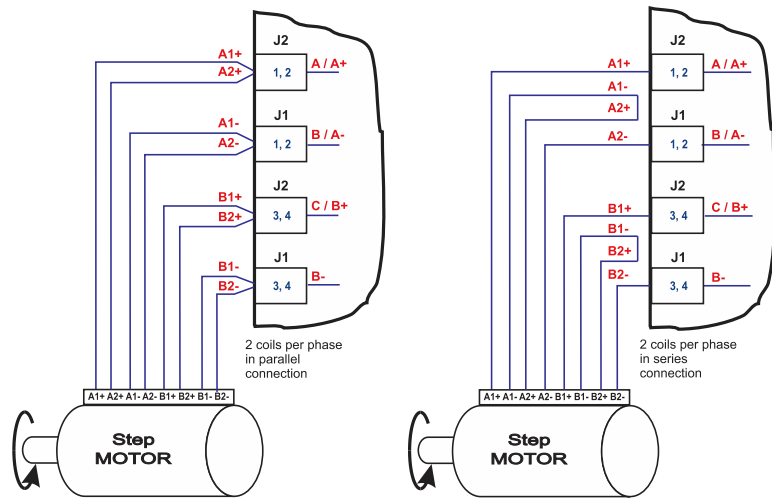


Figure 3.11. 2-phase step motor connection, two coils per phase

3.6.6.3 3-Phase Step Motor connection

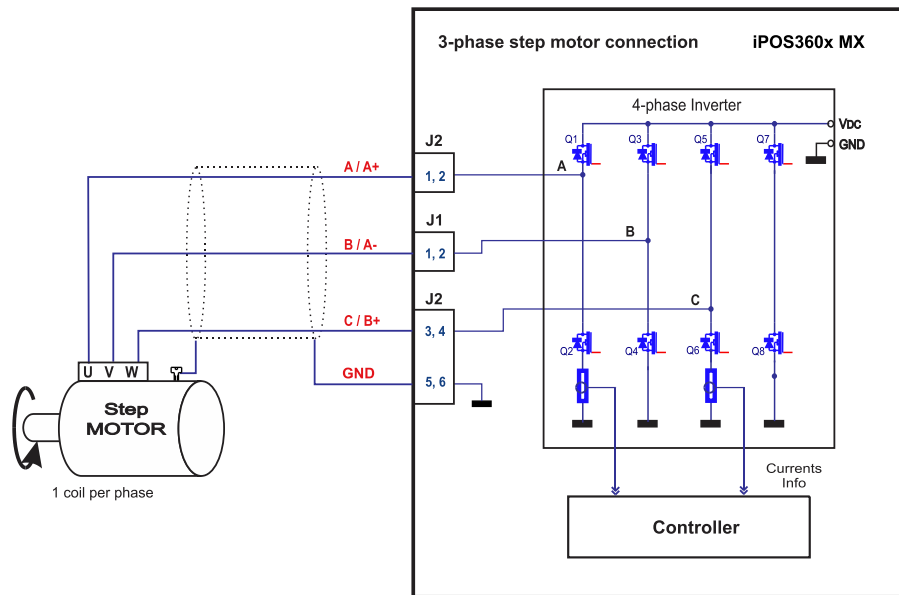


Figure 3.12. 3-phase step motor connection

3.6.6.4 DC Motor connection

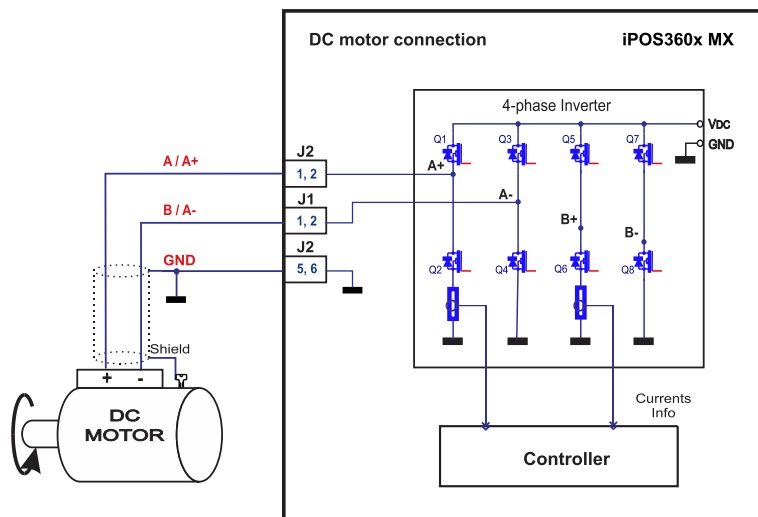


Figure 3.13. DC Motor connection

3.6.6.5 Recommendations for motor wiring

- Avoid running the motor wires in parallel with other wires for a distance longer than 2 meters. If this situation cannot be avoided, use a shielded cable for the motor wires. Connect the cable shield to the iPOS360X GND pin. Leave the other end disconnected.
- The parasitic capacitance between the motor wires must not bypass 10nF. If very long cables (tens of meters) are used, this condition may not be met. In this case, add series inductors between the iPOS360X outputs and the cable. The inductors must be magnetically shielded (toroidal, for example), and must be rated for the motor surge current. Typically the necessary values are around 100 μ H.
- A good shielding can be obtained if the motor wires are running inside a metallic cable guide.

3.6.7 Feedback connections

3.6.7.1 Single-ended Incremental Encoder Connection

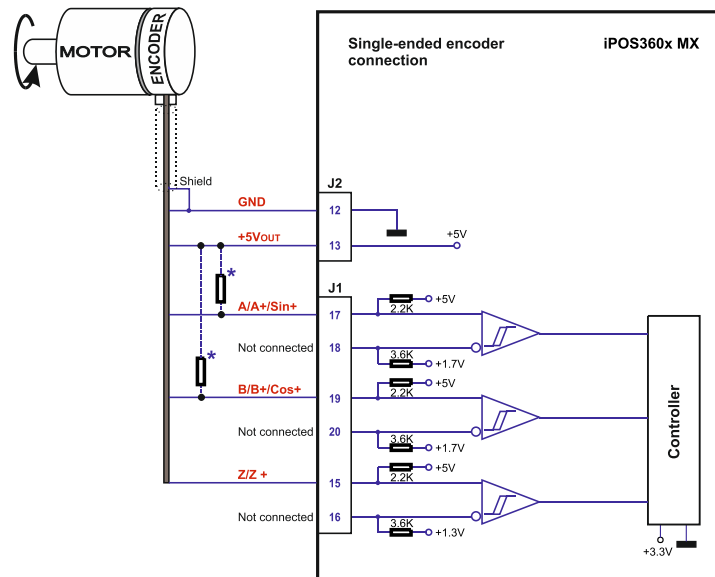


Figure 3.14. Single-ended incremental encoder connection

- * Optional resistors: value should match the current capability of the actual encoder outputs (please also consider the on-board existing 2K2). Lower resistance increases EMC immunity and robustness against electrical noise. Too low resistance can damage the encoder, and alter the logic-low voltage level.



CAUTION!

DO NOT CONNECT UNTERMINATED WIRES. THEY MIGHT PICK UP UNWANTED NOISE AND GIVE FALSE ENCODER READINGS.

3.6.7.2 Differential Incremental Encoder Connection

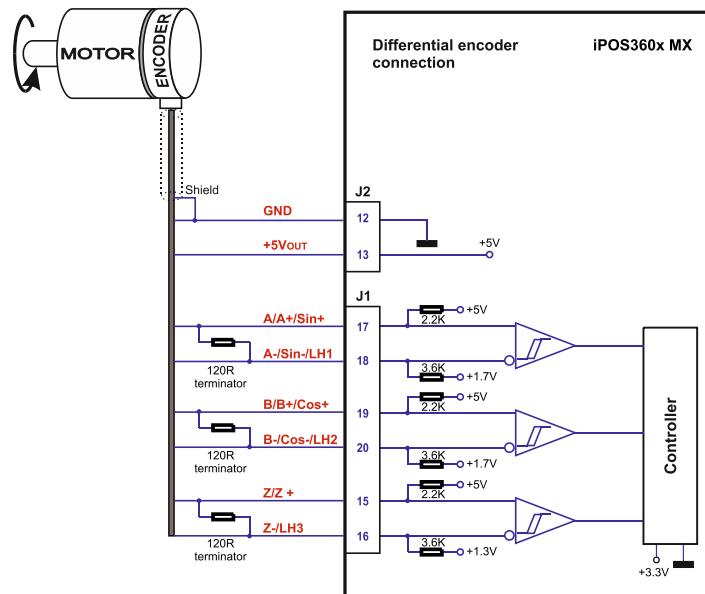


Figure 3.15. Differential incremental encoder connection

Remarks:

1. For the encoder differential connection, external 120Ω (0.25W) terminators are required for long encoder cables, or noisy environments.
2. The length of the cables must be up to 30m, reducing the exposure to voltage surges in industrial environment.

3.6.7.3 Digital Hall Connection for Motor + Hall + Incremental Encoder

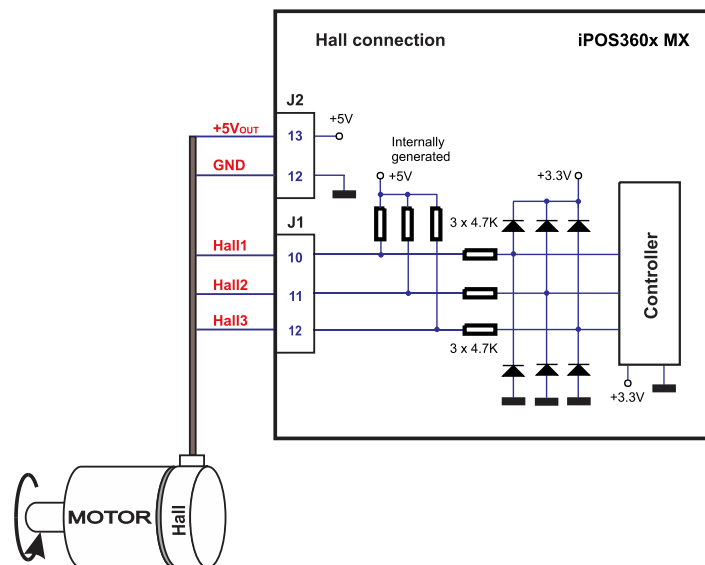


Figure 3.16. Digital Hall connection

Remarks:

1. This connection is required when using Hall start method BLDC or PMSM and also for the Trapezoidal commutation method. The digital halls are not used in this case as a feedback measurement device. The actual motor control is done with an incremental encoder.
2. The length of the cables must be up to 30m, reducing the exposure to voltage surges in industrial environment.

3.6.7.4 Digital Hall Connection for direct motor control without an encoder

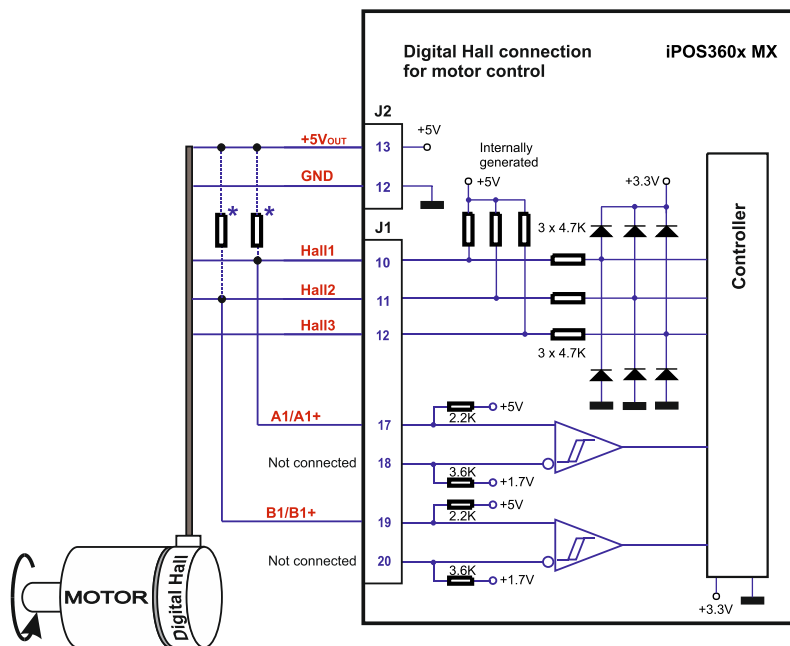


Figure 3.17. Digital Hall connection

- * Optional resistors: value should match the current capability of the actual encoder outputs (please also consider the on-board existing 2K2 and 4K7). Lower resistance increases EMC immunity and robustness against electrical noise. Too low resistance can damage the encoder, and alter the logic-low voltage level.

Remarks:

1. This connection is required when using only Digital hall signals as the main feedback device for motor control. In this case, no incremental encoder is needed.
2. Do not connect unterminated wires. They might pick up unwanted noise and give false encoder readings.
3. The length of the cables must be up to 30m, reducing the exposure to voltage surges in industrial environment.

3.6.7.5 Linear Hall Connection

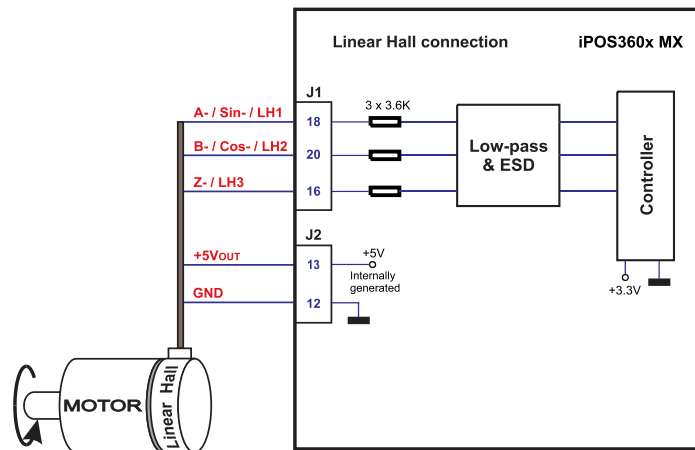


Figure 3.18. Digital Hall connection

3.6.7.6 Sin-Cosine Analog Encoder Connection

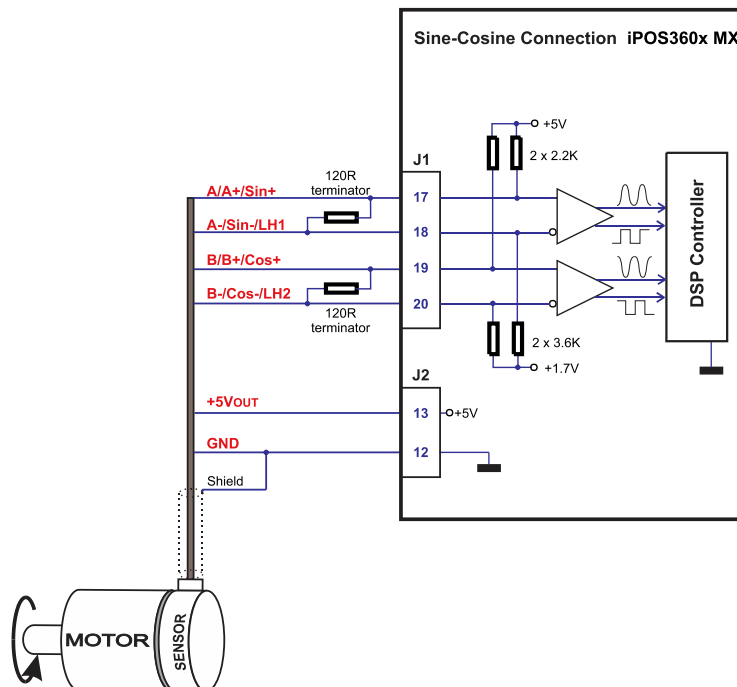


Figure 3.19. Digital Hall connection

3.6.7.7 Recommendations for wiring

- Always connect both positive and negative signals when the position sensor is differential and provides them. Use one twisted pair for each differential group of signals as follows: A+/Sin+ with A-/Sin-/LH1, B+/Cos+ with B-/Cos-/LH2, Z+ with Z-/LH3. Use another twisted pair for the 5V supply and GND.
- Always use shielded cables to avoid capacitive-coupled noise when using single-ended encoders or Hall sensors with cable lengths over 1 meter. Connect the cable shield to the GND, at only one end. This point could be either the iPOS360x (using the GND pin) or the encoder / motor. Do not connect the shield at both ends.
- If the iPOS360x 5V supply output is used by another device (like for example an encoder) and the connection cable is longer than 5 meters, add a decoupling capacitor near the supplied device, between the +5V and GND lines. The capacitor value can be 1...10 μF , rated at 6.3V

3.6.8 Power Supply Connection

3.6.8.1 Supply Connection

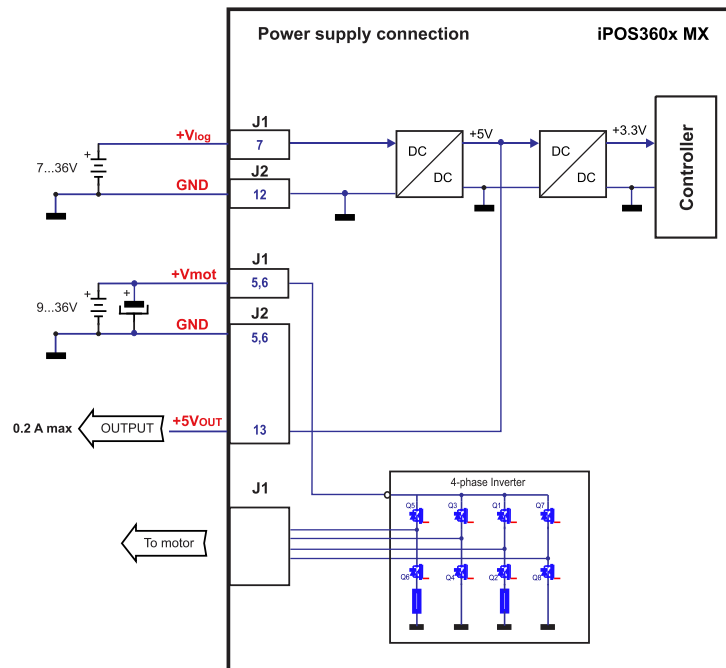


Figure 3.20. Supply connection



CAUTION!

The logic power supply requires a minimum rising slew-rate of 75V/s in order to correctly sample the operation mode and AxisID settings. The drive starts to operate from 4.9V and samples correctly the AD circuit from 7V.

3.6.8.2 Recommendations for Supply Wiring

Always provide a nearby capacitor on the motor supply lines. The capacitor should be located within 10cm of the iPOS360x edge connector, max. 20cm. The minimum recommended capacitance is 330μF for iPOS3604, or 220μF for iPOS3602, always rated at the appropriate voltage.

Use short, thick wires between the iPOS360x and the motor power supply. Connect power supply wires to all the indicated pins. If the wires are longer than 2 meters, use twisted wires for the supply and ground return. For wires longer than 20 meters, add a capacitor of at least 2,200μF (rated at an appropriate voltage) right on the terminals of the iPOS3604, respectively 1,000μF for the iPOS3602.

3.6.8.3 Recommendations to limit over-voltage during energy regeneration

During abrupt motion decelerations or reversals the regenerative energy is injected into the motor power supply. This may cause an increase of the motor supply voltage (depending on the power supply characteristics). If the voltage gets higher than 39V, the drive over-voltage protection is triggered and the drive power stage is disabled. In order to avoid this situation you have 2 options:

Option 1. Add a capacitor on the motor supply big enough to absorb the overall energy flowing back to the supply. The capacitor must be rated to a voltage equal or bigger than the maximum expected over-voltage and can be sized with the formula:

$$C \geq \frac{2 \times E_M}{U_{MAX}^2 - U_{NOM}^2}$$

where:

U_{MAX} = 38V is the over-voltage protection limit

U_{NOM} is the nominal motor supply voltage

E_M = the overall energy flowing back to the supply in Joules. In case of a rotary motor and load, E_M can be computed with the formula:

$$E_M = \underbrace{\frac{1}{2}(J_M + J_L)\omega_M^2}_{\text{Kinetic energy}} + \underbrace{(m_M + m_L)g(h_{\text{initial}} - h_{\text{final}})}_{\text{Potential energy}} - \underbrace{3I_M^2 R_{Ph} t_d}_{\text{Copper losses}} - \underbrace{\frac{t_d \omega_M}{2} T_F}_{\text{Friction losses}}$$

where:

J_M – total rotor inertia [kgm²]

J_L – total load inertia as seen at motor shaft after transmission [kgm²]

ω_M – motor angular speed before deceleration [rad/s]

m_M – motor mass [kg] – when motor is moving in a non-horizontal plane

m_L – load mass [kg] – when load is moving in a non-horizontal plane

g – gravitational acceleration i.e. 9.8 [m/s²]

h_{initial} – initial system altitude [m]

h_{final} – final system altitude [m]

I_M – motor current during deceleration [A_{RMS}/phase]

R_{Ph} – motor phase resistance [Ω]

t_d – time to decelerate [s]

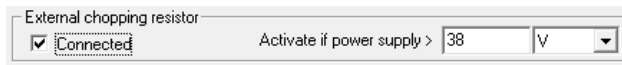
T_F – total friction torque as seen at motor shaft [Nm] – includes load and transmission

In case of a linear motor and load, the motor inertia J_M and the load inertia J_L will be replaced by the motor mass and the load mass measured in [kg], the angular speed ω_M will become linear speed measured in [m/s] and the friction torque T_F will become friction force measured in [N].

Option 2. Connect a chopping resistor R_{CR} between phase CR/B- and ground, and activate the software option of dynamic braking (see below).

This option is not available when the drive is used with a step motor.

The chopping resistor option can be found in the Drive Setup dialogue within EasyMotion / EasySetup.



The chopping will occur when DC bus voltage increases over U_{CHOP} . This parameter (U_{CHOP}) should be adjusted depending on the nominal motor supply. Optimally (from a braking point of view), U_{CHOP} should be a few volts above the maximum nominal supply voltage. This setting will activate the chopping resistor earlier, before reaching dangerous voltages – when the over-voltage protection will stop the drive. Of course, U_{CHOP} must always be less than U_{MAX} – the over-voltage protection threshold.

Remark: This option can be combined with an external capacitor whose value is not enough to absorb the entire regenerative energy E_M but can help reducing the chopping resistor size.

Chopping resistor selection

The chopping resistor value must be chosen to respect the following conditions:

1. to limit the maximum current below the drive peak current $I_{PEAK} = 3.2A$ for iPOS3602 and $I_{PEAK} = 10A$ for iPOS3604.

$$R_{CR} > \frac{U_{MAX}}{I_{PEAK}}$$

2. to sustain the required braking power:

$$P_{CR} = \frac{E_M - \frac{1}{2}C(U_{MAX}^2 - U_{CHOP}^2)}{t_d}$$

where C is the capacitance on the motor supply (external), i.e:

$$R_{CR} < \frac{U_{CHOP}^2}{2 \times P_{CR}}$$

3. to limit the average current below the drive nominal current $I_{NOM}=2A$ for iPOS3602 and $4A$ for iPOS3604

$$R_{CR} > \frac{P_{CR} \times t_d}{t_{CYCLE} \times I_{NOM}^2}$$

where t_{CYCLE} is the time interval between 2 voltage increase cycles in case of repetitive moves.

4. to be rated for an average power $P_{AV} = \frac{P_{CR} \times t_d}{t_{CYCLE}}$ and a peak power $P_{PEAK} = \frac{U_{MAX}^2}{R_{CR}}$

Remarks:

1. If $\frac{U_{MAX}}{I_{PEAK}} > \frac{U_{CHOP}^2}{2 \times P_{CR}}$ the braking power P_{CR} must be reduced by increasing either t_d – the time to decelerate or C – the external capacitor on the motor supply
2. If $\frac{P_{CR} \times t_d}{t_{CYCLE} \times I_{NOM}^2} > \frac{U_{CHOP}^2}{2 \times P_{CR}}$ either the braking power must be reduced (see Remark 1) or t_{CYCLE} – the time interval between braking cycles must be increased

	WARNING!	THE CHOPPING RESISTOR MAY HAVE HOT SURFACES DURING OPERATION.
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3.6.9 Serial RS-232 connection

3.6.9.1 Serial RS-232 connection

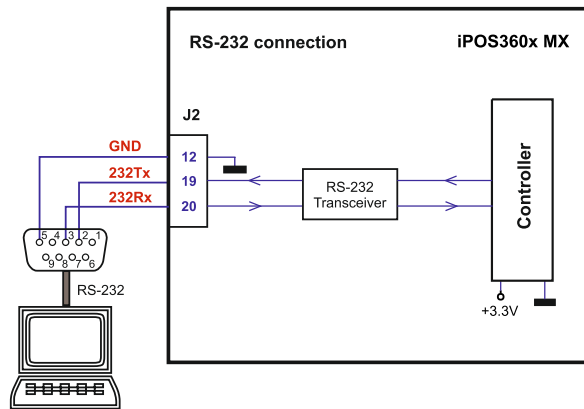


Figure 3.21. Serial RS-232 connection

3.6.9.2 Recommendation for wiring

- a) If you build the serial cable, you can use a 3-wire shielded cable with shield connected to BOTH ends. Do not use the shield as GND. The ground wire must be included inside the shield, like the 232Rx and 232Tx signals
- b) Always power-off all the iPOS360X supplies before inserting/removing the RS-232 serial connector
- c) Do not rely on an earthed PC to provide the iPOS360X GND connection! The drive must be earthed through a separate circuit. Most communication problems are caused by the lack of such connection

3.6.10 CAN-bus connection (for CAN drives only)

3.6.10.1 CAN connection

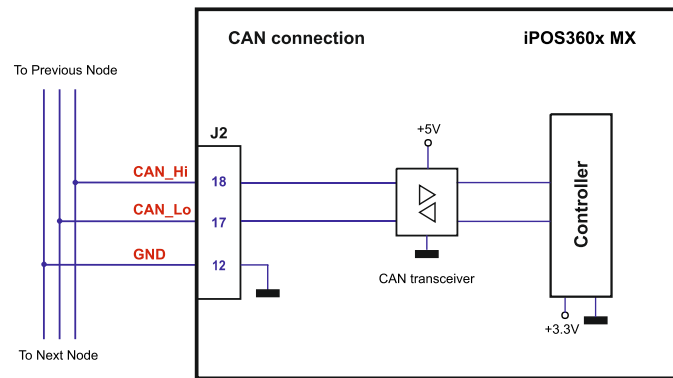


Figure 3.22. CAN connection

Remarks:

1. The CAN network requires a 120-Ohm terminator. This is not included on the board. Figure 3.23 shows how to connect it on your network
2. CAN signals can sustain up to +/-36V without damage.

3.6.10.2 Recommendation for wiring

- a) Build CAN network using cables with twisted wires (2 wires/pair), with CAN-Hi twisted together with CAN-Lo. It is recommended but not mandatory to use a shielded cable. If so, connect the shield to GND. The cable impedance must be 105 ... 135 ohms (120 ohms typical) and a capacitance below 30pF/meter.
- b) When using a printed circuit board (PCB) motherboard based on FR-4 material, build the CAN network using a pair of 12mil (0.012") tracks, spaced 8 to 10mils (0.008"...0.010") apart, placed over a local ground plane (microstrip) which extends at least 1mm left and right to the tracks.
- c) Whenever possible, use daisy-chain links between the CAN nodes. Avoid using stubs. A stub is a "T" connection, where a derivation is taken from the main bus. When stubs can't be avoided keep them as short as possible. For 1 Mbit/s (worst case), the maximum stub length must be below 0.3 meters.
- d) The 120Ω termination resistors must be rated at 0.2W minimum. Do not use winded resistors, which are inductive.

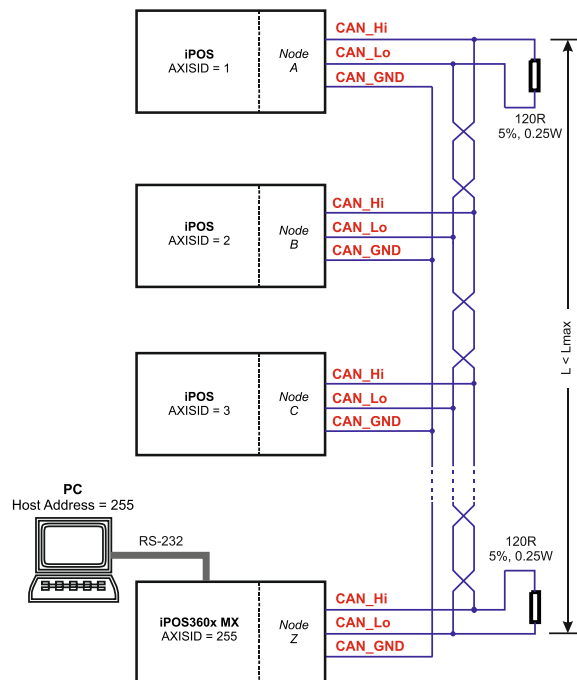


Figure 3.23. Multiple-Axis CAN network

3.6.11 Disable of Autorun Mode (for CAN) / Disable Setup (for CAT)

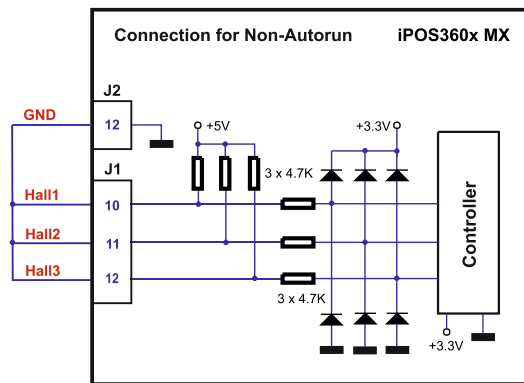


Figure 3.24. Temporary connection during power-on to disable the drive from Autorun mode

When the iPOS360x is configured for TMLCAN communication protocol, the default operation mode is *Autorun*. If a TML program is present in the EEPROM of the drive, the iPOS360x will start its execution.

In case the TML program becomes corrupted, i.e. due to strong electromagnetic fields, the *Autorun* mode can be disabled by:

- Software: writing the value **1** in the first EEPROM location (address 0x4000). You can use the *Command Interpreter* from EasySetUp / EasyMotion Studio to execute the following instructions:

var_i1 = 0x4000; (var_i1), spi = 1;

- Hardware: connecting all digital Hall inputs to GND, as shown in **Figure 3.24**. This option is particularly useful when you are unable to establish communication with the drive.

After the drive is set in *slave / non-Autorun* mode using the second method, the first one may be used to disable the TML application from the EEPROM. On next power on the drive will enter in the *slave / non-Autorun* mode independently of the digital Hall inputs status

3.7 Operation Mode and Axis ID Selection for CAN drives

The iPOS360x MX-CAN drives have 3 dedicated pins which choose the CAN operation mode and hardware Axis ID value. These pins are sampled at drive power up. The drive works correctly when the logic supply is powered with a minimum of 7V.



CAUTION! The logic power supply requires a minimum rising slew-rate of 75V/s in order to correctly sample the operation mode and AxisID settings. The drive starts to operate from 4.9V and samples correctly the AD circuit from 7V.

These settings are done by setting different voltage levels on the inputs AxisID 0 (J2 pin 16), AxisID 1(J2 pin 15) and AxisID 2 (J2 pin 14). Each input can be set to one of the following 7 levels:

Level	Connection needed
L0	Connect input directly to ground (for example J2 pin 12)
L1	Connect input through a 4.7KΩ resistor to ground
L2	Connected input through a 22KΩ resistor to ground
L3	Nothing connected – leave input open
L4	Connect input through a 22KΩ resistor to +5Vdc (for example J2 pin 13)
L5	Connect input through a 4.7Kohm resistor to +5Vdc
L6	Connect input directly to +5V

The operation mode selection is done via AxisID 2:

- CANopen mode, if the input levels are: L0, L1 or L2
- TMLCAN mode, if the input levels are L3, L4, L5, L6

Figure 3.25 shows how to set the 7 levels on the AxisID 0 input and the resulting axis ID values when AxisID 2 input level is set for **CANopen** operation. Chapter **3.7.1** shows how to set all possible values for axis ID in this mode of operation.

Remarks:

1. *AxisID* is computed with formula: $49 \times (\text{AxisID2} - 3) + 7 \times \text{AxisID1} + \text{AxisID0}$, where each *AxisID* can have one of the integer values: 0 to 6 (0 for L0, 1 for L1, 2 for L2, etc.)
2. If the resulting *AxisID* value is 0, the axis ID will be set to 255

Figure 3.26 shows how to set the 7 levels on the *AxisID* 0 input and the resulting axis ID values when *AxisID* 2 input level is set for **TMLCAN** operation. Chapter 3.7.2 shows how to set all possible values for axis ID in this mode of operation.

Remarks:

1. *AxisID* is computed with formula: $49 \times (\text{AxisID2} - 3) + 7 \times \text{AxisID1} + \text{AxisID0}$, where each *AxisID* can have one of the integer values: 0 to 6 (0 for L0, 1 for L1, 2 for L2, etc.)
2. If the resulting *AxisID* value is 0, the axis ID will be set to 255

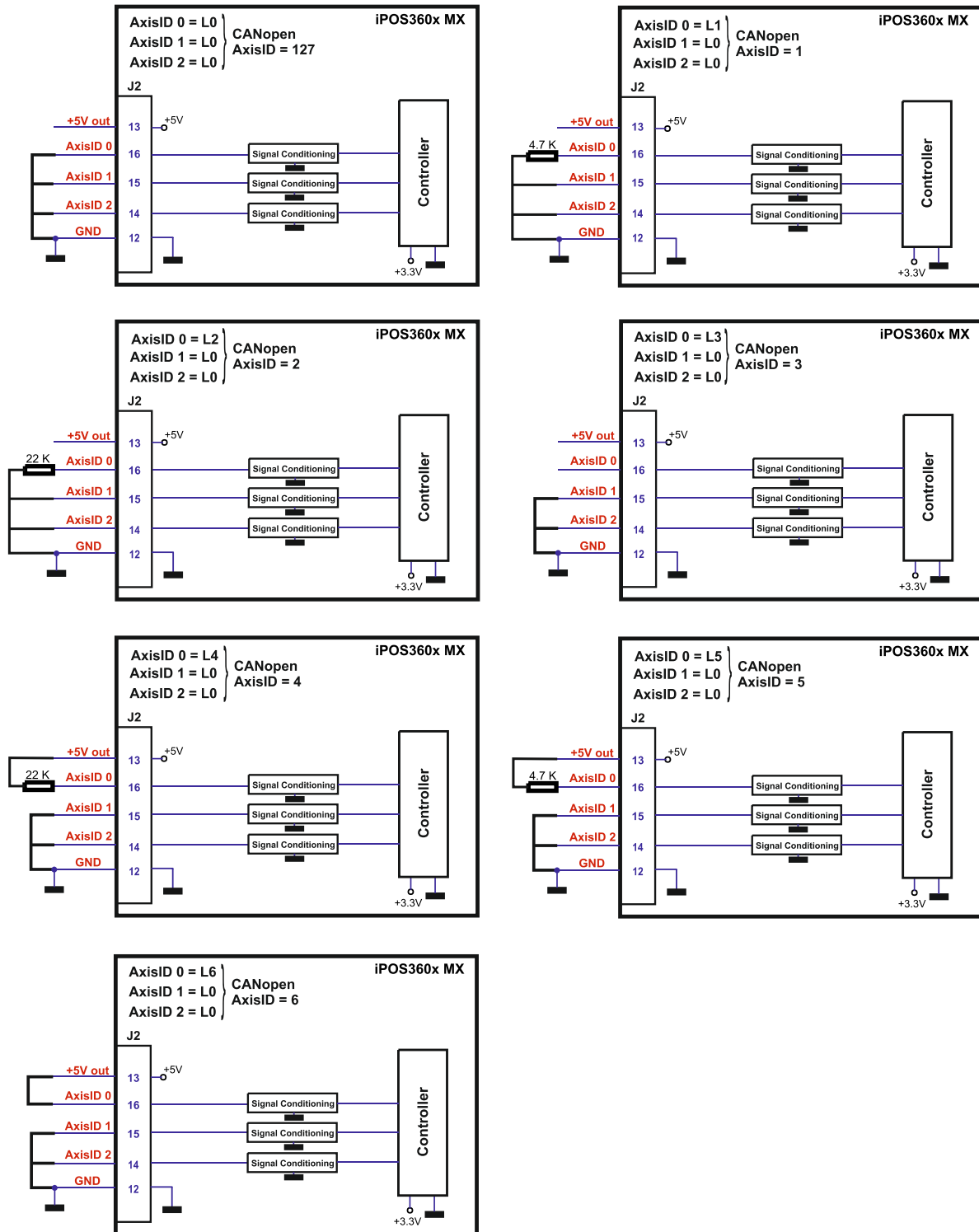


Figure 3.25. Axis ID Setting Examples. CANopen mode

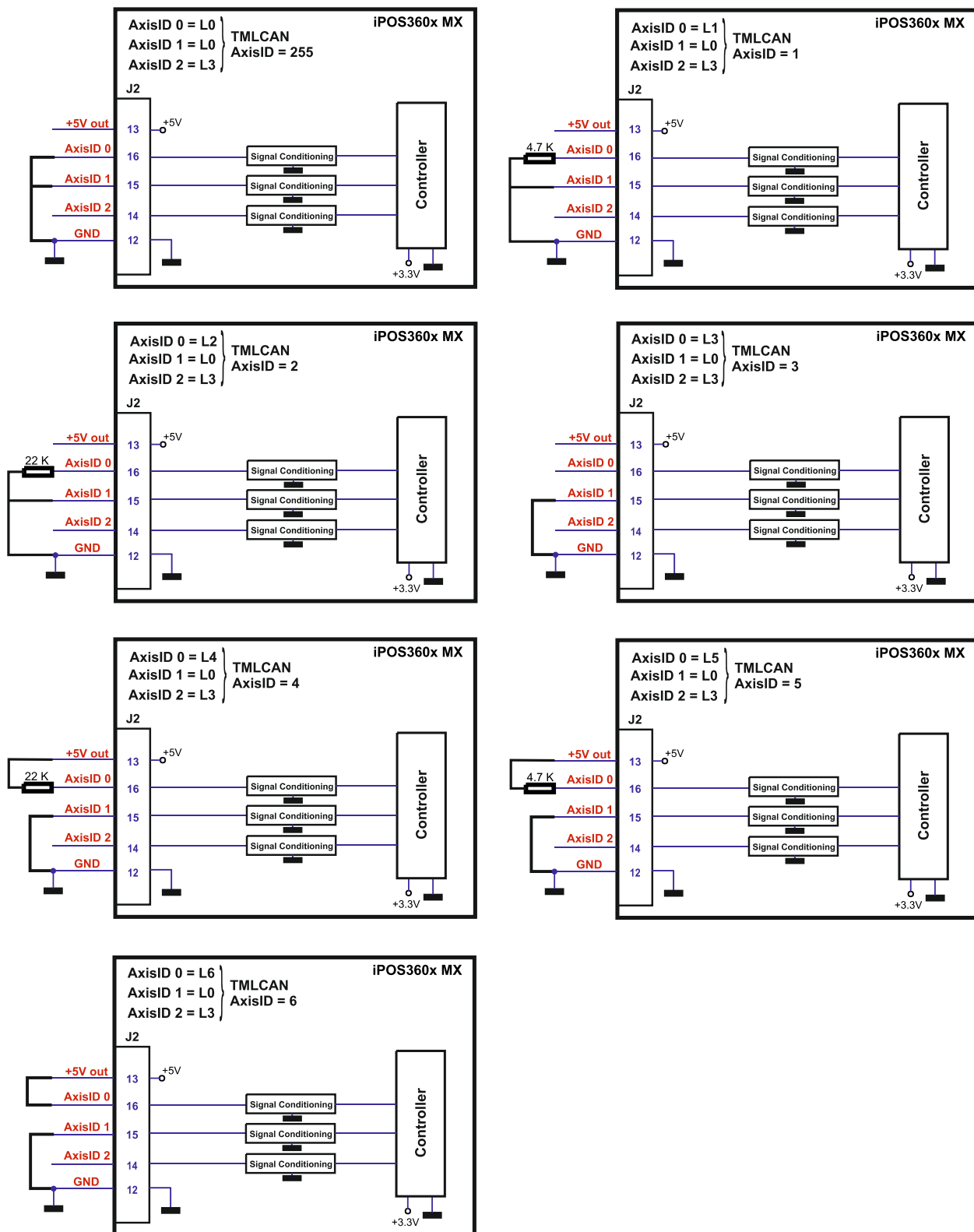


Figure 3.26. Axis ID Setting Examples. TMLCAN mode

3.7.1 Axis ID Settings for CAN drives and CANopen mode

Axis ID 2	Axis ID 1	Axis ID 0	ID CANopen
L0	L0	L0	127
L0	L0	L1	1
L0	L0	L2	2
L0	L0	L3	3
L0	L0	L4	4
L0	L0	L5	5
L0	L0	L6	6
L0	L1	L0	7
L0	L1	L1	8
L0	L1	L2	9
L0	L1	L3	10
L0	L1	L4	11
L0	L1	L5	12
L0	L1	L6	13
L0	L2	L0	14
L0	L2	L1	15
L0	L2	L2	16
L0	L2	L3	17
L0	L2	L4	18
L0	L2	L5	19
L0	L2	L6	20
L0	L3	L0	21
L0	L3	L1	22
L0	L3	L2	23
L0	L3	L3	24
L0	L3	L4	25
L0	L3	L5	26
L0	L3	L6	27
L0	L4	L0	28
L0	L4	L1	29
L0	L4	L2	30
L0	L4	L3	31
L0	L4	L4	32
L0	L4	L5	33
L0	L4	L6	34
L0	L5	L0	35
L0	L5	L1	36
L0	L5	L2	37
L0	L5	L3	38
L0	L5	L4	39
L0	L5	L5	40
L0	L5	L6	41
L0	L6	L0	42
L0	L6	L1	43
L0	L6	L2	44
L0	L6	L3	45
L0	L6	L4	46
L0	L6	L5	47
L0	L6	L6	48

Axis ID 2	Axis ID 1	Axis ID 0	ID CANopen
L1	L0	L0	49
L1	L0	L1	50
L1	L0	L2	51
L1	L0	L3	52
L1	L0	L4	53
L1	L0	L5	54
L1	L0	L6	55
L1	L1	L0	56
L1	L1	L1	57
L1	L1	L2	58
L1	L1	L3	59
L1	L1	L4	60
L1	L1	L5	61
L1	L1	L6	62
L1	L2	L0	63
L1	L2	L1	64
L1	L2	L2	65
L1	L2	L3	66
L1	L2	L4	67
L1	L2	L5	68
L1	L2	L6	69
L1	L3	L0	70
L1	L3	L1	71
L1	L3	L2	72
L1	L3	L3	73
L1	L3	L4	74
L1	L3	L5	75
L1	L3	L6	76
L1	L4	L0	77
L1	L4	L1	78
L1	L4	L2	79
L1	L4	L3	80
L1	L4	L4	81
L1	L4	L5	82
L1	L4	L6	83
L1	L5	L0	84
L1	L5	L1	85
L1	L5	L2	86
L1	L5	L3	87
L1	L5	L4	88
L1	L5	L5	89
L1	L5	L6	90
L1	L6	L0	91
L1	L6	L1	92
L1	L6	L2	93
L1	L6	L3	94
L1	L6	L4	95
L1	L6	L5	96
L1	L6	L6	97

Axis ID 2	Axis ID 1	Axis ID 0	ID CANopen
L2	L0	L0	98
L2	L0	L1	99
L2	L0	L2	100
L2	L0	L3	101
L2	L0	L4	102
L2	L0	L5	103
L2	L0	L6	104
L2	L1	L0	105
L2	L1	L1	106
L2	L1	L2	107
L2	L1	L3	108
L2	L1	L4	109
L2	L1	L5	110
L2	L1	L6	111
L2	L2	L0	112
L2	L2	L1	113
L2	L2	L2	114
L2	L2	L3	115
L2	L2	L4	116
L2	L2	L5	117
L2	L2	L6	118
L2	L3	L0	119
L2	L3	L1	120
L2	L3	L2	121
L2	L3	L3	122
L2	L3	L4	123
L2	L3	L5	124
L2	L3	L6	125
L2	L4	L0	126
L2	L4	L1	255
L2	L4	L2	255
L2	L4	L3	255
L2	L4	L4	255
L2	L4	L5	255
L2	L4	L6	255
L2	L5	L0	255
L2	L5	L1	255
L2	L5	L2	255
L2	L5	L3	255
L2	L5	L4	255
L2	L5	L5	255
L2	L5	L6	255
L2	L6	L0	255
L2	L6	L1	255
L2	L6	L2	255
L2	L6	L3	255
L2	L6	L4	255
L2	L6	L5	255
L2	L6	L6	255

3.7.2 Axis ID Settings for CAN drives and TMLCAN mode

Axis ID 2	Axis ID 1	Axis ID 0	ID TMLCAN
L3	L0	L0	255
L3	L0	L1	1
L3	L0	L2	2
L3	L0	L3	3
L3	L0	L4	4
L3	L0	L5	5
L3	L0	L6	6
L3	L1	L0	7
L3	L1	L1	8
L3	L1	L2	9
L3	L1	L3	10
L3	L1	L4	11
L3	L1	L5	12
L3	L1	L6	13
L3	L2	L0	14
L3	L2	L1	15
L3	L2	L2	16
L3	L2	L3	17
L3	L2	L4	18
L3	L2	L5	19
L3	L2	L6	20
L3	L3	L0	21
L3	L3	L1	22
L3	L3	L2	23
L3	L3	L3	24
L3	L3	L4	25
L3	L3	L5	26
L3	L3	L6	27
L3	L4	L0	28
L3	L4	L1	29
L3	L4	L2	30
L3	L4	L3	31
L3	L4	L4	32
L3	L4	L5	33
L3	L4	L6	34
L3	L5	L0	35
L3	L5	L1	36
L3	L5	L2	37
L3	L5	L3	38
L3	L5	L4	39
L3	L5	L5	40
L3	L5	L6	41
L3	L6	L0	42
L3	L6	L1	43
L3	L6	L2	44
L3	L6	L3	45
L3	L6	L4	46
L3	L6	L5	47
L3	L6	L6	48

Axis ID 2	Axis ID 1	Axis ID 0	ID TMLCAN
L4	L0	L0	49
L4	L0	L1	50
L4	L0	L2	51
L4	L0	L3	52
L4	L0	L4	53
L4	L0	L5	54
L4	L0	L6	55
L4	L1	L0	56
L4	L1	L1	57
L4	L1	L2	58
L4	L1	L3	59
L4	L1	L4	60
L4	L1	L5	61
L4	L1	L6	62
L4	L2	L0	63
L4	L2	L1	64
L4	L2	L2	65
L4	L2	L3	66
L4	L2	L4	67
L4	L2	L5	68
L4	L2	L6	69
L4	L3	L0	70
L4	L3	L1	71
L4	L3	L2	72
L4	L3	L3	73
L4	L3	L4	74
L4	L3	L5	75
L4	L3	L6	76
L4	L4	L0	77
L4	L4	L1	78
L4	L4	L2	79
L4	L4	L3	80
L4	L4	L4	81
L4	L4	L5	82
L4	L4	L6	83
L4	L5	L0	84
L4	L5	L1	85
L4	L5	L2	86
L4	L5	L3	87
L4	L5	L4	88
L4	L5	L5	89
L4	L5	L6	90
L4	L6	L0	91
L4	L6	L1	92
L4	L6	L2	93
L4	L6	L3	94
L4	L6	L4	95
L4	L6	L5	96
L4	L6	L6	97

Axis ID 2	Axis ID 1	Axis ID 0	ID TMLCAN
L5	L0	L0	98
L5	L0	L1	99
L5	L0	L2	100
L5	L0	L3	101
L5	L0	L4	102
L5	L0	L5	103
L5	L0	L6	104
L5	L1	L0	105
L5	L1	L1	106
L5	L1	L2	107
L5	L1	L3	108
L5	L1	L4	109
L5	L1	L5	110
L5	L1	L6	111
L5	L2	L0	112
L5	L2	L1	113
L5	L2	L2	114
L5	L2	L3	115
L5	L2	L4	116
L5	L2	L5	117
L5	L2	L6	118
L5	L3	L0	119
L5	L3	L1	120
L5	L3	L2	121
L5	L3	L3	122
L5	L3	L4	123
L5	L3	L5	124
L5	L3	L6	125
L5	L4	L0	126
L5	L4	L1	127
L5	L4	L2	128
L5	L4	L3	129
L5	L4	L4	130
L5	L4	L5	131
L5	L4	L6	132
L5	L5	L0	133
L5	L5	L1	134
L5	L5	L2	135
L5	L5	L3	136
L5	L5	L4	137
L5	L5	L5	138
L5	L5	L6	139
L5	L6	L0	140
L5	L6	L1	141
L5	L6	L2	142
L5	L6	L3	143
L5	L6	L4	144
L5	L6	L5	145
L5	L6	L6	146

Axis ID 2	Axis ID 1	Axis ID 0	ID TMLCAN
L6	L0	L0	147
L6	L0	L1	148
L6	L0	L2	149
L6	L0	L3	150
L6	L0	L4	151
L6	L0	L5	152
L6	L0	L6	153
L6	L1	L0	154
L6	L1	L1	155
L6	L1	L2	156
L6	L1	L3	157
L6	L1	L4	158
L6	L1	L5	159
L6	L1	L6	160
L6	L2	L0	161
L6	L2	L1	162
L6	L2	L2	163
L6	L2	L3	164
L6	L2	L4	165
L6	L2	L5	166
L6	L2	L6	167
L6	L3	L0	168
L6	L3	L1	169
L6	L3	L2	170
L6	L3	L3	171
L6	L3	L4	172
L6	L3	L5	173
L6	L3	L6	174
L6	L4	L0	175
L6	L4	L1	176
L6	L4	L2	177
L6	L4	L3	178
L6	L4	L4	179
L6	L4	L5	180
L6	L4	L6	181
L6	L5	L0	182
L6	L5	L1	183
L6	L5	L2	184
L6	L5	L3	185
L6	L5	L4	186
L6	L5	L5	187
L6	L5	L6	188
L6	L6	L0	189
L6	L6	L1	190
L6	L6	L2	191

3.8 Electrical Specifications

All parameters measured under the following conditions (unless otherwise specified):

$T_{amb} = 0 \dots 40^{\circ}\text{C}$, $V_{LOG} = 24\text{ V}_{DC}$; $V_{MOT} = 24\text{ V}_{DC}$; Supplies start-up / shutdown sequence: **-any-**

Load current (sinusoidal amplitude / continuous BLDC,DC,stepper) = 4A iPOS3604/ 2A iPOS3602

3.8.1 Operating Conditions

		Min.	Typ.	Max.	Units
Ambient temperature	iPOS360X MX-CAN	0		+40	$^{\circ}\text{C}$
Ambient humidity	Non-condensing	0		90	%Rh
Altitude / pressure ¹	Altitude (referenced to sea level)	-0.1	0 ± 2.5	¹	Km
	Ambient Pressure	0^1	0.75 ± 1	10.0	atm

3.8.2 Storage Conditions

		Min.	Typ.	Max.	Units
Ambient temperature	iPOS360X MX-CAN	-40		105	$^{\circ}\text{C}$
Ambient humidity	Non-condensing	0		100	%Rh
Ambient Pressure		0		10.0	atm
ESD capability (Human body model)	Not powered; applies to any accessible part			± 0.5	kV
	Original packaging			± 15	kV

3.8.3 Mechanical Mounting

		Min.	Typ.	Max.	Units
Airflow		natural convection, closed box			
Spacing required for vertical mounting	Between adjacent drives	30			mm
	Between drives and nearby walls	30			mm
	Between drives and roof-top	20			mm
Spacing required for horizontal mounting	Between adjacent drives	4			mm
	Between drives and nearby walls	5			mm
	Space needed for drive removal	10			mm
	Between drives and roof-top	15			mm
Insertion force	Using recommended mating connectors; without retainer		20	36	N
Extraction force		5	10		N

3.8.4 Environmental Characteristics

		Min.	Typ.	Max.	Units
iPOS360x MX-CAN	Global size	55 x 26.4 x 13.1			mm
Size (Length x Width x Height)		$\sim 2.2 \times 1 \times 0.5$			inch
Weight		8			g
Cleaning agents	Dry cleaning is recommended	Only Water- or Alcohol- based			
Protection degree	According to IEC60529, UL508	IP00			-

3.8.5 Logic Supply Input (+V_{LOG})

		Min.	Typ.	Max.	Units
Supply voltage	Nominal values	7	24	36	V_{DC}
	Absolute maximum values, drive operating but outside guaranteed parameters	4.9		42	V_{DC}
	Absolute maximum values, surge (duration $\leq 10\text{ms}$) [†]	-1		+45	V
	Minimum power supply voltage rising slew-rate	75			V/s
Supply current	+V _{LOG} = 7V		125	300	mA
	+V _{LOG} = 12V		80	200	
	+V _{LOG} = 24V		50	125	
	+V _{LOG} = 40V		40	100	

3.8.6 Motor Supply Input (+V_{MOT})

			Min.	Typ.	Max.	Units
Supply voltage	Nominal values		9		36	V _{DC}
	Absolute maximum values, drive operating but outside guaranteed parameters		8.5		40	V _{DC}
	Absolute maximum values, surge (duration ≤ 10ms) [†]		-1		45	V
Supply current	Idle			1	5	mA
	Operating	iPOS3604	-10	±4	+10	A
		iPOS3602	-3.2	±2	+3.2	A
	Absolute maximum value, short-circuit condition (duration ≤ 10ms) [†]	iPOS3604			15	A
		iPOS3602			5	A

¹ iPOS360x can be operated in vacuum (no altitude restriction), but at altitudes over 2,500m, current and power rating are reduced due to thermal dissipation efficiency.

3.8.7 Motor Outputs (A/A+, B/A-, C/B+, BR/B-)

			Min.	Typ.	Max.	Units
Nominal output current, continuous	for DC brushed, steppers and BLDC motors with Hall-based trapezoidal control	iPOS3604			4	A
		iPOS3602			2	
	for PMSM motors with FOC sinusoidal control (sinusoidal amplitude value)	iPOS3604			4	
		iPOS3602			2	
		iPOS3604			2.82	
Motor output current, peak	maximum 2.5s	iPOS3604	-10		+10	A
		iPOS3602	-3.2		+3.2	
Short-circuit protection threshold	measurement range	iPOS3604		±13	±15	A
		iPOS3602		±4.3	±5	
Short-circuit protection delay			5	10		µs
On-state voltage drop	Nominal output current; including typical mating connector contact resistance			±0.3	±0.5	V
Off-state leakage current				±0.5	±1	mA
Motor inductance (phase-to-phase)	Recommended value, for ripple ±5% of measurement range; +V _{MOT} = 36 V	F _{PWM} = 20 kHz	250			µH
		F _{PWM} = 40 kHz	120			
		F _{PWM} = 80 kHz	60			
		F _{PWM} = 60 kHz	100			
		F _{PWM} = 100 kHz	45			
	Absolute minimum value, limited by short-circuit protection; +V _{MOT} = 36 V	F _{PWM} = 20 kHz	75			µH
		F _{PWM} = 40 kHz	25			
		F _{PWM} = 60 kHz	20			
		F _{PWM} = 80 kHz	10			
		F _{PWM} = 100 kHz	5			
Motor electrical time-constant (L/R)	Recommended value, for ±5% current measurement error due to ripple	F _{PWM} = 20 kHz	250			µs
		F _{PWM} = 40 kHz	125			
		F _{PWM} = 60 kHz	100			
		F _{PWM} = 80 kHz	63			
		F _{PWM} = 100 kHz	50			
Current measurement accuracy	FS = Full Scale			±4	±8	%FS

3.8.8 Digital Inputs (IN0, IN1, IN2/LSP, IN3/LSN, IN4/Enable)

		Min.	Typ.	Max.	Units
Mode compliance		TTL / CMOS / LVTTTL (3.3V) / Open-collector / NPN / 24V outputs			
Default state	Input floating (wiring disconnected)	Logic HIGH			
Input voltage	Logic "LOW"		0	0.8	V
	Logic "HIGH"	2	5+24		
	Floating voltage (not connected)		3		
	Absolute maximum, continuous	-10		+30	
	Absolute maximum, surge (duration ≤ 1s)†	-20		+40	
Input current	Logic "LOW"; Pulled to GND		0.6	1	mA
	Logic "HIGH"; Internal 4.7KΩ pull-up to +3.3	0	0	0	
	Logic "HIGH"; Pulled to +5V		0.15	0.2	
	Logic "HIGH"; Pulled to +24V		2	2.5	
Input frequency		0		150	kHz
Minimum pulse width		3.3			µs
ESD protection	Human body model	±2			kV

3.8.9 Digital Outputs (OUT0, OUT2/Error, OUT3/ Ready)

			Min.	Typ.	Max.	Units
Mode compliance	All outputs (OUT0, OUT2/Error, OUT3/Ready)		TTL / CMOS / Open-collector / NPN 24V			
Default state	Not supplied (+V _{LOG} floating or to GND)		High-Z (floating)			
	Immediately after power-up	OUT0	Logic "HIGH"			
		OUT2/Error, OUT3/ Ready	Logic "LOW"			
	Normal operation	OUT0, OUT2/Error	Logic "HIGH"			
		OUT3/Ready	Logic "LOW"			
Output voltage	Logic "LOW"; output current = 0.5A			0.2	0.8	V
	Logic "HIGH"; output current = 0, no load	OUT2/Error, OUT3/ Ready	2.9	3	3.3	
		OUT0	4	4.5	5	
	Logic "HIGH", external load to +V _{LOG}			V _{LOG}		
	Absolute maximum, continuous		-0.5		V _{LOG} +0.5	
Output current	Absolute maximum, surge (duration ≤ 1s)†		-1		V _{LOG} +1	A
	Logic "LOW", sink current, continuous				0.5	
	Logic "LOW", sink current, pulse ≤ 5 sec.				1	
	Logic "HIGH", source current; external load to GND; V _{OUT} ≥ 2.0V	OUT2/Error, OUT3/ Ready			2	
		OUT0, OUT1			4	
Minimum pulse width	Logic "HIGH", leakage current; external load to +V _{LOG} ; V _{OUT} = V _{LOG} max = 40V			0.1	0.2	mA
ESD protection	Human body model		±5			kV

3.8.10 Digital Hall Inputs (Hall1, Hall2, Hall3)

		Min.	Typ.	Max.	Units
Mode compliance		TTL / CMOS / Open-collector			
Default state	Input floating (wiring disconnected)	Logic HIGH			
Input voltage	Logic "LOW"		0	0.8	V
	Logic "HIGH"	2	5		
	Floating voltage (not connected)		4.4		
	Absolute maximum, surge (duration ≤ 1s) †	-10		+15	
Input current	Logic "LOW"; Pull to GND			1.2	mA
	Logic "HIGH"; Internal 4.7KΩ pull-up to +5	0	0	0	
Minimum pulse width		2			μs
ESD protection	Human body model	±5			kV

3.8.11 Linear Hall Inputs (LH1, LH2, LH3)

		Min.	Typ.	Max.	Units
Input voltage	Operational range	0	0.5+4.5	4.9	V
	Absolute maximum values, continuous	-7		+7	
	Absolute maximum, surge (duration ≤ 1s)	-11		+14	
Input current	Input voltage 0...+5V	-1	±0.9	+1	mA
Interpolation resolution	Depending on software settings	9		13	bits
Frequency		0		4	kHz
ESD protection	Human body model	±1			kV

3.8.12 Analog 0..5V Input (REF)

		Min.	Typ.	Max.	Units
Input voltage	Operational range 0..5V mode	0		4.95	V
	Absolute maximum values, continuous	-12		+18	
	Absolute maximum, surge (duration ≤ 1s) †			±36	
Input impedance	To GND		30		kΩ
Resolution			12		bits
Integral linearity				±4	bits
Differential linearity	No missing codes			±1	bits
Offset error	Assuming parameter RFOFFSET=0		±4	±24	bits
Gain error	Assuming parameter RFGAIN=0x7EB8 (32440)		±1.5%	±4%	% FS ¹
Bandwidth (-3dB)	Software selectable	0		1	kHz
ESD protection	Human body model	±2			kV

3.8.13 Encoder Inputs (A+, A-, B+, B-, Z+, Z-)²

		Min.	Typ.	Max.	Units
Single-ended mode compliance	Leave negative inputs disconnected	TTL / CMOS / Open-collector			
Input voltage, single-ended mode A/A+, B/B+	Logic "LOW"			1.6	V
	Logic "HIGH"	1.8			
	Floating voltage (not connected)		4.5		
Input voltage, single-ended mode Z/Z+	Logic "LOW"			1.2	V
	Logic "HIGH"	1.4			
	Floating voltage (not connected)		4.7		
Input current, single-ended mode A/A+, B/B+, Z/Z+	Logic "LOW"; Pull to GND		2.5	3	mA
	Logic "HIGH"; Internal 2.2KΩ pull-up to +5	0	0	0	
Differential mode compliance	For full RS422 compliance, see ³	TIA/EIA-422-A			
Input voltage, differential mode	Hysteresis	±0.06	±0.1	±0.2	V
	Differential mode	-14		+14	
	Common-mode range (A+ to GND, etc.)	-7		+7	
Input impedance, differential	A+ to A-, B+ to B-	4.2	4.7		kΩ
	Z+ to Z-	6.1	7.2		
Input frequency	Single-ended mode, Open-collector / NPN	0		500	kHz
	Differential mode, or Single-ended driven by push-pull (TTL / CMOS)	0		10	
Minimum pulse width	Single-ended mode, Open-collector / NPN	1			μs
	Differential mode, or Single-ended driven by push-pull (TTL / CMOS)	50			ns
Input voltage, any pin to GND	Absolute maximum values, continuous	-7		+7	V
	Absolute maximum, surge (duration ≤ 1s) [†]	-11		+14	
ESD protection	Human body model	±1			kV

¹ "FS" stands for "Full Scale"

² Encoder differential input pins do not have internal 120Ω termination resistors connected across

³ For full RS-422 compliance, 120Ω termination resistors must be connected across the differential pairs, as close as possible to the drive input pins. See Figure 3.15. Differential incremental encoder connection

3.8.14 RS-232

		Min.	Typ.	Max.	Units
Standards compliance			TIA/EIA-232-C		
Bit rate	Depending on software settings	9600		115200	Baud
Short-circuit protection	232TX short to GND		Guaranteed		
ESD protection	Human body model	±2			kV

3.8.15 CAN-Bus (for CAN drives)

		Min.	Typ.	Max.	Units
Compliance		ISO11898, CiA-301v4.2, 402 2v4.1			
Bit rate	Software selectable	125		1000	125
Bus length	1Mbps			40	m
	500Kbps			100	
	≤ 250Kbps			250	
Resistor	Between CAN-Hi, CAN-Lo	none on-board			
Node addressing	Hardware (CANOpen selection pin)	127 (CANopen); 255 (TMLCAN);			
	Software	1 - 127 (CANopen); 1- 255 (TMLCAN)			
Voltage, CAN-Hi or CAN-Lo to GND		-36		36	V
ESD protection	Human body model	±15			kV

3.8.16 Supply Output (+5V)

		Min.	Typ.	Max.	Units
+5V output voltage	Current sourced = 350mA	4.8	5	5.2	V
+5V output current	iPOS360X MX-CAN	250	350		mA
Short-circuit protection		Yes / Drive resets at event			
Over-voltage protection		NOT protected			
ESD protection	Human body model	±1			kV

3.8.17 Conformity

EU Declaration	2014/30/EU (EMC), 2014/35/EU (LVD), 2011/65/EU (RoHS), 1907/2006/EC (REACH), 93/68/EEC (CE Marking Directive), EC 428/2009 (non dual-use item, output frequency limited to 590Hz)
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† Stresses beyond values listed under “absolute maximum ratings” may cause permanent damage to the device. Exposure to absolute-maximum-rated conditions for extended periods may affect device reliability.

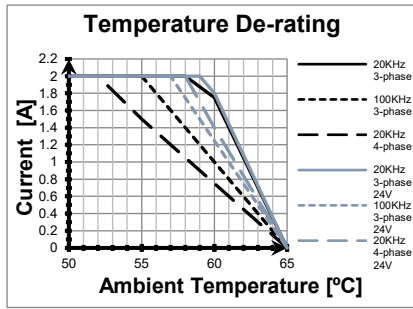


Figure 3.27 iPOS3602 MX De-rating with ambient temperature

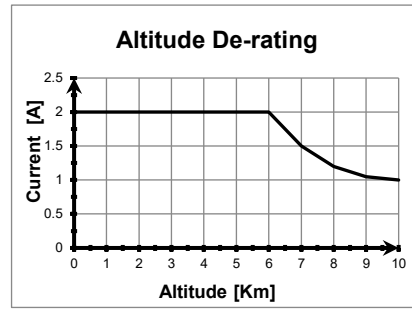


Figure 3.28 iPOS3602 MX De-rating with altitude

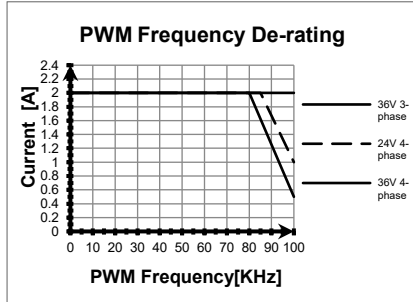


Figure 3.29 iPOS3602 MX Current De-rating with PWM frequency

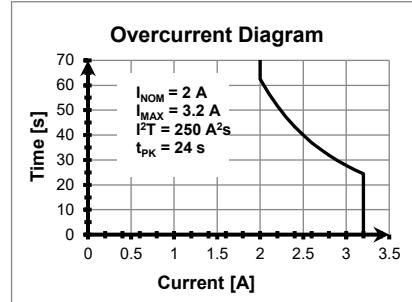


Figure 3.30 iPOS3602 MX Over-current diagram

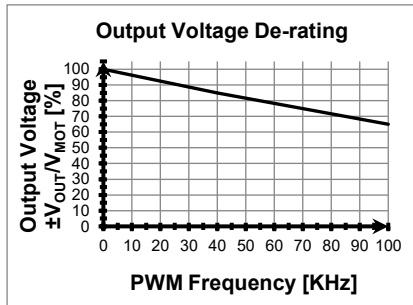


Figure 3.31. iPOS360x MX Output Voltage De-rating with PWM frequency¹

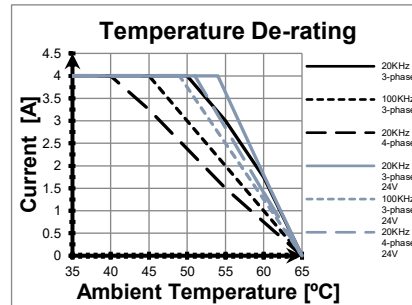


Figure 3.32. iPOS3604 MX De-rating with ambient temperature

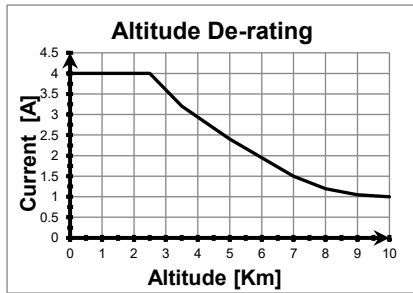


Figure 3.33. iPOS3604 MX De-rating with altitude

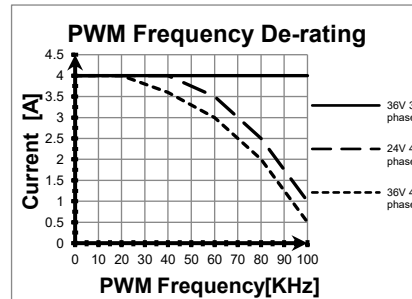


Figure 3.34. iPOS3604 MX Current De-rating with PWM frequency

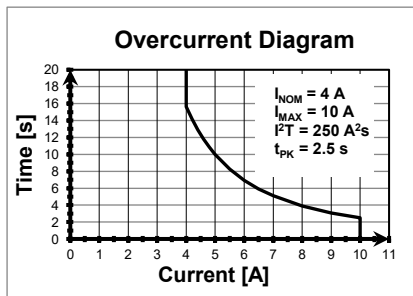


Figure 3.35. iPOS3604 MX Over-current diagram



CAUTION!

FOR PWM FREQUENCIES LESS THAN 20 KHZ, CORRELATE THE PWM FREQUENCY WITH THE MOTOR PARAMETERS IN ORDER TO AVOID POSSIBLE MOTOR DAMAGE.

¹ V_{OUT} – the output voltage, V_{MOT} – the motor supply voltage

4 Memory Map

iPOS360X MX has 2 types of memory available for user applications: 2K×16 SRAM and 4K×16 serial E²ROM.

The SRAM memory is mapped in the address range: 9800h to 9FFFh. It can be used to download and run a TML program, to save real-time data acquisitions and to keep the cam tables during run-time.

The E²ROM is mapped in the address range: 4000h to 4FFFh. It is used to keep in a non-volatile memory the TML programs, the cam tables and the drive setup information.

Remark: EasyMotion Studio handles automatically the memory allocation for each motion application. The memory map can be accessed and modified from the main folder of each application

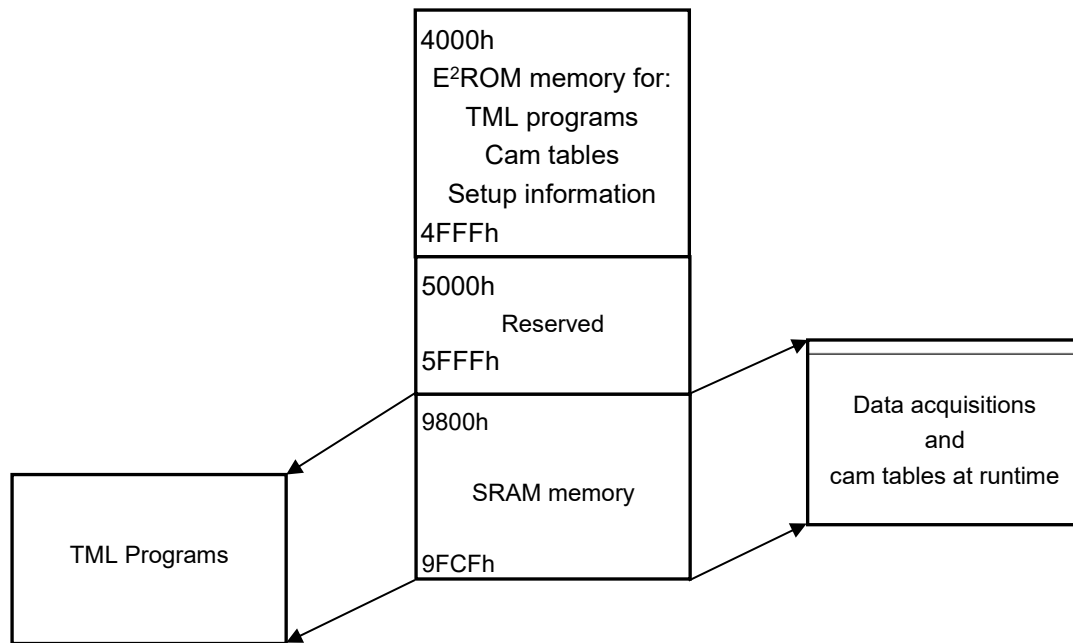


Figure 4.1. iPOS360X MX Memory Map



T E C H N O S O F T