

Servo Positioning Controller ARS 2320 and 2340

Mounting Instructions

Version 6.0

1 General

1.1 Documentation

This installation information serves the purpose of a safe use of the ARS 2300 series servo positioning controller. It contains safety notes, which must be complied with.

Further information can be found in the following manuals of the ARS 2000 product range:

- ❖ **Product Manual “Servo Positioning Controller ARS 2320, 2320W, 2340 and 2360W”:**
Description of the technical specifications and the device functionality as well as notes on the installation and the operation of the servo positioning controller ARS 2320, 2320W, 2340 and 2360W.
- ❖ **CANopen Manual “Servo Positioning Controller ARS 2000”:** Description of the implemented CANopen protocol as per DSP402.
- ❖ **PROFIBUS Manual “Servo Positioning Controller ARS 2000”:** Description of the implemented PROFIBUS-DP protocol.
- ❖ **SERCOS Manual “Servo Positioning Controller ARS 2000”:** Description of the implemented SERCOS protocol.
- ❖ **Software Manual “Servo Positioning Controller ARS 2000”:** Description of the device functionality and the software functions of the firmware including RS232 communication.
Description of the parameterisation program Metronix ServoCommander with instructions on the commissioning of an ARS 2000 series servo positioning controller.

2 Safety notes for electrical drives and controllers

2.1 Used symbols



Information

Important information and notes.



Caution!

Nonobservance may result in severe property damages.



DANGER!

Nonobservance may result in **property damages** and in **personal injuries**.



Caution! Dangerous voltages.

The safety note indicates a possible perilous voltage.

2.2 General notes

In case of damage resulting from non-compliance with the safety notes in this manual, Metronix Meßgeräte und Elektronik GmbH will not assume any liability.

Sound and safe operation of the servo drive controller requires proper and professional transportation, storage, assembly and installation as well as proper operation and maintenance. Only trained and qualified personnel may handle electrical devices:

TRAINED AND QUALIFIED PERSONNEL

in the sense of this product manual or the safety notes on the product itself are persons who are sufficiently familiar with the project planning, the setup, assembly, commissioning and operation of the product as well as all warnings and precautions as per the instructions in this manual and who are sufficiently qualified in their field of expertise:

- ❖ Education and instruction of standard specifications and accident prevention regulations, which are necessary in the application, and authorisation to switch devices/systems on and off and to ground them as per the standards of safety engineering and to efficiently label them as per the job demands.
- ❖ Education and instruction as per the standards of safety engineering regarding the maintenance and use of adequate safety equipment.
- ❖ First aid training.

The following notes must be read prior to the initial operation of the system to prevent personal injuries and/or property damages:



These safety notes must be complied with at all times.



Do not try to install or commission the servo drive controller before carefully reading all safety notes for electrical drives and controllers contained in this document. These safety instructions and all other user notes must be read prior to any work with the servo drive controller.



In case you do not have any user notes for the servo drive controller, please contact your sales representative. Immediately demand these documents to be sent to the person responsible for the safe operation of the servo drive controller.



If you sell, rent and/or otherwise make this device available to others, these safety notes must also be included.



The user must not open the servo drive controller for safety and warranty reasons.



Professional control process design is a prerequisite for sound functioning of the servo drive controller!



DANGER!

Inappropriate handling of the servo drive controller and non-compliance of the warnings as well as inappropriate intervention in the safety features may result in property damage, personal injuries, electric shock or in extreme cases even death.

2.3 Danger resulting from misuse



DANGER!

High electrical voltages and high load currents!
Danger to life or serious personal injury from electrical shock!



DANGER!

High electrical voltage caused by wrong connections!
Danger to life or serious personal injury from electrical shock!



DANGER!

Surfaces of device housing may be hot!
Risk of injury! Risk of burning!



DANGER!

Dangerous movements!

Danger to life, serious personal injury or property damage due to unintentional movements of the motors!

2.4 Safety notes

2.4.1 General safety notes



The servo drive controller corresponds to IP20 class of protection as well as pollution level 1. Make sure that the environment corresponds to this class of protection and pollution level.



Only use replacements parts and accessories approved by the manufacturer.



The devices must be connected to the mains supply as per EN regulations, so that they can be cut off the mains supply by means of corresponding separation devices (e.g. main switch, contactor, power switch).



The servo drive controller may be protected using an AC/DC sensitive 300mA fault current protection switch (RCD = Residual Current protective Device).



Gold contacts or contacts with a high contact pressure should be used to switch the control contacts.



Preventive interference rejection measures should be taken for control panels, such as connecting contactors and relays using RC elements or diodes.



The safety rules and regulations of the country in which the device will be operated must be complied with.



The environment conditions defined in the product documentation must be kept. Safety-critical applications are not allowed, unless specifically approved by the manufacturer.



The compliance with the limits required by national regulations is the responsibility of the manufacturer of the machine or system.



The technical data and the connection and installation conditions for the servo drive controller are to be found in this product manual and must be met.



DANGER!

The general setup and safety regulations for work on power installations (e.g. DIN, VDE, EN, IEC or other national and international regulations) must be complied with.

Non-compliance may result in death, personal injury or serious property damages.

**Without claiming completeness, the following regulations and others apply:**

| | |
|----------------|---|
| VDE 0100 | Erection of power installations with nominal voltages up to 1000 V |
| EN 1037 | Safety of machinery - Prevention of unexpected start-up |
| EN 60204-1 | Safety of machinery - Electrical equipment of machines Part 1: General requirements |
| EN 61800-3 | Adjustable speed electrical power drive systems Part 3: EMC requirements and specific test methods |
| EN 61800-5-1 | Adjustable speed electrical power drive systems Part 5-1: Safety requirements - Electrical, thermal and energy |
| EN 61800-5-2 | Adjustable speed electrical power drive systems Part 5-2: Safety requirements - Functional |
| EN ISO 12100 | Safety of machinery - General principles for design - Risk assessment and risk reduction |
| EN ISO 13849-1 | Safety of machinery - Safety-related parts of control systems Part 1: General principles for design |
| EN ISO 13849-2 | Safety of machinery - Safety-related parts of control systems Part 2: Validation |

**More standards to be respected by the user:**

| | |
|--------------|---|
| EN 574 | Safety of machinery - Two-hand control devices |
| EN 1088 | Safety of machinery - Interlocking devices associated with guards |
| EN ISO 13850 | Safety of machinery - Emergency stop |

2.4.2 Safety notes for assembly and maintenance

The appropriate DIN, VDE, EN and IEC regulations as well as all national and local safety regulations and rules for the prevention of accidents apply for the assembly and maintenance of the system. The plant engineer or the operator is responsible for compliance with these regulations:



The servo drive controller must only be operated, maintained and/or repaired by personnel trained and qualified for working on or with electrical devices.

Prevention of accidents, injuries and/or damages:



Additionally secure vertical axes against falling down or lowering after the motor has been switched off, e.g. by means of:

- Mechanical locking of the vertical axle,
- External braking, catching or clamping devices or
- Sufficient balancing of the axle.



The motor holding brake supplied by default or an external motor holding brake driven by the drive controller alone is not suitable for personal protection!



Render the electrical equipment voltage-free using the main switch and protect it from being switched on again until the DC bus circuit is discharged, in the case of:

- Maintenance and repair work
- Cleaning
- long machine shutdowns



Prior to carrying out maintenance work make sure that the power supply has been turned off, locked and the DC bus circuit is discharged.



The external or internal brake resistor carries dangerous DC bus voltages during operation of the servo drive controller and up to 5 minutes thereafter. Contact may result in death or serious personal injury.



Be careful during the assembly. During the assembly and also later during operation of the drive, make sure to prevent drill chips, metal dust or assembly parts (screws, nuts, cable sections) from falling into the device.



Also make sure that the external power supply of the controller (24V) is switched off.



The DC bus circuit or the mains supply must always be switched off prior to switching off the 24V controller supply.



Carry out work in the machine area only, if AC and/or DC supplies are switched off. Switched off output stages or controller enablings are no suitable means of locking. In the case of a malfunction the drive may accidentally be put into action, except drives with active safety function "Safe standstill" according to EN 954-1 CAT 3.



Initial operation must be carried out with idle motors, to prevent mechanical damages e.g. due to the wrong direction of rotation.



Electronic devices are never fail-safe. It is the user's responsibility, in the case an electrical device fails, to make sure the system is transferred into a secure state.



The servo drive controller and in particular the brake resistor, externally or internally, can assume high temperatures, which may cause serious burns.

2.4.3 Protection against contact with electrical parts

This section only concerns devices and drive components carrying voltages exceeding 50 V. Contact with parts carrying voltages of more than 50 V can be dangerous for people and may cause electrical shock. During operation of electrical devices some parts of these devices will inevitably carry dangerous voltages.

**DANGER!**

High electrical voltage!

Danger to life, danger due to electrical shock or serious personal injury!

The appropriate DIN, VDE, EN and IEC regulations as well as all national and local safety regulations and rules for the prevention of accidents apply for the assembly and maintenance of the system. The plant engineer or the operator is responsible for compliance with these regulations:



Before switching on the device, install the appropriate covers and protections against accidental contact. Rack-mounted devices must be protected against accidental contact by means of a housing, e.g. a switch cabinet. The regulations VGB4 must be complied with!



Always connect the ground conductor of the electrical equipment and devices securely to the mains supply. Due to the integrated line filter the leakage current exceeds 3.5 mA!



Comply with the minimum copper cross-section for the ground conductor over its entire length as per EN60617!



Prior to the initial operation, even for short measuring or testing purposes, always connect the ground conductor of all electrical devices as per the terminal diagram or connect it to the ground wire. Otherwise the housing may carry high voltages which can cause electrical shock.



Do not touch electrical connections of the components when switched on.



Prior to accessing electrical parts carrying voltages exceeding 50 Volts, disconnect the device from the mains or power supply. Protect it from being switched on again.



For the installation the amount of DC bus voltage must be considered, particularly regarding insulation and protective measures. Ensure proper grounding, wire dimensioning and corresponding short-circuit protection.



The device comprises a rapid discharge circuit for the DC bus as per EN60204 section 6.2.4. In certain device constellations, however, mostly in the case of parallel connection of several servo drive controllers in the DC bus or in the case of an unconnected brake resistor, this rapid discharge may be rendered ineffective. The servo drive controllers can carry voltage until up to 5 minutes after being switched off (residual capacitor charge).

2.4.4 Protection against electrical shock by means of protective extra-low voltage (PELV)

All connections and terminals with voltages between 5 and 50 Volts at the servo drive controller are protective extra-low voltage, which are designed safe from contact in correspondence with the following standards:

International: IEC 60364-4-41

European countries within the EU: EN 50178/1998, section 5.2.8.1.



DANGER!

High electrical voltages due to wrong connections!

Danger to life, risk of injury due to electrical shock!

Only devices and electrical components and wires with a protective extra low voltage (PELV) may be connected to connectors and terminals with voltages between 0 to 50 Volts.

Only connect voltages and circuits with protection against dangerous voltages. Such protection may be achieved by means of isolation transformers, safe optocouplers or battery operation.

2.4.5 Protection against dangerous movements

Dangerous movements can be caused by faulty control of connected motors, for different reasons:

- ❖ Improper or faulty wiring or cabling
- ❖ Error in handling of components
- ❖ Error in sensor or transducer
- ❖ Defective or non-EMC-compliant components
- ❖ Error in software in superordinated control system

These errors can occur directly after switching on the device or after an indeterminate time of operation.

The monitors in the drive components for the most part rule out malfunctions in the connected drives. In view of personal protection, particularly the danger of personal injury and/or property damage, this may not be relied on exclusively. Until the built-in monitors come into effect, faulty drive movements must be taken into account; their magnitude depends on the type of control and on the operating state.



DANGER!

Dangerous movements!

Danger to life, risk of injury, serious personal injuries or property damage!

For the reasons mentioned above, personal protection must be ensured by means of monitoring or superordinated measures on the device. These are installed in accordance with the specific data of the system and a danger and error analysis by the manufacturer. The safety regulations applying to the system are also taken into consideration. Random movements or other malfunctions may be caused by switching the safety installations off, by bypassing them or by not activating them.

2.4.6 Protection against contact with hot parts

**DANGER!**

Housing surfaces may be hot!

Risk of injury! Risk of burning!



Do not touch housing surfaces in the vicinity of heat sources! Danger of burning!



Before accessing devices let them cool down for 10 minutes after switching them off.



Touching hot parts of the equipment such as the housing, which contain heat sinks and resistors, may cause burns!

2.4.7 Protection during handling and assembly

Handling and assembly of certain parts and components in an unsuitable manner may under adverse conditions cause injuries.

**DANGER!**

Risk of injury due to improper handling!

Personal injury due to pinching, shearing, cutting, crushing!

The following general safety notes apply:



Comply with the general setup and safety regulations on handling and assembly.



Use suitable assembly and transportation devices.



Prevent incarcerations and contusions by means of suitable protective measures.



Use suitable tools only. If specified, use special tools.



Use lifting devices and tools appropriately.



If necessary, use suitable protective equipment (e.g. goggles, protective footwear, protective gloves).



Do not stand underneath hanging loads.



Remove leaking liquids on the floor immediately to prevent slipping.

3 Technical data

| Range | ARS 2320 | ARS 2340 |
|--|--|----------|
| Ambient conditions and qualification: | | |
| Admissible temperature ranges | Storage temperature: -25°C to +70°C | |
| | Operating temperature: 0°C to +40°C +40°C to +50°C at reduced power 2,5%/K | |
| Admissible installation height | Mounting height maximum 2000 m above msl, above 1000 m above msl with power reduction 1% per 100 m | |
| Humidity | Relative humidity up to 90%, not bedewing | |
| Protection class | IP20 | |
| Pollution degree | 1 | |
| CE conformity Low-voltage directive: | 2006/95/EC verified by application of the harmonised standard EN 61800-5-1 | |
| EMC directive: | 2004/108/EC verified by application of the harmonised standard EN 61800-3 | |

| Dimensions and weight: | | |
|----------------------------------|-----------------------|------------------------|
| Dimensions: H*W*D | ca. 330 x 89 x 242 mm | ca. 330 x 164 x 242 mm |
| Dimensions of the mounting plate | ca. 369 x 80 x 2 mm | ca. 369 x 160 x 2 mm |
| Weight | ca. 8 kg | ca. 13,5 kg |

| Performance data [X9]: | |
|-------------------------------|--|
| Supply voltage | 3 x 230 ... 480 VAC [+/- 10%], 50...60Hz |
| Alternative DC supply | 60 ... 700 VDC |

| Internal brake resistor [X9]: | | |
|--------------------------------------|---------|---------|
| Brake resistance internal | 47 Ω | 23,5 Ω |
| Pulse power | 12 kW | 23 kW |
| Continuous power | > 110 W | > 220 W |
| Threshold limit | 760 V | |

| Motor connection specifications [X6]: | | |
|---|-----------------------|---------------------|
| Specifications for operation with 3x 400 VAC [$\pm 10\%$], 50 Hz, with an output stage clock frequency of 5 kHz | | |
| Output power | 12 kVA | 20 kVA |
| Max. output power for 2 s | 25 kVA | 50 kVA |
| Output current | 20 A _{eff} | 40 A _{eff} |
| Max. output current for 2 s | 41,5 A _{eff} | 70 A _{eff} |
| Clock frequency | max. 12,5 kHz | |
| Max. mains current for continuous operation | 19 A _{eff} | 32 A _{eff} |

| External brake resistor [X9]: | | |
|--------------------------------------|---|--|
| Brake resistance external | $30\Omega \leq R_{\text{Extern}} \leq 100 \Omega$ | $18\Omega \leq R_{\text{Extern}} \leq 75 \Omega$ |
| Continuous power | $\leq 5 \text{ kW}$ | $\leq 10 \text{ kW}$ |
| Operating voltage | $\geq 800 \text{ V}$ | |

| Maximum motor cable length for interference emission as per EN 61800-3 (corresponds to EN 55011, EN 55022): | |
|--|----------------------------|
| First ambient Switch cabinet assembly (residential area) | $l \leq 15 \text{ m}$ |
| Second ambient (industrial area) | $l \leq 50 \text{ m}$ |
| Cable capacity of a phase against shield or between two lines | $C' \leq 200 \text{ pF/m}$ |

| Motor temperature monitoring: | |
|--------------------------------------|---|
| Digital sensor | Normally closed contact: $R_{\text{cold}} < 500 \Omega$ $R_{\text{hot}} > 100 \text{ k}\Omega$ |
| Analog sensor | Silicon temperature sensor, e.g. KTY81, 82 or similar $R_{25} \approx 2000 \Omega$ $R_{100} \approx 3400 \Omega$ |

| Resolver [X2A]: | |
|--------------------------------------|---------------------------|
| Resolution | 16 Bit |
| Delay time signal detection | $< 200 \mu\text{s}$ |
| Speed resolution | ca. 4 min^{-1} |
| Absolute accuracy of angle detection | $< 5^\circ$ |
| Max. rotational speed | 16.000 min^{-1} |

| Encoder evaluation [X2B]: | |
|---|---|
| Parameterisable number of encoder lines | 1 – 2 ¹⁸ lines/rev |
| Angular resolution / Interpolation | 10 Bit / period |
| Encoder signals A, B | 1 V _{PP} differential; 2.5 V offset |
| Encoder signal N | 0.2 to 1 V _{PP} differential; 2.5 V offset |
| Commutation track A1, B1 (optional) | 1 V _{PP} differential; 2.5 V offset |
| Input impedance encoder signals | Differential input 120 Ω |
| Limit frequency | f _{Limit} > 300 kHz (high-res. signal) f _{Limit} ca. 10 kHz (commutation track) |
| Additional communication interface | EnDat (Heidenhain) and HIPERFACE (Stegmann) |
| Output supply | 5 V or 12 V; max. 300 mA; currentlimited control via sensor lines Setpoint programmable via software |

| Digital inputs and outputs [X1]: | |
|---|--|
| Signal level | 24V (8V...30V) active high, conforming with DIN EN 61131-2 |
| Logic inputs general | |
| DIN0 | Bit 0 \ |
| DIN1 | Bit 1, \ Target selection for positioning |
| DIN2 | Bit 2, / 16 targets selectable from target table |
| DIN3 | Bit 3 / |
| DIN4 | Control input stage enable at High |
| DIN5 | Controller enable at High, clear error high-low transition at Low |
| DIN6 | End switch input 0 |
| DIN7 | End switch input 1 |
| DIN8 | Control signal Start positioning |
| DIN9 | Home switch for homing or saving of positions |
| Logic outputs general | Galvanically separated, 24V (8V...30V) active high |
| DOUT0 | Operational state 24 V, max. 100 mA |
| DOUT1 | Freely configurable 24 V, max. 100 mA |
| DOUT2 | Freely configurable, optional use as input DIN10 24 V, max. 100 mA |
| DOUT3 | Freely configurable, optional use as input DIN11 24 V, max. 100 mA |
| DOUT4 (X6) | Holding brake 24 V, max. 2 A |

| Analog inputs and outputs [X1]: | |
|--|--|
| High-resolution analog input: AIN0 | ±10V input range, 16 Bit, differentially, < 250µs delay time |
| Analog input: AIN1 | Optionally, this input can also be parameterized as digital input DIN AIN1 with a switching threshold at 8V. ±10V, 10 Bit, single ended, < 250µs delay time |
| Analog input: AIN2 | Optionally, this input can also be parameterized as digital input DIN AIN2 with a switching threshold at 8V. ±10V, 10 Bit, single ended, < 250µs delay time |
| Analog outputs: AOUT0 and AOUT1 | ±10V output range, 9 bit resolution, $f_{Limit} > 1\text{kHz}$ |

| Incremental encoder input [X10]: | |
|---|-------------------------------|
| parametrierbare Strichzahl | 1 – 2 ²⁸ lines/rev |
| Trace signals | As per RS422 specification |
| Max. input frequency | 1000 kHz |
| Pulse-direction interface | As per RS422 specification |
| Ausgang Versorgung | 5 V, max. 100 mA |

| Incremental encoder output [X11]: | |
|--|---|
| Number of lines | Programmable 1 – 16384 lines/rev. |
| Connection level | Differential / RS422 specification |
| Encoder signals A, B, N | As per RS422 specification |
| speciality | N-Trace disconnectible |
| Output impedance | $R_{a,diff} = 66 \Omega$ |
| Limit frequency | $f_{Limit} > 1,8 \text{ MHz (lines/s)}$ |
| Edge triggering (minimum pulse width) | Can be limited by parameters |
| Output supply | 5 V, max. 100 mA |

4 Mechanical installation

4.1 Important notes

- ❖ Use the ARS 2300 servo positioning controllers exclusively as cabinet controllers for control cabinet installation.
- ❖ Vertical installation position with the fan down the technology slots TECH1 and TECH2 up.
- ❖ Fasten the servo positioning controller to the control cabinet plate using the mounting plate.
- ❖ Installation spaces: Keep a minimum distance of 100 mm underneath and above the servo positioning controller to other components to ensure sufficient ventilation.
- ❖ The servo positioning controller ARS 2300 may be installed adjacently in one switch cabinet without a gap, proper usage and installation on a heat-dissipating rear panel provided. Please note that excessive heat may cause premature aging and/or damaging of the device. In case the servo positioning controller ARS 2300 are subject to high thermal stress, a space of 75 mm is recommended!

i The connections of the following illustrations for the servo positioning controller ARS 2320 also apply to the servo positioning controller ARS 2340!

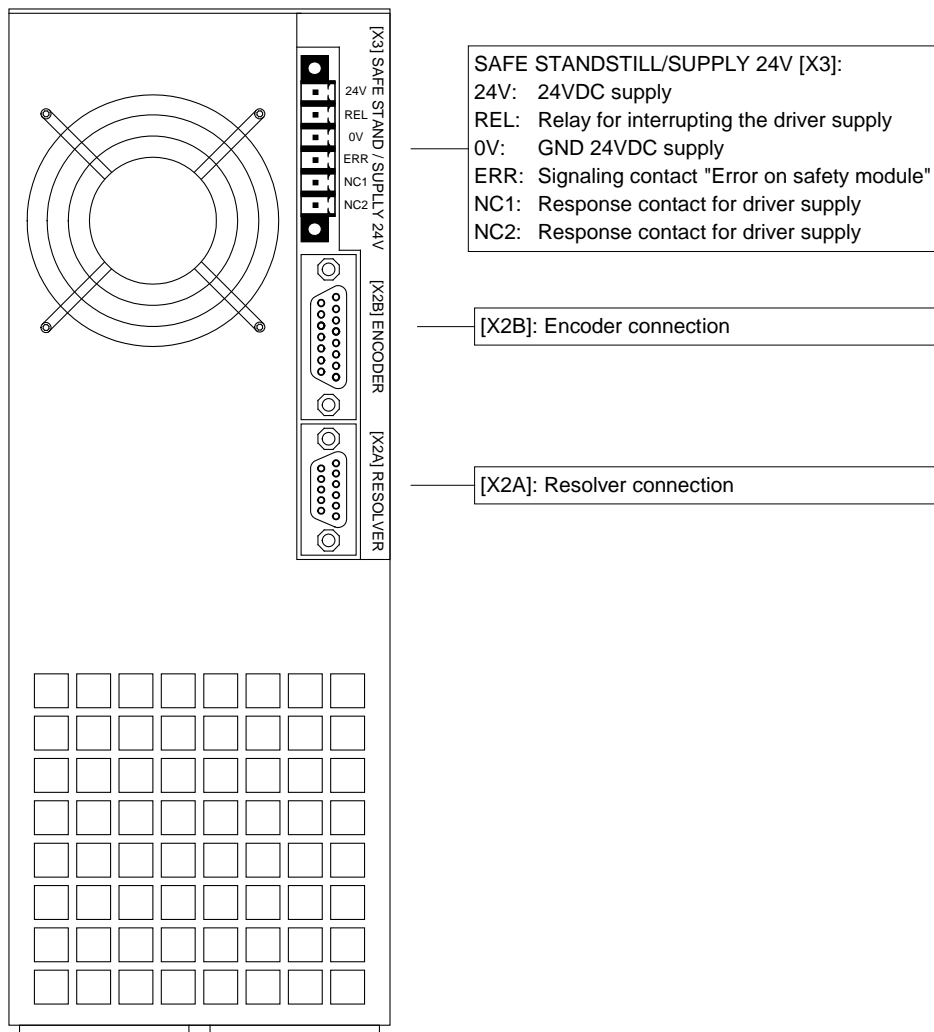


Figure 1: Servo positioning controller ARS 2320: Bottom view

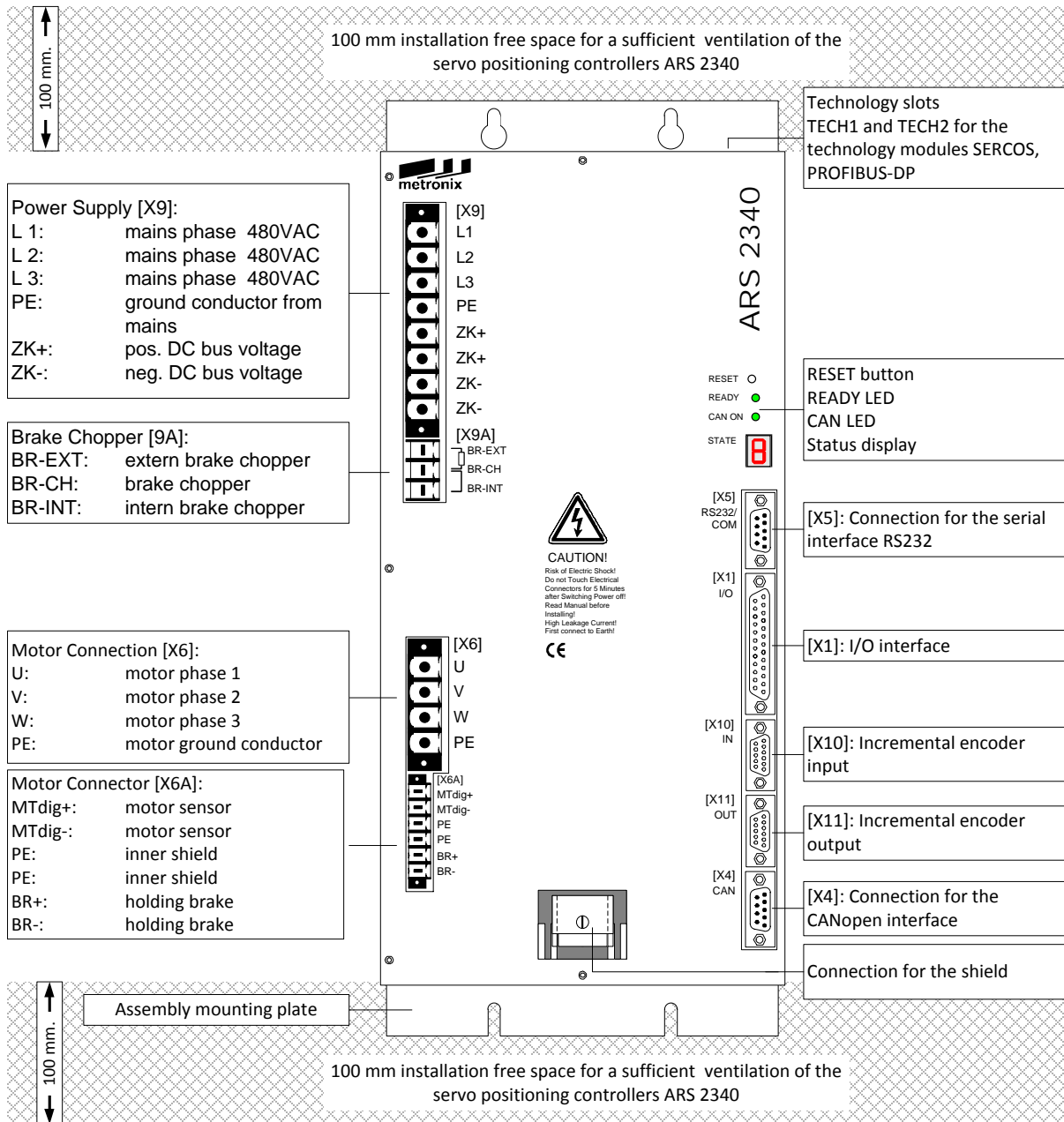


Figure 2: Servo positioning controller ARS 2340: Front view and Installation space

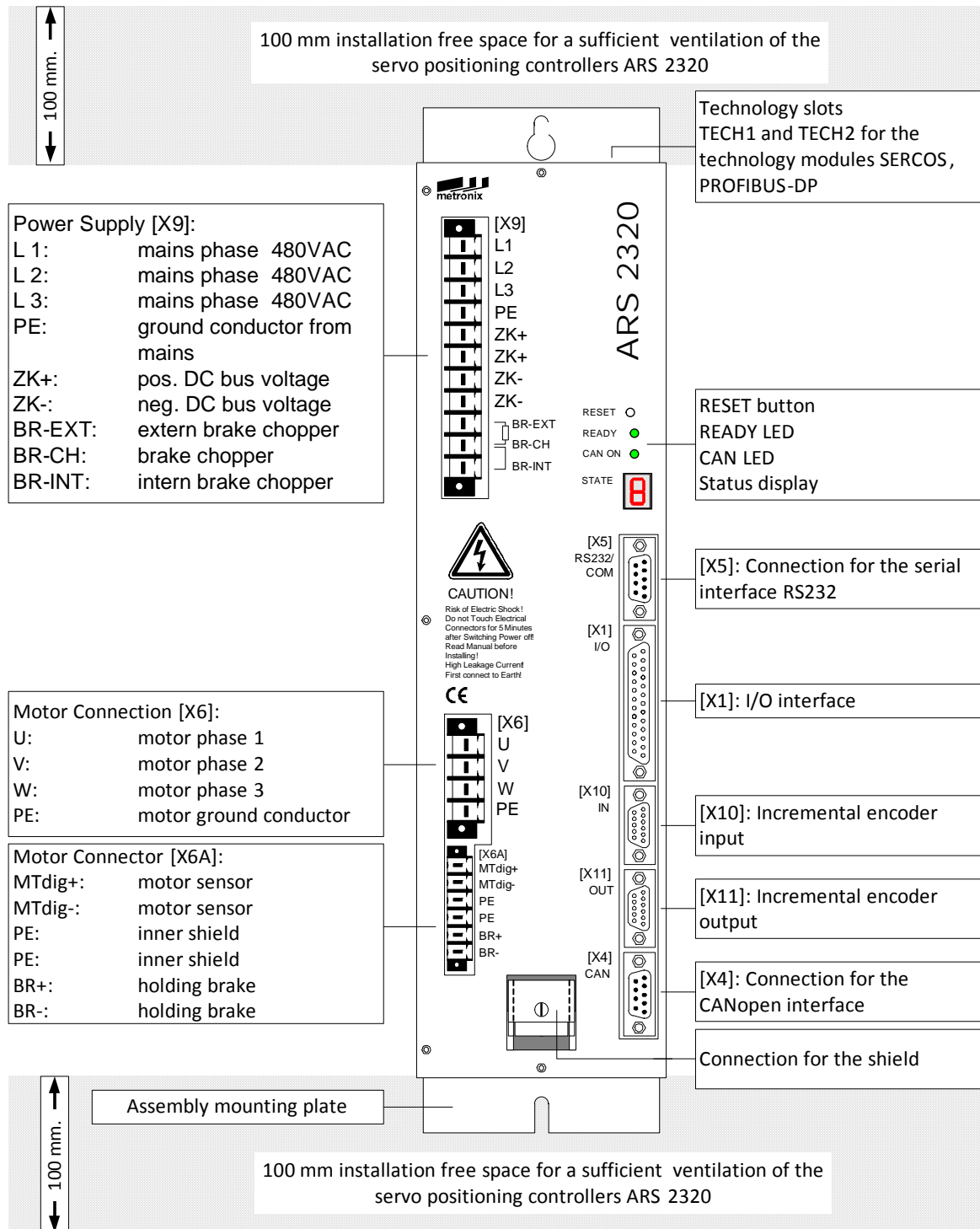


Figure 3: Servo positioning controller ARS 2320: Front view and Installation space

4.2 Mounting

The servo positioning controller ARS 2300 has attachment lugs on the top and the bottom of the device. These are used to mount the servo positioning controller vertically to a control cabinet plate. The lugs are part of the cooling body profile, thereby providing optimum heat transmission to the control cabinet plate.

Please use M5 screws for the mounting of the servo positioning controller 2320 and 2340.

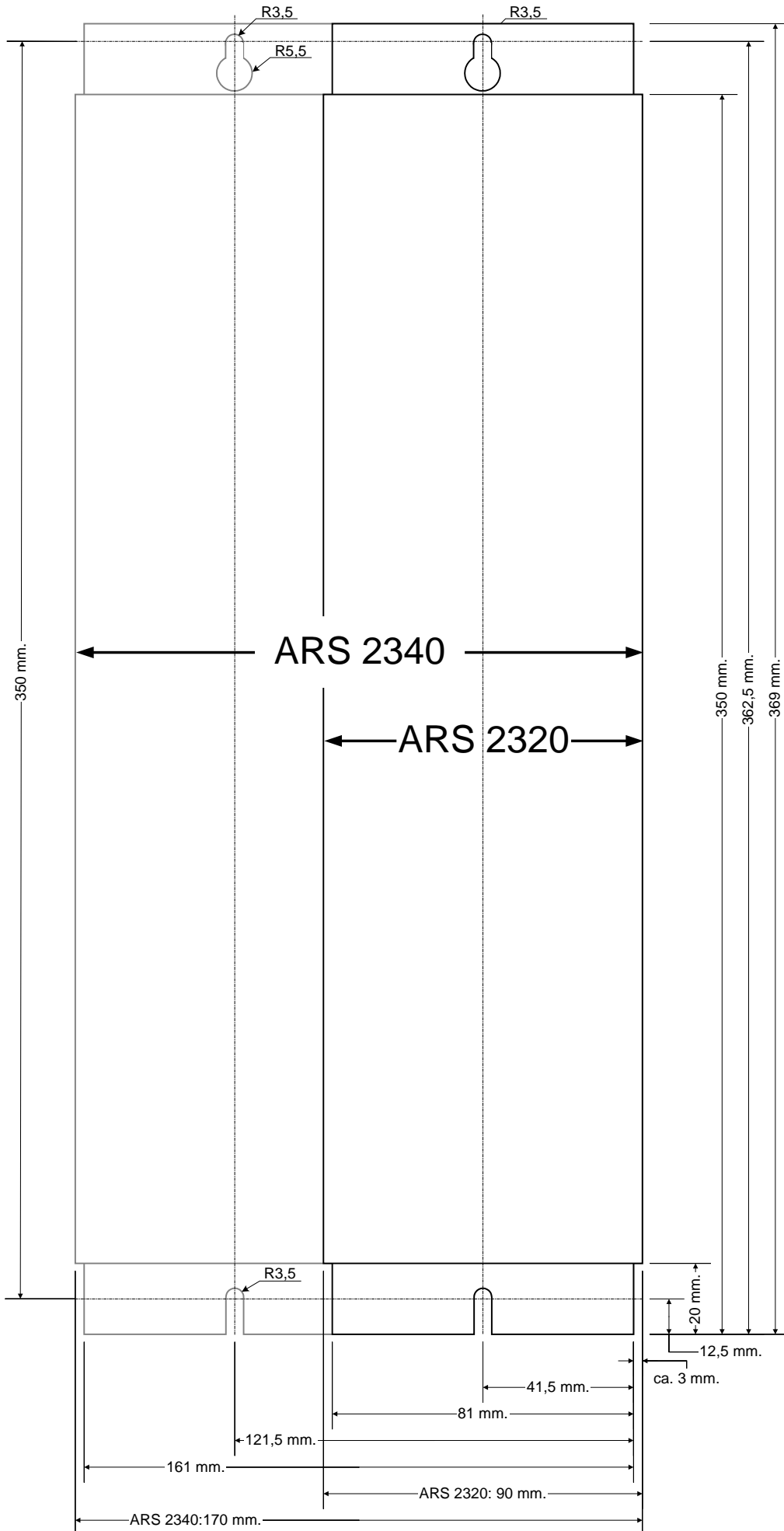


Figure 4: Servo positioning controller ARS 2300: Mounting plate

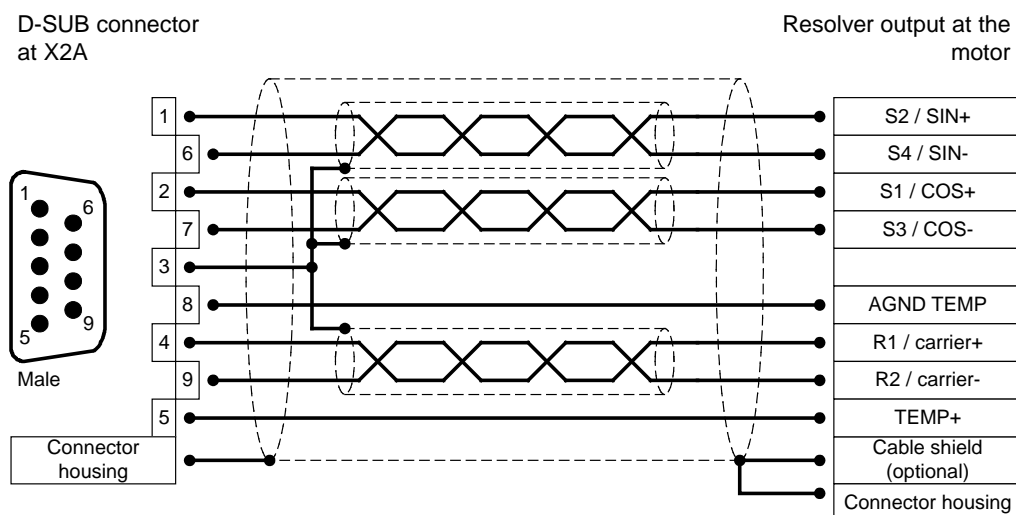
5 Electrical installation

5.1 Pin configuration I/O [X1]

| Pin No. | Denomination | Value | Specification |
|---------|--------------|--|---|
| 1 | AGND | 0V | Shield for analog signals, AGND |
| | 14 | AGND | Reference potential for analog signals |
| 2 | AIn0 | $U_{on} = \pm 10V$ $R_I \geq 30k\Omega$ | Setpoint input 0, differential, max. 30V input voltage |
| | 15 | #AIn0 | |
| 3 | Ain1 | $U_{on} = \pm 10V$ $R_I \geq 30k\Omega$ | Setpoint inputs 1 and 2, single ended, max. 30V input voltage |
| | 16 | Ain2 | |
| 4 | +VREF | +10V | Reference output for setpoint potentiometer |
| | 17 | AMON0 | $\pm 10V$ Analog monitor output 0 |
| 5 | AMON1 | $\pm 10V$ | Analog monitor output 1 |
| | 18 | +24V | 24V / 100mA 24V supply out |
| 6 | GND24 | corresponding GND | Reference potential for digital I/Os |
| | 19 | DIn0 | POS Bit0 Target selection positioning Bit0 |
| 7 | DIn1 | POS Bit1 | Target selection positioning Bit1 |
| | 20 | DIn2 | POS Bit2 Target selection positioning Bit2 |
| 8 | DIn3 | POS Bit3 | Target selection positioning Bit3 |
| | 21 | DIn4 | FG_E Power stage enable |
| 9 | DIn5 | FG_R | Controller enable |
| | 22 | DIn6 | END0 Input end switch 0 (locks $n > 0$) |
| 10 | DIn7 | END1 | Input end switch 1 (locks $n < 0$) |
| | 23 | DIn8 | START Input for positioning start |
| 11 | DIn9 | SAMP | High-speed input |
| | 24 | DOut0 / READY | 24V / 100mA Output operational |
| 12 | DOut1 | 24V / 100mA | Output freely programmable |
| | 25 | DOut2 | 24V / 100mA Output freely programmable |
| 13 | DOut3 | 24V / 100mA | Output freely programmable |

5.2 Pin configuration Resolver [X2A]

| Pin No. | Denomination | Value | Specification |
|---------|--------------|--|--|
| 1 | S2 | $3,5V_{RMS} / 5-10kHz$ | SINE trace signal, differential |
| 6 | S4 | $R_i > 5k\Omega$ | |
| 2 | S1 | $3,5V_{RMS} / 5-10kHz$ | COSINE trace signal, differential |
| 7 | S3 | $R_i > 5k\Omega$ | |
| 3 | AGND | 0V | Shield for signal pairs (inner shield) |
| 8 | MT- | GND | Reference potential temperature sensor |
| 4 | R1 | $7V_{RMS} / 5-10kHz$ $I_A \leq 150mA_{RMS}$ | Carrier signal for resolver |
| 9 | R2 | GND | |
| 5 | MT+ | $+3,3V / R_i=2k\Omega$ | Motor temperature sensor, normally closed contact, PTC, KTY... |



- ❖ The outer shield is always connected to PE (connector housing) on the controller side.
- ❖ The three inner shields are connected on one side of the servo positioning controller ARS 2300 to PIN 3 of [X2A].

5.3 Pin configuration Encoder [X2B]

At the 15-pole D-Sub connection [X2B], motors with encoder can be fed back. The possible incremental encoders for the encoder connection are divided into several groups.

- ❖ Standard incremental encoders with and without commutation signals
- ❖ Stegmann encoders: Single-turn SinCos encoders: SCS 60, SCS 70, SR 50, SR 60
- ❖ Stegmann encoders: Multi-turn SinCos encoders: SRM 50, SRM 60, SCM 60, SCM 70
- ❖ SinCoder encoders: SNS 50, SNS 60
- ❖ SinCos encoders for hollow-shaft motor drives: SCS-Kit 101, SCM-Kit 101, SHS 170
- ❖ Heidenhain ERN1085, ERN 1387, ECN1313, RCN220, RCN 723, RON786, ERO1285, etc.
- ❖ Encoders with EnDat interface

| Pin No | Incremental encoder with serial communication interface (e.g. EnDat, HIPERFACE) | | Analog incremental encoder | | Digital incremental encoder | |
|--------|---|---|---|---|---|---|
| | MT+ | U_SENS+ U_SENS- | US | GND | MT+ | U_SENS+ U_SENS- |
| 1 | Motor temperature sensor, normally closed contact, PTC, KTY... | Motor temperature sensor, normally closed contact, PTC, KTY... | Motor temperature sensor, normally closed contact, PTC, KTY... | Motor temperature sensor, normally closed contact, PTC, KTY... | Motor temperature sensor, normally closed contact, PTC, KTY... | Motor temperature sensor, normally closed contact, PTC, KTY... |
| 2 | Sensor cables for encoder supply | Sensor cables for encoder supply | Sensor cables for encoder supply | Sensor cables for encoder supply | Sensor cables for encoder supply | Sensor cables for encoder supply |
| 3 | Supply voltages for high-resolution incremental encoder | Supply voltages for high-resolution incremental encoder | Supply voltages for high-resolution incremental encoder | Supply voltages for high-resolution incremental encoder | Supply voltages for high-resolution incremental encoder | Supply voltages for high-resolution incremental encoder |
| 4 | Reference potential encoder supply and motor temperature sensor | Reference potential encoder supply and motor temperature sensor | Reference potential encoder supply and motor temperature sensor | Reference potential encoder supply and motor temperature sensor | Reference potential encoder supply and motor temperature sensor | Reference potential encoder supply and motor temperature sensor |
| 5 | | | | | | |
| 6 | | | | | | |
| 7 | | | | | | |
| 8 | | | | | | |
| 9 | | | | | | |
| 10 | | | | | | |
| 11 | | | | | | |
| 12 | | | | | | |
| 13 | | | | | | |
| 14 | | | | | | |
| 15 | | | | | | |

*) Heidenhain encoder: A = SIN_Z0; B = COS_Z0; C = SIN_Z1; D = COS_Z1

5.4 Pin configuration Safe Torque Off (STO) and 24V supply [X3]

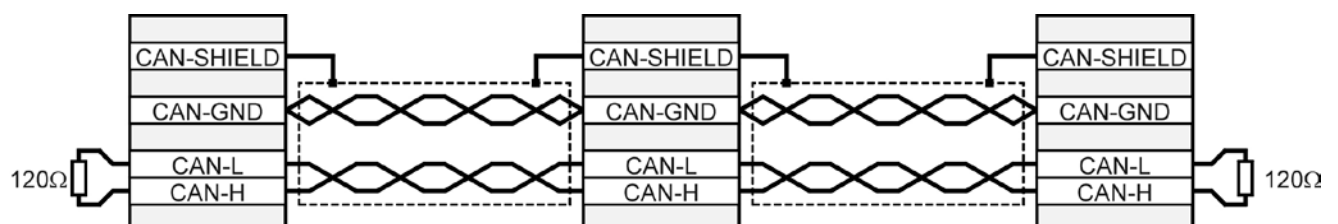
Further information to the safety function is in the product manual ARS 2320 and 2340 in chapter 6 "Functional safety technology".

| Pin No. | Denomination | Value | Specification |
|---------|--------------|--|--|
| 1 | 24V | 24VDC | 24VDC supply, led out (Without safety measures in accordance with category 3: Bridge pin 1 and 2) |
| 2 | REL | 0V / 24VDC | Setting and resetting of the relay for interrupting the driver supply of the output stage |
| 3 | 0V | 0V | Reference potential for PLC |
| 4 | ERR | 0V / 24 VDC | Signalling contact „Error on safty modul“ |
| 5 | NC1 | max 50VAC or 60VDC, switching voltage | Floating response contact of driver supply; normally closed contact |
| 6 | NC2 | | |

5.5 Pin configuration CAN [X4]

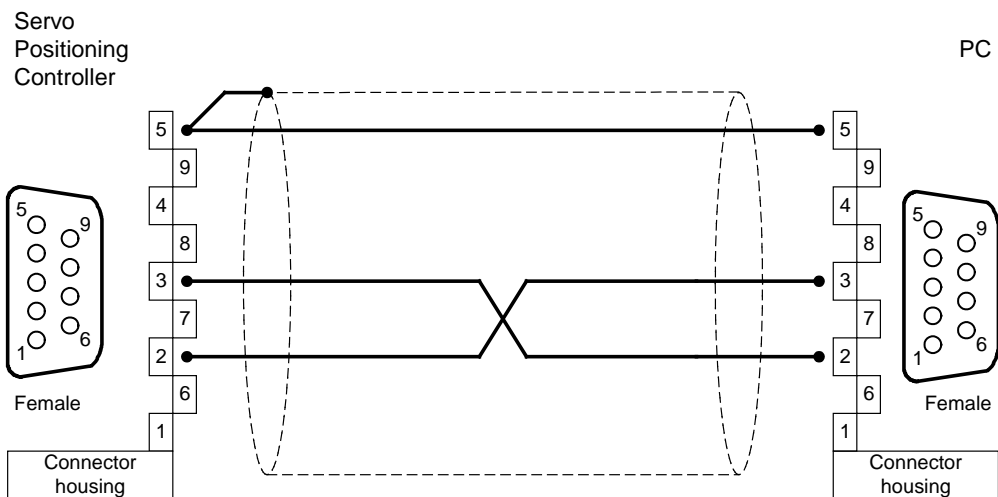
| Pin No. | Denomination | Value | Specification |
|---------|--------------|-------|--|
| 1 | - | - | Not occupied |
| 6 | GND | 0V | CAN-GND, galvanically connected to GND in controller |
| 2 | CANL | *) | CAN-Low signal line |
| 7 | CANH | *) | CAN-High signal line |
| 3 | GND | 0V | See Pin no. 6 |
| 8 | - | - | Not occupied |
| 4 | - | - | Not occupied |
| 9 | - | - | Not occupied |
| 5 | Cable shield | PE | Connection for cable shield |

*) External terminating resistor 120Ω required on both ends of the bus



5.6 Pin configuration RS232 [X5]

| Pin No. | Denomination | Value | Specification |
|---------|--------------|-------------------------|--|
| 1 | - | - | Not occupied |
| 6 | - | - | Not occupied |
| 2 | RxD | 10 V / $R_I > 2k\Omega$ | Receive line, RS232 specification |
| 7 | - | - | Not occupied |
| 3 | TxD | 10 V / $R_A < 2k\Omega$ | Transmitting line, RS232 specification |
| 8 | - | - | Not occupied |
| 4 | +RS485 | - | Reserve for option RS485 Interface |
| 9 | -RS485 | - | Reserve for option RS485 Interface |
| 5 | GND | 0V | Interfaces GND, galvanically connected to DGND |



5.7 Wiring diagram Motor [X6] and Power Supply [X9]

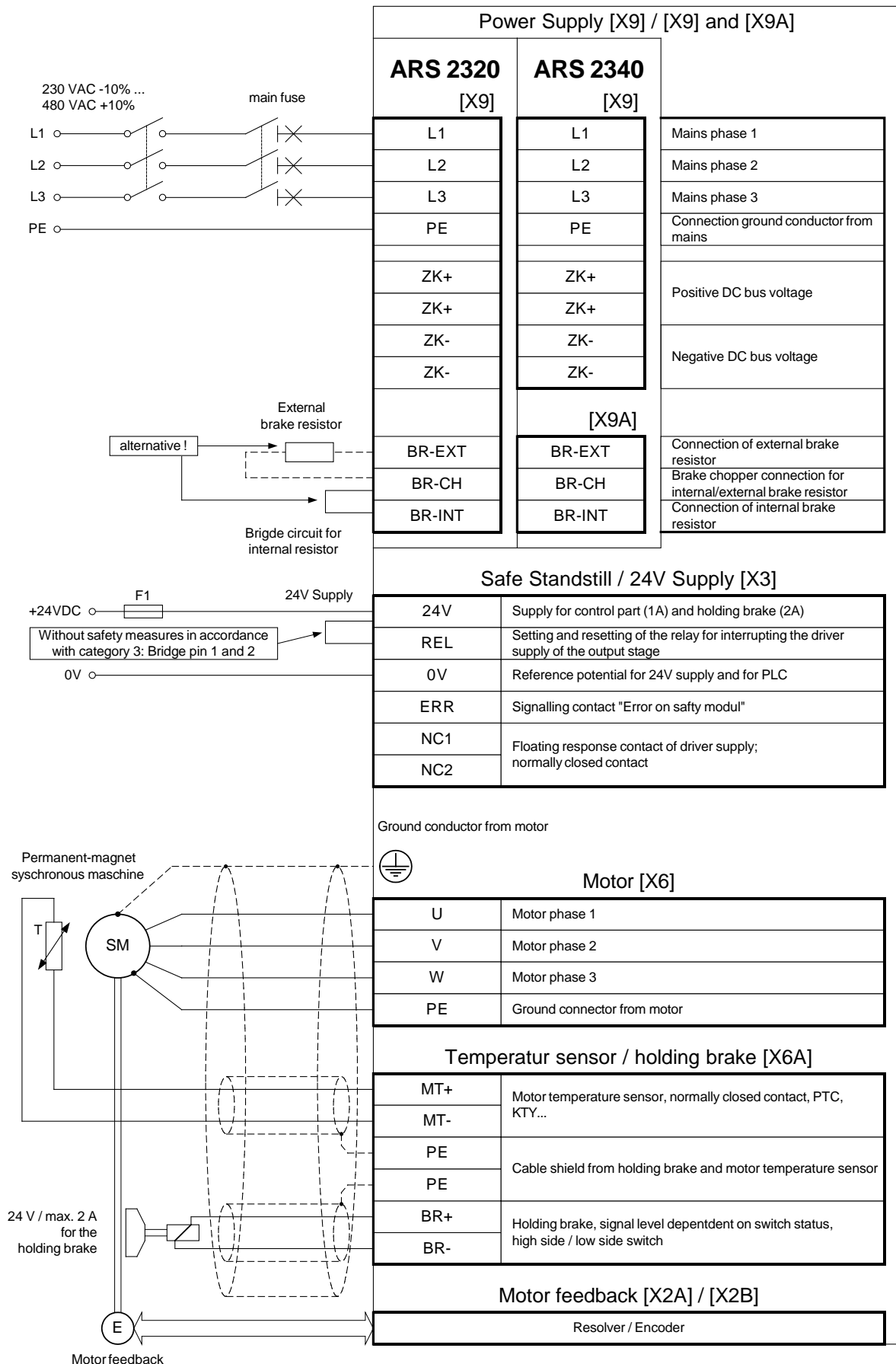


Figure 5: Connection to power supply [X9] and motor [X6]

The servo positioning controller ARS 2300 is connected to the supply voltage, the motor, the brake resistor and the holding brakes as shown in Figure 5. The operation of the servo positioning controller ARS 2300 requires a 24V supply source for the electronics, which is connected to the terminals +24V and 0V. The connection to the supply for the power output stage is either made to terminals L1, L2 and L3 for AC supply or to ZK+ and ZK- for DC supply.

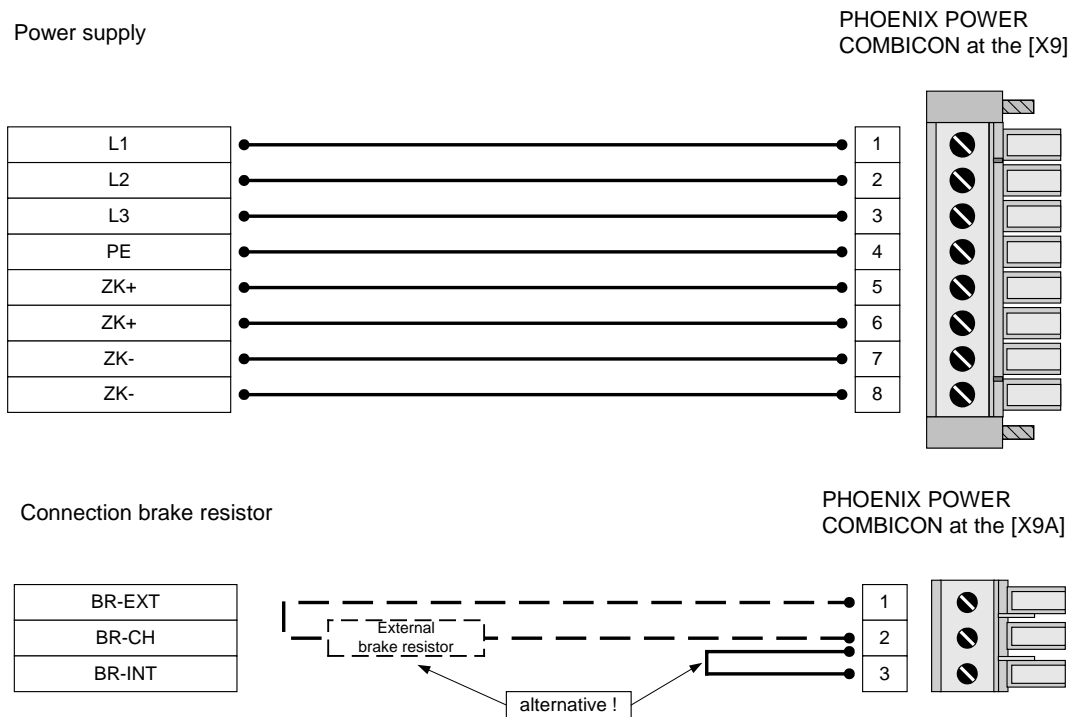


Figure 6: Servo positioning controller ARS 2320: Power supply [X9] and brake resistor [X9A]

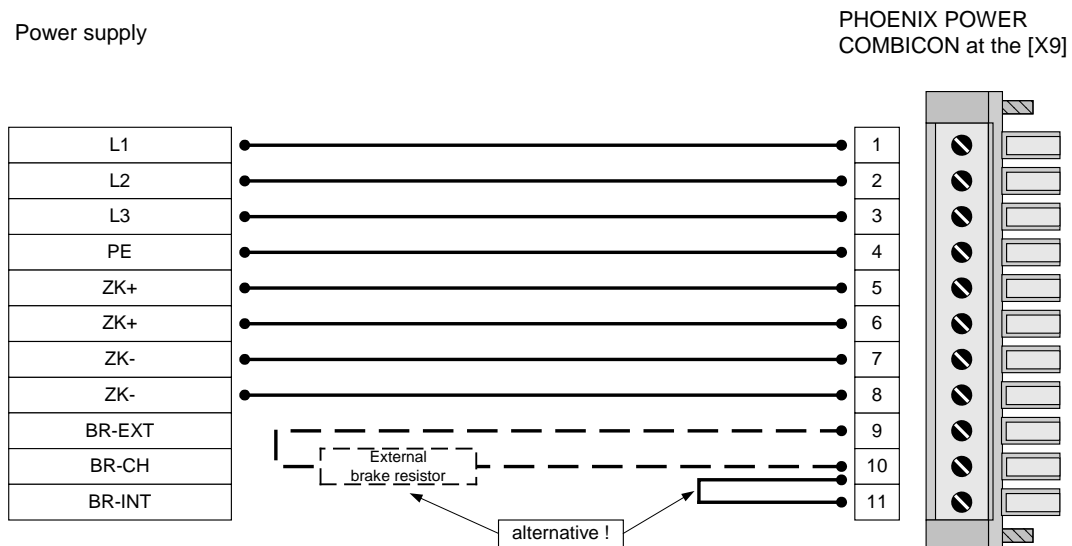


Figure 7: Servo positioning controller ARS 2340: Power supply and brake resistor [X9]

The motor is connected to terminals U,V,W. The motor temperature switch (PTC or normally closed contact) is connected to terminals MT+ and MT-, if it is lead into one cable together with the motor phases. If an analog temperature sensor (e.g. KTY81) is used in the motor, it is connected via the encoder cable to [X2A] or [X2B].

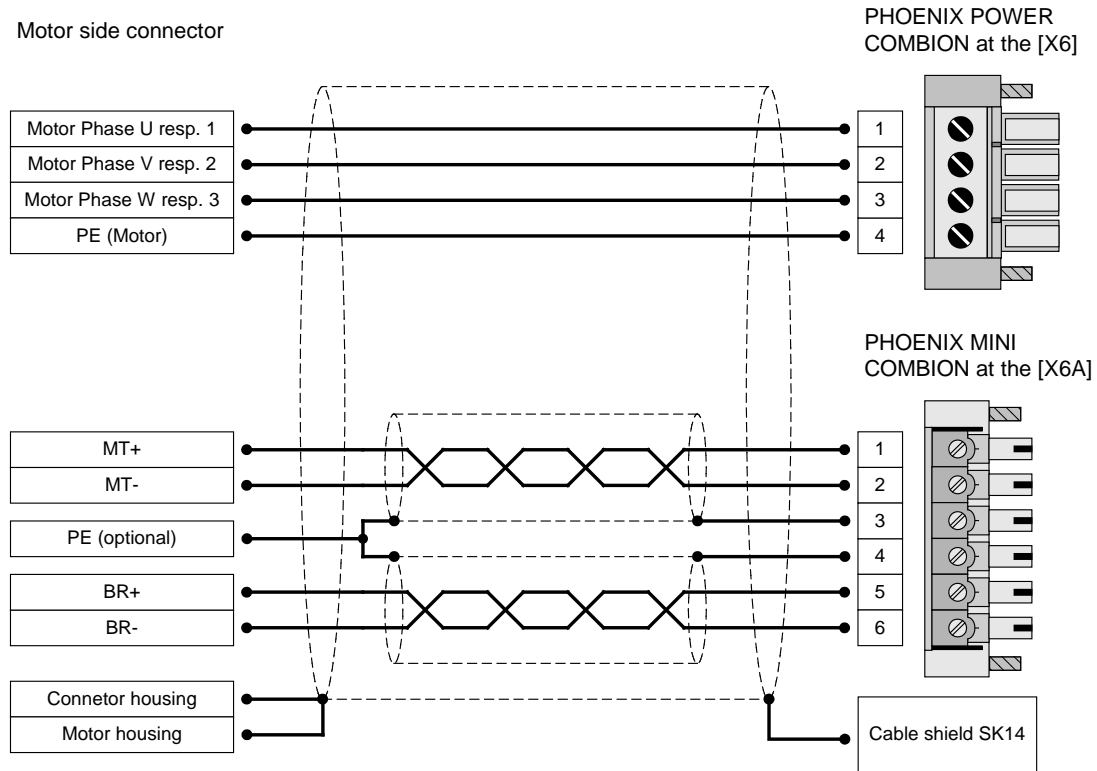


Figure 8: Servo positioning controller ARS 2320 and 2340: Motor [X6]

- ❖ Connect the inner shields to PIN 3 and 4 of [X6A]; maximum length 40 mm.
- ❖ Length of unshielded cores maximum 35 mm.
- ❖ Connect total shield on controller side flat to PE terminal; maximum length 40 mm.
- ❖ Connect total shield on motor side flat to connector or motor housing; maximum length 40 mm.



The cable shield of the motor cable must also be connected to the controller housing (PE screw terminal).

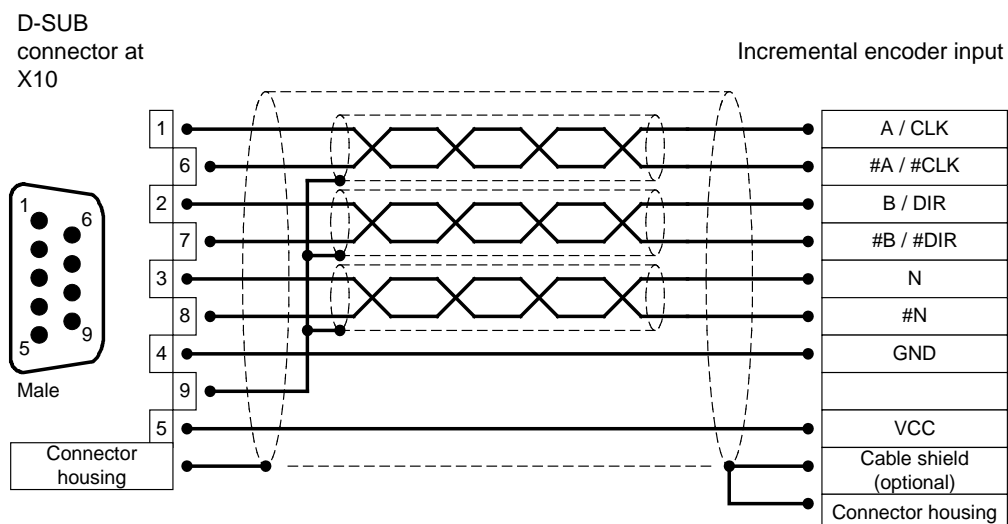
The connection of the shaft encoder via the D-Sub connector to [X2A] / [X2B] is roughly shown in Figure 5.

The servo positioning controller ARS 2300 must be connected to ground with its PE connection.

The ARS 2300 must be completely wired first. Only then may the operating voltages for the DC bus and the electronics supply be switched on. In the case of inversed wiring of the operating voltage connections, excessive operating voltage or in the case of confusing the connections for operating voltage and motor the servo positioning controller will be damaged.

5.8 Pin configuration Incremental Encoder Input [X10]

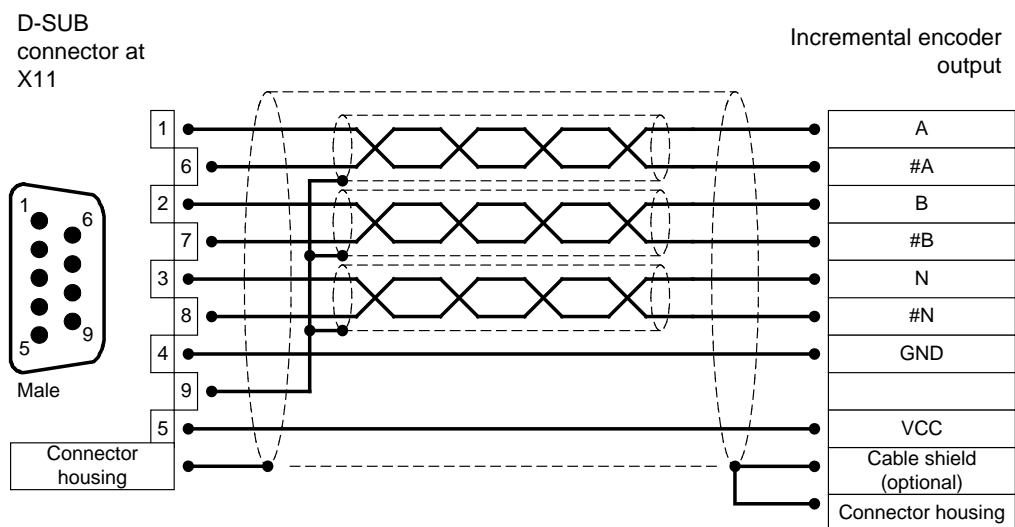
| Pin No. | Denomination | Value | Specification |
|---------|--------------|------------------------------|--|
| 1 | A / CLK | $5V / R_1 \approx 120\Omega$ | Incremental encoder signal A / Stepper motor signal CLK pos. polarity as per RS422 |
| 6 | #A / #CLK | $5V / R_1 \approx 120\Omega$ | Incremental encoder signal A / Stepper motor signal CLK neg. polarity as per RS422 |
| 2 | B / DIR | $5V / R_1 \approx 120\Omega$ | Incremental encoder signal B / Stepper motor signal DIR pos. polarity as per RS422 |
| 7 | #B / #DIR | $5V / R_1 \approx 120\Omega$ | Incremental encoder signal B / Stepper motor signal DIR neg. polarity as per RS422 |
| 3 | N | $5V / R_1 \approx 120\Omega$ | Incremental encoder index pulse N pos. polarity as per RS422 |
| 8 | #N | $5V / R_1 \approx 120\Omega$ | Incremental encoder index pulse N neg. polarity as per RS422 |
| 4 | GND | - | Supply GND for encoder |
| 9 | GND | - | Shield for the connection cable |
| 5 | VCC | $+5V \pm 5\%$ 100mA | Auxiliary supply, load with 100mA maximum, short circuit-proof |



5.9 Pin configuration Incremental Encoder Output [X11]

| Pin No. | Denomination | Value | Specification |
|---------|--------------|------------------------------|--|
| 1 | A | 5V / R _A ≈ 66Ω *) | Incremental encoder signal A |
| 6 | #A | 5V / R _A ≈ 66Ω *) | Incremental encoder signal #A |
| 2 | B | 5V / R _A ≈ 66Ω *) | Incremental encoder signal B |
| 7 | #B | 5V / R _A ≈ 66Ω *) | Incremental encoder signal #B |
| 3 | N | 5V / R _A ≈ 66Ω *) | Incremental encoder index pulse N |
| 8 | #N | 5V / R _A ≈ 66Ω *) | Incremental encoder index pulse #N |
| 4 | GND | - | Reference GND for encoder |
| 9 | GND | - | Shield for connection cable |
| 5 | VCC | +5V ±5% 100mA | Auxiliary supply, to be loaded with maximal 100mA, short-circuit-proof |

*) The value for R_A is the differential output resistance



6 EMC-compliant cabling

The following must be considered for an EMC-compliant setup of the drive system:

- ❖ In the first environment, the servo positioning controller ARS 2300 must be installed in a steel switch cabinet. In most cases a standard model will sufficiently attenuate emitted interference. The cable shields must be connected with the switch cabinet housing by means of metal cable glands.
- ❖ In the second environment the servo positioning controller ARS 2300 can also be used without a steel control cabinet. Installation in a control cabinet (possibly plastic), however, is still necessary to guarantee proper usage.
- ❖ The control cabinet bed plate must be conducting (zinc-coated design). The imperative central grounding point should also be located on the control cabinet bed plate.
- ❖ The signal lines must be as far away from the power cables as possible. They should not be placed parallel. If intersections cannot be avoided, they should be perpendicular (i.e. at a 90° angle), if possible.
- ❖ In order to keep the leakage currents and the losses in the motor connection cable as small as possible, the servo positioning controller ARS 2300 should be located as close to the motor as possible (see also the following chapter).
- ❖ The shield of the motor cable is connected to the housing of the servo positioning controller ARS 2300 (shield connection terminal). In the first environment the shield of the motor cable also has to be connected to the control cabinet housing by means of metal cable glands.
- ❖ The mains-end PE connection is connected to the PE connection point of the supply connection [X9].
- ❖ The inner PE conductor of the motor cable is connected to the PE connection point of the motor connection [X6].
- ❖ Motor cable and angle encoder cable must be shielded.
- ❖ Unshielded signal and control lines should not be used. If their use is inevitable they should at least be twisted.
- ❖ Even shielded cables have short unshielded ends (unless shielded connector housings are used). In general, the following applies:
 - Connect the inner shields to the associated pins of the connectors. Maximum length: 40 mm.
 - Maximum length of unshielded cores: 35 mm.
- ❖ The following applies to the motor cable:
 - Strip the motor cable as shown in figur 8:
 1. Strip 30 mm of the insulation of the motor cable 240 mm away from the end of the cable.
 2. Strip 140 mm of the insulation of the motor cable at the end of the cable.
 3. Remove 140 mm of the outer motor cable shield of the insulated cable.
 4. Shorten the cables for the motor phases and the protective ground conductor of the motor to 90 mm.
 - Connect the outer stripped motor cable shield (30 mm long) on the controller side flat to the motor shield terminal.
 - Connect the motor temperature sensor, the holding brake and the inner shields to connector [X6A].
 - Connect the motor phase and the protective ground conductor of the motor to connector [X6].
 - Connect the shield on the motor side flat to the connector or motor housing. Maximum length: 40 mm.

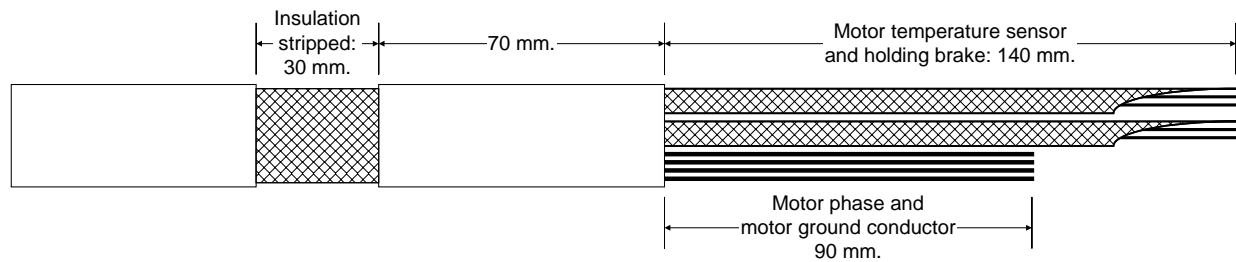


Figure 9: Motor cable: Lengths of shields and cables



DANGER!

For safety reasons, all PE ground conductors must be connected prior to initial operation.

The EN 50178 regulations for protective earthing must be complied with during installation!

6.1 Operation with long motor cables

In applications involving long motor cables and/or unsuitable motor cables with an inadvertently high cable capacity, the filters may be thermally overloaded. To avoid such problems we highly recommend the following procedure for applications that require long motor cables:

- ❖ As of a cable length of more than 50 m, only use cable with less than 150 pF/m (capacitance per unit length) between the motor phase and the shield!
(Please contact your motor cable supplier if necessary)
- ❖ Lower the power stage clock frequency when using cable lengths of 50 m or longer.

Both measures are also good for the EMC behavior of the entire drive:

The servo positioning controller generates less and less severe interference and the emission of interference into the mains is reduced.