

# ***EPOS2 P 24/5***

***Programmable Positioning Controller***

***Hardware Reference***



[epos.maxonmotor.com](http://epos.maxonmotor.com)

***Document ID: rel5876***

## PLEASE READ THIS FIRST



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

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

We have tried to provide you with all information necessary to install and commission the equipment in a **secure, safe and time-saving** manner. Our main focus is ...

- to familiarize you with all relevant technical aspects,
- to let you know the easiest way of doing,
- to alert you of any possibly dangerous situation you might encounter or that you might cause if you do not follow the description,
- to **write as little** and to **say as much** as possible and
- not to bore you with things you already know.

Likewise, we tried to skip repetitive information! Thus, you will find things **mentioned just once**. If, for example, an earlier mentioned action fits other occasions you then will be directed to that text passage with a respective reference.



***Follow any stated reference – observe respective information – then go back and continue with the task!***

## PREREQUISITES FOR PERMISSION TO COMMENCE INSTALLATION

The **EPOS2 P 24/5** is considered as partly completed machinery according to EU directive 2006/42/EC, Article 2, Clause (g) and therefore **is intended to be incorporated into or assembled with other machinery or other partly completed machinery or equipment**.



***You must not put the device into service, ...***

- unless you have made completely sure that the other machinery – the surrounding system the device is intended to be incorporated to – fully complies with the requirements stated in EU directive 2006/42/EC!
- unless the surrounding system fulfills all relevant health and safety aspects!
- unless all respective interfaces have been established and fulfill the stated requirements!

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# 1 About this Document

## 1.1 Intended Purpose

The purpose of the present document is to familiarize you with the described equipment and the tasks on safe and adequate installation and/or commissioning.

Observing the described instructions in this document will help you ...

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

Use for other and/or additional purposes is not permitted. maxon motor, the manufacturer of the equipment described, does not assume any liability for loss or damage that may arise from any other and/or additional use than the intended purpose.

## 1.2 Target Audience

This document is meant for trained and skilled personnel working with the equipment described. It conveys information on how to understand and fulfill the respective work and duties.

This document is a reference book. It does require particular knowledge and expertise specific to the equipment described.

## 1.3 How to use

Take note of the following notations and codes which will be used throughout the document.

Notation	Explanation
(n)	referring to an item (such as order number, list item, etc.)
→	denotes “see”, “see also”, “take note of” or “go to”

Table 1-1 Notations used in this Document

## 1.4 Symbols and Signs

In the course of the present document, the following symbols and signs will be used.







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

Table 1-2 Symbols & Signs

## 1.5 Trademarks and Brand Names

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

Brand Name	Trademark Owner
Adobe® Reader®	© Adobe Systems Incorporated, USA-San Jose, CA
CANopen® CiA®	© CiA CAN in Automation e.V, DE-Nuremberg
Micro-Fit™ Mini-Fit Jr.™	© Molex, USA-Lisle, IL

Table 1-3 Brand Names and Trademark Owners

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## 1.6 Copyright

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## 2 Introduction

The present document provides you with information on the EPOS2 P 24/5 Programmable Positioning Controller's hardware. It contains...

- performance data and specifications,
- information on connections and pin assignment and
- wiring examples.

maxon motor control's EPOS2 P 24/5 is a small-sized, full digital and free programmable positioning control unit. Due to its flexible and high efficient power stage, the EPOS2 P 24/5 drives brushed DC motors with digital encoder as well as brushless EC motors with digital Hall sensors and encoder.

The sinusoidal current commutation by space vector control offers to drive brushless EC motors with minimal torque ripple and low noise. The integrated position, velocity and current control functionality allows sophisticated positioning applications. The EPOS2 P 24/5 is programmable with a very efficient software tool. The programming languages are according to IEC 61131-3 standard. The built-in CANopen interface allows the design of an easy-to-use standalone multiple axis system, particularly with standard maxon EPOS controllers. In addition, the unit can be operated via any USB or RS232 communication port.

Find the latest edition of the present document, as well as additional documentation and software to the EPOS2 P 24/5 Programmable Positioning Controller also on the Internet: →[www.maxonmotor.com](http://www.maxonmotor.com)

### 2.1 Documentation Structure

The present document is part of a documentation set. Please find below an overview on the documentation hierarchy and the interrelationship of its individual parts:

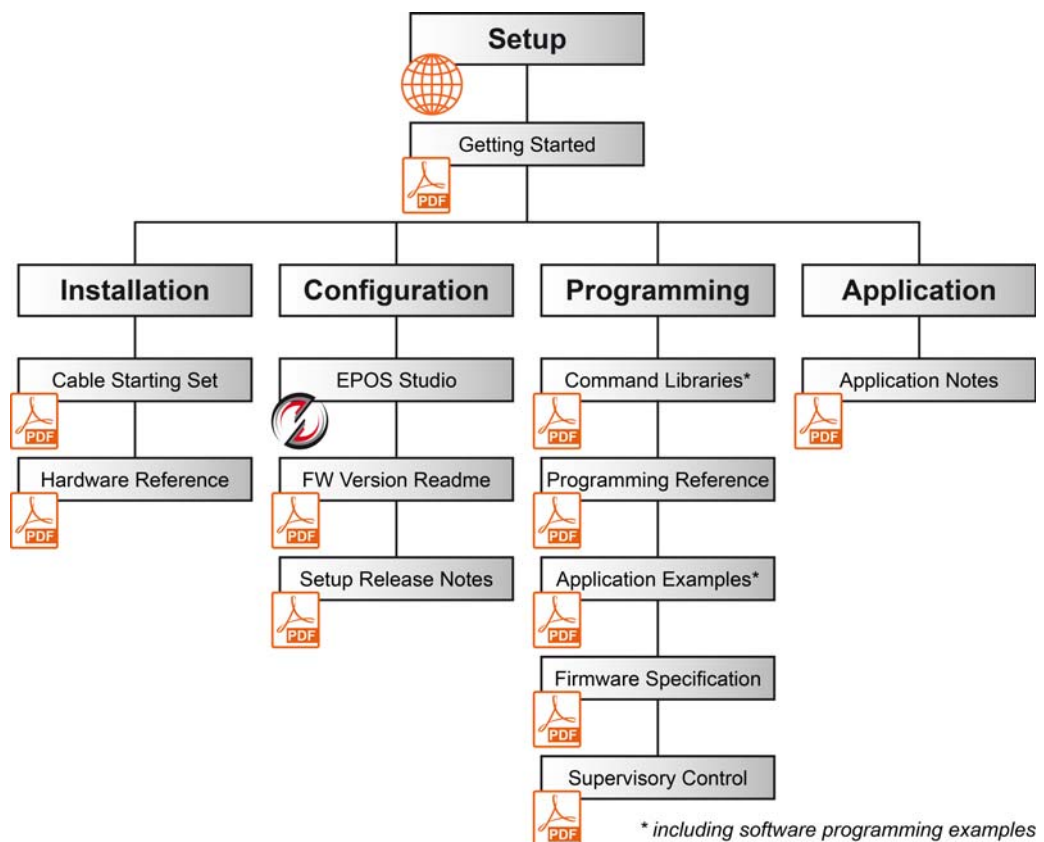


Figure 2-1 Documentation Structure

## 2.2 Safety Precautions

Prior continuing ...

- make sure you have read and understood chapter “ PLEASE READ THIS FIRST” on page A-2,
- do not engage with any work unless you possess the stated skills (→chapter “1.2 Target Audience” on page 1-5),
- refer to chapter “1.4 Symbols and Signs” on page 1-6 to understand the subsequently used indicators,
- you must observe any regulation applicable in the country and/or at the site of implementation with regard to health and safety/accident prevention and/or environmental protection,
- take note of the subsequently used indicators and follow them at all times.



### DANGER

#### **High Voltage and/or Electrical Shock**

#### **Touching live wires causes death or serious injuries!**

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



#### **Requirements**

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



#### **Best Practice**

- For initial operation, make sure that the motor is free running. If not the case, mechanically disconnect the motor from the load.



#### **Maximal permitted Supply Voltage**

- Make sure that supply power is between 11...24 VDC.
- Supply voltages above 30 VDC will destroy the unit.
- Wrong polarity will destroy the unit.



#### **Electrostatic Sensitive Device (ESD)**

- Make sure to wear working cloth in compliance with ESD.
- Handle device with extra care.

### 3 Technical Data

#### 3.1 Electrical Data

Rating	
Nominal power supply voltage $V_{CC}$	11...24 VDC
Nominal logic supply voltage $V_C$ (optional)	11...24 VDC
Absolute minimum supply voltage	10 VDC
Absolute max. supply voltage	28 VDC
Max. output voltage	$0.9 \cdot V_{CC}$
Max. output current $I_{max}$ (<1sec)	10 A
Continuous output current $I_{cont}$	5 A
Switching frequency	50 kHz
Max. efficiency	92%
Sample rate PI – current controller	10 kHz
Sample rate PI – speed controller	1 kHz
Sample rate PID – positioning controller	1 kHz
Max. speed @ sinusoidal commutation (motors with 1 pole pair)	25 000 rpm
Max. speed @ block commutation (motors with 1 pole pair)	100 000 rpm
Built-in motor choke per phase	15 $\mu$ H / 5 A

Table 3-4 Electrical Data – Rating

Inputs	
Hall sensor signals	Hall sensor 1, Hall sensor 2 and Hall sensor 3 for Hall effect sensor ICs (Schmitt trigger with open collector output)
Encoder signals	A, A\, B, B\, I, I\ (max. 5 MHz) internal line receiver EIA RS422 Standard
Digital Input 1 (“General Purpose”)	+3...+24 VDC ( $R_i = 8 \text{ k}\Omega$ )
Digital Input 2 (“General Purpose”)	+3...+24 VDC ( $R_i = 8 \text{ k}\Omega$ )
Digital Input 3 (“General Purpose”)	+3...+24 VDC ( $R_i = 8 \text{ k}\Omega$ )
Digital Input 4 (“Home Switch”)	+9...+24 VDC ( $R_i = 4 \text{ k}\Omega$ )
Digital Input 5 (“Positive Limit Switch”)	+9...+24 VDC ( $R_i = 4 \text{ k}\Omega$ )
Digital Input 6 (“Negative Limit Switch”)	+9...+24 VDC ( $R_i = 4 \text{ k}\Omega$ )
Analog Input 1	resolution 12-bit 0...+5 V ( $R_i = 47 \text{ k}\Omega$ )
Analog Input 2	resolution 12-bit 0...+5 V ( $R_i = 47 \text{ k}\Omega$ )
CAN ID (CAN identification)	ID 1...127 configurable via DIP switch or software

Table 3-5 Electrical Data – Inputs

Outputs	
Digital Output 1 (“General Purpose”), open drain	max. 24 VDC ( $I_L < 100 \text{ mA}$ )
Digital Output 2 (“General Purpose”), open drain	max. 24 VDC ( $I_L < 100 \text{ mA}$ )
Digital Output 3 (“General Purpose”), open drain	max. 24 VDC ( $I_L < 100 \text{ mA}$ )
Digital Output 4 (“Brake”) open drain	max. 24 VDC ( $I_L < 1000 \text{ mA}$ )

Table 3-6 Electrical Data – Outputs

Voltage Outputs	
Encoder supply voltage	+5 VDC ( $I_L < 100$ mA)
Hall sensors supply voltage	+5 VDC ( $I_L < 30$ mA)
Auxiliary output voltage	$V_{cc}$ ( $I_L < 1300$ mA)

Table 3-7 Electrical Data – Voltage Outputs

Motor Connections	
maxon EC motor	maxon DC motor
Motor winding 1	+ Motor
Motor winding 2	- Motor
Motor winding 3	

Table 3-8 Electrical Data – Motor Connections

Interfaces		
RS232	RxD; TxD	max. 115 200 bit/s
USB 2.0 / USB 3.0	Data+; Data-	full speed
CAN-S	CAN_H (high); CAN_L (low)	max. 1 Mbit/s
CAN-M	CAN_H (high); CAN_L (low)	max. 1 Mbit/s

Table 3-9 Electrical Data – Interfaces

Memory	
Total memory	1 MByte
Application memory (free programmable)	768 kByte
Non-volatile memory	4 kByte

Table 3-10 Electrical Data – Memory

Status Indicators	
Operation	green LED
Error	red LED
Program status	blue LED
Program error	orange LED

Table 3-11 Electrical Data – LEDs

Connections		
Power Supply	On board: Suitable plug: Suitable terminal:	dual row male header (2 poles) Molex Mini-Fit Jr dual row female receptacle (2 poles) Molex Mini-Fit Jr. 39-01-2020 female crimp terminal Molex Mini-Fit Jr. 44476-xxxx (AWG 16-20)
Motor	On board: Suitable plug: Suitable terminal:	dual row male header (4 poles) Molex Mini-Fit Jr dual row female receptacle (4 poles) Molex Mini-Fit Jr. 39-01-2040 female crimp terminal Molex Mini-Fit Jr. 44476-xxxx (AWG 16-20)
Hall	On board: Suitable plug: Suitable terminal:	dual row male header (6 poles) Molex Micro-Fit 3.0 dual row female receptacle (6 poles) Molex Micro-Fit 3.0 430-25-0600 female crimp terminal Molex Micro-Fit 3.0 43030-xxxx (AWG 20-30)
Signal	On board: Suitable plug: Suitable terminal:	dual row male header (16 poles) Molex Micro-Fit 3.0 dual row female receptacle (12 poles) Molex Micro-Fit 3.0 430-25-1600 female crimp terminal Molex Micro-Fit 3.0 43030-xxxx (AWG 20-30)
RS232	On board: Suitable plug: Suitable terminal:	dual row male header (6 poles) Molex Micro-Fit 3.0 dual row female receptacle (6 poles) Molex Micro-Fit 3.0 430-25-0600 female crimp terminal Molex Micro-Fit 3.0 43030-xxxx (AWG 20-30)
USB	On board: Suitable plug:	USB connector type mini B jack (5 poles) Standard USB cable with type mini B plug connector (5 poles)
CAN-S	On board: Suitable plug: Suitable terminal:	dual row male header (4 poles) Molex Micro-Fit 3.0 dual row female receptacle (4 poles) Molex Micro-Fit 3.0 430-25-0400 female crimp terminal Molex Micro-Fit 3.0 43030-xxxx (AWG 20-30)
CAN-M	On board: Suitable plug: Suitable terminal:	dual row male header (4 poles) Molex Micro-Fit 3.0 dual row female receptacle (4 poles) Molex Micro-Fit 3.0 430-25-0400 female crimp terminal Molex Micro-Fit 3.0 43030-xxxx (AWG 20-30)
Encoder	On board: Suitable locking clip:	Plug DIN41651 (10 poles) for flat band cable, pitch 1.27mm, AWG 28 Tyco C42334-A421-C42 (right) / Tyco C42334-A421-C52 (left)

Table 3-12 Electrical Data – Connections

3.2 Mechanical Data

Mechanical Data	
Weight	approx. 180 g
Dimensions (L x W x H)	105 x 83 x 24 mm
Mounting plate	for M3 screws

Table 3-13 Mechanical Data

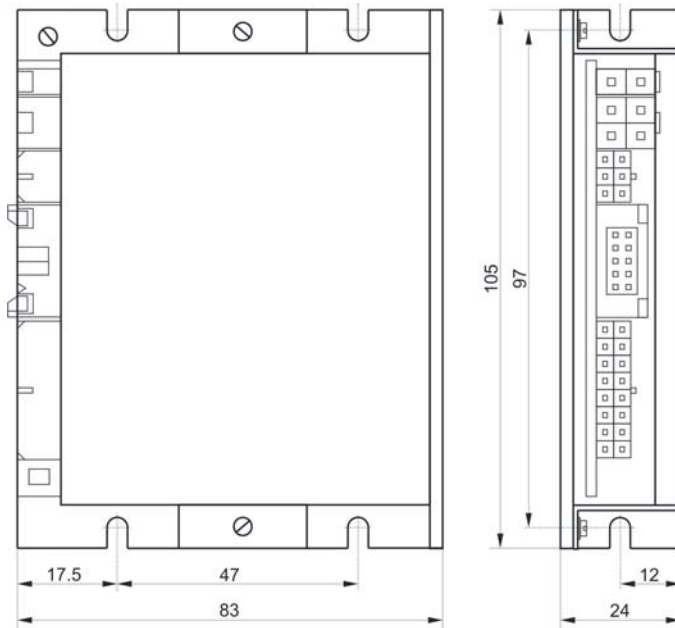


Figure 3-2 Dimensional Drawing [mm]

### 3.3 Environmental Conditions

Environmental Condition		
Temperature	Operation	-10...+55 °C
	Extended Range *1)	+55...+83 °C / Derating: → Figure 3-3
	Storage	-40...+85 °C
Altitude *2)	Operation	0...10'000 m MSL
Humidity		5...90% (condensation not permitted)

\*1) Operation within the extended range (temperature and altitude) is permitted. However, a respective derating (declination of output current  $I_{cont}$ ) as to the stated values will apply.

\*2) Operating altitude in meters above Mean Sea Level, MSL.

Table 3-14 Environmental Conditions

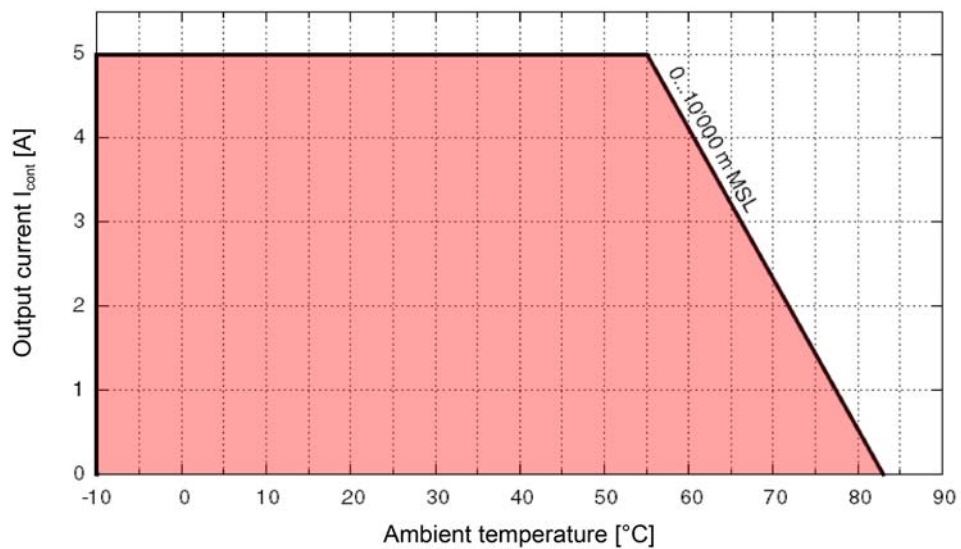


Figure 3-3 Derating Output Current

### 3.4 Order Details

Order Details	
EPOS2 P 24/5	Order number 378308

Table 3-15 Order Details

3.5 Standards

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



**Important Notice**

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

Electromagnetic Compatibility		
Generic Standards	IEC/EN 61000-6-2	Immunity for industrial environments
	IEC/EN 61000-6-3	Emission standard for residential, commercial and light-industrial environments
Applied Standards	IEC/EN 61000-6-3 IEC/EN 55022 (CISPR22)	Radio disturbance characteristics / radio interference
	IEC/EN 61000-4-2	Electrostatic discharge immunity test 8 kV/6 kV
	IEC/EN 61000-4-3	Radiated, radio-frequency, electromagnetic field immunity test >10 V/m
	IEC/EN 61000-4-4	Electrical fast transient/burst immunity test ±1 kV/±2 kV
	IEC/EN 61000-4-6	Immunity to conducted disturbances, induced by radio-frequency fields 10 Vrms
	IEC/EN 61000-4-8	Power frequency magnetic field 30 A/m
Others		
Environmental Standards	IEC/EN 60068-2-6	Environmental testing – Test Fc: Vibration (sinusoidal, 10...500 Hz, 20 m/s <sup>2</sup> )
	MIL-STD-810F	Random transport (10...500 Hz up to 1.05 g <sub>rms</sub> )
Safety Standards	UL File Number E187447 and E232940; unassembled printed circuit board	
Reliability	MIL-HDBK-217F	Reliability prediction of electronic equipment Environment: Ground, benign Ambient temperature: 298 K (25 °C) Component stress: In accordance with circuit diagram and nominal power Mean Time Between Failures (MTBF): 320'814 hours

Table 3-16 Standards



## 4 Connections



Figure 4-4 Interfaces – Designations and Location

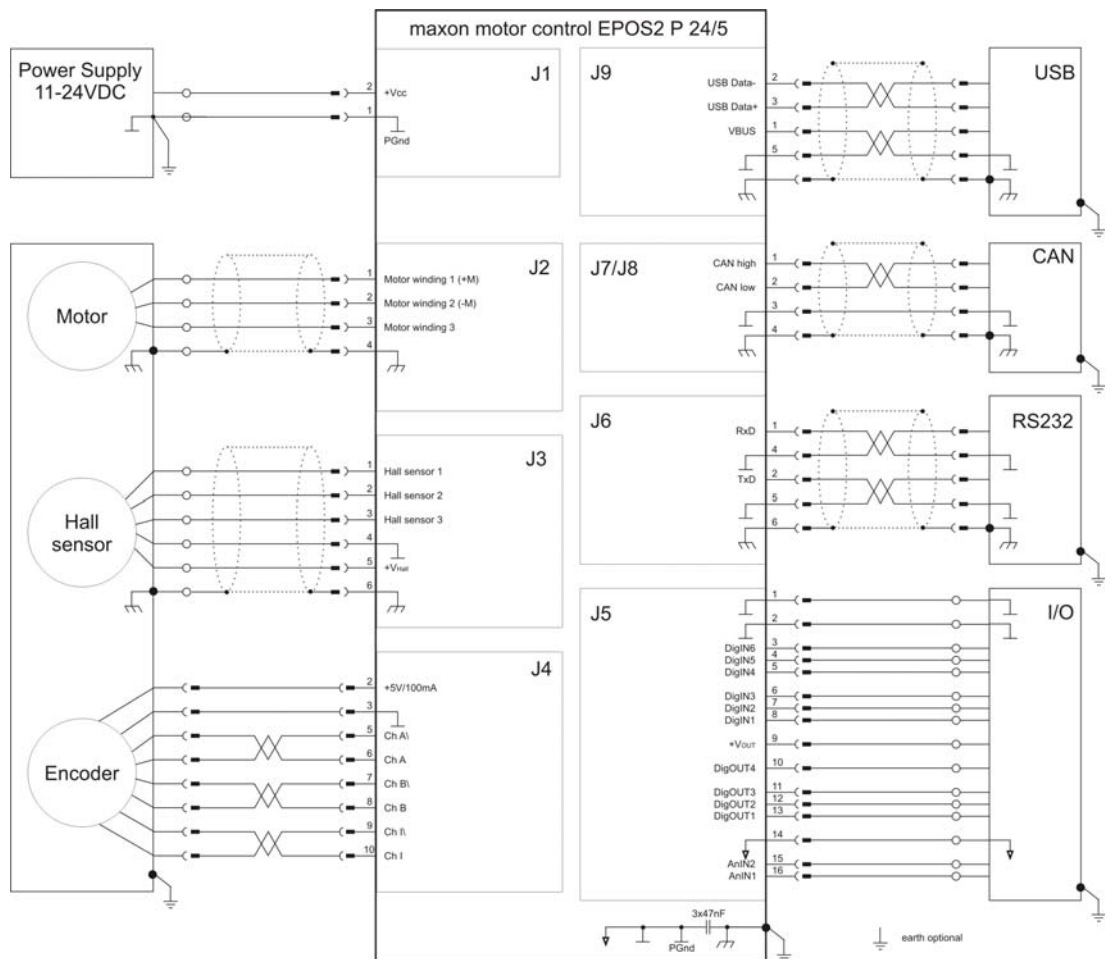


Figure 4-5 Wiring Diagram

## 4.1 Power Supply Connector (J1)



### **Best Practice**

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

### 4.1.1 Determination of Power Supply

Basically, any power supply may be used, provided it meets below stated minimal requirements.

Power Supply Requirements	
Output voltage	$V_{CC}$ min. 11 VDC; $V_{CC}$ max. 24 VDC
Absolute output voltage	min. 10 VDC; max. 28 VDC
Output current	Depending on load (continuous max. 5 A / acceleration, short-time max. 10 A)

- 1) Calculate required voltage under load using following scheme (the formula takes a max. PWM cycle of 90% and a max. voltage drop of -1 V at EPOS2 P 24/5 into account):

#### Known values:

- Operating torque  $M_B$  [mNm]
- Operating speed  $n_B$  [ $\text{min}^{-1}$ ]
- Nominal motor voltage  $U_N$  [Volt]
- Motor no-load speed at  $U_N$ ,  $n_0$  [ $\text{min}^{-1}$ ]
- Speed/torque gradient of the motor  $\Delta n/\Delta M$  [ $\text{min}^{-1}$  mNm $^{-1}$ ]

#### Sought value:

- Supply voltage  $V_{CC}$  [Volt]

#### Solution:

$$V_{CC} = \frac{U_N}{n_0} \cdot \left( n_B + \frac{\Delta n}{\Delta M} \cdot M_B \right) \cdot \frac{1}{0.9} + 1 [V]$$

- 2) Choose power supply capable as to above calculation. Thereby consider:
  - a) During braking of the load, the power supply must be capable of buffering the fed back energy, e.g. in a capacitor.
  - b) When using an electronically stabilized power supply, observe that the overcurrent protection must not be activated in any operating state.

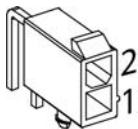


Figure 4-6 Power Connector (J1)

Pin	Signal	Description
1	Power_Gnd	Ground of supply voltage
2	+ $V_{CC}$	Power supply voltage +11...+24 VDC

<b>Accessories</b>	Cable	Power Cable (275829)
<b>Notes</b>	Suitable connector	Molex Mini-Fit Jr. 2 poles (39-01-2020)
	Suitable crimp terminals	Molex Mini-Fit Jr. female crimp terminals (44476-xxxx)
	Suitable hand crimper	Molex hand crimper (63819-0900)

## 4.1.2 Use of separate Logic Supply

By default, the logic is powered by the regular supply voltage. Optionally, you may wish to feed the logic supply voltage separately, permitting a safe and economical power backup feature.

Basically, any power supply may be used, provided it meets below stated minimal requirements.

Logic Power Supply Requirements	
Output voltage	$V_c$ min. 11 VDC; $V_c$ max. 24 VDC
Absolute output voltage	min. 10 VDC; max. 28 VDC
Min. output power	$P_c$ min. 3 W

Using a **separate logic supply**, you will need to change the jumper JP4.



**STOP!**  
**Check on safety precautions before continuing (→page 2-10).**

- 1) Open housing and find jumper JP4.
- 2) Open jumper JP4 (→Figure 4-8, right).
- 3) Connect to respective supply voltage (→chapter “4.5 Signal Connector (J5)” on page 4-25).

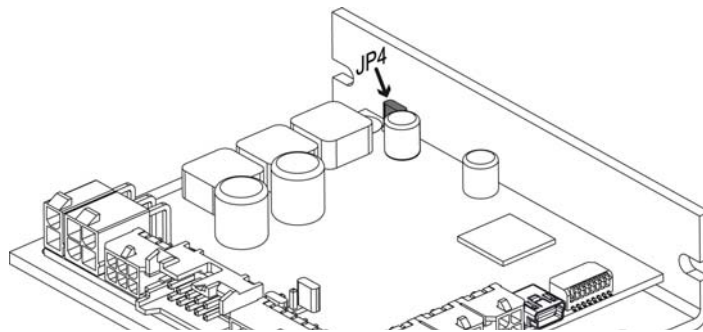


Figure 4-7 Jumper JP4 – Location and Factory Setting

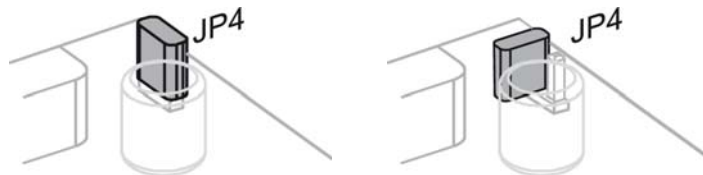


Figure 4-8 Jumper JP4 – closed (left) / open (right)

## 4.2 Motor Connector (J2)

By default, the controller is set to drive either maxon EC motor (brushless) or maxon DC motor (brushed) with separated motor/encoder cable. Using a **maxon DC motor with integrated motor/encoder ribbon cable**, you will need to change the jumpers JP2 and JP3.

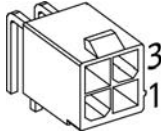


Figure 4-9 Motor Connector (J2)

<b>Accessories</b>	Cable	Motor Cable (275851)
<b>Notes</b>	Suitable connector Suitable crimp terminals Suitable hand crimper	Molex Mini-Fit Jr. 4 poles (39-01-2040) Molex Mini-Fit Jr. female crimp terminals (44476-xxxx) Molex hand crimper (63819-0900)

### 4.2.1 maxon EC motor (brushless)

Pin	Signal	Description
1	Motor winding 1	EC motor: Winding 1
2	Motor winding 2	EC motor: Winding 2
3	Motor winding 3	EC motor: Winding 3
4	Motor shield	Cable shield

### 4.2.2 maxon DC motor with separated Motor/Encoder Cable

Pin	Signal	Description
1	Motor (+M)	DC motor: Motor +
2	Motor (-M)	DC motor: Motor -
3	do not connect	
4	Motor shield	Cable shield

## 4.2.3 maxon DC motor with integrated Motor/Encoder Ribbon Cable



### **STOP!**

**Check on safety precautions before continuing (→page 2-10).**

- 1) Open housing and find jumpers JP2 and JP3.
- 2) Set jumpers JP2 and JP3 to “closed” position (→Figure 4-11, right).
- 3) For encoder connections →chapter “4.4 Encoder Connector (J4)” on page 4-23.

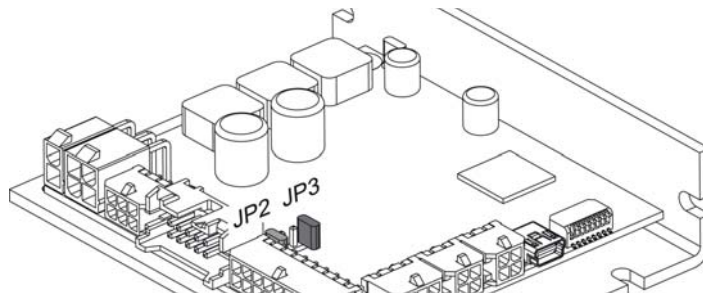


Figure 4-10 Jumpers JP2/JP3 – Location and Factory Setting

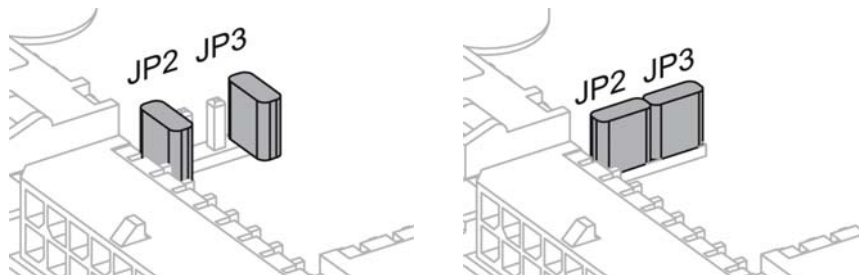


Figure 4-11 Jumpers JP2/JP3 – open (left) / closed (right)

### 4.3 Hall Sensor Connector (J3)

Hall sensors are required to detect the rotor position of maxon EC motors (brushless).

Suitable Hall effect sensors IC use «Schmitt trigger» with open collector output.

Hall sensor supply voltage	+5 VDC
Max. Hall sensor supply current	30 mA
Input voltage	0...+24 VDC
Logic 0	typically <0.8 VDC
Logic 1	typically >2.4 VDC
Internal pull-up resistor	2.7 kΩ (against +5 VDC)

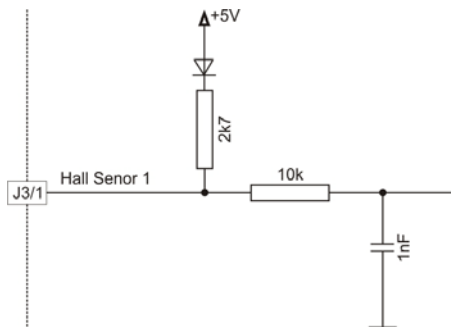


Figure 4-12 Hall Sensor Input Circuit

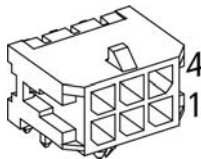


Figure 4-13 Hall Sensor Connector (J3)

Pin	Signal	Description
1	Hall sensor 1	Hall sensor 1 Input
2	Hall sensor 2	Hall sensor 2 Input
3	Hall sensor 3	Hall sensor 3 Input
4	GND	Ground of Hall sensor supply
5	+VHall	Hall sensor supply voltage +5 VDC / 30 mA
6	Hall shield	Cable shield

<b>Accessories</b>	Cable	Hall Sensor Cable (275878)
<b>Notes</b>	Suitable connector	Molex Micro-Fit 3.0 6 poles (430-25-0600)
	Suitable crimp terminals	Molex Micro-Fit 3.0 female crimp terminals (43030-xxxx)
	Suitable hand crimper	Molex hand crimper (63819-0000)

#### 4.4 Encoder Connector (J4)



**Best Practice**

*The use of encoder with built-in line driver is mandatory. Even though 2-channel will do, we strongly recommend to use only 3-channel versions!*

By default, the controller is set for a 500 count per turn encoder. For other encoders, you will need to adjust respective settings via software.

Encoder supply voltage	+5 VDC
Max. encoder supply current	100 mA
Min. differential input voltage	±200 mV
Line receiver (internal)	EIA RS422 Standard
Max. encoder input frequency	5 MHz

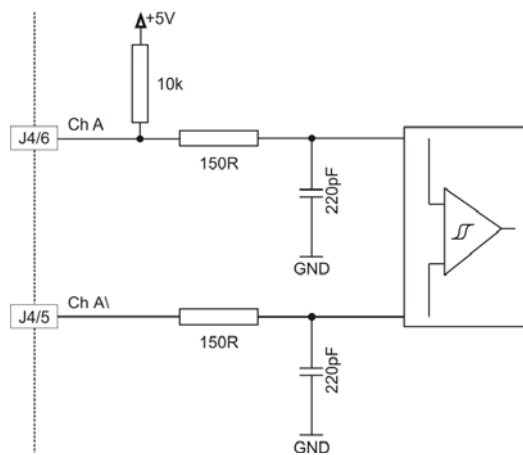


Figure 4-14 Encoder Input Channel

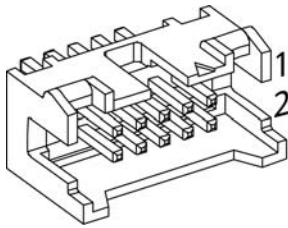


Figure 4-15 Encoder Connector (J4)

Pin	Signal	Description
1	EC motor: none DC motor: Motor +	EC motor: not connected DC motor: + Motor *1)
2	+5 VDC / 100 mA	Encoder supply voltage
3	GND	Ground
4	EC motor: none DC motor: Motor -	EC motor: not connected DC motor: - Motor *1)
5	Channel A\	Channel A complement
6	Channel A	Channel A
7	Channel B\	Channel B complement
8	Channel B	Channel B
9	Channel I\	Index complement
10	Channel I	Index

**Remark:**

\*1) may require change of jumper (J2 / J3) settings (→chapter “4.2.3 maxon DC motor with integrated Motor/Encoder Ribbon Cable” on page 4-21)

<b>Accessories</b>	Cable	Encoder Cable (275934)
<b>Notes</b>	Suitable connector	DIN 41651 Plug, pitch 2.54 mm, 10 poles, plug strain relief



## 4.5 Signal Connector (J5)

Contains smart multi-purpose digital I/Os configurable as “Positive Limit Switch”, “Negative Limit Switch”, “Home Switch” and “Brake Output”.

Additionally offered are “General Purpose” digital inputs and outputs and analog inputs.

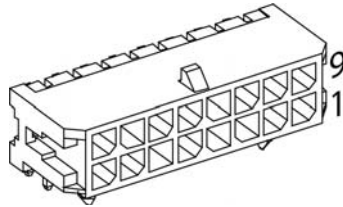


Figure 4-16 Signal Connector (J5)

Pin	Signal	Description
1	D_Gnd	Digital signal ground
2	D_Gnd	Digital signal ground
3	DigIN6	Digital Input 6 “Negative Limit Switch”
4	DigIN5	Digital Input 5 “Positive Limit Switch”
5	DigIN4	Digital Input 4 “Home Switch”
6	DigIN3	Digital Input 3 “General Purpose”
7	DigIN2	Digital Input 2 “General Purpose”
8	DigIN1	Digital Input 1 “General Purpose”
9	+V <sub>OUT</sub> *1) +V <sub>C</sub> *2)	Auxiliary supply voltage output (+11...24 VDC) Logic supply voltage input (+11...24 VDC)
10	DigOUT4	Digital Output 4 “Brake”
11	DigOUT3	Digital Output 3 “General Purpose”
12	DigOUT2	Digital Output 2 “General Purpose”
13	DigOUT1	Digital Output 1 “General Purpose”
14	A_Gnd	Analog signal ground
15	AnIN2	Analog Input 2
16	AnIN1	Analog Input 1

### Remarks:

\*1) jumper JP4 is set (initial setting)

\*2) if jumper JP4 is open, a independent logic supply voltage may be applied (→chapter “4.1.2 Use of separate Logic Supply” on page 4-19)

Accessories	Cable	Signal Cable 16core (275932)
<b>Notes</b>	Suitable connector Suitable crimp terminals Suitable hand crimper	Molex Micro-Fit 3.0 16 poles (430-25-1600) Molex Micro-Fit 3.0 female crimp terminals (43030-xxxx) Molex hand crimper (63819-0000)

### 4.5.1 Digital Inputs 1, 2 and 3

By default, the digital inputs are defined as “General Purpose” and may be configured via software.

DigIN1 “General Purpose”	Connector [J5] Pin [8]
DigIN2 “General Purpose”	Connector [J5] Pin [7]
DigIN3 “General Purpose”	Connector [J5] Pin [6]
D_Gnd	Connector [J5] Pin [1], [2]
Input voltage	0...24 VDC
Max. input voltage	±30 VDC
Logic 0	typically <1.5 V
Logic 1	typically >3.0 V
Input resistance	typically 8 kΩ
Input current at logic 1	typically 3 mA @ 24 VDC
Switching delay	<2 μs @ 5 VDC

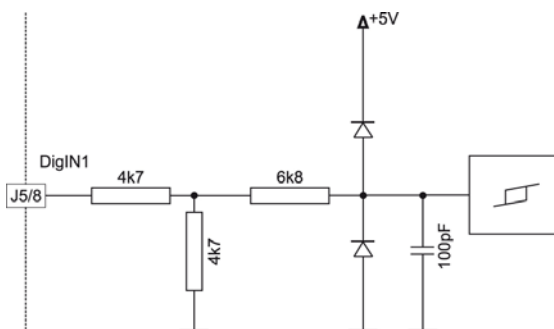


Figure 4-17 DigIN1 Circuit (analogously valid also for DigIN2/3)

## 4.5.2 Digital Inputs 4, 5 and 6

By default, the digital inputs are defined as follows and may be configured via software.

- Digital Input 4 “Home Switch”
- Digital Input 5 “Positive Limit Switch”
- Digital Input 6 “Negative Limit Switch”

DigIN4 “Home Switch”	Connector [J5] Pin [5]
DigIN5 “Positive Limit Switch”	Connector [J5] Pin [4]
DigIN6 “Negative Limit Switch”	Connector [J5] Pin [3]
D_Gnd	Connector [J5] Pin [1], [2]
Input voltage	0...24 VDC
Max. input voltage	±30 VDC
Logic 0	typically <5.0 V
Logic 1	typically >9.0 V
Input resistance	typically 4 kΩ
Input current at logic 1	typically 6 mA @ 24 VDC
Switching delay	<50 μs @ 11...24 VDC

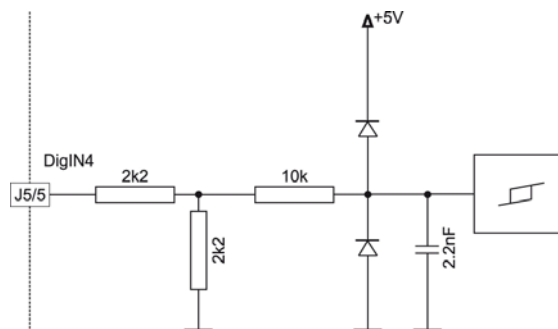


Figure 4-18 DigIN4 Circuit (analogously valid also for DigIN5/6)

For wiring examples →page 4-28.

Wiring Example: "Proximity Switch Type PNP"

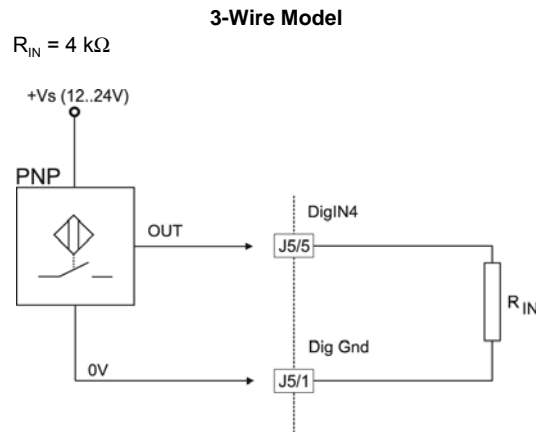


Figure 4-19 DigIN4 – Type PNP Proximity Switch (analogously valid also for DigIN5/6)

Wiring Example: "Proximity Switch Type NPN"

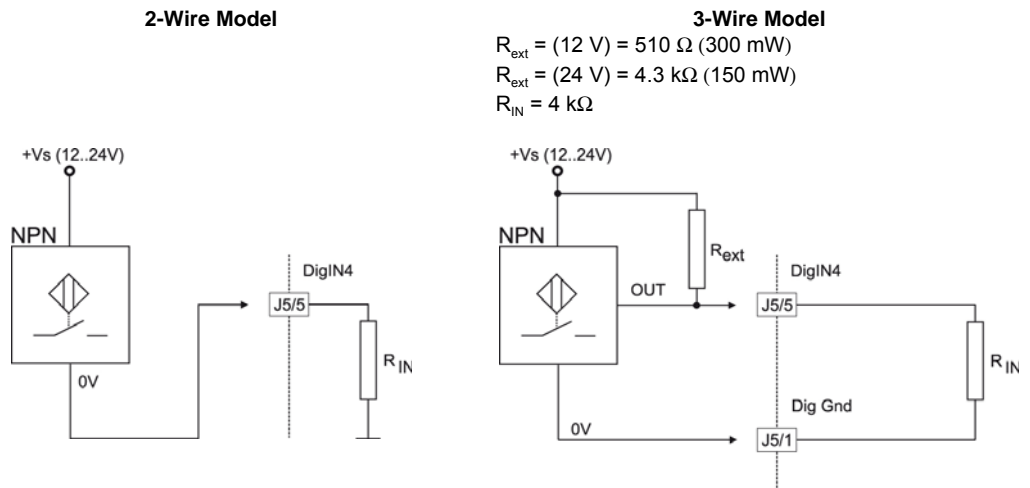


Figure 4-20 DigIN4 – Type NPN Proximity Switch (analogously valid also for DigIN5/6)

### 4.5.3 Analog Inputs 1 and 2

By default, the analog inputs are defined as “General Purpose” and may be configured via software.

AnIN1	Connector [J5] Pin [16]
AnIN2	Connector [J5] Pin [15]
A_Gnd	Connector [J5] Pin [14]
Input voltage	0...5 VDC
Max. input voltage	±30 VDC
Input resistance	typically 47 kΩ (referenced to A_Gnd)
A/D converter	12-bit
Resolution	0.0012 V
Bandwidth	5 kHz

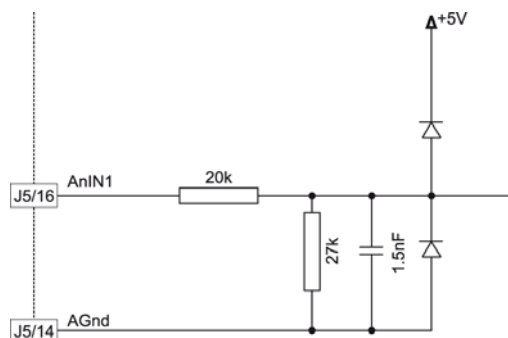


Figure 4-21 AnIN1 Circuit (analogously valid also for AnIN2)

### 4.5.4 Auxiliary Supply Voltage Output

Can be used as supply voltage for external loads connected to EPOS2 P 24/5's digital outputs.

+V <sub>OUT</sub>	Connector [J5] Pin [9]
D_Gnd	Connector [J5] Pins [1]; [2]
Output voltage	+11...24 VDC
Output current	max. 1300 mA

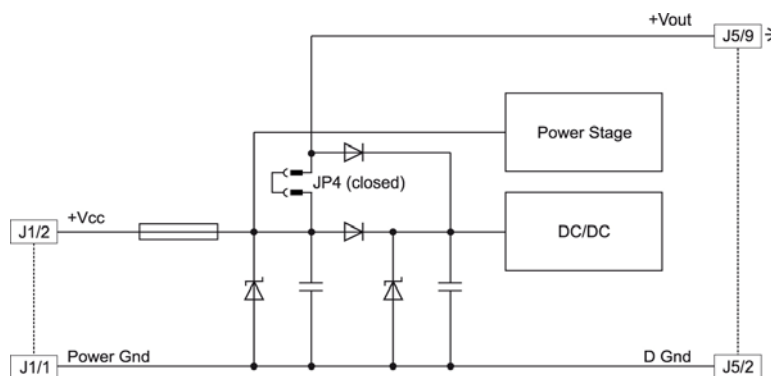


Figure 4-22 Auxiliary Output Voltage Circuit

## 4.5.5 Digital Outputs 1, 2 and 3

By default, the digital outputs are defined as “General Purpose” and may be configured via software.

DigOUT1 DigOUT2 DigOUT3 D_Gnd	Connector [J5] Pin [13] Connector [J5] Pin [12] Connector [J5] Pin [11] Connector [J5] Pins [1]; [2]
Circuit	Open drain (internal pull-up resistor 2k2 and diode to +5 VDC)

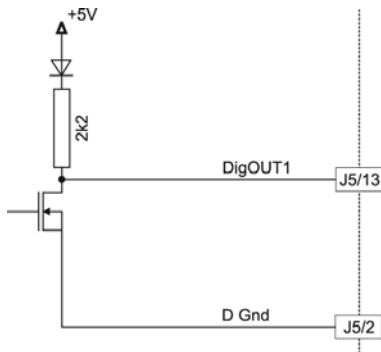


Figure 4-23 DigOUT1 Circuit (analogously valid also for DigOUT2/3)

### Wiring Examples:

DigOUT “Sinks”	
Max. input voltage	+30 VDC
Max. load current	100 mA
Max. voltage drop	0.5 V @ 100 mA

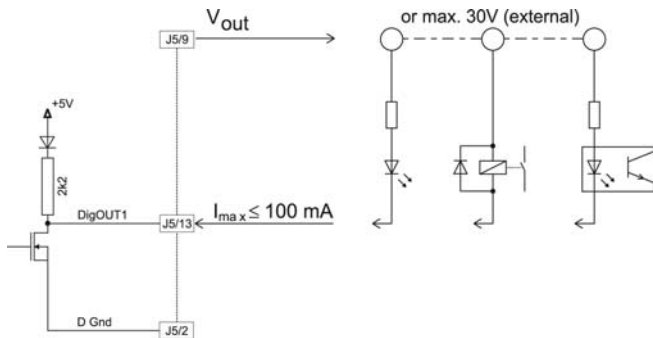


Figure 4-24 DigOUT1 “Sinks” Circuit (analogously valid also for DigOUT2/3)

DigOUT “Source”	
Output voltage	$U_{out} \approx 5V - 0.75 V - (I_{load} \times 2200 \Omega)$
Max. load current	$I_{load} \leq 2 \text{ mA}$

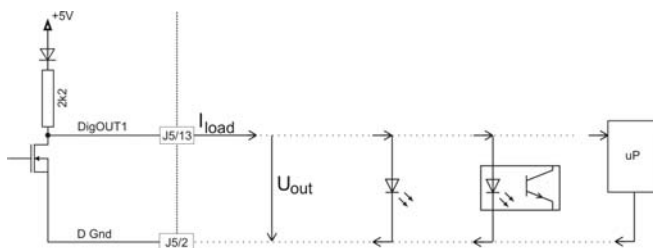


Figure 4-25 DigOUT1 “Source” Circuit (analogously valid also for DigOUT2/3)

## 4.5.6 Digital Output 4

The digital output is defined as “Brake” (permanent DC voltage applied to serve as magnet brake).

DigOUT4 D_Gnd	Connector [J5] Pin [10] Connector [J5] Pins [1]; [2]
Circuit	Open drain (internal pull-up resistor 2k2 and diode to +5 VDC)

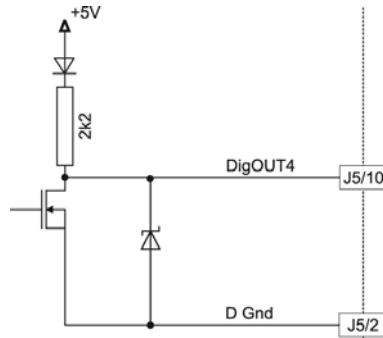


Figure 4-26 DigOUT4 Circuit

### Wiring Examples:

DigOUT “Sinks”	
Max. input voltage	+30 VDC
Max. load current	1 A
Max. voltage drop	0.3 V @ 1 A

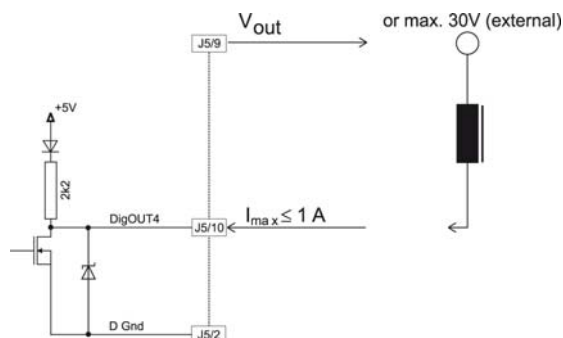


Figure 4-27 DigOUT4 “Sinks” Circuit

DigOUT “Source”	
Output voltage	$U_{out} \approx 5V - 0.75 V - (I_{load} \times 2200 \Omega)$
Max. load current	$I_{load} \leq 2 \text{ mA}$

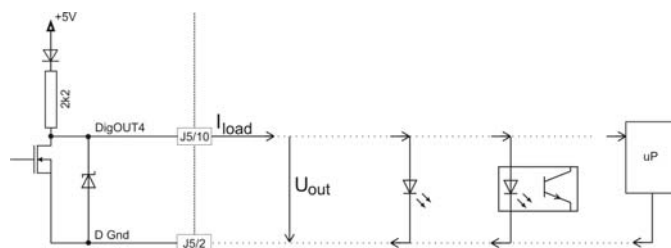


Figure 4-28 DigOUT4 “Source” Circuit

## 4.6 RS232 Connector (J6)

Max. input voltage	±30 V
Output voltage	typically ±9 V @ 3 kΩ to Ground
Max. bit rate	115 200 bit/s
Internal RS232 driver/receiver	EIA RS232 Standard

### Connection of Positioning Controller to PC

EPOS2 P 24/5	PC Interface (RS232), DIN41652
Connector [J6] Pins [4] + [5] "GND"	Pin 5 "GND"
Connector [J6] Pin [1] "EPOS RxD"	Pin 3 "PC TxD"
Connector [J6] Pin [2] "EPOS TxD"	Pin 2 "PC RxD"



#### Note

- Consider your PC's serial port maximal baud rate.
- The standard baud rate setting (factory setting) is 115'200 bauds.

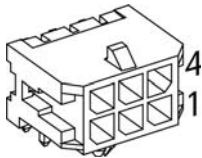


Figure 4-29 RS232 Connector (J6)

Pin	Signal	Description
1	EPOS RxD	EPOS RS232 receive
2	EPOS TxD	EPOS RS232 transmit
3	not connected	
4	GND	RS232_Ground
5	GND	RS232_Ground
6	Shield	Cable shield

Accessories	Cable	RS232-COM Cable (275900)
<b>Notes</b>	Suitable connector Suitable crimp terminals Suitable hand crimper	Molex Micro-Fit 3.0 6 poles (430-25-0600) Molex Micro-Fit 3.0 female crimp terminals (43030-xxxx) Molex hand crimper (63819-0000)



## 4.7 CAN Connector (J7, J8)

Standard	ISO 11898-2:2003
Max. bit rate	1 Mbit/s
Max. number of CAN nodes	127
Protocol	CANopen DS-301
Identifier setting	DIP switch or software

### Connection of Positioning Controller to CAN Bus Line CiA DS-102

EPOS2 P 24/5	CAN 9 pin D-Sub (DIN41652)
Connector [J7] or [J8] Pin [1] "CAN high"	Pin 7 "CAN_H" high bus line
Connector [J7] or [J8] Pin [2] "CAN low"	Pin 2 "CAN_L" low bus line"
Connector [J7] or [J8] Pin [3] "CAN GND"	Pin 3 "CAN_GND" Ground
Connector [J7] or [J8] Pin [4] "CAN shield"	Pin 5 "CAN_Shield" cable shield



#### Note

- Consider CAN devices' maximal baud rate.
- The standard baud rate setting (factory setting) is 1 MBit/s.
- Use termination resistor at both ends of the CAN bus (→chapter "4.8.2 CAN Bus Termination in "CAN-M" Supervisor Control (Master) Network" on page 4-35 and chapter "4.8.4 CAN Bus Termination in "CAN-S" Slave Network" on page 4-35).
- CAN-S (J7) is used for a CAN Slaves Network.
- CAN-M (J8) is used for a Supervisor Control (Master) Network.
- For detailed CAN information →separate document «EPOS2 Communication Guide».

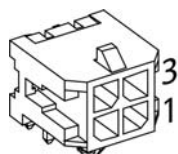


Figure 4-30 CAN Connector (J7/J8)

Pin	Signal	Description
1	CAN high	CAN high bus line
2	CAN low	CAN low bus line
3	CAN GND	CAN Ground
4	CAN shield	Cable shield

<b>Accessories</b>	Cables	CAN-COM Cable (275908) CAN-CAN Cable (275926) CAN-Y Cable (319471)
<b>Notes</b>	Suitable connector Suitable crimp terminals Suitable hand crimper	Molex Micro-Fit 3.0 4 poles (430-25-0400) Molex Micro-Fit 3.0 female crimp terminals (43030-xxxx) Molex hand crimper (63819-0000)

## 4.8 CAN Configuration (JP1 & JP1A)

### 4.8.1 CAN ID (Node Address) in “CAN-M” Supervisor Control (Master) Network

The CAN ID is set with DIP switch JP1 [1...7]. Addresses (1...127) may be coded using binary code.



**Note**

- By setting DIP switch JP1 [1...7] address 0 (“OFF”), the CAN ID may be configured by software (changing object “Node ID”, range 1...127).
- The CAN ID results in the summed values of DIP switch addresses 1 (“ON”).
- DIP switch JP1 [8] does not have any impact on the CAN ID.


Switch	Binary Code	Valence	DIP Switch
1	2 <sup>0</sup>	1	 <p>Figure 4-31 JP1 (Numbering Scheme)</p>
2	2 <sup>1</sup>	2	
3	2 <sup>2</sup>	4	
4	2 <sup>3</sup>	8	
5	2 <sup>4</sup>	16	
6	2 <sup>5</sup>	32	
7	2 <sup>6</sup>	64	

Table 4-17 CAN ID – Binary Code Values

**Examples:**

Use following table as a (non-concluding) guide:




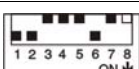
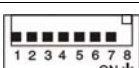
CAN ID	DIP Setting	CAN ID/Switch							Calculation	
		1	2	3	4	5	6	7		
		Valence	1	2	4	8	16	32	64	
1			1	0	0	0	0	0	0	1
2			0	1	0	0	0	0	0	2
32			0	0	0	0	0	1	0	32
35			1	1	0	0	0	1	0	1 + 2 + 32
127			1	1	1	1	1	1	1	1 + 2 + 4 + 8 + 16 + 32 + 64

Table 4-18 CAN ID – DIP Switch Settings (Example)

#### 4.8.2 CAN Bus Termination in “CAN-M” Supervisor Control (Master) Network

The CAN bus must be terminated at both ends by a termination resistor of 120 Ω, typically. Depending on utilization of the controller, individual CAN bus termination settings must be performed.

Using DIP switch JP1A [1], the controller-internal bus termination resistor can be activated/deactivated. By default, bus termination is “OFF”, nevertheless, the bus is not terminated.



Figure 4-32 DIP Switch (JP1A) – CAN Bus Termination in CAN-M (left “OFF” right “ON”)

#### 4.8.3 CAN Bus Autobitrate in “CAN-M” Supervisor Control (Master) Network

Using DIP switch JP1A [2], autobitrate can be activated/deactivated. By default, autobitrate is “OFF”.



Figure 4-33 DIP Switch (JP1A) – CAN Bus Autobitrate in CAN-M (left “OFF” right “ON”)

#### 4.8.4 CAN Bus Termination in “CAN-S” Slave Network

The CAN bus must be terminated at both ends by a termination resistor of 120 Ω, typically. Depending on utilization of the controller, individual CAN bus termination settings must be performed.

Using DIP switch JP1 [8], the controller-internal bus termination resistor can be activated/deactivated. By default, bus termination is “OFF”, nevertheless, the bus is not terminated.

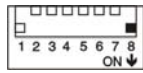
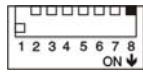


Figure 4-34 DIP Switch (JP1 [8]) – CAN Bus Termination in CAN-S (left “OFF” right “ON”)

## 4.9 USB Connector (J9)

USB Standard	USB 2.0 / USB 3.0 (full speed)
Max. bus supply voltage	+5.25 VDC
Typical input current	15 mA
Max. DC data input voltage	-0.5...+3.8 VDC

### Connection of Positioning Controller to PC

EPOS2 P 24/5	PC Interface (USB 2.0 / USB 3.0)
Connector [J9] Pin [1] "V <sub>BUS</sub> "	Pin 1 "V <sub>BUS</sub> "
Connector [J9] Pin [2] "USB D-"	Pin 2 "USB D-"
Connector [J9] Pin [3] "USB D+"	Pin 3 "USB D+"
Connector [J9] Pin [5] "GND"	Pin 4 "GND"
Connector [J9] housing "Shield"	Housing "Shield"



Figure 4-35 USB Connector (J9)

Pin	Signal	Description
1	V <sub>BUS</sub>	USB bus supply input voltage +5 VDC
2	USB D-	USB Data-
3	USB D+	USB Data+
4	not connected	
5	GND	USB Ground
	Shield	Cable Shield

<b>Accessories</b>	Cable	USB Type A - mini B Cable (370513)
<b>Notes</b>	Suitable connector	Standard USB cable with type mini B plug (5 poles)

## 4.10 Status LEDs

The LEDs display the current status of the EPOS2 P 24/5 as well as possible errors:

- Green LED shows the operating status
- Red LED indicates errors
- Blue LED shows the program status
- Orange LED indicates program errors



**For detailed information → separate document «EPOS2 Firmware Specification».**

LED				Status / Error
Red	Green	Orange	Blue	
OFF	Slow			Power stage is disabled. Device is in status... • "Switch ON Disabled" • "Ready to Switch ON" • "Switched ON"
OFF	ON			Power stage is enabled. Device is in status... • "Operation Enable" • "Quick Stop Active"
ON	OFF			FAULT state. Device is in status... • "Fault"
ON	ON			Power stage is enabled. Device is in temporary status... • "Fault Reaction Active"
		OFF	Fast	No valid application program.
		OFF	Slow	Application program has stopped.
		OFF	ON	Application program is running.
		Slow (alternating)		Application program in ERROR state.
ON	Flash			No valid firmware or firmware download in progress.
		ON	OFF	Waiting for communication with EPOS Studio due to interrupted firmware download.
		ON	Flash	Firmware download in progress.
Fast = Fast blinking (≈4 Hz) Flash = Flashing (≈0.9 s OFF/≈0.1 s ON) Slow = Slow blinking (≈1 Hz)				

Table 4-19 LEDs – Interpretation of Condition

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