



Absolute Encoders

AMT58...16x14 PB



Profibus-DP Profile for Encoders

Instruction Manual



Datalogic S.r.l.
Via S. Vitalino 13
40012 Calderara di Reno
Bologna - Italy

© 2014 - 2017 Datalogic S.p.A. and/or its affiliates ♦ ALL RIGHTS RESERVED. ♦ Without limiting the rights under copyright, no part of this documentation may be reproduced, stored in or introduced into a retrieval system, or transmitted in any form or by any means, or for any purpose, without the express written permission of Datalogic S.p.A. and/or its affiliates.

Datalogic and the Datalogic logo are registered trademarks of Datalogic S.p.A. in many countries, including the U.S.A. and the E.U.

All other trademarks and brands are property of their respective owners. Datalogic reserves the right to make modifications and improvements without prior notification.

16/06/17

INDEX

1.	Safety summary	1
2.	Identification.....	3
3.	Mounting instructions	4
3.1	Solid shaft encoders	4
3.1.1	Customary installation.....	4
3.1.2	Fissaggio con graffe (codice ST-58-KIT)	4
3.2	Hollow shaft encoders.....	6
3.2.1	AMT58-H15.....	6
4.	Electrical connections	7
4.1	Connection cap	7
4.2	Ground connection.....	8
4.3	Connection cap with PG gland.....	8
4.4	Connection cap with M12 connectors	9
4.5	Connection of the shield	10
4.6	Bus termination resistance.....	10
4.7	Baud rate	10
4.8	Node number: DIP A.....	11
4.9	Diagnostic LEDs	12
5.	Quick reference.....	13
5.1	STEP7 configuration	13
5.1.1	Importing GSD file.....	13
5.1.2	Adding a node to the project	14
5.1.3	Encoder configuration parameters	14
5.2	Reading diagnostic information.....	16
5.3	Setting the Preset value.....	18
5.4	Set node number via BUS	19
6.	Profibus® interface	20
6.1	GSD file	20
6.2	Classes of the Device profile	20
6.3	Modes of operation	21
6.4	DDL_M_Set_Prm.....	22
6.4.1	Byte 10 - Operating parameters.....	23
Code sequence.....	23	
Class 2 functionality	24	
Scaling function control.....	24	
Diagnostic type	24	
Exchange type	24	
6.4.2	Bytes 11...14	25
Counts per revolution.....	25	
6.4.3	Bytes 15...18	26
Total resolution	26	
Velocity measure unit.....	28	
6.5	DDL_M_Chk_Cfg.....	28
6.6	DDL_M_Data_Exchange	28
Position value	28	
Position and velocity values	29	
Preset value.....	29	
6.7	DDL_M_Slave_Diag	31
6.8	Set_Slave_Address (service SAP55).....	33
6.9	"Red Zone"	34

Subject index

C			
Class 2 functionality	24	Position value	28
Code sequence	23	Preset value	29
Counts per revolution	25	S	
D		Scaling function control	24
Diagnostic type	24	T	
E		Total resolution	26
Exchange type	24	V	
P		Velocity measure unit	28
Position and velocity values	29		

Typographic and iconographic conventions

In this guide, to make it easier to understand and read the text the following typographic and iconographic conventions are used:

- parameters and objects both of the device and the interface are coloured in **ORANGE**;
- alarms are coloured in **RED**;
- states are coloured in **FUCSIA**.

When scrolling through the text some icons can be found on the side of the page: they are expressly designed to highlight the parts of the text which are of great interest and significance for the user. Sometimes they are used to warn against dangers or potential sources of danger arising from the use of the device. You are advised to follow strictly the instructions given in this guide in order to guarantee the safety of the user and ensure the performance of the device. In this guide the following symbols are used:

	<p>This icon, followed by the word WARNING, is meant to highlight the parts of the text where information of great significance for the user can be found: user must pay the greatest attention to them! Instructions must be followed strictly in order to guarantee the safety of the user and a correct use of the device. Failure to heed a warning or comply with instructions could lead to personal injury and/or damage to the unit or other equipment.</p>
	<p>This icon, followed by the word NOTE, is meant to highlight the parts of the text where important notes needful for a correct and reliable use of the device can be found. User must pay attention to them! Failure to comply with instructions could cause the equipment to be set wrongly: hence a faulty and improper working of the device could be the consequence.</p>
	<p>This icon is meant to highlight the parts of the text where suggestions useful for making it easier to set the device and optimize performance and reliability can be found. Sometimes this symbol is followed by the word EXAMPLE when instructions for setting parameters are accompanied by examples to clarify the explanation.</p>

Preliminary information

This guide is designed to describe the technical characteristics, installation and use of the Profibus encoders of the AMT58-PB series. For any further information please refer to the product datasheet.

To make it easier to read the text, this guide is divided into two main sections.

In the first section general information concerning the safety, the mechanical installation and the electrical connection as well as tips for setting up and running properly and efficiently the unit are provided.

In the second section, entitled Profibus Interface, both general and specific information is given on the Profibus interface. In this section the interface features and the parameters implemented in the unit are fully described.

1. Safety summary



Safety

- Always adhere to the professional safety and accident prevention regulations applicable to your country during device installation and operation;
- installation and maintenance operations have to be carried out by qualified personnel only, with power supply disconnected and stationary mechanical parts;
- device must be used only for the purpose appropriate to its design: use for purposes other than those for which it has been designed could result in serious personal and/or the environment damage;
- high current, voltage and moving mechanical parts can cause serious or fatal injury;
- warning ! Do not use in explosive or flammable areas;
- failure to comply with these precautions or with specific warnings elsewhere in this manual violates safety standards of design, manufacture, and intended use of the equipment;
- Datalogic Automation S.r.l. assumes no liability for the customer's failure to comply with these requirements.



Electrical safety

- Turn off power supply before connecting the device;
- connect according to explanation in section "4 – electrical connections";
- in compliance with the 2014/30/EU norm on electromagnetic compatibility, following precautions must be taken:
 - before handling and installing, discharge electrical charge from your body and tools which may come in touch with the device;
 - power supply must be stabilized without noise, install EMC filters on device power supply if needed;
 - always use shielded cables (twisted pair cables whenever possible);
 - avoid cables runs longer than necessary;
 - avoid running the signal cable near high voltage power cables;
 - mount the device as far as possible from any capacitive or inductive noise source, shield the device from noise source if needed;
 - to guarantee a correct working of the device, avoid using strong magnets on or near by the unit;
 - minimize noise by connecting the shield and/or the connector housing and/or the frame to ground. Make sure that ground is not affected by noise. The connection point to ground can be situated both on the device side and on user's side. The best solution to minimize the interference must be carried out by the user.





Mechanical safety

- Install the device following strictly the information in the section “3 – Mounting instructions”;
- mechanical installation has to be carried out with stationary mechanical parts;
- do not disassemble the encoder;
- do not tool the encoder or its shaft;
- delicate electronic equipment: handle with care; do not subject the device and the shaft to knocks or shocks;
- respect the environmental characteristics declared by manufacturer;
- unit with solid shaft: in order to guarantee maximum reliability over time of mechanical parts, we recommend a flexible coupling to be installed to connect the encoder and user's shaft; make sure the misalignment tolerances of the flexible coupling are respected;
- unit with hollow shaft: the encoder can be mounted directly on a shaft whose diameter has to respect the technical characteristics specified in the purchase order and clamped by means of the collar and, when requested, the anti-rotation pin.

2. Identification

Device can be identified through the ordering code and the serial number printed on the label applied to its body. Information is listed in the delivery document too.

Please always quote the ordering code and the serial number when reaching contatta Datalogic Automation s.r.l. for purchasing spare parts or needing assistance.

For any information on the technical characteristics of the product refer to the technical catalogue.

3. Mounting instructions



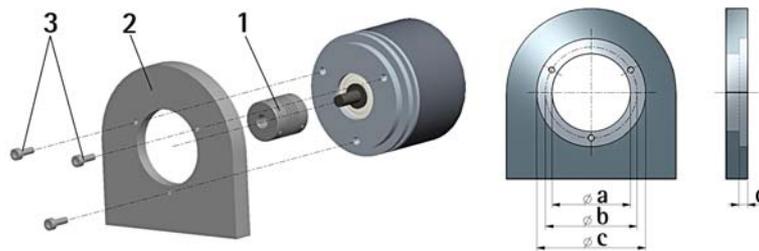
WARNING

Installation has to be carried out by qualified personnel only, with power supply disconnected and mechanical parts compulsorily in stop.

3.1 Solid shaft encoders

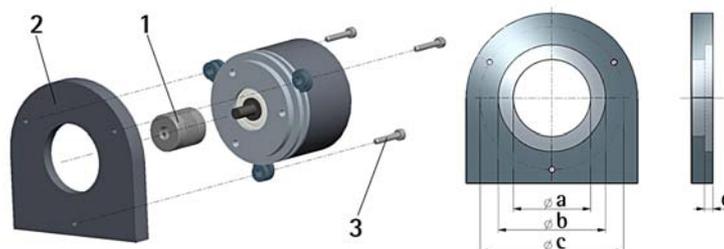
- Mount the flexible coupling 1 on the encoder shaft;
- fix the encoder to the flange 2 (or to the mounting bell) by means of screws 3;
- secure the flange 2 to the support (or the mounting bell to the motor);
- mount the flexible coupling 1 on the motor shaft;
- make sure the misalignment tolerances of the flexible coupling 1 are respected.

3.1.1 Customary installation



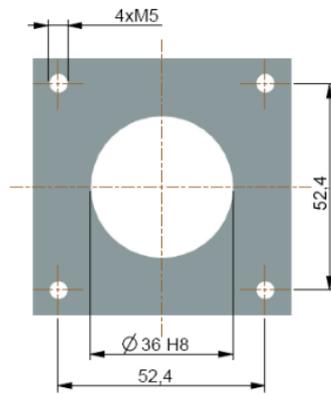
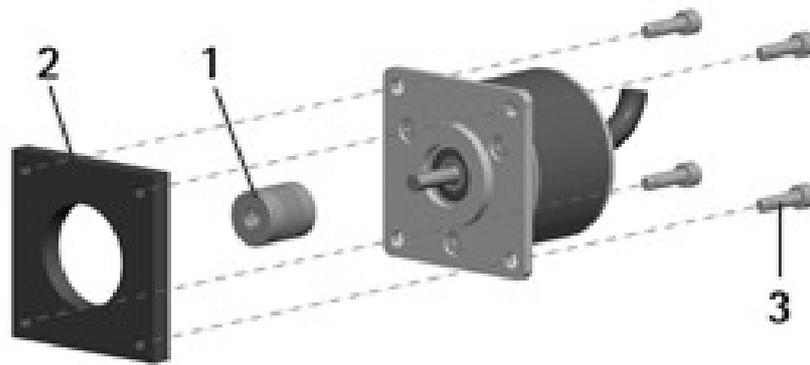
	a [mm]	b [mm]	c [mm]	d [mm]
AMT58	36 H7	48	-	-

3.1.2 Fissaggio con graffe (codice ST-58-KIT)



	a [mm]	b [mm]	c [mm]	d [mm]
AMT58	36 H7	-	67	-

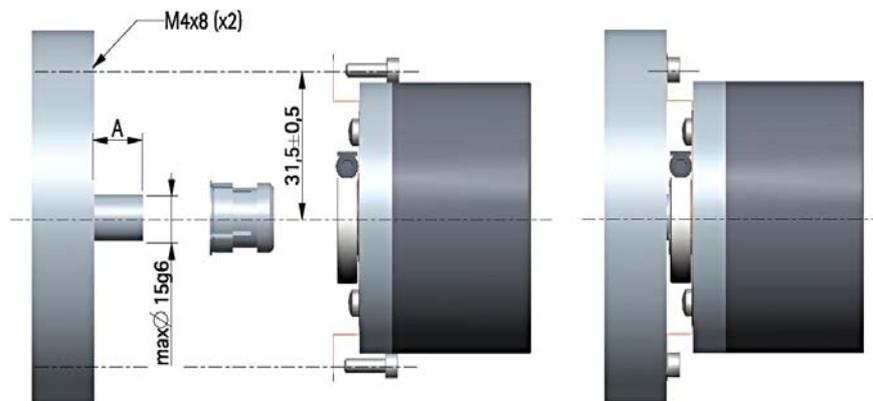
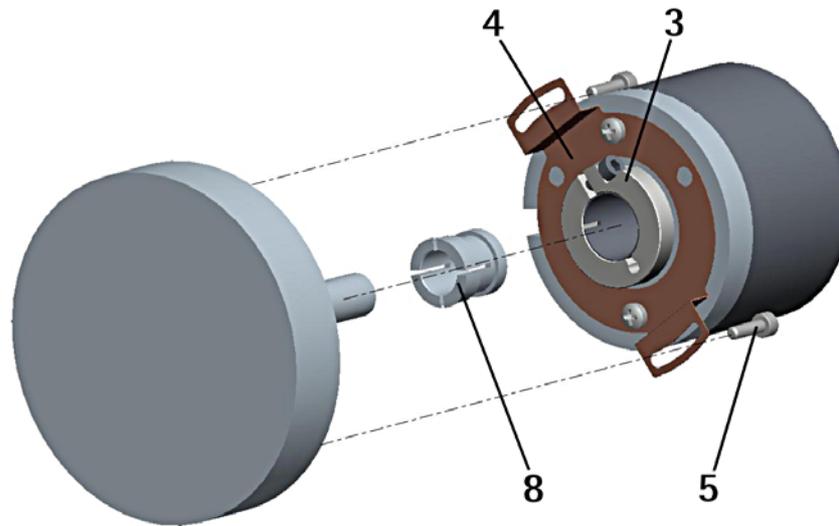
3.1.3 Installation using a flange (code ST-58-FLNG)



3.2 Hollow shaft encoders

3.2.1 AMT58-H15

- Mount the encoder on the motor shaft using the reducing sleeve 8 (if supplied). Avoid forcing the encoder shaft;
- fasten the fixing plate 4 to the rear of the motor using two M3 cylindrical head screws 5;
- fix the collar 3 to the encoder shaft (apply threadlocker to screw 3).



4. Electrical connections

4.1 Connection cap



WARNING

Do not remove or mount the connection cap with power supply switched ON. Damage may be caused to internal components.

The terminal connectors for connecting the power supply and the BUS IN and BUS OUT cables (BC-PB connection cap) as well as the dip-switches meant to set the node ID and activate the termination resistance are located inside the encoder connection cap. Thus you must remove the connection cap to access any of them.



NOTE

Be careful not to damage the internal components when you perform this operation.

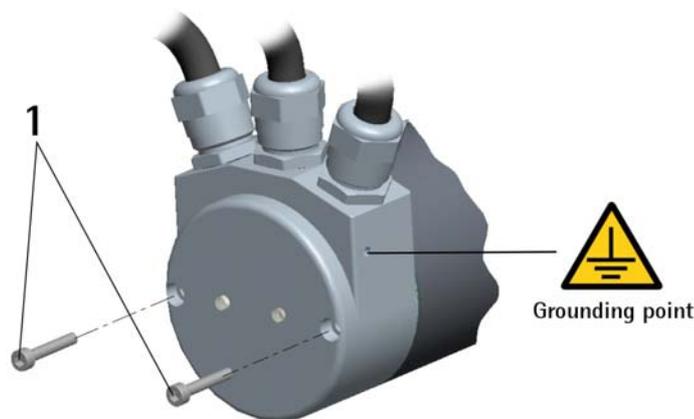
To remove the connection cap loosen the two screws 1. Please be careful with the internal connector.

Always replace the connection cap at the end of the operation. Take care in re-connecting the internal connector. Tighten the screws 1 using a tightening torque of approx. 2.5 Nm.



WARNING

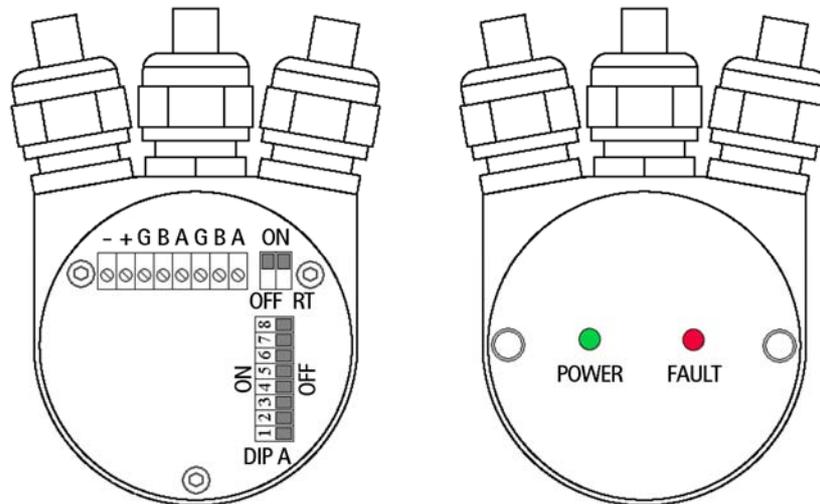
You are required to check that the encoder body and the connection cap are at the same potential before replacing the connection cap!



4.2 Ground connection

Minimize noise by connecting the shield and/or the connector housing and/or the frame to ground. Make sure that ground is not affected by noise. The connection point to ground can be situated both on the device side and on user's side. The best solution to minimize the interference must be carried out by the user. You are advised to provide the ground connection as close as possible to the encoder. We suggest using the ground point provided in the cap (see Figure, use 1 TCEI M3 x 6 cylindrical head screw with 2 tooth lock washers).

4.3 Connection cap with PG gland



BC-PB connection cap is fitted with three PG9 cable glands for bus-IN and bus-OUT connections and power supply connection. The bus cables can be connected directly to the terminal connectors located in front of each cable gland.

We recommend Profibus-DP certificated cables to be used. Core diameter should not exceed Ø 1,5 mm (0.06 inches).

Terminal connector	Description
-	0 VDC Supply voltage
+	+10VDC +30VDC Supply voltage
G	Profibus GND ¹
B	Profibus B (Red)
A	Profibus A (Green)
PG	Shield ²

¹ Profibus GND is the 0V reference of Profibus signals, it is not connected to 0VDC supply voltage.

² Connect the cable shield to cable gland.

4.4 Connection cap with M12 connectors

BC-PB-C connection cap is fitted with three M12 connectors with pin-out in compliance with Profibus standard. Therefore you can use standard Profibus cables commercially available.

Power supply
M12 connector
A coding
(frontal side)

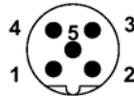


male

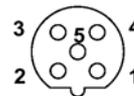
Pin	Function
1	+10VDC +30VDC
3	0 VDC GND
4 ¹	Shield
Case	

¹ Shield is also connected to pin 4 to allow the connection of the shield even if the plug connector has a plastic case.

Profibus signals
M12 connector
B coding
(frontal side)



male
(BUS IN)



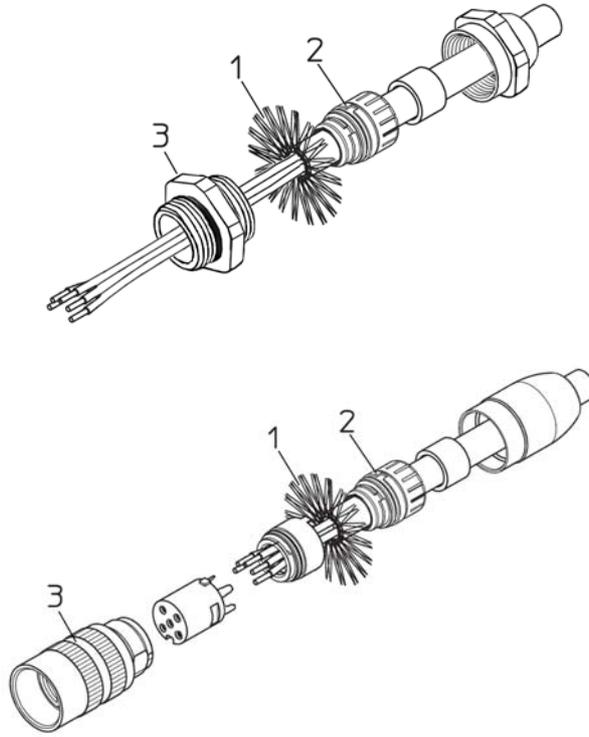
female
(BUS OUT)

Pin	Function
1	n.c.
2	Profibus A (Green)
3	n.c.
4	Profibus B (Red)
5	n.c.
Case	Shield

n.c. = not connected

4.5 Connection of the shield

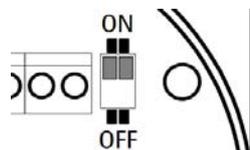
Disentangle and shorten the shielding 1 and then bend it over the part 2; finally place the ring nut 3 of the connector. Be sure that the shielding 1 is in tight contact with the ring nut 3.



4.6 Bus termination resistance

A bus termination resistance is provided in the connection cap. This has to be activated as line termination in the last device. Use RT Switch to activate or deactivate the bus termination.

RT	Description
1 = 2 = ON	Activated: if the encoder is the last device in the transmission line
1 = 2 = OFF	Deactivated: if the encoder is not the last device in the transmission line



4.7 Baud rate

The baud rate is set by the Master via software during configuration of the node (slave). Supported baud rates are listed in the enclosed GSD file.

4.8 Node number: DIP A



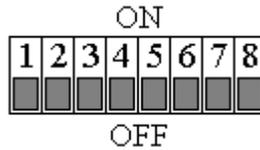
WARNING

Power supply must be turned off before performing this operation!

The node number must be set via hardware using DIP A dip-switches.

Allowed addresses are from 0 to 125. The default value is 1.

DIP A:



Turn the power supply off and set the node number in binary value; consider that: ON=1, OFF=0

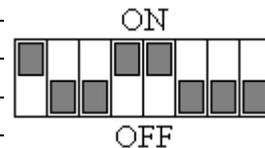
bit	1 LSB	2	3	4	5	6	7 MSB	8 not used
	2^0	2^1	2^2	2^3	2^4	2^5	2^6	



Example

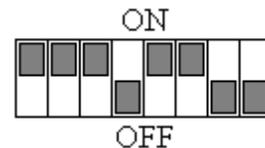
Set node number = 25:
 $25_{10} = 0001\ 1001_2$ (binary value)

bit	1	2	3	4	5	6	7	8
	2^0	2^1	2^2	2^3	2^4	2^5	2^6	
	ON	OFF	OFF	ON	ON	OFF	OFF	OFF



Set node number = 55:
 $55_{10} = 0011\ 0111_2$ (binary value)

bit	1	2	3	4	5	6	7	8
	2^0	2^1	2^2	2^3	2^4	2^5	2^6	
	ON	ON	ON	OFF	ON	ON	OFF	OFF



4.9 Diagnostic LEDs

Two LEDs located in the rear side of the connection cap are designed to show the operating or fault status of the Profibus-DP interface.

Fault (red)	Power (green)	Event
OFF	OFF	No power supply or hardware fault
OFF	ON	Correct operation (correct communication)
OFF	Flashing	Red Zone, see section "6.9 Red Zone"
ON	Flashing	Configuration parameters not valid
ON	OFF	Transmission time-out error
Flashing	ON	Bus communication failure
Flashing	Flashing	Flash memory error

5. Quick reference

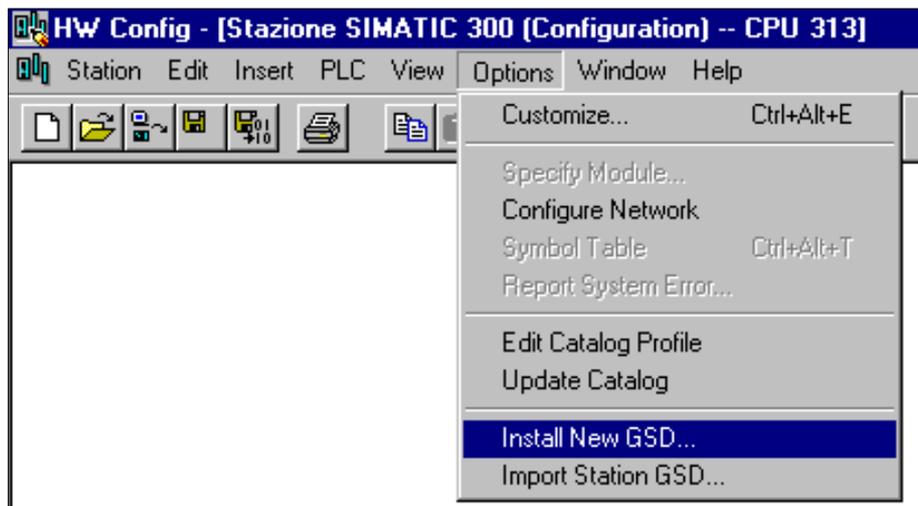
5.1 STEP7 configuration

5.1.1 Importing GSD file

Profibus encoders are supplied with their own GSD file **AMT58-xxx-16x14-FBUS-PB** (see enclosed documentation or www.datalogic.com).

In the menu bar of the HW Config window, press Options and then Install New GSD... command.

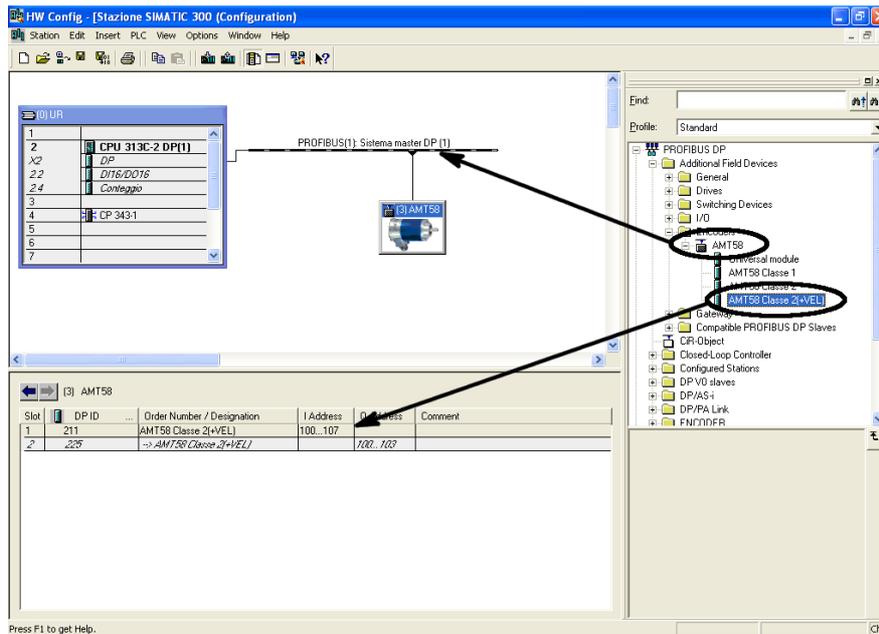
Select the correct GSD file in the installation window and install it.



5.1.2 Adding a node to the project

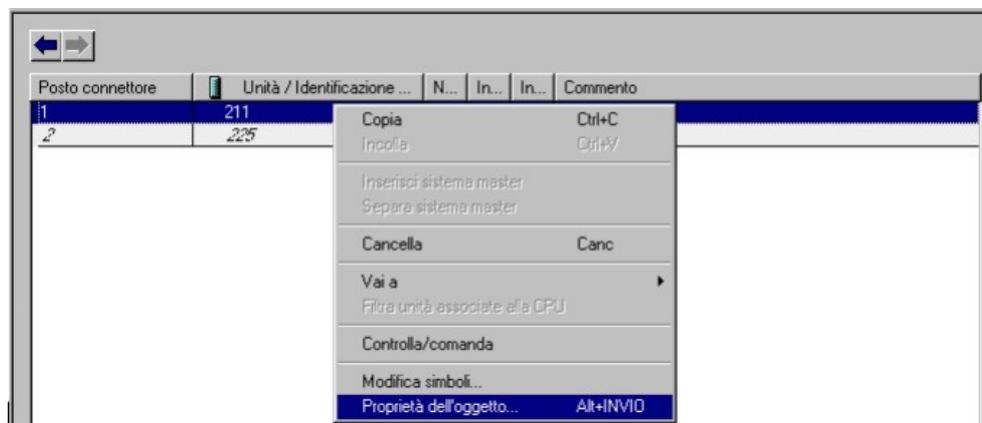
In the left pane of the HW Config window, open the directory tree and select AMT58 module to the window on the right and drop it on "BUS".

Then drag the desired submodule (Class 1, Class 2 or Class 2(+VEL)) to the variables table in the bottom right; in this way you set the class of the device (for further details see section "6.2 Classes of the Device profile")

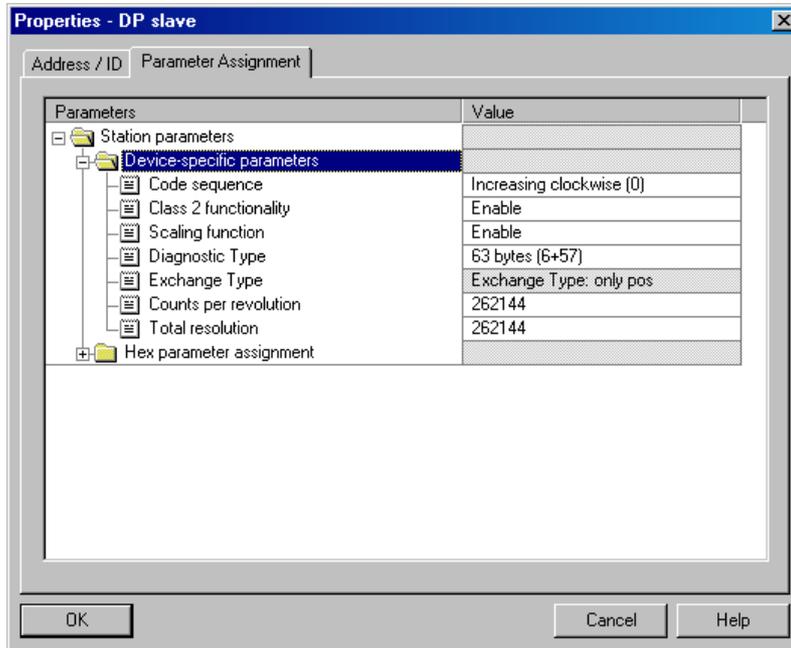


5.1.3 Encoder configuration parameters

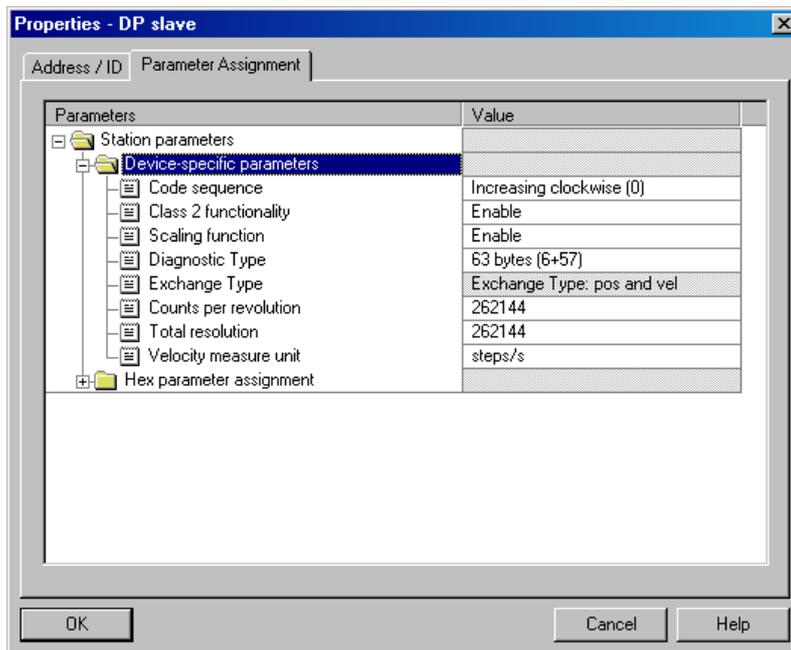
To enter the Encoder configuration parameters window, select the device in the bottom right of the HW Config window and right-click to open the menu; then choose the Object Properties... command.



Properties – DP slave window will appear; in the Parameter Assignment page the list of all encoder parameters is available. For any information on using and setting each parameter refer to section “6.4 DDLM_Set_Prm”.



Class 2 example



Class 2(+VEL) example



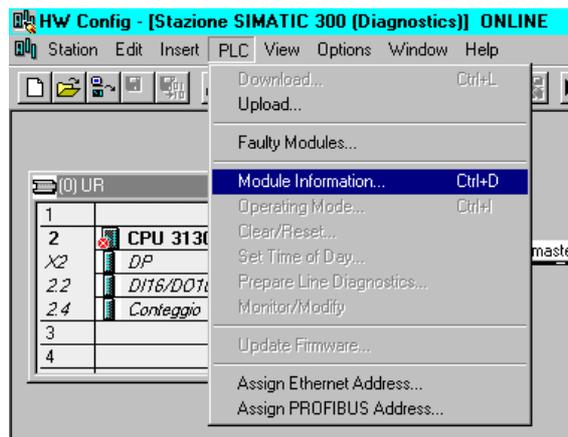
After having set new parameter values, click the OK button to close the Properties – DP slave window and then the Download button (see icon on the left) in the toolbar of the HW Config window to download set parameters.

5.2 Reading diagnostic information

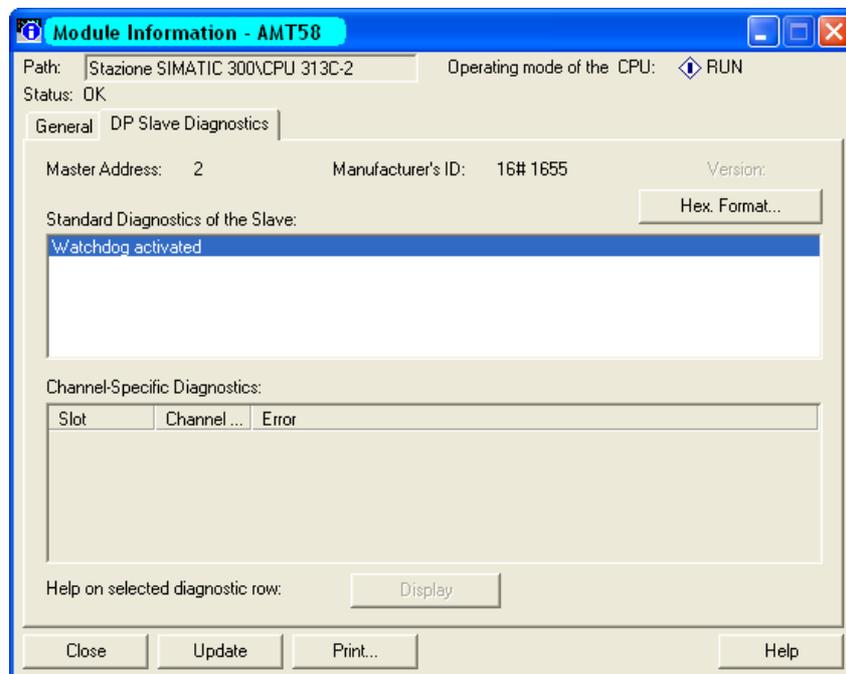
The diagnostic information message can be set either to 16 or 63 bytes, see **Diagnostic type** in encoder parameters.



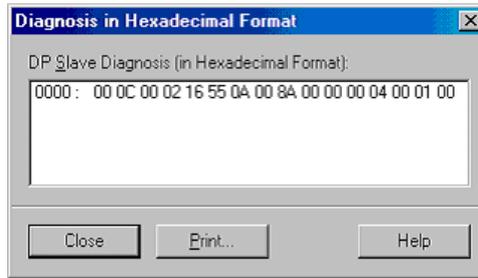
Before entering the diagnostic page, it is necessary to connect to the unit (enter online status). To do this, select Station\Open online in the HW Config window or click the Online<->Offline button (see icon on the left). Then select PLC\Module information... to enter the Module information window. Finally open the DP Slave Diagnostic page.



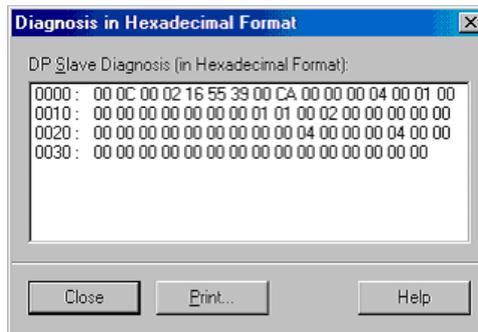
Click the Hex. Format... button to display diagnostic information:



16-byte Diagnostic:



63-byte Diagnostic:



NOTE

Should the 63-byte diagnostic not work properly using STEP7 software we suggest setting the 16-byte diagnostic. If diagnostic information is not used, it is recommended to set 16-byte diagnostic (see "5.1.3 Encoders configuration parameters" section). See section "6.7 DDLM_Slave_Diag" for a complete list and meaning of each diagnostic byte.

5.3 Setting the Preset **Errore**. L'origine riferimento non è stata trovata.



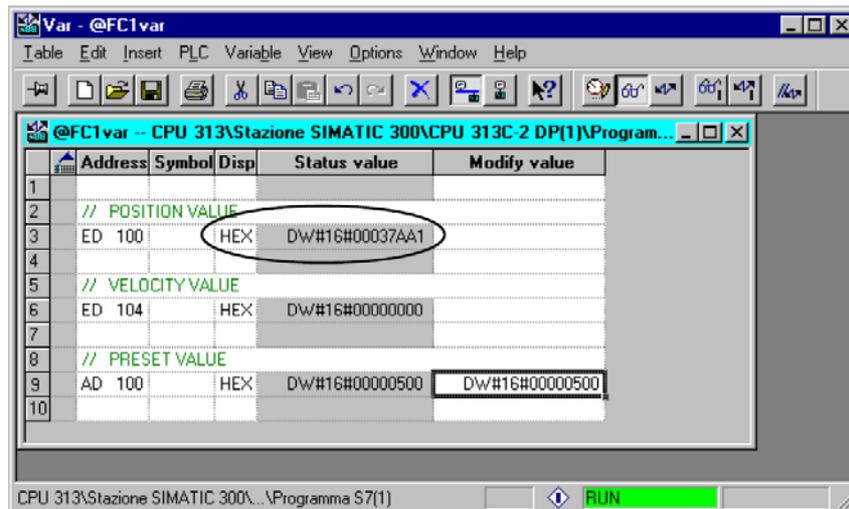
Example

The encoder having device address 1 transmits the position value to the Master.

Position value is loaded into variables ED 100...103 (4 bytes).

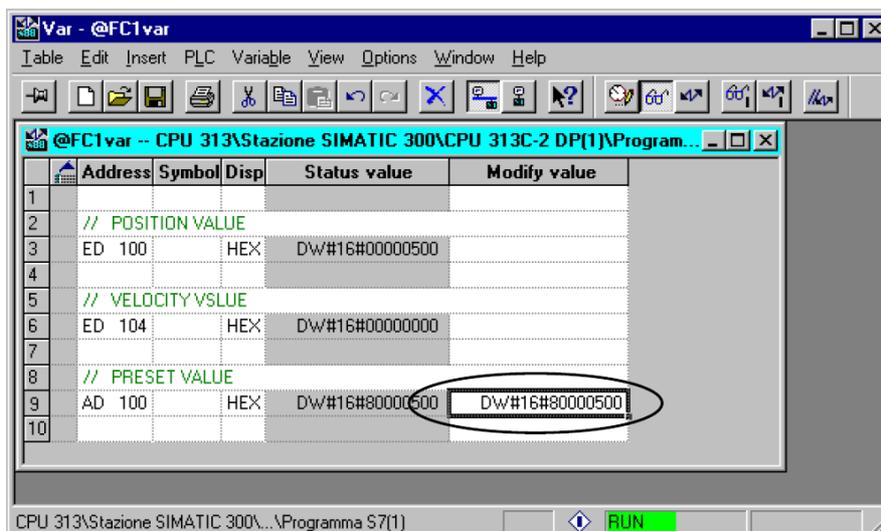
Speed value is loaded into variables ED 104...107 (4 bytes).

The **Preset value** is sent to the encoder using variables AD 100...103 (4 bytes).



The current position of the encoder is 0003 7AA1hex.

To set the **Preset value** = 0000 0500hex, set bit 31 of variable AD 100 = "1" (8000 0500hex).



Finally click Command variables button in the Toolbar (see right icon).

Now the position of the encoder is 0000 0500hex.

To close "Preset" procedure set bit 31 of variable 100 back to "0" and then click the "Command variables" button again.

NOTE



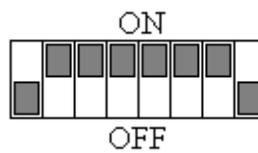
It may occur that data variables having index higher than 127 or data greater than 4 bytes are not treated properly in STEP7 software. Should this happen, we recommend "MD" reference operators (pointers) for encoder position, speed and Preset to be used.

5.4 Set node number via BUS

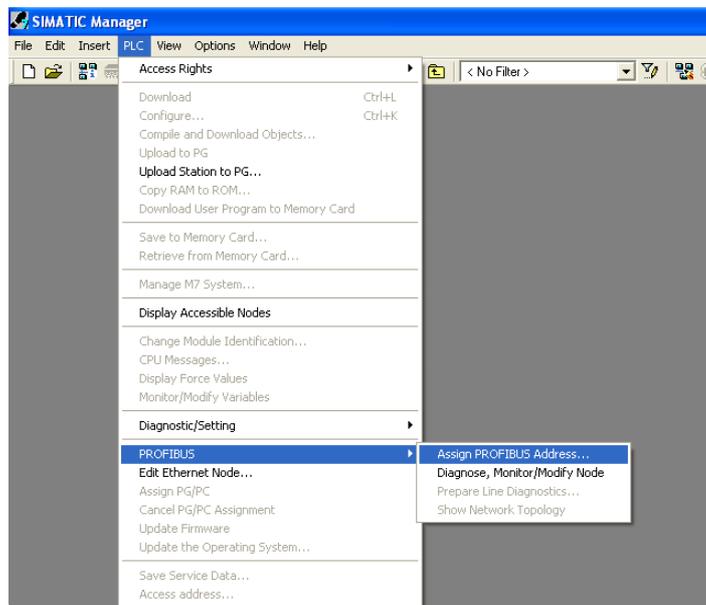
To access this function, PLC must be able to run the SAP55 service.

To set the node number via BUS, set dip-switches to address 126 (0111 1110₂):

DIP A:



To set node number, select PLC\PROFIBUS\Assign PROFIBUS Address... in the SIMATIC Manager window and open the Assign PROFIBUS Address window.



Choose the current address 126 in the first Current PROFIBUS Address combo box and then set the new address in the second New PROFIBUS Address combo box. Press the Apply and OK buttons to confirm.



6. Profibus® interface

Datalogic units are slave devices and comply with “Profibus-DP Profile for Encoders”; they can be set as Class 1, Class 2 or Class 2(+VEL) devices (see section “6.2 Classes of the Device profile **Errore. L'origine riferimento non è stata trovata.**”).

For any omitted information refer to the official Profibus website www.profibus.com.

6.1 GSD file

Profibus encoders are supplied with their own GSD file AMT58-xxx-16x14-FBUS-PB.GSD (see enclosed documentation or click www.datalogic.com). GSD file has to be installed on your Profibus master device.

6.2 Classes of the Device profile

Encoder class must be set when configuring the device.

Class 1 allows basic functions of the device and should be used for:

- sending the position value (see parameter **Position value**);
- changing the counting direction (see parameter **Code sequence**);
- setting the preset value (see parameter **Preset value**).

Class 2 allows to use Class 1 functions and extended functions such as:

- scaling function (see **Scaling function control**);
- diagnostic type (see parameter **Errore. L'origine riferimento non è stata trovata.**).

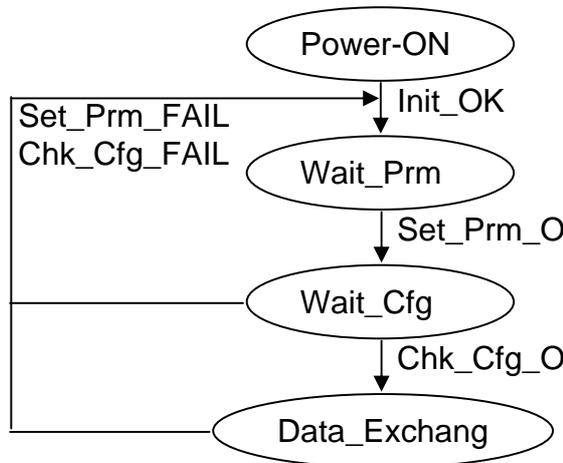
Class 2(+VEL) allows to use Class 2 functions and extended functions such as:

transmission of velocity value (see parameter **Errore. L'origine riferimento non è stata trovata.Position and velocity values**);

- velocity measure unit (see parameter **Velocity measure unit**).

6.3 Modes of operation

Profibus-DP devices allow operation using different communication modes (see Figure below):



NOTE

All parameters -except for **Preset value**- are transmitted in **Set_Prm** mode.

Preset value is transmitted only in **Data_Exchang** mode.

Types of communication

Transmission of data between Master and Slave is carried out using the following types of messages:

- **DDL_M_Set_Prm:**
Used for configuring the slave. This communication mode is active immediately after power is turned ON and used to send parameters from Master to Slave (see section “6.4 DDL_M_Set_Prm”).
- **DDL_M_Chk_Cfg:**
Sets the number of bytes used for data transmission in **Data_Exchang** mode (see section “6.5 DDL_M_Chk_Cfg”).
- **DDL_M_Data_Exchang:**
Used as "standard operation mode".
Used by Master to send the **Preset value**; used by Slave to transmit position and velocity values (see section “6.6 DDL_M_Data_Exchang”).
- **DDL_M_Slave_Diag:**
Used when power is turned on and whenever Master needs to know diagnostic information from Slave device (see section “6.7 DDL_M_Slave_Diag”).
- **Set_Slave_Address:**
Used to set a new node number via BUS (service SAP55, see section “6.8 Set_Slave_Address (service SAP55)”).

6.4 DDLM_Set_Prm

When system is turned on, configuration data set by the operator is sent to the absolute encoder by the controller. Parameters transmission depends on the configuration chosen by the operator. Customarily data is sent automatically while data setting is carried out through a user's interface available in the controller's software (for instance, STEP7, see section "5.1 STEP7 configuration") However sometimes it is necessary to set some bits and bytes according to the working specifications you want to set. Data transmission is carried out in compliance with values set for the encoder profile and shown in the following tables.

DDLM_Set_Prm with Class 1:

Byte	Parameter	
0...9	Reserved for PROFIBUS network	
10	Operating parameters	
	bit 0	Code sequence
	bit 1	Class 2 functionality
	bits2...5	Reserved
	bit 6	Diagnostic type
bit 7	Exchange type	
11...20	Reserved	

DDLM_Set_Prm with Class 2:

Byte	Parameter	
0...9	Reserved for PROFIBUS network	
10	Operating parameters	
	bit 0	Code sequence
	bit 1	Class 2 functionality
	bit 2	Reserved
	bit 3	Scaling function control
	bits 4, 5	Reserved
	bit 6	Diagnostic type
bit 7	Exchange type	
11...14	Counts per revolution	
15...18	Total resolution	
19...20	Reserved	

DDL_M_Set_Prm with Class 2 (+VEL):

Byte	Parameter	
0...9	Reserved for PROFIBUS	
10	Operating parameters	
	bit 0	Code sequence
	bit 1	Class 2 functionality
	bit 2	Reserved
	bit 3	Scaling function control
	bits 4, 5	Reserved
	bit 6	Diagnostic type
	bit 7	Exchange type
11...14	Counts per revolution	
15...18	Total resolution	
19	Velocity measure unit	
20	Reserved	

6.4.1 Byte 10 - Operating parameters

Bit	Function	bit = 0	bit = 1
0	Code sequence	CW	CCW
1	Class 2 functionality	disabled	enabled
2	Reserved		
3	Scaling function control	disabled	enabled
4, 5	Reserved		
6	Diagnostic type	reduced	large
7	Exchange type	pos	pos + vel

Code sequence

It defines whether the position value output by the transducer increases when the encoder shaft rotates clockwise (CW) or counterclockwise (CCW). When **Code sequence** = 0, the position value increases when the encoder shaft rotates clockwise; on the contrary, when **Code sequence** = 1, the position value increases when the encoder shaft rotates counterclockwise. CW and CCW rotations are viewed from shaft end.

Default = 0 (min. = 0, max. = 1)

Class 2 functionality

Two device classes are defined in the encoder profile, one mandatory class (Class 1) and one class with optional functions (Class 2). This encoder implements functions of both Class 1 and Class 2. For any information on the available encoder classes see the section “6.2 Classes of the Device profile on page 20.

0 = Disabled = Encoder Class 1 is set.

1 = Enabled = Encoder Class 2 (or Class2(+VEL) is set.

Default = 1 (min. = 0, max. = 1) **Scaling function control**

When this option is disabled (0), device uses the hardware resolution, i.e. the hardware counts per revolution and the hardware number of revolutions, see the encoder data on the label applied to the device; when it is enabled (1), device uses the resolution transmitted through bytes from 11 to 18 (**Counts per revolution** and **Total resolution**).

For a correct use of this function see sections “6.4.2 Bytes 11...14” and “6.4.3 Bytes 15...18”.

Default = 1 (min. = 0, max. = 1)



WARNING

You can set new values next to the **Counts per revolution** and **Total resolution** items only if **Class 2 functionality** = ENABLED; if **Scaling function control** = ENABLED the set resolution values are enabled and used by the encoder; on the contrary, if **Scaling function control** = DISABLED you are allowed to set new resolution values, however they are not enabled even if sent to the encoder: the encoder still goes on using the default values uploaded from the GSD file, NOT the new entered values, until you enable the **Scaling function control**.

Diagnostic type

0 = Reduced = 16-byte diagnostic information

1 = Extended = 63-byte diagnostic information

Encoder Class 1 provides only reduced diagnostic.

The meaning of each diagnostic byte is detailed in the section “6.7 DDLM_Slave_Diag”.

Default = 0 (min. = 0, max. = 0) for Class 1

Default = 0 (min. = 0, max. = 1) for Class 2 and Class 2 (+VEL)

Exchange type

0 = Pos = device transmits only position value (Class 1 and Class 2).

1 = Pos + vel = device transmits both position and velocity values (Class 2(+VEL)).

Default = 0 (min. = 0, max. = 0) for Class 1 and Class 2

Default = 1 (min. = 1, max. = 1) for Class 2 (+VEL)

6.4.2 Bytes 11...14 **Counts per revolution**



WARNING

You can set a new value next to the **Counts per revolution** item only if **Class 2 functionality** = ENABLED; if **Scaling function control** = ENABLED the set resolution values are enabled and used by the encoder; on the contrary, if **Scaling function control** = DISABLED you are allowed to set new resolution values, however they are not enabled even if sent to the encoder: the encoder still goes on using the default values uploaded from the GSD file, NOT the new entered values, until you enable the **Scaling function control**.

See the section “6.4.1 Byte 10 – Operating parameters” on page 23.

Counts per revolution parameter allows to program a user specific singleturn resolution (i.e. the desired number of information per revolution).

Byte	11	12	13	14
Bit	31-24	23-16	15-8	7-0
Data	2^{31} to 2^{24}	2^{23} to 2^{16}	2^{15} to 2^8	2^7 to 2^0

Allowed values are equal to or lower than Hardware counts per revolution value. We suggest setting power of 2 values (1, 2, 4, ... 2048, 4096, ...).

Setting a value greater than allowed causes the resolution to be forced to Hardware counts per revolution value.

Default = 262144 (min. = 1, max. = 262144) for HS58

Default = 65536 (min. = 1, max. = 65536) for HM58



WARNING

When you set a new value next to **Counts per revolution** item, please always check also **Total resolution** item value and be sure that the resulting number of revolution complies with the Hardware number of revolutions of the device.

Let's say our encoder is programmed as follows:

Counts per revolution: 8192

Total resolution = 33554432_{10} = 8192 (cpr) * 4096 (rev.)

Let's set a new singleturn resolution, for instance: **Counts per revolution** = 360.

If we do not change the **Errore. L'origine riferimento non è stata trovata.** value at the same time, we will get the following result:

$$\text{Number of revolutions} = \frac{33554432 \text{ (Total resolution)}}{360 \text{ (Counts per revolution)}} = 93206.755\dots$$

As you can see, the encoder is required to carry out more than 93000 revolutions, this cannot be as the hardware number of revolutions is, as stated, 16384. When this happens, the encoder falls into an error signalling the faulty condition through the diagnostic LEDs (see on page 12).

6.4.3 Bytes 15...18

Total resolution



WARNING

You can set a new value next to the **Total resolution** item only if **Class 2 functionality** = ENABLED; if **Scaling function control** = ENABLED the set resolution values are enabled and used by the encoder; on the contrary, if **Scaling function control** = DISABLED you are allowed to set new resolution values, however they are not enabled even if sent to the encoder: the encoder still goes on using the default values uploaded from the GSD file, NOT the new entered values, until you enable the **Scaling function control**. See the section "6.4.1 Byte 10 – Operating parameters" on page 23.

This parameter is intended to set the number of distinguishable steps over the total measuring range. The total resolution of the encoder results from the product of **Counts per revolution** by Number of revolutions.

Byte	15	16	17	18
Bit	31-24	23-16	15-8	7-0
Data	2^{31} to 2^{24}	2^{23} to 2^{16}	2^{15} to 2^8	2^7 to 2^0

Allowed values are equal to or lower than the Total hardware resolution value.

Setting a value greater than allowed causes the resolution to be forced to the Total hardware resolution value.

$$\text{Number of revolutions} = \frac{\text{Total resolution}}{\text{Counts per revolution}}$$

We recommend the Number of revolutions to be set to a power of 2. This is meant to avoid problems when using the device in endless operation (when crossing the physical zero) and entering the "Red Zone" (see the section "6.9 Red Zone").

Default = 262144 (min. = 1, max. = 262144) for HS58

Default = 1073741824 (min. = 1, max. = 1073741824) for HM58



WARNING

When you set a new value next to the **Total resolution** item, please always check also the **Counts per revolution** item value and be sure that the resulting number of revolutions complies with the **Hardware number of revolutions** of the device.

Let's say our encoder is programmed as follows:

Counts per revolution: 8192

Total resolution = $33554432_{10} = 8192 \text{ (cpr)} * 4096 \text{ (rev.)}$

Let's set a new total resolution, for instance: **Total resolution** = 360.

As the **Total resolution** must be greater than or equal to the **Counts per revolution**, the above setting is not allowed. When this happens, the encoder falls into an error signalling the faulty condition through the diagnostic LEDs (see on page 12).



Example

“HS5818/FB-xx”: singleturn encoder

- Hardware counts per revolution = 18 bit/turn ($2^{18} = 262144 \text{ cpr}$)
- Hardware number of turns = 1
- Total hardware resolution = 18 bit ($262144 * 1 = 262144$)

“HM5816/16384/FB-xx”: multiturn encoder

- Hardware counts per revolution = 16 bit/turn ($2^{16} = 65536 \text{ cpr}$)
- Hardware number of turns = 14 bit (16384 turn)
- Total hardware resolution = 30 bit ($65536 * 16384 = 2^{30} = 1073741824$)



Example

Multiturn encoder “HM5816/16384/FB-6” with “BC-PB-C” connection cap.

Resolution is:

- Hardware counts per revolution = 65536 (2^{16})
 - Hardware number of turns = 16384 (2^{14})
 - Total hardware resolution = 1073741824 (2^{30})
- 2048 steps per revolution * 1024 turns are required:
- Enable **Scaling function control**: byte 10=0A hex (bit 1=bit 3=“1”)
 - **Counts per revolution** = 2048: byte 11...14 = 0000 0800 hex
 - **Total resolution** = 2048 * 1024 = 2097152: byte 15...18 = 0020 0000 hex.



NOTE

When new values are set next to the items **Counts per revolution** and/or **Total resolution**, a new **Preset value** and zero-setting values are required according to the new resolution.

6.4.4 Byte 19 **Velocity measure unit**

This byte is available only when Class 2(+VEL) is set (see also **Class 2 functionality** and **Exchange type** items). It defines the unit of measurement for speed value transmitted by the device.

00 = rpm (revolutions per minute);

01 = step/s (steps per second).

Default = 0 (min. = 0, max. = 1)

6.5 DDLM_Chk_Cfg

Configuration function allows the Master to send configuration data to the Slave for any check operation. The main purpose of this function is to set the number of bytes used for the Data_Exchange as viewed from Master side.

Chk_Cfg message structure (1 byte):

bit 7 = Consistency (= "1")

bit 6 = Word format ("0"=byte, "1"=word=4byte)

bit 5...4 = In/out data ("01"=Input, "10"=output)

bit 3...0 = Length code



Example

bit	7	6	5	4	3	2	1	0	
Data	1	1	0	1	0	0	0	1	D1h
	1	1	0	1	0	0	1	1	D3h
	1	1	1	0	0	0	0	1	E1h

Class 1 and Class 2:

D1hex = 4 byte input

E1hex = 4 byte output

Class 2(+VEL):

D3hex = 8 byte input

E1hex = 4 byte output

6.6 DDLM_Data_Exchange

This is the normal operation status of the system. The Slave (for both Class 1 and Class 2) can transmit the position value (and speed value if Class 2+VEL is set) and receive the **Preset value** from the Master.

Position value

when Class 1 and Class 2 are set (Encoder → Master)

Byte	1	2	3	4
Bit	31-24	23-16	15-8	7-0
Data	2^{31} to 2^{24}	2^{23} to 2^{16}	2^{15} to 2^8	2^7 to 2^0

Position and velocity values

when Class 2 (+VEL) is set (Encoder → Master)

Byte	1	...	4	5	...	8
Bit	31-24	...	7-0	31-24	...	7-0
	Position			Velocity		

Preset value

when any Class is set (Master → Slave)

Byte	1	2	3	4
Bit	31-24	23-16	15-8	7-0
Data	2^{31} to 2^{24}	2^{23} to 2^{16}	2^{15} to 2^8	2^7 to 2^0

The Preset function is meant to assign a desired value to a physical position of the encoder. The chosen physical position will get the value set next to this item and all the previous and following positions will get a value according to it. This function is useful, for example, when the zero position of the encoder and the zero position of the axis need to match. The preset value will be set for the position of the encoder in the moment when the preset value is sent. The **Preset value** value is sent by the Master to the Slave in **Data_Exchange** mode by setting bit 31 = "1" for 3 cycles.

The MSB of the preset value controls the preset function in the following way:

Normal operating mode: MSB = 0 (bit 31): the encoder will make no change in preset value.

Preset mode: MSB = 1 (bit 31): with the MSB = 1 the encoder accepts the transferred value (bits 0 ... 30) as a preset value in binary code.

- If **Scaling function control** = DISABLED, then **Preset value** must be less than the **Total hardware resolution**.
- If **Scaling function control** = ENABLED, then **Preset value** must be less than the **Total resolution**.



Example

Preset value to be set = 0000 1000hex
 Current **Position value** = 0005 5000hex

	Byte	1	2	3	4
Cycle	Bit	31-24	23-16	15-8	7-0
1°	M→S	80	00	10	00
	S→M	00	05	50	00
2°	M→S	80	00	10	00
	S→M	00	05	50	00
3°	M→S	80	00	10	00
	S→M	00	00	10	00



NOTE

We suggest setting the **Preset value** when the shaft is in stop.
 The new **Preset value** is saved immediately after receipt.

6.7 DDLM_Slave_Diag

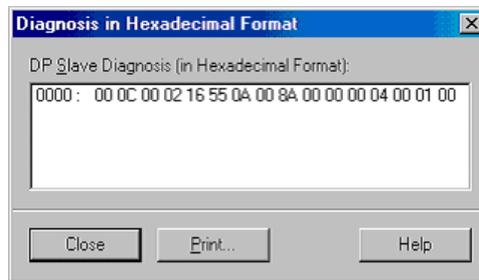
The Master device can send a request for diagnostic information at any time to the Slave device.

Datalogic devices provide two types of diagnostics:

- reduced (16 bytes)
- extended (63 bytes).

Set the diagnostic type during DDLM_Set_Prm, operating parameters (byte 10), see section “6.4.1 Byte 10 - Operating parameters”.

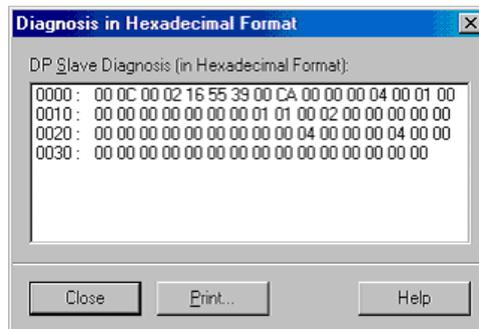
16-byte Diagnostic:



Byte	Description
0	Status 1
1	Status 2
2	Status 3
3	Master ID
4	Manufacturer ID
5	
6	Extended diagnostic header
7	Alarms

Byte	Description
8	Operating status
9	Encoder type
10	Hardware single-turn resolution
11	
12	
13	Hardware number of revolution
14	
15	

63-byte Diagnostic:

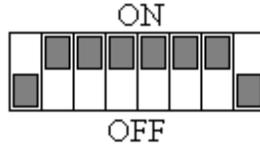


Byte	Description	Byte	Description
0	Status 1	31	Offset
1	Status 2	32	
2	Status 3	33	
3	Master ID	34	
4	Manufacturer ID	35	Manufacturer offset value
5		36	
6	Extended diagnostic header	37	
7	Alarms	38	
8	Operating status	39	Programmed single-turn resolution
9	Encoder type	40	
10	Hardware single-turn resolution	41	
11		42	
12		43	
13	Hardware number of revolution	44	Programmed total resolution
14		45	
15		46	
16	Additional alarms	47	Serial number
17	Supported alarms	48	
18		49	
19	Warnings	50	
20		51	
21	Supported warnings	52	
22		53	
23	Profile version	54	
24		55	
25	Software version	56	
26		57	Reserved
27	Operating time	58	Reserved
28		59	Reserved
29		60	Reserved
30		61	Reserved
		62	Reserved

6.8 Set_Slave_Address (service SAP55)

To access this function, the PLC must be able to run the SAP55 service.

Set dip-switch to address 126 (0111 1110₂):
DIP A:



The message has the following DATA bytes:

Byte	Description
0	New node number
1	Manufacturer ID
2	
3	Lock node number (= 0: not supported)

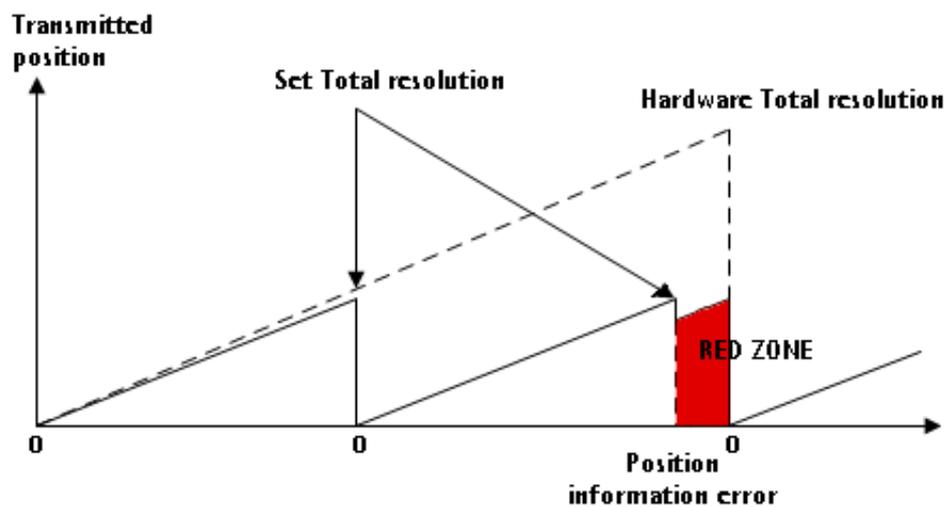
6.9 "Red Zone"

The so-called "Red Zone" occurs when:

$$\text{Number of revolutions} = \frac{\text{Total resolution}}{\text{Counts per revolution}}$$

is not a power of 2.

When this problem arises, the device must operate within the "red zone" for a certain number of positions. The size of the "red zone" is variable. To calculate it we must subtract the **Total resolution** value from the **Hardware total resolution** of the device as many times as until the difference is less than the the set **Total resolution** value. When the encoder crosses the limit of the last **Total resolution** section thus entering the "red zone", a counting error occurs, i.e. a jump in the position count. The problem can be represented graphically in the Figure below.





Example

“HM5816/16384/FB-xx”: multiturn encoder

- Hardware counts per revolution = 65536 (2^{16})
- Hardware number of turns = 16384 (2^{14})
- Total hardware resolution = 1073741824 (2^{30})

Set parameters values:

- **Counts per revolution** = 50000
- Number of revolutions = 8000
- **Total resolution** = 400000000

$$\frac{\text{Hardware number of turns}}{\text{Number of revolutions}} = \frac{16384}{8000} = 2.048$$

It follows that, for 384 revolutions ($16384 - 2 * 8000 = 384$), the encoder will work within the "Red Zone" limits.



NOTE

- The “Red Zone” status is indicated by the green LED flashing while the red LED is OFF (see the section “4.9 Diagnostic LEDs” on page 12).
- Within the limits of the “Red Zone”, the transmitted position is coherent with setting resolution: it is calculated so that the last position transmitted before zero position is **Total resolution** -1.
- Make attention using the values sent by the encoder while working in “Red Zone”. When the encoder changes from normal status to “Red Zone” status (and vice versa) a jump of position occurs.

- Default parameters list

Parameters list	Default values
Code sequence	0
Class 2 functionality	1
Scaling function control	1
Diagnostic type	0
Exchange type	Class 1 and Class 2 = 0 Class 2 (+VEL) = 1
Counts per revolution	16384
Total resolution	1073741824
Velocity measure unit	0