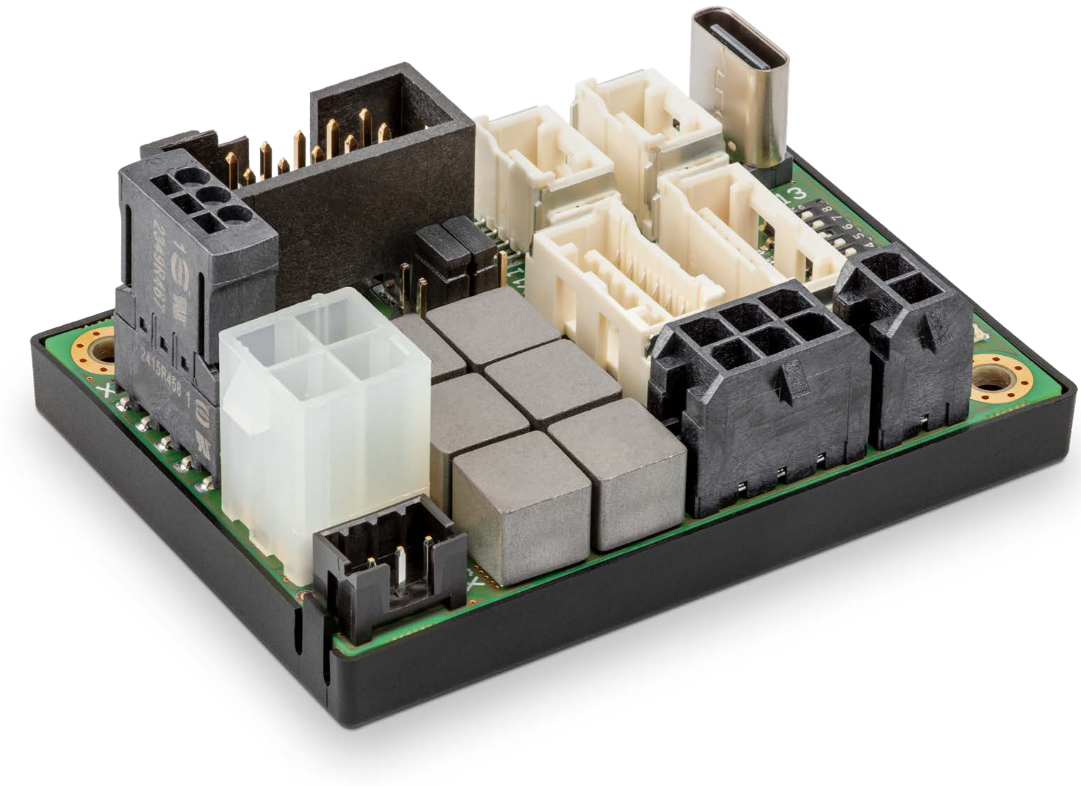
maxon

Servo Controller

ESCON2 Compact 60/2

Hardware Reference



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ESCON2 Compact 60/2 Servo Controller | P/N 903540
Hardware Reference
CCMC | Edition 2026-01 | DocID rel12934

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TABLE OF CONTENTS

READ THIS FIRST

These instructions are for qualified technical personnel only. Before you start any work:

- *Read this manual carefully.*
- *Make sure that you understand this manual.*
- *Follow all instructions in this manual.*

The product is partly completed machinery according to EU Directive 2006/42/EC, Article 2, Clause (g). You must incorporate it into or assemble it with other machinery or other partly completed machinery or equipment.
You must not put the device into service unless all these conditions are met:

- *The complete machinery complies with all applicable requirements of EU Directive 2006/42/EC.*
- *The complete machinery fulfills all applicable health and safety requirements.*
- *All interfaces are implemented and comply with the requirements given in this manual.*

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1 ABOUT

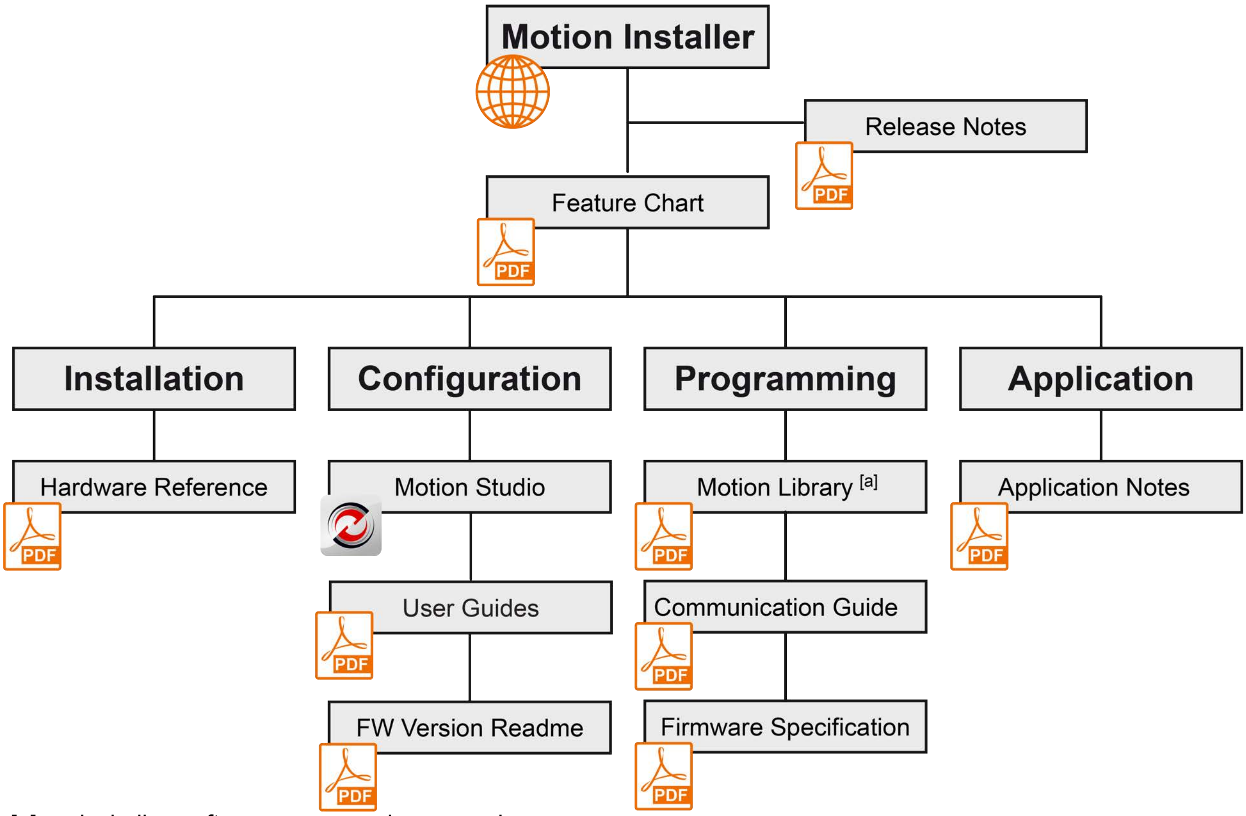
1.1 About this document

1.1.1 Intended purpose

This document familiarizes you with the ESCON2 Compact 60/2 Servo Controller. It describes the tasks for safe and proper installation and commissioning. Follow the instructions:

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

This document is part of a documentation set. It includes performance data, specifications, standards information, connection details, pin assignments, and wiring examples. The overview below shows the documentation hierarchy and how its parts are related:



[a] including software programming examples

Figure 1-1 Documentation structure

Find the latest edition of this document, along with additional documentation and software for ESCON2 Servo Controllers, at: http://escon.maxongroup.com

1.1.2 Target audience

This document is intended for trained and skilled personnel. It provides information on how to understand and perform the respective tasks and duties.

1.1.3 How to use

Follow these notations and codes throughout the document.

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

Table 1-1 Notations used in this document

1.1.4 Symbols & signs

This document uses the following symbols and signs:

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

Table 1-2 Symbols and signs

1.1.5 Trademarks and brand names

All trademarks, brand names or other signs mentioned in this manual remain the property of their respective owners. They are protected by trademark, copyright, and/or other applicable laws. For easier reading, no symbols such as ® or ™ are being used with respect to the trademarks or brand names mentioned herein.
Nothing in this manual shall be construed as granting any rights with respect to the mentioned trademarks, brand named or other signs, including without limitation neither the right to use the mentioned trademarks, brand names or other signs without permission of the respective owners.

The trademarks, brand names or other signs are mentioned in this manual solely for information or identification purposes.

1.1.6 Copyright

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1.1.7 Sources for additional information

For further details and additional information, please refer to the resources listed below:

Ref. no.	Reference
[1]	maxon: ESCON2 Communication Guide http://escon.maxongroup.com
[2]	maxon: ESCON2 Firmware Specification http://escon.maxongroup.com

Table 1-3 Sources for additional information

1.2 About the device

The ESCON2 Compact 60/2 is a small, powerful 4-quadrant PWM Servo Controller. Its high power density allows flexible use for brushed DC motors and brushless EC (BLDC) motors up to 120 Watts. It supports various feedback options, such as Hall sensors, incremental encoders, and absolute sensors for many drive applications.

The device is designed to be controlled by analog and digital set values, or as a slave node in a CANopen network. You can also operate it via any USB communication port of a Windows workstation. It has extensive analog and digital I/O functions.

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

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

You can find the latest edition of this document on the Internet: ➔http://escon.maxongroup.com. This website also gives you access to related documents and software for ESCON2 servo controllers.

In addition, you can watch video tutorials in the ESCON video library. These tutorials show how to start with «Motion Studio». They also show how to set up communication interfaces, configure the controller, and give helpful tips, etc. Explore the video library on Vimeo: ➔https://vimeo.com/album/4646396

1.3 About the safety precautions

- Read and understand the note ➔«READ THIS FIRST»!
- Do not start any work unless you have the required skills ➔Chapter “1.1.2 Target audience” on page 1-5.
- Refer to ➔Chapter “1.1.4 Symbols & signs” on page 1-6 to understand the subsequently used indicators!
- Follow all applicable health, safety, accident prevention, and environmental protection regulations for your country and work site.

DANGER

High voltage and/or electrical shock
Touching live wires can cause death or serious injuries.

- *Treat all power cables as live unless proven otherwise.*
- *Ensure neither end of the cable is connected to live power.*
- *Ensure the power source cannot be turned on while you work.*
- *Follow lock-out/tag-out procedures.*

Requirements

- *Install all devices and components according to local regulations.*
- *Electronic devices are not fail-safe. Install separate monitoring and safety equipment for each machine. If the machine has a failure, the drive system must go into a safe state and stay in this state. Possible failures include incorrect operation, failure of the control unit, failure of the cables, or other faults.*
- *Do not repair any components that maxon supplies.*

Electrostatic sensitive device (ESD)

- *Observe precautions for handling Electrostatic sensitive devices.*
- *Handle the device with care.*

2 SPECIFICATIONS

2.1 Technical data

ESCON2 Compact 60/2 (P/N 903540)		
Electrical data	Nominal power supply voltage V_{CC}	10…60 VDC
	Nominal logic supply voltage V_C	10…60 VDC
	Absolute supply voltage V_{min} / V_{max}	8 VDC / 62 VDC
	Output voltage (max.)	0.90 × V_{CC}
	Output current I_{cont} / I_{max} (< 30 s)	2 A / 6 A (current measurement resolution: 5.37 mA)
	Pulse Width Modulation (PWM) frequency	100 kHz
	Sampling rate PI current controller	50 kHz
	Sampling rate PI speed controller	10 kHz
	Sampling rate analog input	50 kHz
	Max. efficiency	96 % ➔Figure 2-3
	Max. speed DC motor	Is limited by the max. permissible motor speed and the max. output voltage of the controller.
	Max. speed EC motor	120,000 rpm (FOC, 1 pole pair). Can be limited by the max. permissible motor speed and the max. output voltage of the controller.
	Built-in motor choke per phase	44 µH / 5 A
Inputs & outputs	Sensor 1 Digital Hall sensor H1, H2, H3	0...24 VDC (internal pull-up)
	Sensor 2 (choice between multiple functions): • Digital incremental encoder • SSI absolute encoder • BISS C unidirectional absolute encoder • High-speed digital inputs 1…2 • High-speed digital inputs 3…4 • High-speed digital output 1	 2-channel, EIA/RS422, max. 6.67 MHz 0.4...2 MHz (single-ended, configurable) 0.4...4 MHz (single-ended, configurable) EIA/RS422, max. 6.67 MHz Logic: 0...12 VDC, max. 6.25 MHz 3.3 VDC / I_L ≤ 24 mA / R_i = 75 Ω
	Digital Inputs 1...4	Logic: 0…30 VDC, inputs 1…2 PWM capable
	Digital Outputs 1...2	max. 36 VDC / I_L ≤ 500 mA (open drain with internal pull-up)
	Analog Inputs 1...2	Resolution 12-bit, ± 10 VDC (differential), 10 kHz
	Analog Outputs 1...2	Resolution 12-bit, ± 4 VDC (referenced to GND), 25 kHz
	Motor temperature sensor [a]	Resolution 12-bit, 0...3.3 VDC (internal pull-up)
Voltage outputs	Sensor supply voltage V_{Sensor}	5 VDC / I_L ≤ 145 mA
	Peripheral supply voltage $V_{Peripheral}$	-

Continued on next page.

ESCON2 Compact 60/2 (P/N 903540)			
Motor connections	DC motor		+ Motor, − Motor
	EC motor		Motor winding 1, Motor winding 2, Motor winding 3
Communi-cation interfaces	CAN		Max. 1 Mbit/s
	RS232		-
	USB		12 Mbit/s (Full Speed)
Status indicators	Device status		Operation (green) Warning/Error (red)
Mechanical data	Dimensions (L × W × H)		55 × 40 × 22.8 mm
	Weight (approx.)		32 g
	Mounting		M2.5 screws (max. tightening torque 0.16 Nm)
Environmen-tal conditions	Temperature	Operation	−40…+60 °C
		Extended range [b]	+60…+65 °C Derating: approx. -0.235 A/°C ➔Figure 2-2
		Storage	−40…+85 °C
	Altitude [c]	Operation	0…500 m MSL
		Extended range [b]	500...10'000 m MSL Derating ➔Figure 2-2
	Humidity		5…90 % (condensation not permitted)

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

Table 2-4 Technical data

2.2 Thermal data

Mandatory operation within the specified limits
- *Operation within the specified thermal limits is mandatory.*
- *If the ambient temperature exceeds the specified limits, thermal overload can occur even at low output currents.*

2.2.1 Test setup for data collection

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

2.2.2 Derating of output current

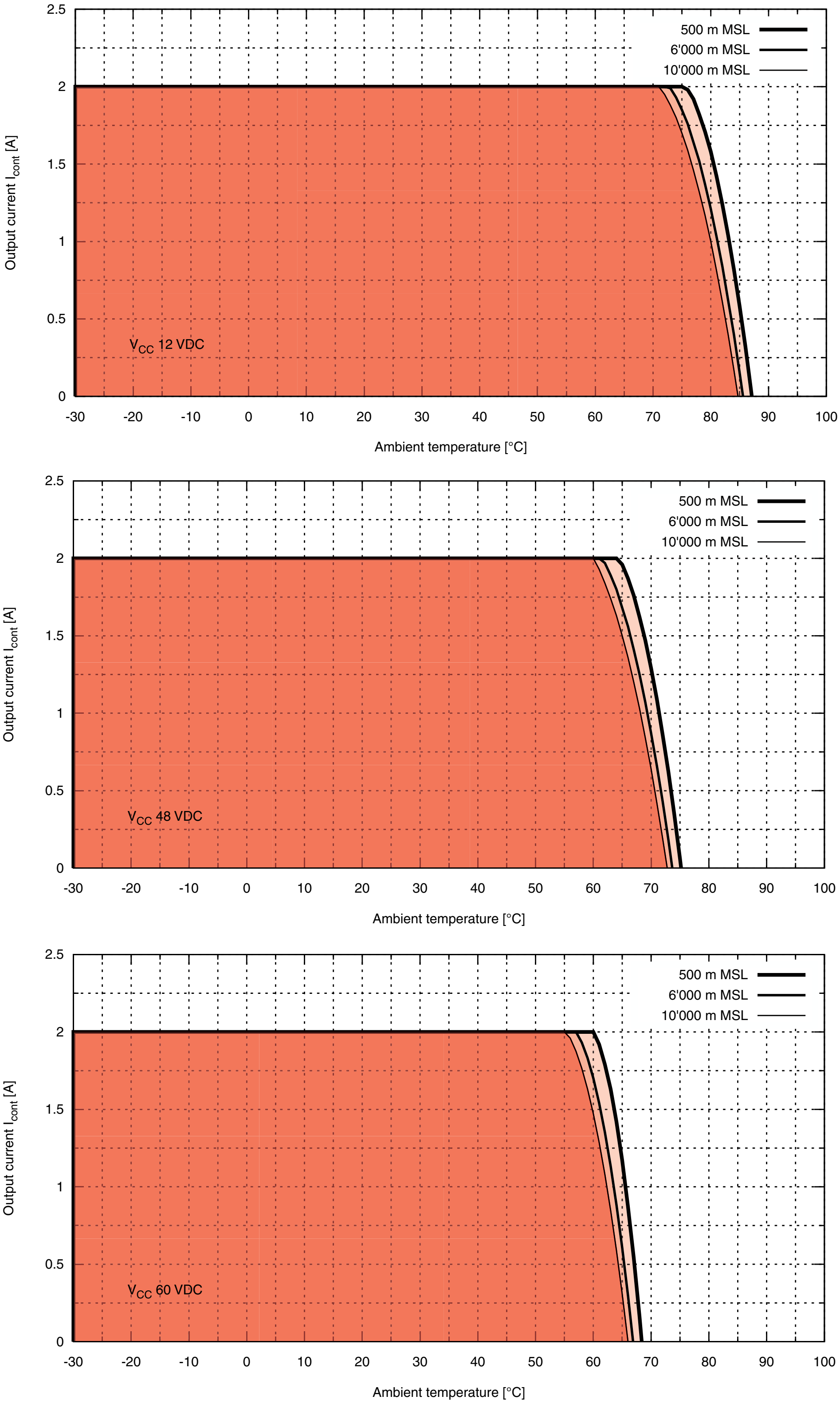

Figure 2-2 Derating of output current

2.2.3 Power dissipation and efficiency

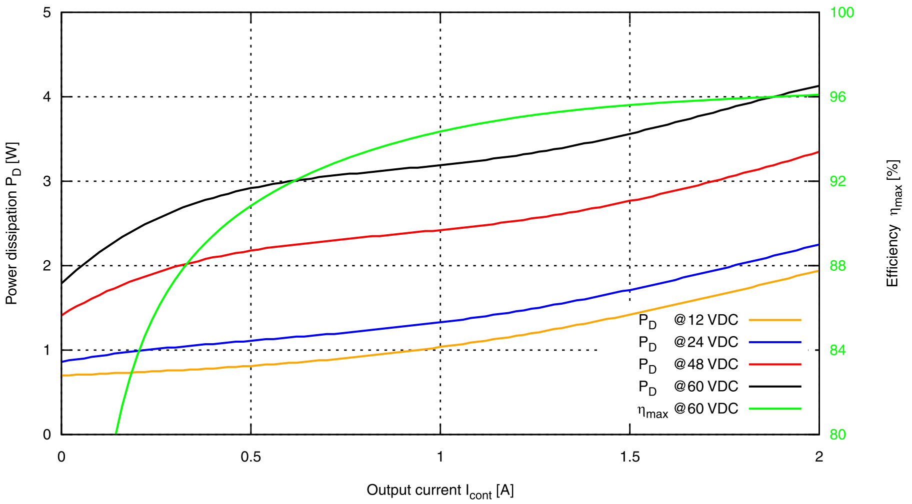

Figure 2-3 Power dissipation and efficiency

2.3 Limitations

Functionality		Switch-off threshold [a]	Recovery threshold [b]
Undervoltage		7.5 VDC	7.75 VDC
Overvoltage		65 VDC	64 VDC
Overcurrent		10 A	—
Thermal overload	logic	117 °C	107 °C
	power stage	100 °C	—

[a] The controller triggers the corresponding fault reaction. The controller changes to the disabled state. Refer to ➔ESCON2 Firmware Specification [2].

[b] The system allows you to reset the fault.

Table 2-5 Limitations

The device has a configurable output current limit and an overcurrent protection function. This protects the controller in case of a short circuit in a motor winding or a damaged power stage. The undervoltage, overvoltage, and thermal overload power stage protection limits are also configurable. For the thermal overload power stage protection, a linear derating of the maximum output current is implemented, which starts 10 °C below the switch-off threshold. For more information, see the ➔ESCON2 Firmware Specification [2].

2.4 Dimensional drawing

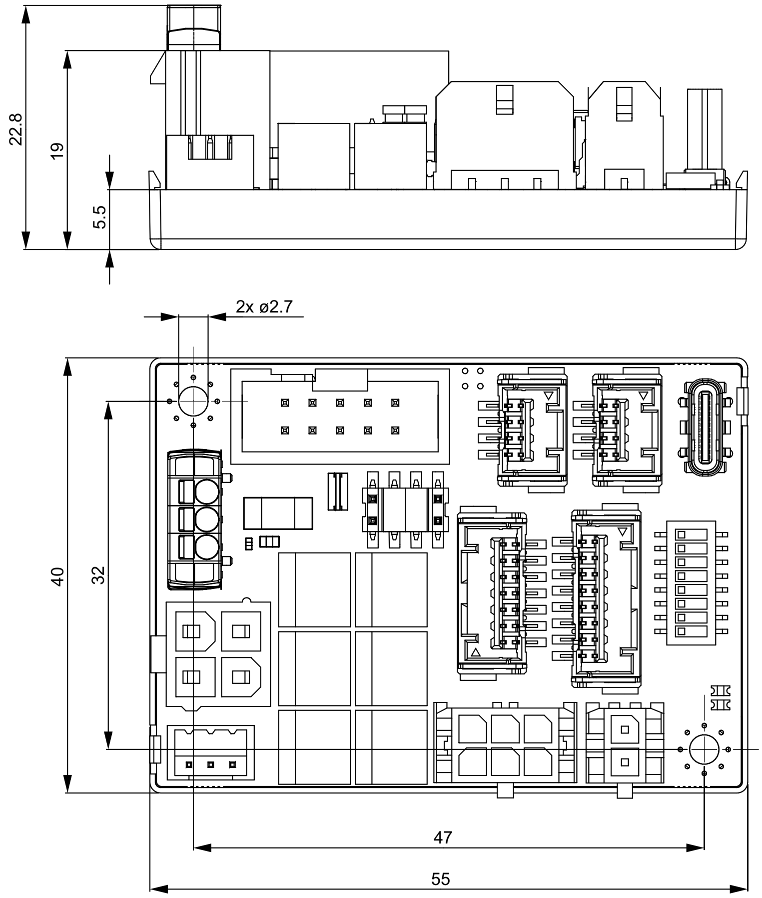

Figure 2-4 Dimensional drawing [mm]

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2.5 Standards

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

Important notice
Compliance of the device with the mentioned standards does not guarantee compliance in the final, ready-to-operate setup. To achieve compliance for your operational system, you must perform EMC testing on the complete equipment as a whole.

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

<table>
<tr><th colspan="3">Others</th></tr>
<tr><th rowspan="2">Environment</th><td>IEC/EN 60068-2-6</td><td>Environmental testing – Test Fc: Vibration (sinusoidal, 10…500 Hz, 20 m/s^2)</td></tr>
<tr><td>MIL-STD-810F</td><td>Random transport (10…500 Hz up to 2.53 g_{rms})</td></tr>
<tr><th>Safety</th><td>UL File Number</td><td>Unassembled printed circuit boards: E207844</td></tr>
<tr><th>Reliability</th><td>MIL-HDBK-217F [a]</td><td>Reliability prediction of electronic equipment
Environment: Ground, benign (GB)
Ambient temperature: 298 K (25 °C)
Component stress: In accordance with circuit diagram and nominal power
Mean Time Between Failures (MTBF): 379’151 hours</td></tr>
</table>

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

Table 2-6 Standards

3 SETUP

IMPORTANT NOTICE: PREREQUISITES FOR PERMISSION TO COMMENCE INSTALLATION

The **ESCON2 Compact 60/2** is considered partly completed machinery according to EU Directive 2006/42/EC, Article 2, Clause (g). **It is intended to be incorporated into or assembled with other machinery or partly completed machinery or equipment.**

WARNING

Risk of injury

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

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

CAUTION

Burn hazard

Hot surfaces can cause burns.

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

3.1 Generally applicable rules

Maximum permitted supply voltage

- *Make sure that the power supply voltage is between 10…60 VDC.*
- *Supply voltages above 65 VDC, or wrong polarity will destroy the unit.*
- *The necessary output current depends on the load torque. The output current limits are:*
  – continuous max. 2 A
  – short-time (acceleration) max. 6 A (< 30 s)

Hot plugging the USB interface may cause hardware damage

Do not hot-plug the USB interface (connecting while the power supply is on), the possibly high potential differences of the two power supplies of controller and PC/Notebook can lead to damaged hardware.

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

Best practice

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

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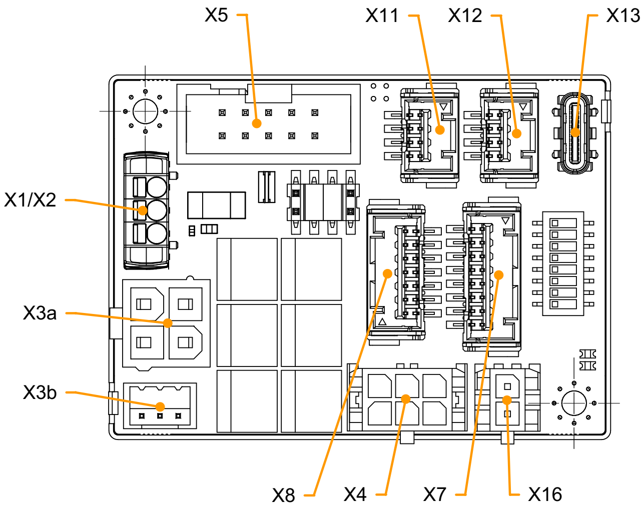
3.2 Connections

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



X1/X2	Power & Logic supply ➔page 3-18
X3a/b	Motor ➔page 3-20
X4	Sensor 1 Hall sensor ➔page 3-21
X5	Sensor 2 ➔page 3-23
X7	Digital I/Os ➔page 3-32
X8	Analog I/Os ➔page 3-36
X11	CAN 1 ➔page 3-38
X12	CAN 2 ➔page 3-38
X13	USB ➔page 3-40
X16	Motor temperature sensor ➔page 3-41

Figure 3-5 Connections

3.2.1 Cabling

PLUG&PLAY

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

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

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

Prefab cable assembly			
Connector	**Designation**	**Part Number**	**➔Page**
X3a	Motor cable X3a	275851	3-20
X3b	Motor cable X3b	931651	3-21
X4	Hall sensor cable	275878	3-22
X5	Encoder cable	275934	3-24
X7	Signal cable 8core	520853	3-32
X8	Signal cable 7core	520854	3-37
X11	CAN-CAN cable CAN-COM cable	520858 520857	3-39 3-39
X12	CAN-CAN cable CAN-COM cable	520858 520857	3-39 3-39
X13	USB Type C – Type C cable USB Type A – Type C cable	845854 838461	3-40 3-40
X16	NTC cable	847301	3-41

Table 3-7 Prefab maxon cables

MAKE&BAKE YOUR OWN

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

Motion connector set (P/N 846644)		
Connector	**Specification**	**Quantity**
Connectors		
X3a	Molex Mini-Fit Jr., 4 poles (39012040)	1
X3b	Hirose DF3 Series, 3 poles (DF3-3S-2C)	1
X4	Molex Micro-Fit 3.0, 6 poles (430250600)	1
X7	Molex CLIK-Mate, 8 poles (5025780800)	1
X8	Molex CLIK-Mate, 7 poles (5025780700)	1
X11, X12	Molex CLIK-Mate, 4 poles (5025780400)	2
X16	Molex Micro-Fit 3.0, 2 poles (430250200)	1
Crimp Terminals		
X3a	Molex Mini-Fit Plus, AWG16 (457503112, 457503111)	4
X3b	Hirose DF3 Series, AWG22 (DF3-22SC)	3
X4, X16	Molex Micro-Fit 3.0, AWG26-30 (430300010, 430300004)	8
X7, X8, X11, X12	Molex CLIK-Mate, AWG24-28 (5025790100, 5025790000)	25

Table 3-8 Motion connector set – Content

TOOLS

Tool	Manufacturer	Part Number
Hand crimper for Mini-Fit Jr. crimp terminals	Molex	2002182200
Hand crimper for Micro-Fit 3.0 crimp terminals	Molex	0638190000
Hand crimper for CLIK-Mate crimp terminals	Molex	2002187400
Hand crimper for crimp terminals DF3-22SC...	Hirose	DF3-TA22HC

Table 3-9 Recommended tools

3.3 Connection specifications

The actual connection depends on your drive system configuration and the type of motor you are using. Some connections must be established in a specific way. For the motor, you can choose from alternative plug-in locations. Follow the description in the given order and choose the wiring diagram (➔see page 4-47) that best suits your components.

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

3.3.1 Power & logic supply (X1/X2)

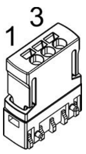


Figure 3-6 Power & logic supply combo connector X1/X2

X1/X2 Pin	Prefab cable Head A Pin	Cable color	Head B Pin	Signal	Description
1	1			GND	Ground
2	2			$+V_{CC}$	Power supply voltage input (10…60 VDC)
3	3			$+V_{C}$	Logic supply voltage input (10…60 VDC)

Table 3-10 Power & logic supply combo connector X1/X2 – Pin assignment

Power & logic supply combo connector X1/X2 (P/N 590736)		
Type	Spring-loaded contacts, 3 poles, pitch 2.54 mm	
Suitable plug	Harting har-flexicon 2.54 FPV-3 BK (14 31 031 3101 000) —included with every Compact version delivery—	
Suitable cables	Rigid	0.14…0.5 mm^2, AWG 26-20 / wire stripping length 6 mm
	Flexible	0.2…0.5 mm^2, AWG 24-20 / wire stripping length 6 mm 0.25…0.34 mm^2, AWG 24-22 / wire stripping length 6 mm, wire end sleeves
Suitable tools	Miniature screwdriver, size “00”	

Table 3-11 Power & logic supply combo connector X1/X2 – Specification and accessories

Power supply requirements	
Nominal output voltage V_{CC}	10…60 VDC
Absolute output voltage V_{CC}	min. 8 VDC / max. 62 VDC
Output current	Depending on load • continuous max. 2 A • short-time (acceleration) max. 6 A (< 30 s)

Table 3-12 Power supply requirements

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

The formula already takes the following into account:
- *Maximum PWM duty cycle of 90 %*
- *Controller's max. voltage drop of 1 V @ 2 A*

KNOWN VALUES:
- Operating torque M [mNm]
- Operating speed n [rpm]
- Nominal motor voltage U_N [Volt]
- Motor no-load speed at U_N; n_0 [rpm]
- Speed/torque gradient of the motor Δn/ΔM [rpm/mNm]

SOUGHT VALUE:
- Supply voltage V_{CC} [Volt]

SOLUTION:

$$V_{CC} \geq \left[\frac{U_N}{n_O} \cdot \left(n + \frac{\Delta n}{\Delta M} \cdot M\right) \cdot \frac{1}{0.9}\right] + 1[V]$$

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

Table 3-13 Logic supply requirements

3.3.2 Motor (X3a/X3b)

The controller is set to drive either maxon EC motor (BLDC, brushless DC motor) or maxon DC motor (brushed DC motor) with separated motor/encoder cable. You can connect these motors through connector X3a or connector X3b. Alternatively, you can connect a maxon DC motor that has an integrated motor/encoder ribbon cable through connector X5.

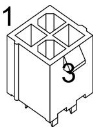


Figure 3-7 Motor connector X3a

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

X3a Pin	Prefab cable Head A Pin	Cable color	Head B Pin	Signal	Description
1	1	white		Motor winding 1	EC motor: Winding 1
				Motor (+M)	DC motor: Motor +
2	2	brown		Motor winding 2	EC motor: Winding 2
				Motor (-M)	DC motor: Motor -
3	3	green		Motor winding 3	EC motor: Winding 3
				-	DC motor: DO NOT CONNECT
4	4	black		Motor shield	Cable shield

Table 3-14 Motor connector X3a – Pin assignment for maxon EC & DC motor

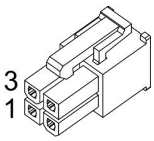
Motor cable X3a (P/N 275851)		
A 		B
Cross-section	3 × 0.75 mm^2, shielded, grey	
Length	3 m	
Head A	Plug	Molex Mini-Fit Jr., 4 poles (39012040)
	Contacts	Molex Mini-Fit Jr. female crimp terminals (45750)
Head B	Wire end sleeves 0.75 mm^2	

Table 3-15 Motor cable X3a

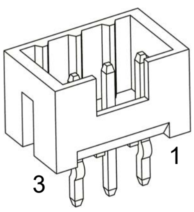


Figure 3-8 Motor connector X3b

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

X3b Pin	Prefab cable Head A Pin	Prefab cable Cable color	Prefab cable Head B Pin	Signal	Description
1	1	white		Motor winding 1	EC motor: Winding 1
				Motor (+M)	DC motor: Motor +
2	2	brown		Motor winding 2	EC motor: Winding 2
				Motor (-M)	DC motor: Motor -
3	3	green		Motor winding 3	EC motor: Winding 3
				—	DC motor: DO NOT CONNECT

Table 3-16 Motor connector X3b – Pin assignment for maxon EC & DC motor

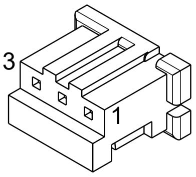
Motor cable X3b (P/N 931651)		
A 	B	
Cross-section	$3 \times 0.34\ mm^2$, grey	
Length	3 m	
Head A	Plug	Hirose DF3 Series, 3 poles (DF3-3S-2C)
	Contacts	Hirose DF3 Series female crimp terminals (DF3-22SC)
Head B	Wire end sleeves $0.34\ mm^2$	

Table 3-17 Motor cable X3b

3.3.3 Sensor 1 Hall sensor (X4)

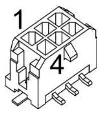


Figure 3-9 Sensor 1 Hall sensor connector X4

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

Table 3-18 Hall sensor connector X4 – Pin assignment

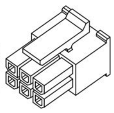
Hall sensor cable (P/N 275878)		
A 4 1 		B
Cross-section	5 × 0.14 mm^2, shielded, grey	
Length	3 m	
Head A	Plug	Molex Micro-Fit 3.0, 6 poles (430250600)
	Contacts	Molex Micro-Fit 3.0 female crimp terminals (430300010)
Head B	Wire end sleeves 0.14 mm^2	

Table 3-19 Hall sensor cable

Important notice

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

- *Hall sensors ➔Chapter “3.3.3 Sensor 1 Hall sensor (X4)” on page 3-21*
- *Incremental encoders ➔Chapter “3.3.4.1 Incremental encoder” on page 3-24*
- *SSI / BiSS C encoders ➔Chapter “3.3.4.2 SSI / BiSS C unidirectional absolute encoder” on page 3-26*
- *Other peripherals which need a 5 VDC supply.*

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

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

Table 3-20 Hall sensor specification

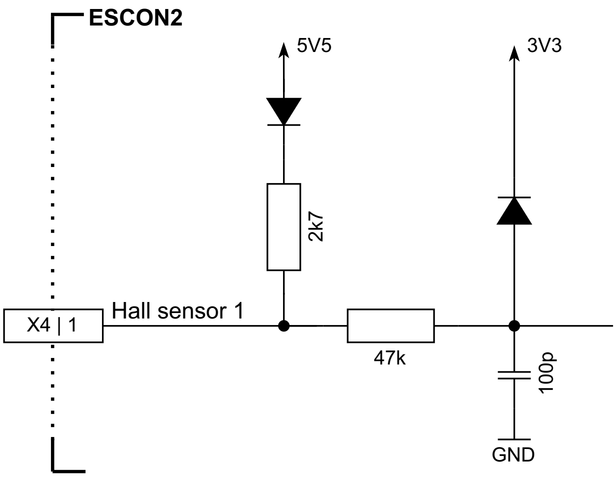


Figure 3-10 Sensor 1 Hall sensor input circuit (analogously valid for Hall sensors 2 & 3)

3.3.4 Sensor 2 Encoder / I/Os (X5)

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

Alternatively, you can connect a maxon DC motor that has an integrated Motor/Encoder Ribbon Cable. This connection type allows both the motor and the encoder to be connected through the same cable and connector.

Note

Use a maxon DC motor with an integrated Motor/Encoder Ribbon Cable. Then set jumper JP1 to the correct position to activate the option *(➔Chapter “3.5 Jumper configuration (JP1)” on page 3-45).*

Best practice

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

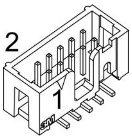


Figure 3-11 Sensor 2 connector X5

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

Table 3-21 Sensor 2 connector X5 – Pin assignment

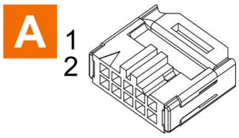
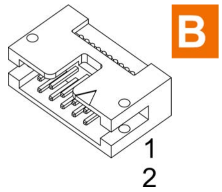
Encoder cable (P/N 275934)	
	
Cross-section	10 × AWG28, round-jacket, flat cable, pitch 1.27 mm
Length	3 m
Head A	DIN 41651 female, pitch 2.54 mm, 10 poles, with strain relief
Head B	DIN 41651 plug, pitch 2.54 mm, 10 poles, with strain relief

Table 3-22 Encoder cable

Important notice

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

- *Hall sensors ➔Chapter "3.3.3 Sensor 1 Hall sensor (X4)" on page 3-21*
- *Incremental encoders ➔Chapter "3.3.4.1 Incremental encoder" on page 3-24*
- *SSI / BiSS C encoders ➔Chapter "3.3.4.2 SSI / BiSS C unidirectional absolute encoder" on page 3-26*
- *Other peripherals which need a 5 VDC supply.*

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

3.3.4.1 Incremental encoder

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

Table 3-23 Differential digital incremental encoder specification

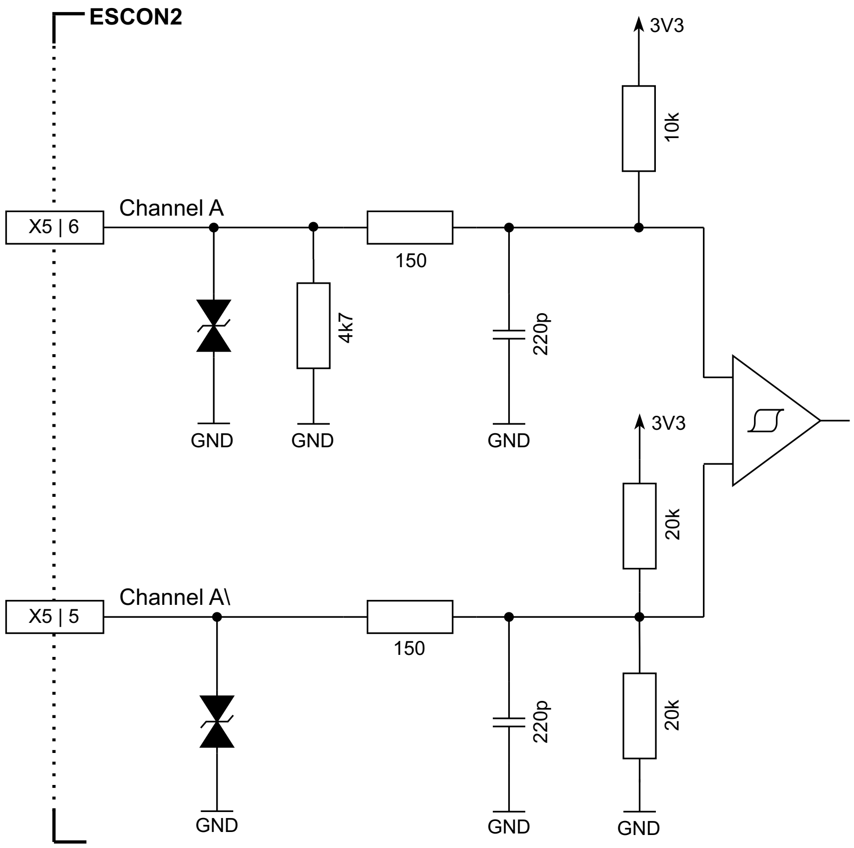


Figure 3-12 Digital incremental encoder input circuit Ch A “differential” (analogously valid for Ch B)

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

Table 3-24 Single-ended digital incremental encoder specification

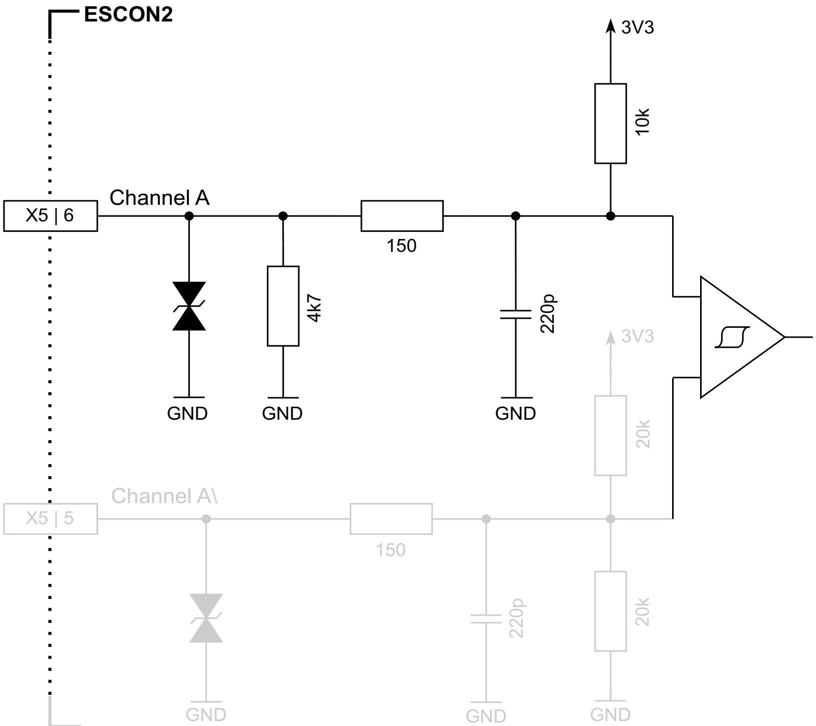


Figure 3-13 Digital incremental encoder input circuit Ch A “single-ended” (analogously valid for Ch B)

3.3.4.2 SSI / BiSS C unidirectional absolute encoder

SSI / BiSS C unidirectional absolute encoder (single-ended)		
Sensor supply voltage output V_{Sensor}		5 VDC
Max. sensor supply current		≤ 145 mA (➔refer to Important notice)
Clock frequency	SSI	0.4...2 MHz
	BiSS C	0.4...4 MHz

Table 3-25 SSI / BISS C unidirectional absolute encoder specification

The maximum clock frequency (data rate) depends on the encoder cable length and the encoder configuration. For more information, for example configurable clock frequencies (data rates), refer to the ➔ESCON2 Firmware Specification [2].

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

Table 3-26 Single-ended SSI / BISS C unidirectional absolute encoder data channel specification

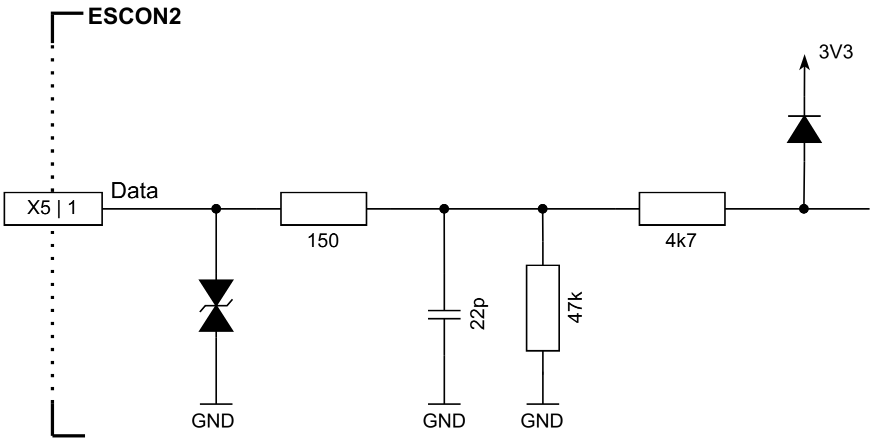


Figure 3-14 SSI absolute encoder data input (analogously valid for BiSS C)

SSI / BiSS C unidirectional absolute encoder clock channel		
Output voltage		3.3 VDC
Output resistance		47 Ω
Max. output current		24 mA
Clock frequency	SSI	0.4...2 MHz
	BiSS C	0.4...4 MHz

Table 3-27 Single-ended SSI / BISS C unidirectional absolute encoder clock channel specification

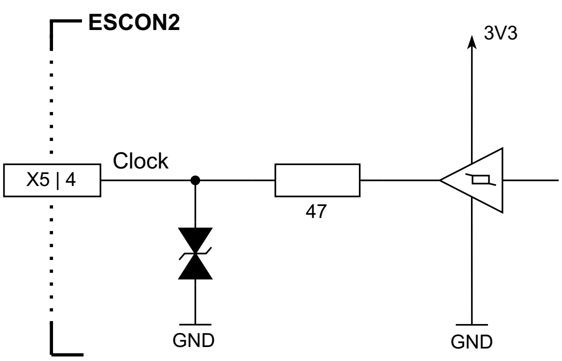


Figure 3-15 SSI absolute encoder clock output (analogously valid for BiSS C)

3.3.4.3 High-speed digital I/Os

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

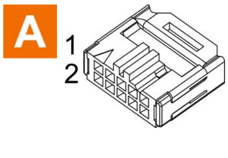
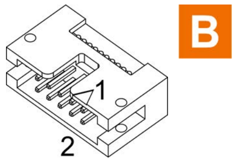
Encoder cable (P/N 275934)	
	
Cross-section	10 × AWG28, round-jacket, flat cable, pitch 1.27 mm
Length	3 m
Head A	DIN 41651 female, pitch 2.54 mm, 10 poles, with strain relief
Head B	DIN 41651 plug, pitch 2.54 mm, 10 poles, with strain relief

Table 3-28 Encoder cable

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

Table 3-29 Differential high-speed digital inputs specification

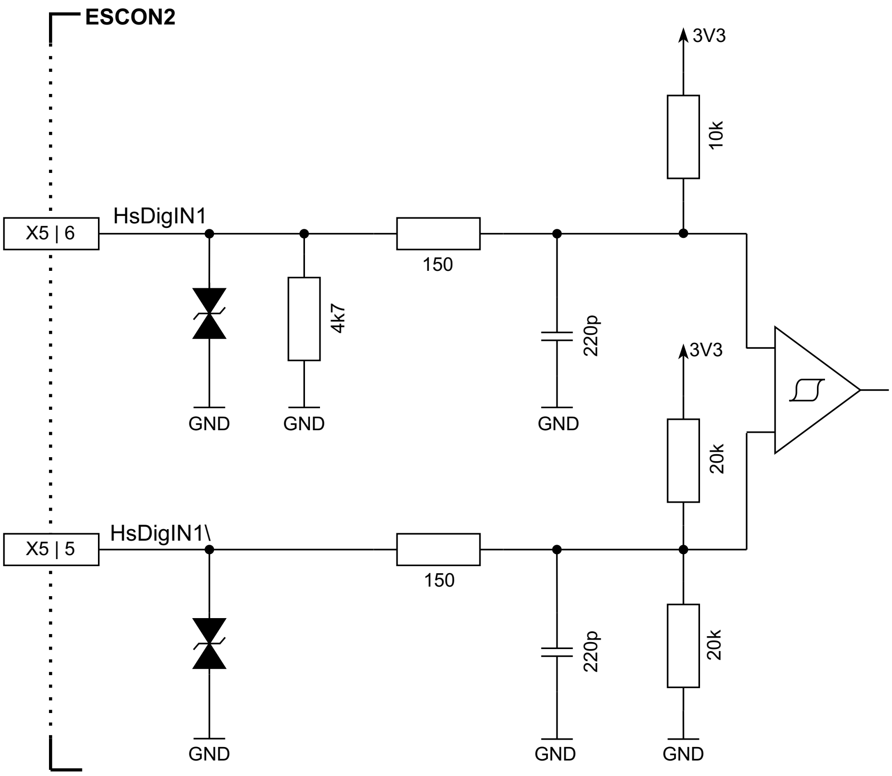


Figure 3-16 HsDigIN1 circuit “differential” (analogously valid for HsDigIN2)

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

Table 3-30 Single-ended high-speed digital inputs specification

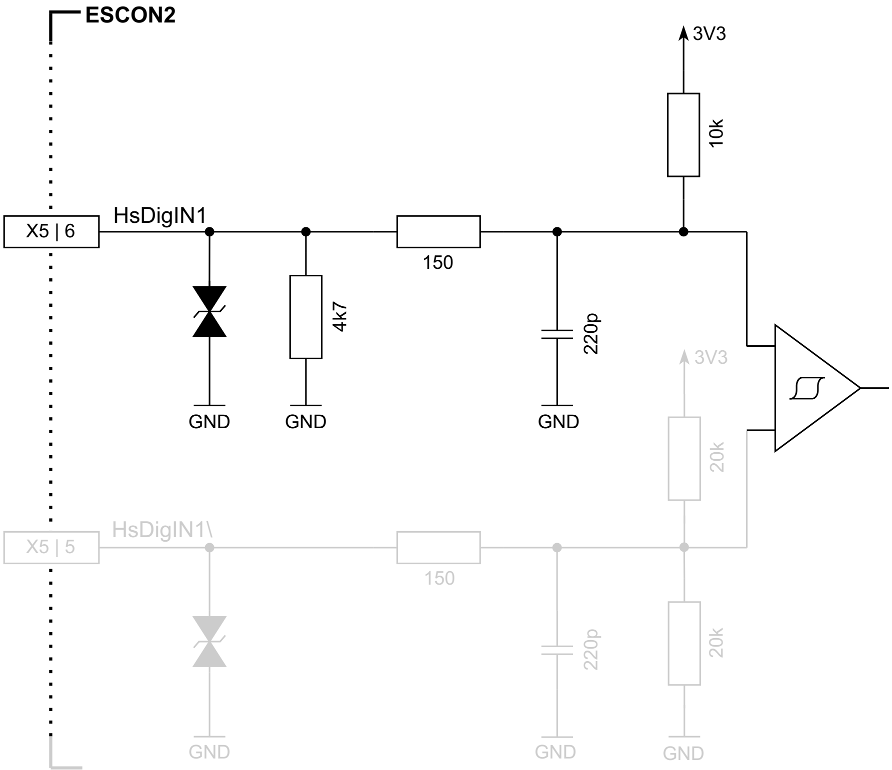


Figure 3-17 HsDigIN1 circuit “single-ended” (analogously valid for HsDigIN2…3)

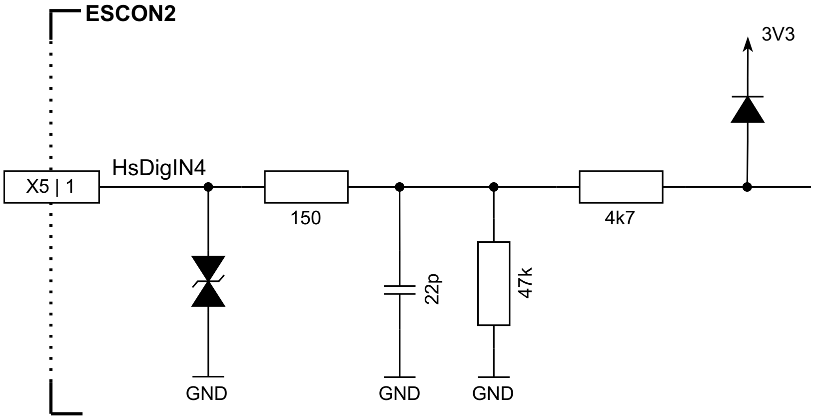


Figure 3-18 HsDigIN4 circuit "single-ended"

WIRING EXAMPLES

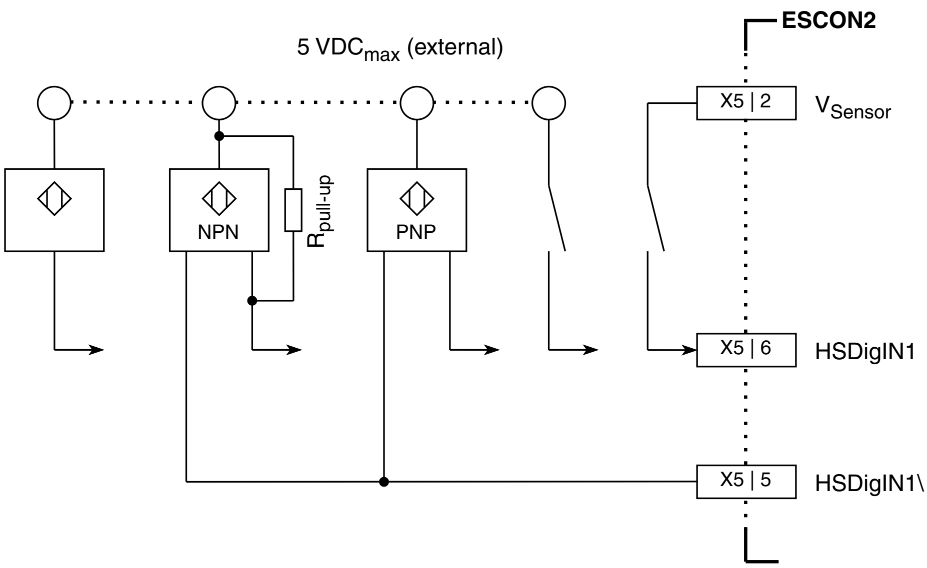


Figure 3-19 Wiring examples for proximity sensors and switches on HsDigIN1 (analogously valid for HsDigIN2)

High-speed digital output 1		
Output voltage		3.3 VDC
Output resistance	Total	75 Ω (47 Ω + 28 Ω)
	Gate internal	28 Ω
Max. output current		24 mA
Max. output frequency		25 kHz

Table 3-31 High-speed digital output specification

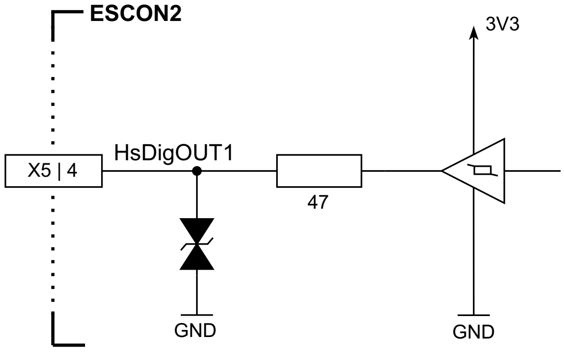


Figure 3-20 HsDigOUT1 circuit

WIRING EXAMPLES

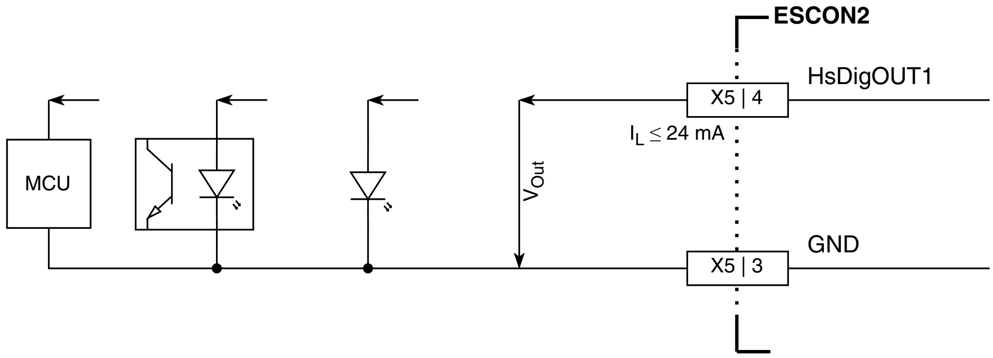


Figure 3-21 Wiring examples for "sourcing" on HsDigOUT1

3.3.5 Digital I/Os (X7)

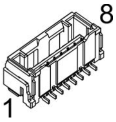


Figure 3-22 Digital I/Os connector X7

X7	Prefab cable			Signal	Description
Pin	Head A Pin	Cable color	Head B Pin		
1	1	white		DigIN1	Digital input 1
2	2	brown		DigIN2	Digital input 2
3	3	green		DigIN3	Digital input 3
4	4	yellow		DigIN4	Digital input 4
5	5	grey		DigOUT1	Digital output 1
6	6	pink		DigOUT2	Digital output 2
7	7	blue		GND	Ground
8	8	red		$V_{I/O}$	Dual-use • Use $V_{I/O}$ as the supply voltage for I/O operation (for example, switches). $V_{I/O} = V_{Sensor}$ (5 VDC) - 0.75 VDC = 4.25 VDC. • Use $V_{I/O}$, internally connected to a freewheeling diode, when switching inductive loads powered by an external supply.

Table 3-32 Digital I/Os connector X7 – Pin assignment

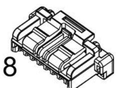
Signal cable 8core (P/N 520853)		
A  8 1		B
Cross-section	8 × 0.14 mm², grey	
Length	3 m	
Head A	Plug	Molex CLIK-Mate, single row, 8 poles (5025780800)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)
Head B	Wire end sleeves 0.14 mm²	

Table 3-33 Signal cable 8core

Digital inputs 1…2	
Input voltage	0…30 VDC
Max. input voltage	±30 VDC
Low-level input voltage	< 0.8 VDC
High-level input voltage	> 2.1 VDC
Input resistance	typically 47 kΩ < 3.3 VDC typically 37 kΩ @ 5 VDC typically 25 kΩ @ 24 VDC
Input current at logic 1	typically 135 µA @ 5 VDC
Hardware switching delay	< 6 µs
Total reaction time	< 2.3 ms
PWM duty cycle (resolution)	10...90 % (0.1 %)
PWM frequency	50 Hz...10 kHz
PWM accuracy	typically +0.1 % absolute @ 50 Hz / 5 VDC typically +1.5 % absolute @ 10 kHz / 5 VDC

Table 3-34 Digital inputs 1...2 specification

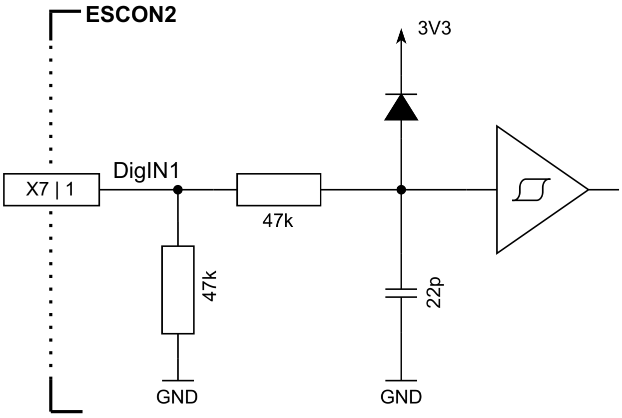


Figure 3-23 DigIN1 circuit (analogously valid for DigIN2)

Digital inputs 3…4	
Input voltage	0…30 VDC
Max. input voltage	±30 VDC
Low-level input voltage	< 0.8 VDC
High-level input voltage	> 2.1 VDC
Input resistance	typically 47 kΩ < 3.3 VDC typically 37 kΩ @ 5 VDC typically 25 kΩ @ 24 VDC
Input current at logic 1	typically 135 µA @ 5 VDC
Hardware switching delay	< 300 µs
Total reaction time	< 2.3 ms

Table 3-35 Digital inputs 3...4 specification

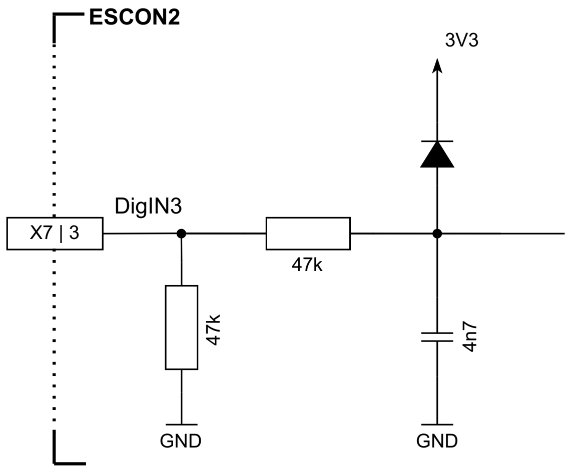


Figure 3-24 DigIN3 circuit (analogously valid for DigIN4)

WIRING EXAMPLES

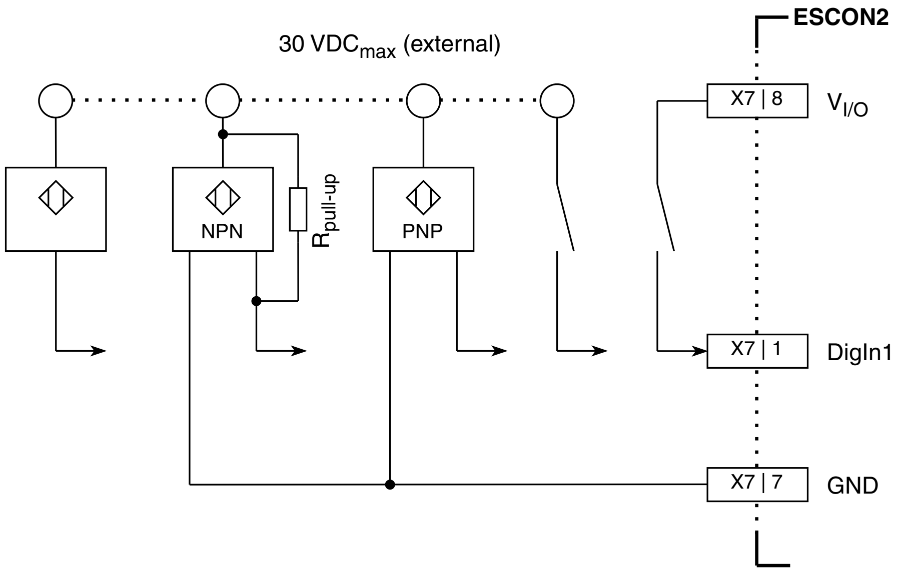


Figure 3-25 Wiring examples for proximity sensors and switches on DigIN1 (analogously valid for DigIN2..4)

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

Table 3-36 Digital outputs specification – Sinking

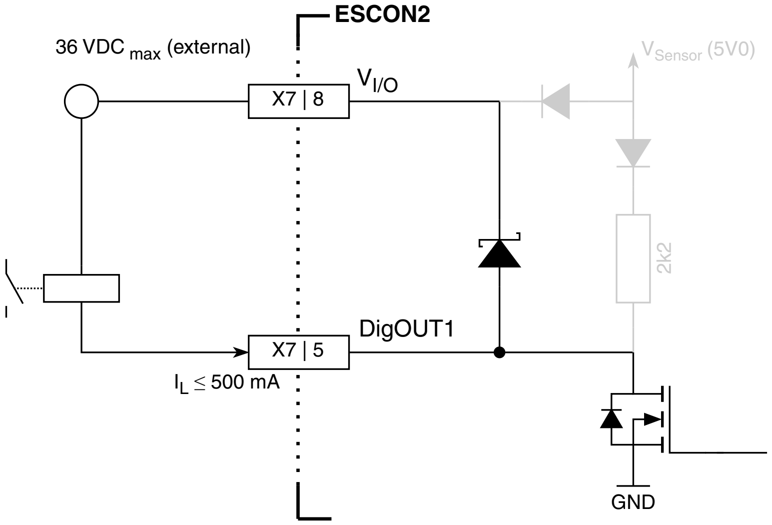


Figure 3-26 DigOUT1 circuit with wiring example for “sinking” inductive loads (analogously valid for DigOUT2)

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

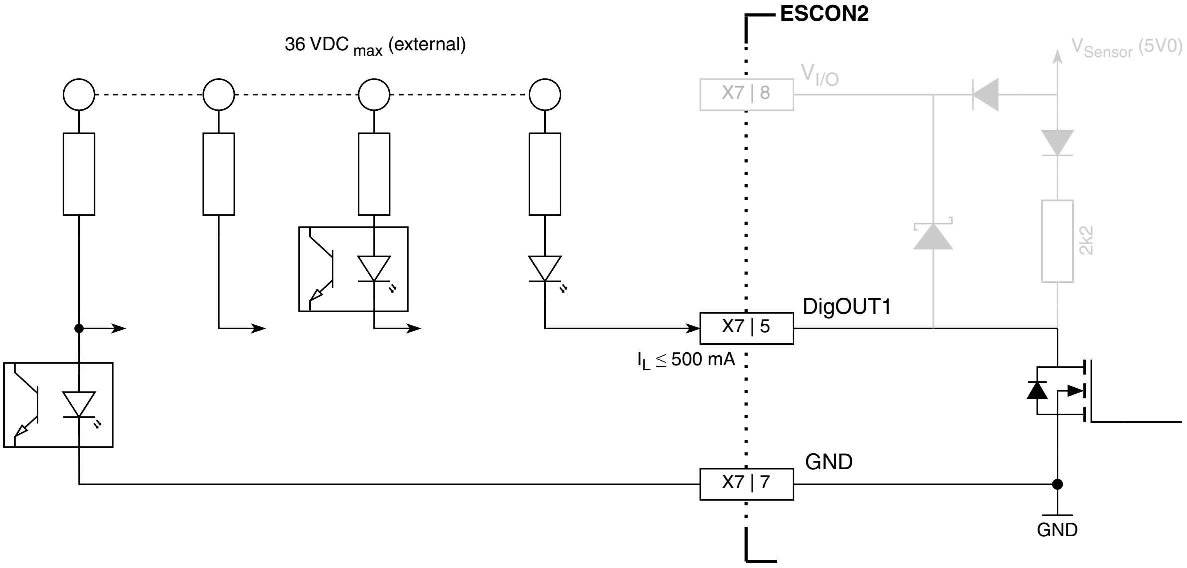


Figure 3-27 DigOUT1 circuit with wiring examples for “sinking” general-purpose loads (also valid for DigOUT2)

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

Table 3-37 Digital outputs specification – Sourcing

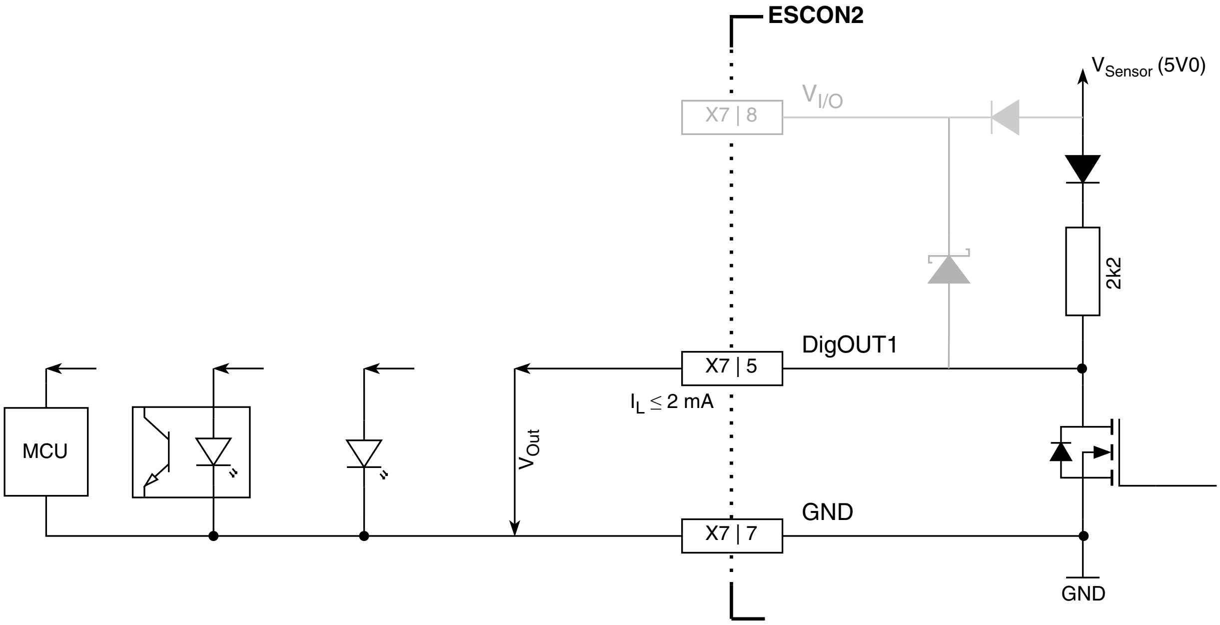


Figure 3-28 DigOUT1 circuit with wiring examples for “sourcing” (analogously valid for DigOUT2)

3.3.6 Analog I/Os (X8)

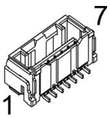
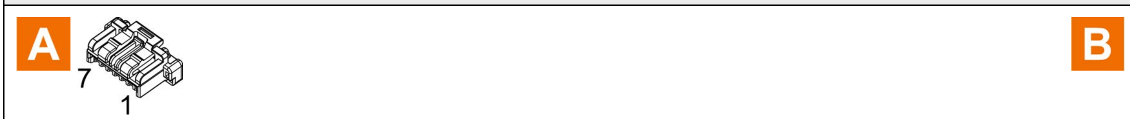


Figure 3-29 Analog I/Os connector X8

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

Table 3-38 Analog I/Os connector X8 – Pin assignment

Signal cable 7core (P/N 520854)



Cross-section	7 × 0.14 mm², grey
Length	3 m

Signal cable 7core (P/N 520854)		
Head A	Plug	Molex CLIK-Mate, single row, 7 poles (5025780700)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)
Head B	Wire end sleeves 0.14 mm^2	

Table 3-39 Signal cable 7core

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

Table 3-40 Analog input specification

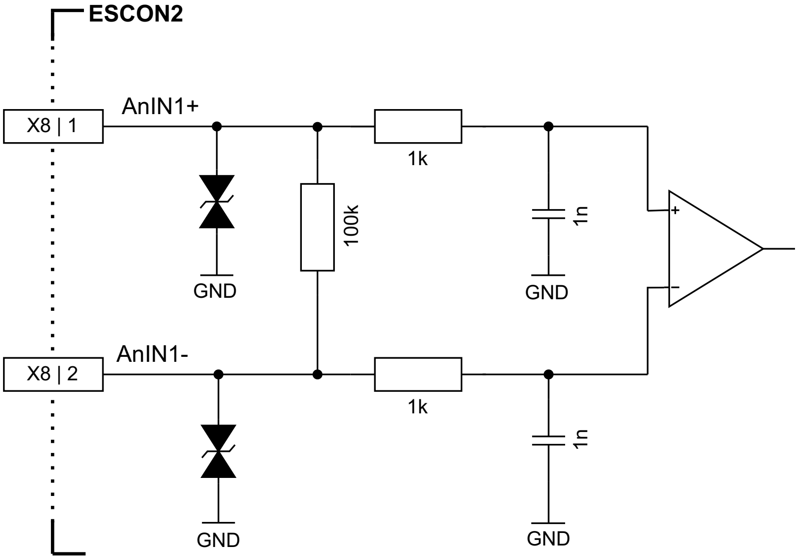


Figure 3-30 AnIN1 circuit (analogously valid for AnIN2)

WIRING EXAMPLES

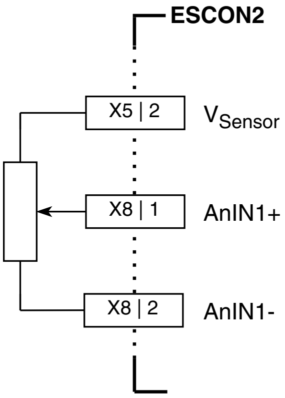


Figure 3-31 Wiring examples for a potentiometer on AnIN1 (analogously valid for AnIN2)

The figure above shows how to connect an external potentiometer to the analog input. It is recommended to use a potentiometer that has a resistance of 10 kΩ or more to reduce the load on the voltage output.

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

Table 3-41 Analog output specification

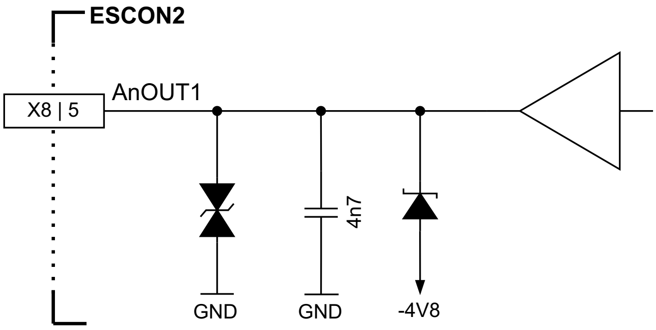


Figure 3-32 AnOUT1 circuit (analogously valid for AnOUT2)

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

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

For the CAN configuration check ➔Chapter “3.4 DIP switch configuration (SW1)” on page 3-42.

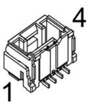


Figure 3-33 CAN 1 connector X11/CAN 2 connector X12

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

Table 3-42 CAN 1 connector X11/CAN 2 connector X12 – Pin assignment

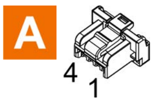
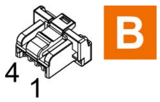
CAN-CAN cable (P/N 520858)		
		
Cross-section	2 × 2 × 0.22 mm^2, twisted pair, shielded	
Length	3 m	
Head A	Plug	Molex CLIK-Mate, single row, 4 poles (5025780400)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)
Head B	Plug	Molex CLIK-Mate, single row, 4 poles (5025780400)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)

Table 3-43 CAN-CAN cable

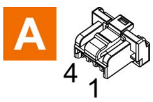
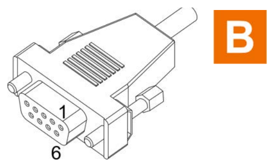
CAN-COM cable (P/N 520857)		
		
Cross-section	2 × 2 × 0.22 mm^2, twisted pair, shielded	
Length	3 m	
Head A	Plug	Molex CLIK-Mate, single row, 4 poles (5025780400)
	Contacts	Molex CLIK-Mate crimp terminals (5025790000)
Head B	Female D-Sub connector DIN 41652 9 poles, with mounting screws	

Table 3-44 CAN-COM cable

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

Table 3-45 CAN interface specification

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

3.3.8 USB (X13)

Hot plugging the USB interface may cause hardware damage

Do not hot-plug the USB interface (connecting while the power supply is on), the possibly high potential differences of the two power supplies of controller and PC/Notebook can lead to damaged hardware.

- *Avoid potential differences between the power supply of controller and PC/Notebook or, if possible, balance them.*
- *Insert the USB connector first, then switch on the power supply of the controller.*
- *It is recommended to use a galvanic isolator to avoid potential differences.*
  With a galvanic isolator, you can also connect the USB while the system is powered (hot-plugging).
  One suitable device is the USB Isolator 33204 from Wiesemann & Theis GmbH.

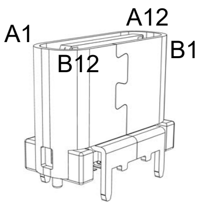


Figure 3-34 USB connector X13

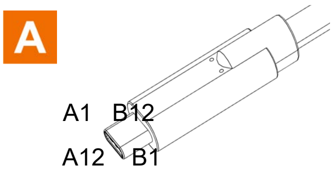
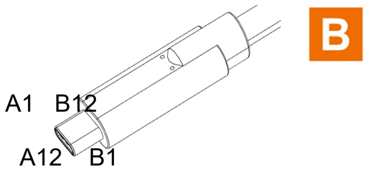
USB Type C - Type C cable (P/N 845854)	
	
USB standard	USB 3.2
Length	1.5 m
Head A	USB Type C
Head B	USB Type C

Table 3-46 USB Type C – Type C cable

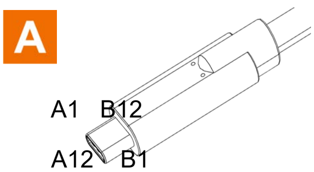
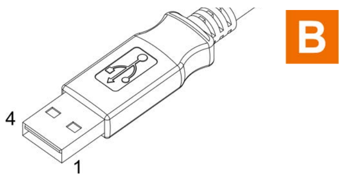
USB Type A - Type C cable (P/N 838461)	
	
USB standard	USB 2.0 / USB 3.0
Length	1.5 m
Head A	USB Type C
Head B	USB Type A

Table 3-47 USB Type A – Type C cable

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

Table 3-48 USB interface specification

3.3.9 Motor temperature sensor (X16) (future release)

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

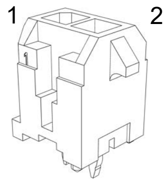


Figure 3-35 Motor temperature sensor connector X16

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

Table 3-49 Motor temperature sensor connector X16 – Pin assignment

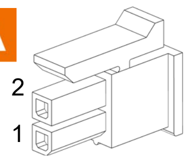
NTC cable (P/N 847301)		
A 		B
Cross-section	2×0.5 mm^2, grey	
Length	3 m	
Head A	Plug	Molex Micro-Fit 3.0, 2 poles (430250200)
	Contacts	Molex Micro-Fit 3.0 female crimp terminals (0430300001)
Head B	Wire end sleeves 0.5 mm^2	

Table 3-50 NTC cable

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

Table 3-51 Motor temperature sensor – specifications

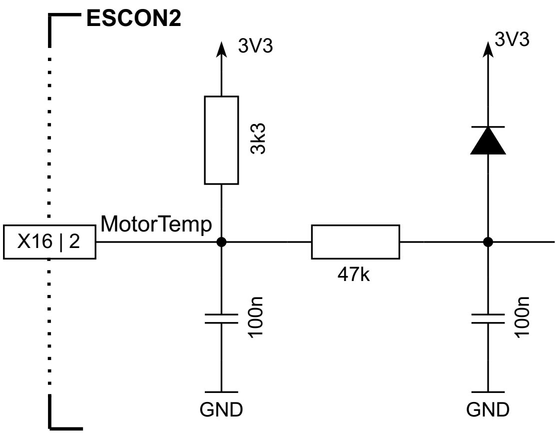


Figure 3-36 Motor temperature circuit

3.4 DIP switch configuration (SW1)

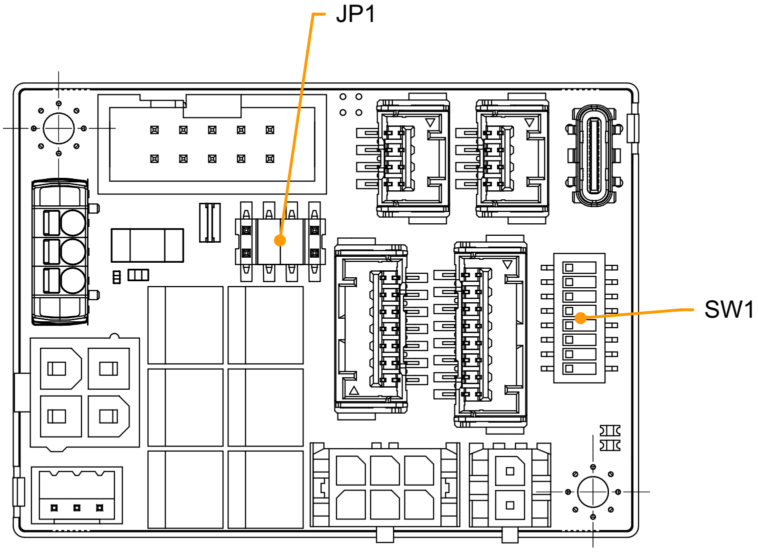


Figure 3-37 DIP switch SW1

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

3.4.1 CAN ID (Node-ID)

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

Setting the ID by DIP switch SW1
- *DIP switches 6…8 do not have any impact on the ID.*

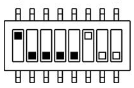
Setting	Switch	Binary Code	Valence
1 8  ON OFF (factory setting)	1	2^0	1
	2	2^1	2
	3	2^2	4
	4	2^3	8
	5	2^4	16

Table 3-52 DIP switch SW1 – Binary code values

Continued on next page.

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

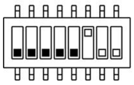
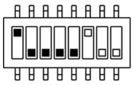
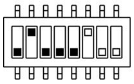
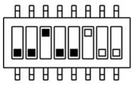
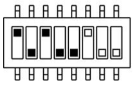
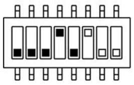
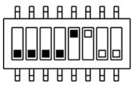
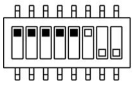
Setting	Switch					ID
	1	2	3	4	5	
1 8  ON OFF	0	0	0	0	0	–
1 8  ON OFF	**1**	0	0	0	0	1
1 8  ON OFF	0	**1**	0	0	0	2
1 8  ON OFF	0	0	**1**	0	0	4
1 8  ON OFF	**1**	0	**1**	0	0	5
1 8  ON OFF	0	0	0	**1**	0	8
1 8  ON OFF	0	0	0	0	**1**	16
1 8  ON OFF	**1**	**1**	**1**	**1**	**1**	31
0 = Switch “OFF” 1 = Switch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

Table 3-53 DIP switch SW1 – Examples

SETTING THE ID BY MEANS OF «MOTION STUDIO»

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

3.4.2 CAN automatic bit rate detection

With this function, the CANopen interface can be put in a “listen only” mode. For further details see separate document ➔ESCON2 Firmware Specification [2]. Automatic bit rate detection is activated with DIP switch 6.

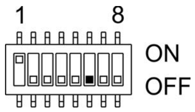
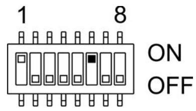
Switch	OFF	ON
6	 Automatic bit rate detection deactivated	 Automatic bit rate detection activated (factory setting)

Table 3-54 DIP switch SW1 – CAN automatic bit rate detection

3.4.3 CAN bus termination

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

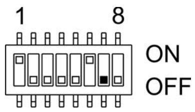
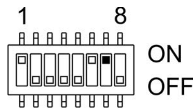
Switch	OFF	ON
7	 Without bus termination (factory setting)	 Bus termination with 120 Ω

Table 3-55 DIP switch SW1 – CAN bus termination

3.5 Jumper configuration (JP1)

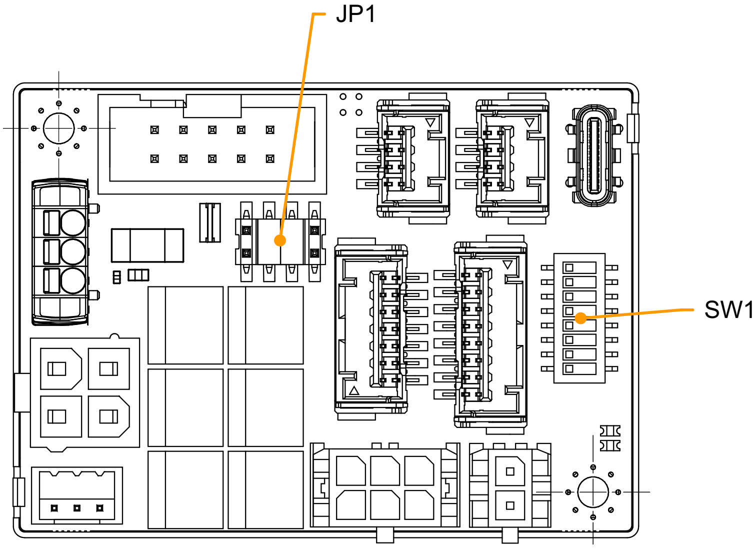


Figure 3-38 Jumper JP1

The motor windings of a DC motor with IMR encoder are connected via an integrated Motor/Encoder Ribbon Cable. To activate that option, you will need to set the jumper JP1 accordingly.

Settings for Jumper JP1

- *Bridging the jumper pins 3/4 and 5/6 disconnects the motor windings from the encoder connector X5 (➔Tabelle 3-56; “OFF”)*
- *Bridging the jumper pins 2/4 and 6/8 connects the motor windings (+M) and (−M) to the encoder connector X5, pins 1 and 4 (➔Tabelle 3-56; “ON”)*

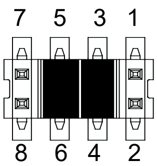
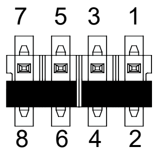
JP1	OFF	ON
Bridges	 Motor windings disconnected (factory setting)	 Motor windings connected

Table 3-56 Jumper JP1 – Power supply for DC motor winding

3.6 Status indicators

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

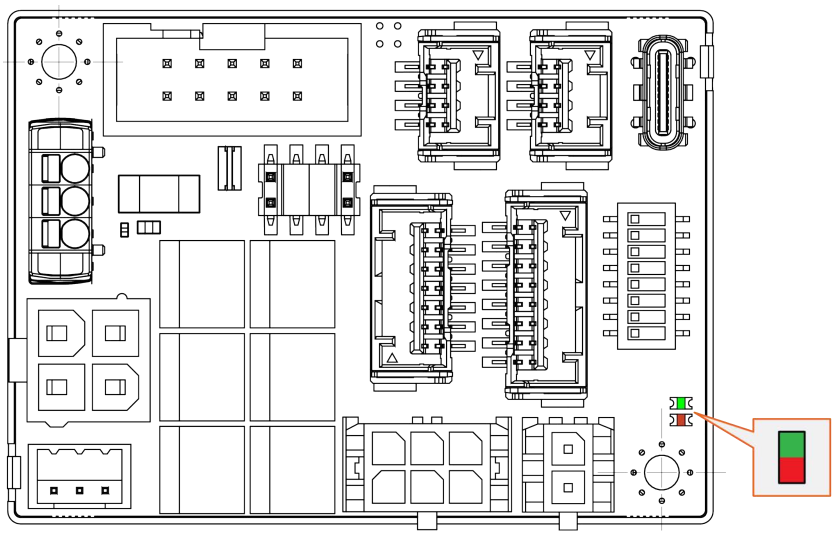


Figure 3-39 LEDs – Location

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

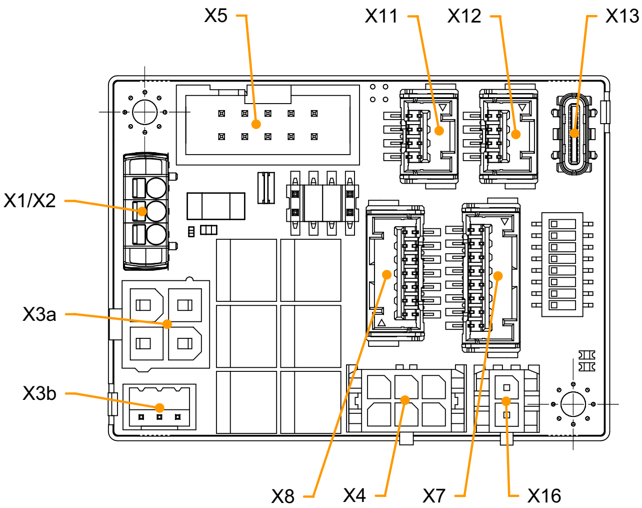
- Green LED shows the operation status
- Red LED indicates warnings and errors

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

Table 3-57 Device status LEDs

4 WIRING

This section provides wiring information for your setup. You can either use the consolidated wiring diagrams (see ➔Figure 4-41) featuring the full scope of interconnectivity and pin assignments, or you may use the connection overviews for either DC motor or EC (BLDC) motor to determine the wiring for your particular motor type and the appropriate feedback signals.



X1/X2	Power & Logic supply
X3a/b	Motor
X4	Sensor 1 Hall sensor
X5	Sensor 2
X7	Digital I/Os
X8	Analog I/Os
X11	CAN 1
X12	CAN 2
X13	USB
X16	Motor temperature sensor

Figure 4-40 Interfaces – Designations and location

Signs and abbreviations used

The subsequent diagrams feature these signs and abbreviations:

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

4.1 Possible combinations to connect a motor

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

1) Decide on the type of motor you are using and go to the respective subsection;
For DC motor, see ➔Chapter “4.1.1 DC motor” on page 4-48 or
For EC (BLDC) motor, see ➔Chapter “4.1.2 EC (BLDC) motor” on page 4-48.
2) Connect the power supply and the logic supply as shown in the referenced figure.
3) Check-out the listing for the combination that best suits your setup. Pick the wiring method # and go to the respective table;
For DC motor see ➔Table 4-58,
For EC (BLDC) motor see ➔Table 4-59.
4) Pick the row with the corresponding wiring method # and refer to the listed figure(s) to find the relevant wiring information.

4.1.1 DC motor

Power and logic supply

Power and logic supply. . . . . Figure 4-42

Motor & feedback signals

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

Digital incremental encoder . . . . Method # DC2

SSI / BISS C unidirectional absolute encoder . . . . Method # DC3

<table>
<tr><th rowspan="2">Method #</th><th>Sensor 2</th><th></th><th rowspan="2" colspan="2">➔Figure(s)</th></tr>
<tr><th>Digital incremental encoder</th><th>SSI / BISS C unidirectional absolute encoder</th></tr>
<tr><td>DC1 [a]</td><td></td><td></td><td colspan="2">4-43</td></tr>
<tr><td>DC2</td><td>✓</td><td></td><td>4-43
4-46</td><td>4-47</td></tr>
<tr><td>DC3</td><td></td><td>✓</td><td colspan="2">4-43
4-48</td></tr>
</table>

[a] For method # DC1, only the operating mode current control can be used.

Table 4-58 Possible combinations of feedback signals for DC motor

4.1.2 EC (BLDC) motor

Power and logic supply

Power and logic supply. . . . . Figure 4-42

Motor & feedback signals

Hall sensors . . . . Method # EC1

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

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

SSI / BISS C unidirectional absolute encoder . . . . Method # EC4

Method #	Sensor 1	Sensor 2		➔Figure(s)
	Hall sensors	Digital incremental encoder	SSI / BISS C unidirectional absolute encoder	
EC1	✓			4-44 4-45
EC2	✓	✓		4-44 4-45 4-46
EC3	✓		✓	4-44 4-45 4-48
EC4			✓	4-44 4-48

Table 4-59 Possible combinations of feedback signals for EC (BLDC) motor

4.2 Main wiring diagram

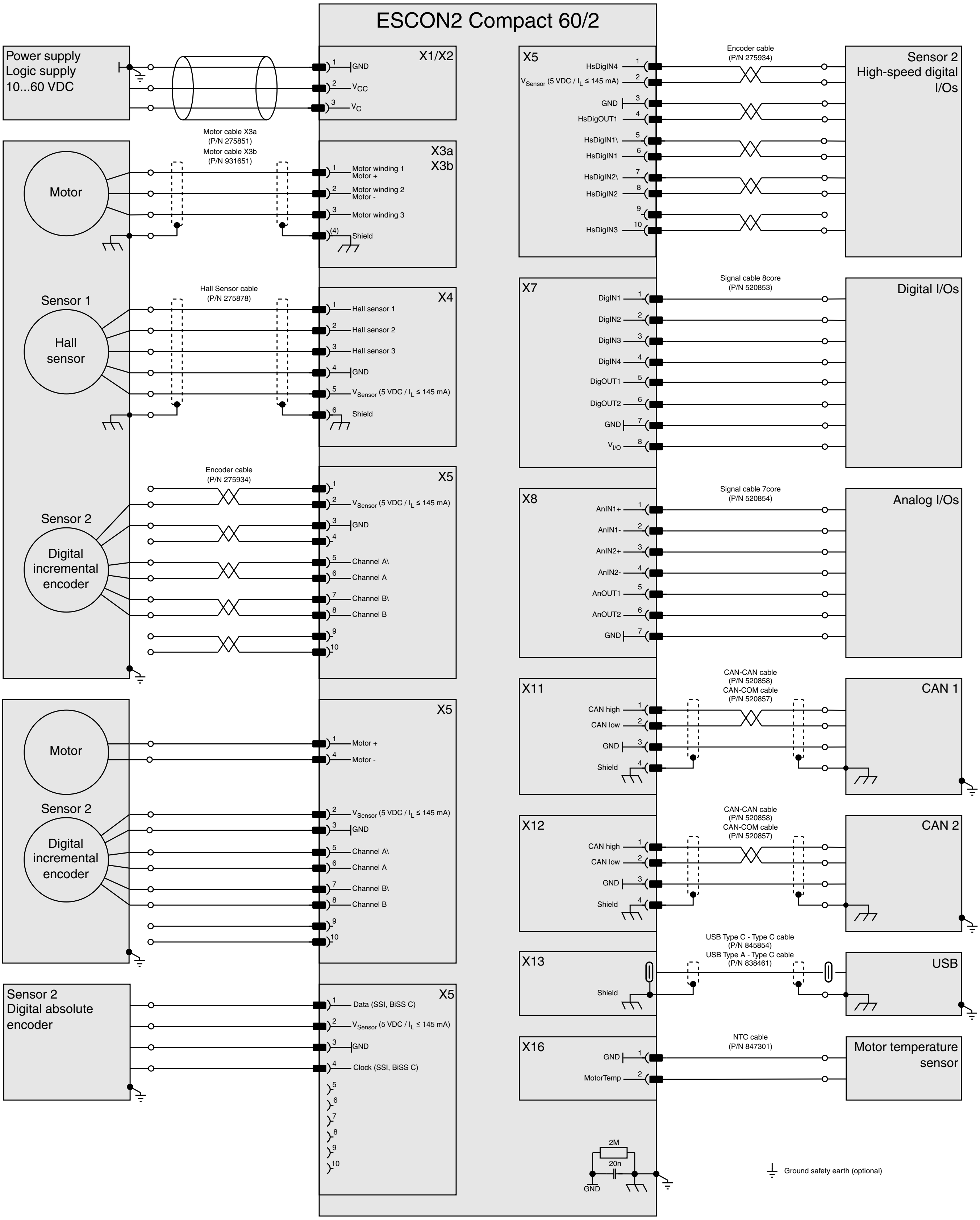


Figure 4-41 Main wiring diagram

maxon

4.3 Excerpts

4.3.1 Power and logic supply

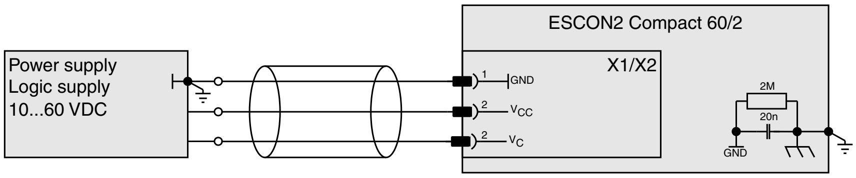


Figure 4-42 Power and logic supply

4.3.2 DC motor

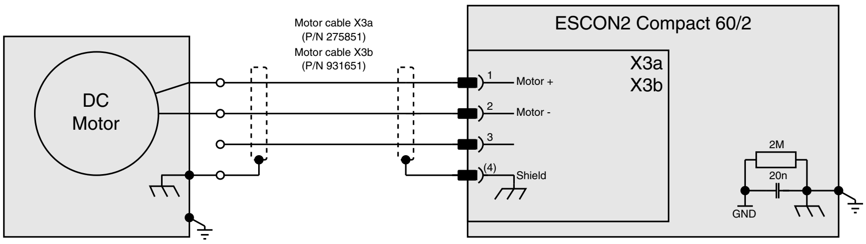


Figure 4-43 DC motor

4.3.3 EC (BLDC) motor

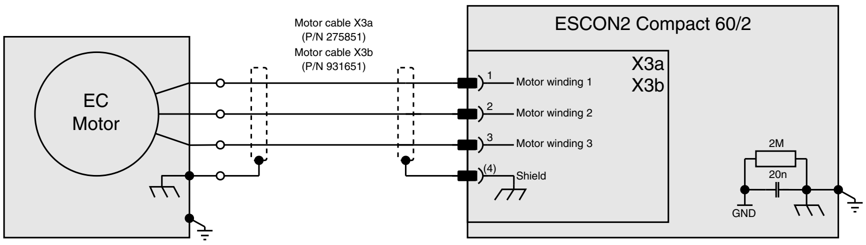


Figure 4-44 EC (BLDC) motor

4.3.4 Sensor 1 Hall sensor

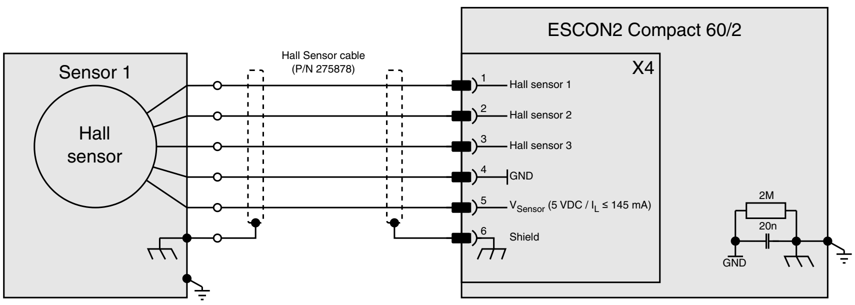


Figure 4-45 Sensor 1 Hall sensor

4.3.5 Sensor 2 Encoder / I/Os

4.3.5.1 Digital incremental encoder

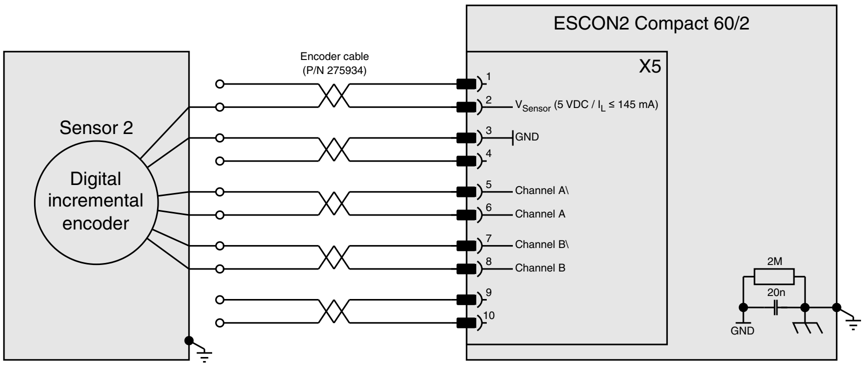


Figure 4-46 Digital incremental encoder

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

4.3.5.2 Digital incremental encoder with motor

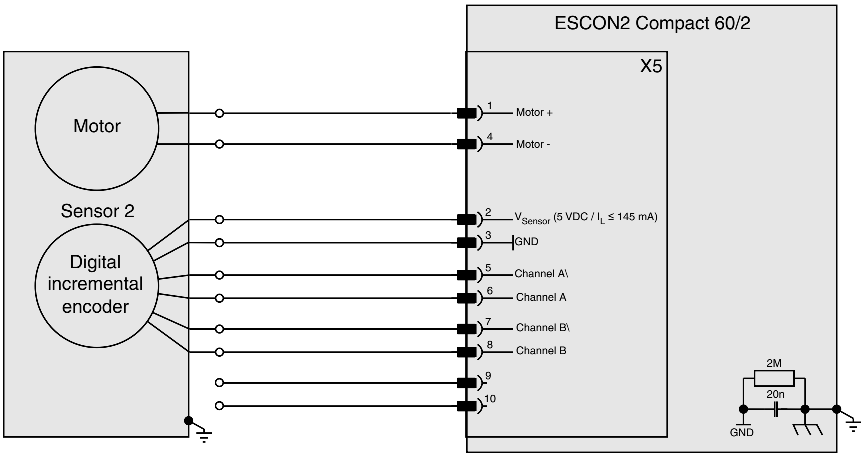


Figure 4-47 Digital incremental encoder with motor

Note
For Jumper settings ➔Chapter “3.5 Jumper configuration (JP1)” on page 3-45.

4.3.5.3 SSI / BISS C unidirectional absolute encoder

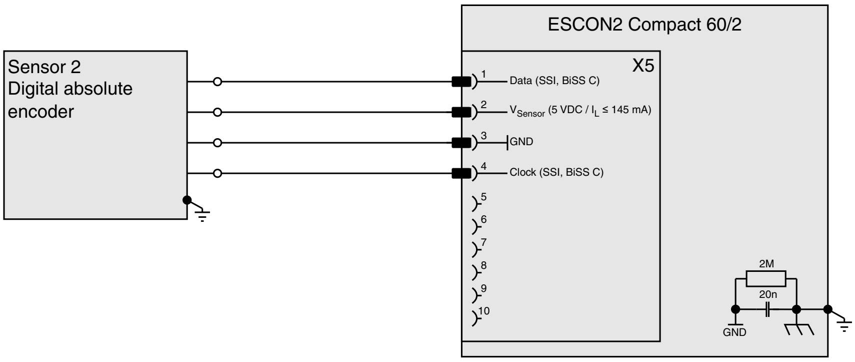


Figure 4-48 SSI / BISS C unidirectional absolute encoder

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

Note
For Jumper settings ➔Chapter “3.5 Jumper configuration (JP1)” on page 3-45.

4.3.5.4 High-speed digital I/Os

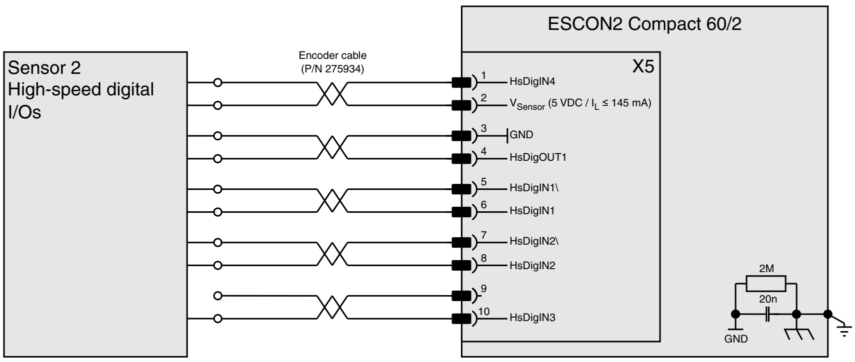


Figure 4-49 High-speed digital I/Os

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

Note
For Jumper settings ➔Chapter “3.5 Jumper configuration (JP1)” on page 3-45.

4.3.6 Digital I/Os

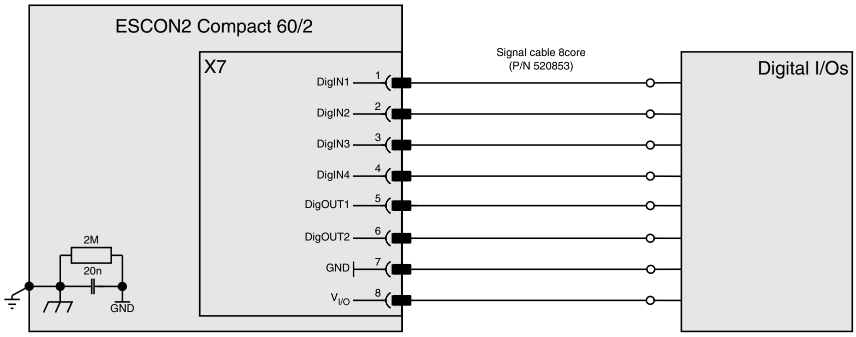


Figure 4-50 Digital I/Os

4.3.7 Analog I/Os

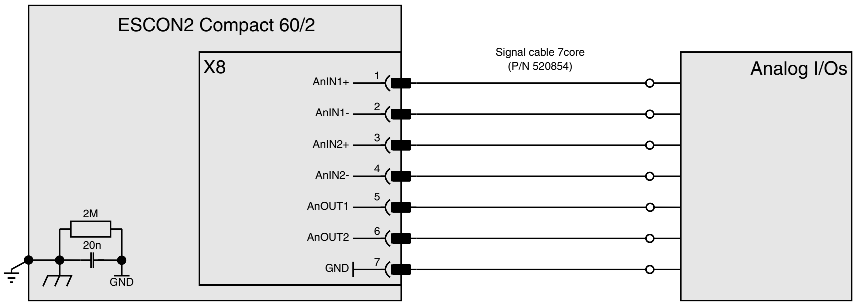


Figure 4-51 Analog I/Os

4.3.8 CAN

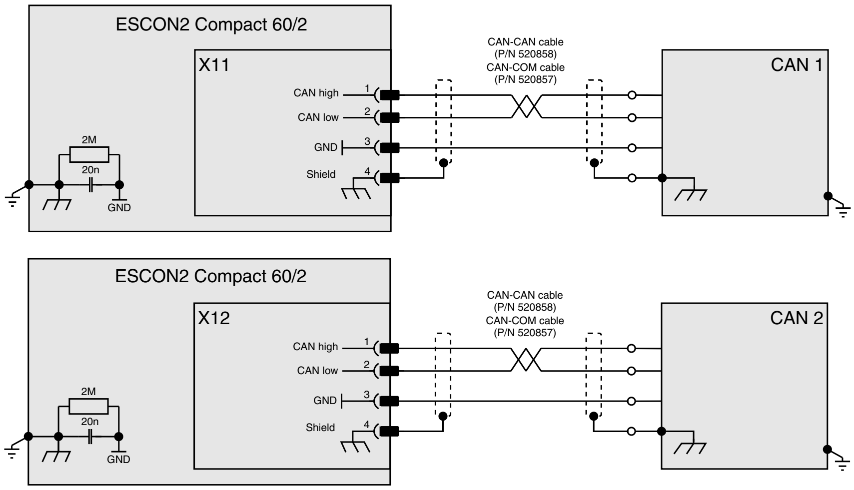


Figure 4-52 CAN

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

4.3.9 USB

4.3.9.1 USB-C

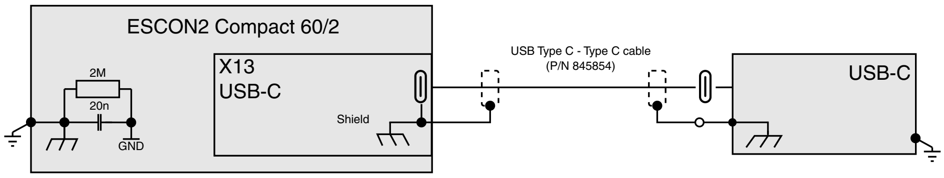


Figure 4-53 USB-C

4.3.9.2 USB-A

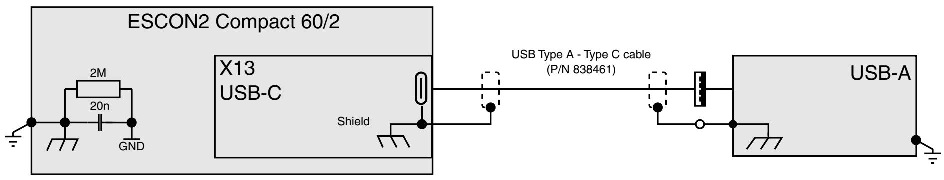


Figure 4-54 USB-A

4.3.10 Motor temperature sensor (future release)

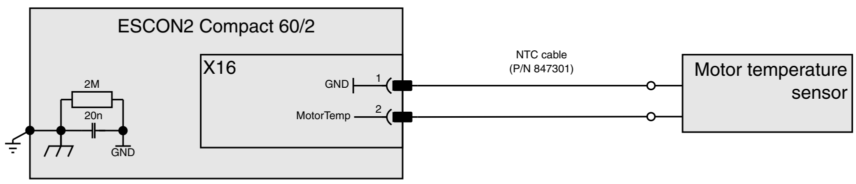


Figure 4-55 Motor temperature sensor

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