Engineering data

Number of axes	2	
Aux supply*	24 ± 10%	V DC (2.0A)
Power supply	0-560	V DC
DC bus voltage	0-560	V DC
Input power (S1)	11.0	kVA
Rated output current 1 axis	10	A (rms)
Rated output current all axes	16	A (rms)
Peak current	2 x 20	A (rms)
Losses at rated load	150	W

** Without power supply for the servomotor holding brake and digital outputs.*

Supported motor feedbacks* 2x

Hiperface DSL

EnDat 2.2

BiSS-C

SSI

Hall effect sensors (using digital inputs)

** Support depending on servoamplifier firmware*

External encoder 1x

Incremental encoder input / emulation output*

** Support depending on servoamplifier firmware*

Recommended filter

TGS-560 built in filter

Mechanical data

Mass	1.8	kg
Mass with cooler	2.1	kg
Protection	IP20	
Operating temperature	<0; 40>	°C

Inputs / outputs

Digital inputs	8x	24 V DC (0-10 V low, 12-24V high) 20mA
Digital outputs	6x	5-24 V DC 300mA / output
Analog inputs	2x	0-10V

Functional safety

Safe torque off (STO) - 2 channels	**SIL 3**
PROFIsafe* - telegrams	**31, 36**

** Support depending on servoamplifier firmware*

Supported communication*

2x Ethernet	EtherCAT / PROFINET
1x Ethernet	service UDP
1x CAN	CANopen / RAW CAN

** Support depending on servoamplifier firmware*

Customs info

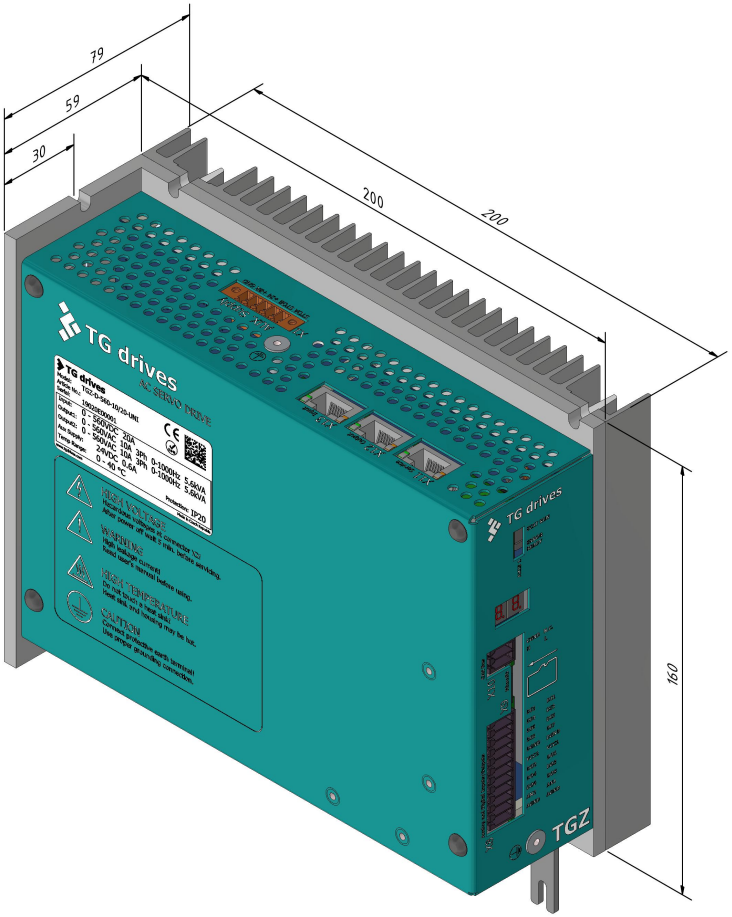
HS Code	85044087

Firmware feature support					
Feature	**Firmware**				
	Standard (EtherCAT)	**PROFINET**	**PROFIsafe**	**CANopen over EtherCAT (CoE)**	**TGZ+Motion***
EtherCAT (slave)	✓			✓	
EtherCAT (master)					✓
PROFINET (device)		✓	✓		✓
PROFIdrive		✓	✓		
PROFIsafe (device)			✓		
CANopen (slave)				✓	
RAW CAN	✓	✓			✓
CANopen over EtherCAT				✓	
Modbus TCP (server)					✓
Interpreted PLC	✓	✓	✓	✓	
TGMotion realtime PLC					✓
External encoder input	✓	✓		✓	✓
External encoder output emulation		✓		✓	

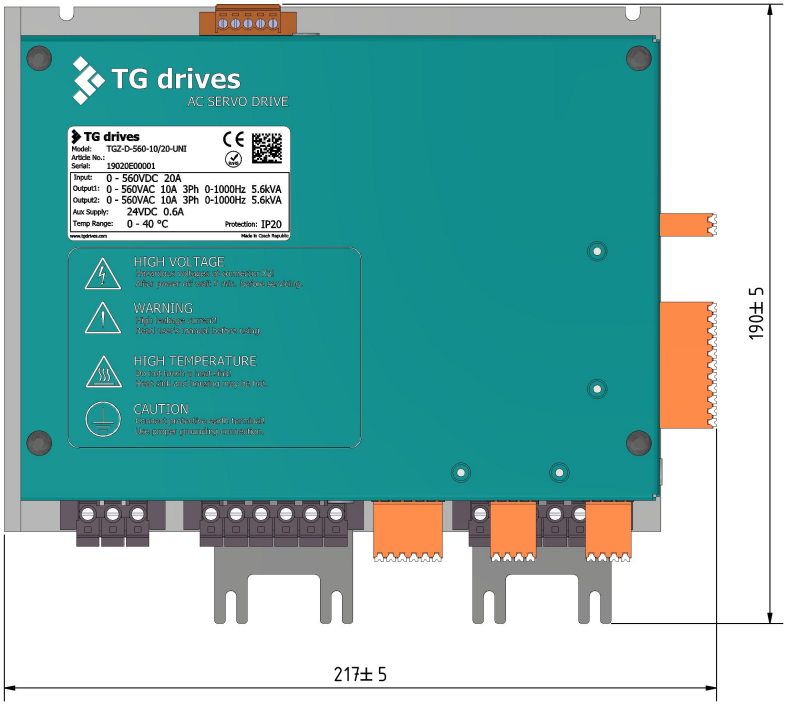
Every motor feedback requires its own specific firmware version. Only one feedback type can be used at a time (for all axes).

**Servoamplifier has to be ordered as a TGZ+Motion variant, otherwise TGZ+Motion firmware can't be loaded.*

Dimensions



Dimensions with connectors



Connectors & interfaces

