## Engineering data

| | | |
|---|---|---|
| Number of axes | 1 | |
| Aux supply | 24 ± 10% | V DC (0.6A)* |
| Power supply | 0-400 | V AC 3~ |
| DC bus voltage | 0-560 | V DC |
| Input power (S1) | 5.6 | kVA |
| Rated output current | 10 | A (rms) |
| Peak current | 20 | A (rms) |
| Losses at rated load | 70 | 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

NCZXX3P49-04

## Mechanical data

| | | |
|---|---|---|
| Weight | 2.25 | 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** |

## Supported communication*

| | |
|---|---|
| 1x Ethernet | EtherCAT |
| 1x Ethernet | fast service protocol (FSP) |
| 1x Ethernet | Modbus TCP / ProfiNET / service TCP or UDP |
| 1x CAN | 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.*

## Connectors & interfaces