

Features


- XGF-PN8A : Dedicated LS ELECTRIC EtherCAT Network Support (XGT Servo N series)
- XGF-PN8B : Standard EtherCAT Network Support(Standard EtherCAT Servo)
- Direct connect with servo driver Max 8
- 2~8 axis linear interpolation, 2axis circular interpolation, 3axis helical interpolation
- Position, speed, feed control is possible through the various operation
- Parameters, the operation data stored in the FRAM(without Battery)
- CAM for controlling up to eight different types of CAM data



Specifications

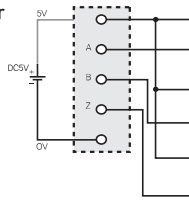
Item		XGF-PN8A/PN8B	XGF-PN4B		
Number of axis		8 axis	4 axis		
Interpolation		2~8 axis linear, 2axis circular, 3axis helical interpolation			
Control method		Position, speed, Speed/position, position/speed position/torque, Feed control			
Setting unit		pulse, mm, inch, degree			
Positioning data		Each axis has 400 data items (Operation step number 1~400). It is available to set with software package or programming.			
XG5000	Port	RS-232C, USB			
	Data	Basic, expansion, manual, servo parameter, operation data, cam data, command information			
	Monitor	Operation, trace, input sort, error information			
Back-up		FRAM(parameter, operation data) no battery			
Positioning	Positoning method	Absolute/Incremental			
		Position address range	Absolute	Incremental	Speed/position, position/speed conversion control
	mm		-214748364.8 ~ 214748364.7(μm)	-214748364.8 ~ 214748364.7(μm)	-214748364.8 ~ 214748364.7(μm)
	inch		-21474.83648 ~ 21474.83647	-21474.83648 ~ 21474.83647	-21474.83648 ~ 21474.83647
	degree		-21474.83648 ~ 21474.83647	-21474.83648 ~ 21474.83647	-21474.83648 ~ 21474.83647
	pulse	-2147483648 ~ 2147483647	-2147483648 ~ 2147483647	-2147483648 ~ 2147483647	
	Position speed range	mm	0.01 ~ 2000000.00(mm/Min)		
inch		0.001 ~ 2000000.000(inch/Min)			
degree		0.001 ~ 2000000.000(degree/Min)			
pulse		1 ~ 20.000000(pulse/Sec)			
RPM	0.1 ~ 100000.0(RPM)				
Accel/Decel pattern	Trapezoidal & S-curve acceleration/deceleration				
Accel/Decel time	1~2,147,483.647 ms				
Manual		Jog/ MPG/ inching			
Homing method		Max+Z(Forward), Min+Z(Backward), Near-point+Z(Forward, Backward), Max+near-point+Z(Forward), Min+near-point+Z(Backward), Z(Forward, Backward), near-point(Forward, Backward)			
The ability to Change speed		Absolute/Percent			
Torque		Rated torque %			
Absolute position System		0 (Absolute encoder type servo)			
Encoder input	Channel	2 Channel			
	Max. Input	Max. 200 Kpps			
	Input method	line-drive input(RS-422A IEC), open collector output type			
	Type	CW/CCW, Pulse/Dir, Phase A/B			
Connector	12 Pin connector				
Communication Cycle		800 μs			
Max. distance		100 m			
Cable		STP(Shielded Twisted pair) cable			
Error display		LED			
Operation display		LED			
Occupied points of I/O		64points (Fixed type), 16points (Variable type)			
Current consumption (mA)		500 mA			
Weight(kg)		115 g			

Terminal block configuration

Pin layout		Pin Number	Signal name	
ENC1A+		1	ENC1A+	Encoder1 A +input
ENC1A-		2	ENC1A-	Encoder1 A -input
ENC1B+		3	ENC1B+	Encoder1 B +input
ENC1B-		4	ENC1B-	Encoder1 B -input
ENC1Z+		5	ENC1Z+	Encoder1 Z +input
ENC1Z-		6	ENC1Z-	Encoder1 Z -input
ENC2A+		7	ENC2A+	Encoder2 A +input
ENC2A-		8	ENC2A-	Encoder2 A -input
ENC2B+		9	ENC2B+	Encoder2 B +input
ENC2B-		10	ENC2B-	Encoder2 B -input
ENC2Z+		11	ENC2Z+	Encoder2 Z +input
ENC2Z-		12	ENC2Z-	Encoder2 Z -input

External encoder wiring

* Open collector type



Pin Number	Signal	
1	ENC1A+	Encoder1 A +input
2	ENC1A-	Encoder1 A -input
3	ENC1B+	Encoder1 B +input
4	ENC1B-	Encoder1 B -input
5	ENC1Z+	Encoder1 Z +input
6	ENC1Z-	Encoder1 Z -input
7	ENC2A+	Encoder2 A +input
8	ENC2A-	Encoder2 A -input
9	ENC2B+	Encoder2 B +input
10	ENC2B-	Encoder2 B -input
11	ENC2Z+	Encoder2 Z +input
12	ENC2Z-	Encoder2 Z -input

* line-drive type

