POSIDYN® SDS 5000

Projecting manual

V 5.6-S or later

08/2020   en

Table of contents

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1 Introduction

1.1 About this manual

This document will give you technical data and information about the installation and connection of the inverter and its accessories. This technical documentation will enable the following personnel to perform their tasks correctly.

- Project engineer - planning
- Electrical specialist - installation and connection

Original version

The original language of this documentation is German.

Please note:

This documentation is valid for device types from hardware version 200. Device types with hardware version up to 199 are described in the documentation up to version V 5.6-N.

The brake module BRS 5001 is the follow-up model to the BRS 5000. The BRS 5001 requires firmware V 5.6-N at least. Information on the previous model BRS 5000 can be found in the documentation up to version V 5.6-N.

1.2 Further documentation

Manual	Contents	ID
Commissioning Instructions SDS 5000	Reinstallation, replacement, function test	442301
Operating manual SDS 5000	Set up the inverter	442289

You can find the latest document versions at www.stoeber.de

You can find information on the POSITool software in the following manuals:

Manual	Contents	ID
POSITool operating manual	Information on the basic functions of POSITool	442233
Programming manual	Information on programming with POSITool	441693

You can find the latest document versions at www.stoeber.de.

Note that the programming functionality of POSITool can only be used after training by STOBER. You can find information on training at www. stoeber.de.

The devices of the 5th generation of STOBER inverters can be optionally connected with different fieldbus systems. The connection is described in the following manuals:

Manuals	ID
PROFIBUS DP operating manual	441687
CANopen operating manual	441686
EtherCAT operating manual	441896
PROFINET operating manual	442340

You can find the latest document versions at www.stoeber.de.

The accessories of the inverter are documented in the following manuals:

Manual	Product description	ID
ASP 5001 operating manual	Safe technical integration of the inverter in a machine	442181
Operating instructions POSISwitch AX 5000	Sequential switchover between up to four axes	441689
Control box operating manual	Operating device for parameterization and configuration of the inverter.	441479
Operating manual Absolute Encoder Support AES	For buffering the power supply when using the inductive absolute value encoder EnDat 2.2 digital with battery-buffered multiturn power unit, for example EBI1135, EBI135.	442343

You can find the latest document versions at www.stoeber.de.

1.3   Further support

If you have technical questions that are not answered by this document, please contact:
- Phone: +49 7231 582-3060
- E-mail: applications@stoeber.de

If you have questions about the documentation, please contact:
- E-mail: electronics@stoeber.de

If you have questions about training sessions, please contact:
- E-mail: training@stoeber.de

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1.4   Abbreviations, formula symbols and indices

Abbreviations	
AA	Analog output
AC	Alternating Current
AE	Analog input
AES	Absolute Encoder Support
BA	Binary output
BAT	Battery
BE	Binary input
CAN	Controller Area Network
CH	Brake chopper
CNC	Computerized Numerical Control
CU	Control Unit
DC	Direct Current
I/O	Input/output
EMC	Electromagnetic Compatibility
EtherCAT	Ethernet for Control Automation Technology
HTL	High Threshold Logic
IGB	Integrated bus
IP	International Protection
MAC	Media Access Control
PE	Protective Earth
PELV	Protective Extra Low Voltage
PTC	Positive Temperature Coefficient
PU	Power Unit
PWM	Pulse Width Modulation
RB	Brake Resistor
RCD	Residual Current protective Device
SPS	Programmable logic controller
SSI	Serial Synchronous Interface
STO	Safe Torque Off
TTL	Transistor-transistor logic
UL	Underwriters Laboratories
ZK	DC link

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Formula symbols	Unit	Explanation
f	**Hz**	**Frequency**
f_2	Hz	Output frequency
f_{2PU}	Hz	Output frequency of the power unit
f_{max}	Hz	Maximum frequency
$f_{PWM,PU}$	Hz	Internal pulse clock frequency of the power unit
I	**A**	**Current**
I_1	A	Input current
I_{1max}	A	Maximum input current
I_{1maxCU}	A	Maximum input current of the control unit
I_{1maxPU}	A	Maximum input current of the power unit
$I_{1N,PU}$	A	Nominal input current of the power unit
I_2	A	Output current
I_{2max}	A	Maximum output current
I_{2maxPU}	A	Maximum output current of the power unit
I_{2min}	A	Minimum output current
$I_{2N,PU}$	A	Nominal output current of the power unit
I_N	A	Nominal current
n	**rpm**	**Speed**
n_N	rpm	Nominal speed: the speed for which the nominal torque M_N is specified
P	**W**	**Power**
P_{2maxPU}	W	Maximum sum of drive power
P_{maxRB}	W	Maximum power at the external braking resistor
P_V	W	Power loss
$P_{V,CU}$	W	Power loss of the control unit
R	**Ω**	**Resistance**
R_{2minRB}	Ω	Minimum resistance of the external braking resistor
R_{int}	Ω	Internal resistance
R_{intRB}	Ω	Resistance of the internal braking resistor
ϑ	**°C**	**Temperature**
$\vartheta_{amb,max}$	°C	Maximum surrounding temperature
τ_{th}	s	Thermal time constant
t	**s**	**Time**
t_{min}	s	Minimum time
R	**V**	**Voltage**

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U_1	V	Input voltage
U_{1CU}	V	Input voltage of the control unit
U_{1PU}	V	Input voltage of the power unit
U_{1max}	V	Maximum input voltage
U_2	V	Output voltage
U_{2BAT}	V	Output voltage of the backup battery
U_{2PU}	V	Output voltage of the power unit
U_{max}	V	Maximum voltage
U_{maxPU}	V	Maximum voltage of the power unit
U_{offCH}	V	Off limit of the brake chopper
U_{onCH}	V	On limit of the brake chopper
		Other
p		Number of pole pairs

1.5   Symbols, identifiers, marks

Symbols	
⏚	Grounding symbol according to IEC 60417-5019 (DB:2002-10).

Identification and test symbols	
	Lead-free identifier for RoHS Lead-free identifier according to RoHS directive 2011-65-EU.
CE	**CE mark** Manufacturer's self declaration: The product meets the requirements of EU directives.
	UL test mark This product is listed by UL for the USA and Canada. Representative samples of this product have been evaluated by UL and meet the requirements of applicable standards.
	UL test marks for recognized components This component or material is recognized by UL. Representative samples of this product have been evaluated by UL and meet applicable requirements.

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2 Notes on safety

The devices can represent a source of danger. Therefore observe

- the safety guidelines, technical rules and regulations given in the following sections and the
- Generally applicable technical rules and regulations.

Always read the corresponding documentation as well. STÖBER Antriebstechnik GmbH + Co. KG shall assume no liability for damage resulting from failure to comply with the instruction manual or relevant regulations. This documentation is purely a production description. It does not include any guaranteed features in terms of a warranty right. We reserve the right to make technical changes for the purpose of improving the devices.

2.1 Component part of the product

As this documentation includes important information for the safe and efficient handling of the product, always keep it in the immediate vicinity of the product until product disposal and ensure it can be accessed by qualified personnel at any time.

Also pass on this documentation if the product is handed over or sold to a third party.

2.2 Operation in accordance with its intended use

As defined by DIN EN 50178 (previously VDE 0160), the inverters are electrical equipment operating as power electronics to control the flow of energy in high voltage systems. They are designed exclusively for installation in the control cabinet with at least protection class IP54 and for supplying

- servo motors and
- asynchronous motors.

Designated use does not include connecting other electrical loads!

2.3 Risk assessment

Before the manufacturer may bring a machine onto the market, he must conduct a risk assessment according to Machine Directive 06/42/EC. As a result, the risks associated with the use of the machine are determined. The risk assessment is a multi-stage and iterative process. On no account can sufficient insight into the Machine Directive be given as part of this documentation.

For this reason, seek detailed information about the norms and legal position. When installing the inverter in machines, commissioning is forbidden until it has been determined that the machine meets the requirements of EC Directive 06/42/EC.

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2.4 Ambient conditions

The inverters are products subject to sales restrictions in accordance with IEC 61800-3. In a residential environment this product may cause high-frequency interference. If this occurs the user may be asked to take suitable measures to reduce it.

The inverters are not designed for use in a public low frequency network that supplies residential areas. High-frequency interference can be expected if the inverters are used in a network of this type. The inverters are designed exclusively for operation in TN networks. The inverters are only suitable for use in supply current networks that are able to provide a maximally symmetrical nominal short circuit current at maximally 480 volts according to the following table:

Size	Max. symmetrical nominal short-circuit current
0 and 1	5,000 A
2	5,000 A
3	10,000 A

Install the inverter in a control cabinet in which the admissible surrounding temperature will not be exceeded.

The following applications are prohibited:
• Use in areas subject to explosion hazard
• Use in environments with harmful substances as specified by EN 60721, for example oils, acids, gases, vapors, dust and radiation
• Use with mechanical vibration and impact loads exceeding the limits specified in the technical data in the projecting manuals

Implementation of the following applications is only permitted after approval is obtained from STOBER:
• Use in non-stationary applications

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2.5 Qualified personnel

Since the devices may harbor residual risks, all configuration, transportation, installation and commissioning tasks including operation and disposal may only be performed by trained personnel who are aware of the possible risks.

Personnel must have the qualifications required for the job. The following table lists examples of occupational qualifications for the jobs:

Activity	Possible occupational qualifications
Transportation and storage	Worker skilled in storage logistics or comparable training
Configuration	- Graduate engineer (electro-technology or electrical power technology) - Technician (m/f) (electro-technology)
Installation and connection	Electronics technician (m/f)
Commissioning (of a standard application)	- Technician (m/f) (electro-technology) - Master electro technician (m/f)
Programming	Graduate engineer (electro-technology or electrical power technology)
Operation	- Technician (m/f) (electro-technology) - Master electro technician (m/f)
Disposal	Electronics technician (m/f)

In addition, the valid regulations, the legal requirements, the reference books, this technical documentation and, in particular, the safety information contained therein must be carefully

- read,
- understood and
- complied with.

2.6 Transportation and storage

Immediately upon receipt, examine the delivery for any transportation damages. Immediately inform the transportation company of any damages. If damages are found, do not commission the product. If the device is not to be installed immediately, store it in a dry, dust-free room. Please see the documentation for how to commission an inverter after it has been in storage for a year or longer.

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2.7 Installation and connection

Installation and connection work are only permitted after the device has been isolated from the power!

The accessory installation instructions allow the following actions during the installation of accessories:
- The housing in the upper slot can be opened
- The housing in the bottom slot can be opened.

Opening the housing in another place or for other purposes is not permitted.

Use only copper conductors. For the line cross sections to be used, refer to DIN VDE 0298-4 or DIN EN 60204-1 Appendix D and Appendix G.

The permissible protection class is protective ground. Operation is not permitted unless the protective ground is connected in accordance with the regulations.

Comply with the applicable instructions for installation and commissioning of motor and brakes.
Main equipment grounding markings: The main ground connections are marked "PE" or with the international ground symbol (IEC 60417, Symbol 5019 ⏚).

The motor must have an integrated temperature monitor with basic isolation in acc. with EN 61800-5-1 or external motor overload protection must be used.

Protect the device from falling parts (pieces of wire, leads, metal parts, and so on) during installation or other tasks in the switching cabinet. Parts with conductive properties inside the inverter can cause short circuits or device failure.

Note for UL-compliant use additionally 2.11.

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2.8 Commissioning, operation and service

Remove the additional covers before commissioning so that the device will not overheat. Note the minimum open areas specified in the projecting manuals during installation to prevent the inverter and its accessories from overheating.

The inverter housing must be closed before you turn on the power supply voltage. When the power supply voltage is turned on, hazardous voltages may be present on the connection terminals and the cables and motor terminals connected to them. Note that the device is not reliably free of voltage simply because all the displays are blank.

The following actions are prohibited while the supply voltage is applied
- Opening the housing
- Connecting or disconnecting connection clamps and
- Installing/removing or attaching/detaching accessories.

Apply the 5 safety rules in the order stated before performing any work on the machine:
1. Disconnect.
   Also ensure that the auxiliary circuits are disconnected.
2. Protect against being turned on again.
3. Check that voltage is not present.
4. Ground and short circuit.
5. Cover adjacent live parts.

Information
Note that the discharge time of the DC link capacitors is up to 6 minutes. You can only determine the absence of voltage after this time period.

You can carry out work on the inverter later. Repairs may only be performed by STOBER.

Send faulty devices with a fault description to:
STÖBER Antriebstechnik GmbH + Co. KG
Department VS-EL
Kieselbronner Str.12
75177 Pforzheim
GERMANY

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2.9   Disposal

Please observe the current national and regional regulations! Dispose of the individual parts separately depending on the quality and currently applicable regulations, e.g. as
- Electronic waste (circuit boards)
- Plastic
- Sheet metal
- Copper
- Aluminum
- Battery

2.10   Residual dangers

The connected motor can be damaged with certain settings of inverters:
- Longer operation against an applied motor halting brake
- Longer operation of self-cooled motors at slow speeds

Drives can reach dangerous excess speeds (e.g., setting of high output frequencies for motors and motor settings which are unsuitable for this). Secure the drive accordingly.

2.11   UL-compliant use

Additional information for use under UL conditions (UL – Underwriters Laboratories).

Surrounding temperature and pollution degree
The maximum surrounding temperature for UL-compliant operation is 45 °C.
Observe the specifications in the general data for use in an environment with a pollution degree, see section 3.3.1.

Mains configuration
All device types that are supplied with 480 V are designed exclusively for operation on Wye source with 480/277 V.

Power supply and motor overload protection
Observe the specifications in the electrical data of the inverter for this, see section 3.4.

Line fuse
Observe the specifications for the UL-compliant line fuse in section 5.3.1.

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Motor protection

All models of the 5th generation of STOBER inverters have a certified i²t model, a calculation model for thermal monitoring of the motor. This fulfills the requirements of a semiconductor motor overload protection in accordance with the change to UL 508C from May 2013. To activate the protective function and set it up, make the following parameter settings – which differ from the default values: U10 = *2:Warning* and U11 = 1.00 s. This module can be used as an alternative or in addition to motor protection with temperature monitoring as described in section 5.8.

> **i** **Information**
> STÖBER Antriebstechnik GmbH + Co. KG recommends using PTC thermistors as thermal motor protection.

Motor temperature sensor

All models of the 5th generation of STOBER inverters starting with HW 200 have connections for PTC thermistors (NAT 145 °C) or KTY (KT84-130) or Pt temperature sensors (Pt1000). Observe the terminal description X2 for proper connection, see section 5.8.

Braking resistor

If the inverters will be fitted with an externally mounted braking resistor, separate overtemperature protection must be made available.

24 vdc power supply

Low voltage circuits must be supplied by a source isolated from the mains whose maximum output voltage does not exceed 28.8 V.
Observe terminal description X11 for this, see section 5.4.

Lines

Use only copper conductors for an surrounding temperature of 60/75 °C.

Fuses

Use a 1 A fuse (time lag) before relay 1. The fuse must be approved according to UL 248.
Refer to the connection example of terminal description X1 for this, see section 5.5.

Branch circuit protection

An integral solid state short circuit protection does not provide branch circuit protection. If you would like to branch the output of the inverter, branch circuit protection must be ensured in conformity with the instructions of STOBER, the National Electrical Code and all additional applicable local regulations or equivalent specifications.

UL test

During the UL acceptance process of STÖBER Antriebstechnik GmbH + Co. KG, only risks for electrical shock and fire hazard were examined. Aspects of functional safety were not assessed. These aspects are assessed for STOBER by the TÜV SÜD certification authority, for example.

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2.12   Presentation of notes on safety

NOTICE

Notice

means that property damage may occur

▶   if the stated precautionary measures are not taken.

⚠ **CAUTION!**

Caution

with warning triangle means that minor injury may occur

▶   if the stated precautionary measures are not taken.

⚠ **WARNING!**

Warning

means that there may be a serious danger of death

▶   if the stated precautionary measures are not taken.

⚠ **DANGER!**

Danger

means that serious danger of death exists

▶   if the stated precautionary measures are not taken.

Information

refers to important information about the product or serves to emphasize a section in the documentation to which the reader should pay special attention.

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3 Technical data

3.1 Type designation

Sample code

SDS	5	075	A

Explanation

Code	Designation	Design
SDS	Series	
5	Generation	5th Generation
075	Power	075 = 7.5 kW
– **A**	Hardware variants	No identification: up to HW 199 A: HW 200 and above

3.2 Sizes

The SDS 5000 series includes the following types and sizes:

Type	Size
SDS 5007A	Size 0
SDS 5008A	Size 0
SDS 5015A	Size 0
SDS 5040A	Size 1
SDS 5075A	Size 1
SDS 5110A	Size 2
SDS 5150A	Size 2
SDS 5220A	Size 3
SDS 5370A	Size 3
SDS 5450A	Size 3

3.3 General data of the inverters

3.3.1 Transportation, storage and operating environment

NOTICE

Material damage!

The DC link capacitors in devices of sizes 0, 1 and 2 can lose their electrical strength through long storage times. Considerable material damage can arise from a reduced electrical strength of the DC link capacitors when switching on.

▶ Use devices in storage annually or before startup.

Maximum surrounding air temperature during operation	0 °C to 45 °C for rated data Up to 55 °C with power reduction, 2.5 %/K
Temperature during storage/transportation	-20 °C to +70 °C Maximum change: 20 K/h
Humidity	Relative humidity: 85 %, no condensation
Installation altitude	Up to 1000 m above sea level without restrictions 1000 to 2000 m above sea level with power reduction, 1.5 %/100 m
Pollution degree	2 as per EN 50178
Ventilation	Built-in fan
Vibration (operation) acc. to DIN EN 60068-2-6	5 Hz ≤ f ≤ 9 Hz: 0.35 mm 9 Hz ≤ f ≤ 200 Hz: 1 m/s
Vibration (transportation) acc. to DIN EN 60068-2-6	5 Hz ≤ f ≤ 9 Hz: 3.5 mm 9 Hz ≤ f ≤ 200 Hz: 10 m/s 200 Hz ≤ f ≤ 500 Hz: 15 m/s

3.3.2 Device features

Protection class	IP20
Radio interference suppression	Integrated line filter according to EN 61800-3, interference emission class C3
Overvoltage category	III to EN 61800-5-1

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3.3.3   Weight

Device	Weight	
	Without packaging [kg]	**With packaging [kg]**
SDS 5007A	2.3	3.5
SDS 5008A		
SDS 5015A		
SDS 5040A	3.9	5.3
SDS 5075A		
SDS 5110A	5.0	6.2
SDS 5150A		
SDS 5220A	11.9	13.7
SDS 5370A	13.3	15.1
SDS 5450A		

If you order an inverter with accessory parts, the weight is increased by the following amounts:
- Accessory parts for upper option (fieldbus): 0.1 kg
- Accessory parts for lower option (terminals): 0.2 kg

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3.4 Electrical data

> **Information**
>
> An explanation of the most important formula symbols can be found in section 1.4 Abbreviations, formula symbols and indices.

3.4.1 Size 0: SDS 5007A to SDS 5015A

Type	SDS 5007A	SDS 5008A	SDS 5015A
ID no.	55428	55429	55430
Recommended motor rating	0.75 kW	0.75 kW	1.5 kW
U_{1PU}	1×230 V +20 % / -40 % 50/60 Hz	3×400 V, +32 % / -50 %, 50 Hz 3×480 V, +10 % / -58 %, 60 Hz	
$I_{1N,PU}$	1×5.9 A	3×2.2 A	3×4 A
f_{2PU}	$0 - 700$ Hz		
U_{2PU}	0 to 230 V	0 to 400 V	

Operation with synchronous servo motor

$I_{2N,PU}$	3×3 A	3×1.7 A	3×3.4 A
I_{2maxPU}	250 % for 2 s; 200 % for 5 s		
$f_{PWM,PU}$	8 kHz[a]		

a) Clock frequency adjustable from 4 to 16 kHz, see section 3.4.7 Derating by increasing the switching frequency.

Operation with asynchronous motor

$I_{2N,PU}$	3×4 A	3×2.3 A	3×4.5 A
I_{2maxPU}	180 % for 5 s; 150 % for 30 s		
$f_{PWM,PU}$	4 kHz[a]		

a) Clock frequency adjustable from 4 to 16 kHz, see section 3.4.7 Derating by increasing the switching frequency.

U_{maxPU}	440 V	830 V
U_{onCH}	400 V – 420 V	780 V – 800 V
U_{offCH}	360 V – 380 V	740 V – 760 V
R_{2minRB}	100 Ω	100 Ω
P_{maxRB}	1.8 kW	6.4 kW

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3.4.2 Size 1: SDS 5040A to SDS 5075A

Type	SDS 5040A	SDS 5075A
ID no.	55431	55432
Recommended motor rating	4.0 kW	7.5 kW
U_{1PU}	3×400 V, +32 % / -50 %, 50 Hz 3×480 V, +10 % / -58 %, 60 Hz	
$I_{1N,PU}$	3×9.3 A	3×15.8 A
f_{2PU}	0 – 700 Hz	
U_{2PU}	0 – 400 V	

Operation with synchronous servo motor

$I_{2N,PU}$	3×6 A	3×10 A
I_{2maxPU}	250 % for 2 s; 200 % for 5 s	
$f_{PWM,PU}$	8 kHz[a]	

a) Clock frequency adjustable from 4 to 16 kHz, see section 3.4.7 Derating by increasing the switching frequency.

Operation with asynchronous motor

$I_{2N,PU}$	3×10 A	3×16 A
I_{2maxPU}	180 % for 5 s; 150 % for 30 s	
$f_{PWM,PU}$	4 kHz[a]	

a) Clock frequency adjustable from 4 to 16 kHz, see section 3.4.7 Derating by increasing the switching frequency.

U_{maxPU}	830 V	
U_{onCH}	780 V – 800 V	
U_{offCH}	740 V – 760 V	
R_{2minRB}	47 Ω	47 Ω
P_{maxRB}	13.6 kW	13.6 kW

3.4.3 Size 2: SDS 5110A and SDS 5150A

Type	SDS 5110A	SDS 5150A
ID no.	55433	55434
Recommended motor rating	11 kW	15 kW
U_{1PU}	3 × 400 V, +32 % / -50 %, 50 Hz 3 × 480 V, +10 % / -58 %, 60 Hz	
$I_{1N,PU}$	3 × 24.5 A	3 × 32.6 A
f_{2PU}	0 – 700 Hz	
U_{2PU}	0 – 400 V	

Operation with synchronous servo motor

$I_{2N,PU}$	3 × 14 A	3 × 20 A
I_{2maxPU}	250 % for 2 s; 200 % for 5 s	
$f_{PWM,PU}$	8 kHz[a]	

a) Clock frequency adjustable from 4 to 16 kHz, see section 3.4.7 Derating by increasing the switching frequency.

Operation with asynchronous motor

$I_{2N,PU}$	3 × 22 A	3 × 32 A
I_{2maxPU}	180 % for 5 s; 150 % for 30 s	
$f_{PWM,PU}$	4 kHz[a]	

a) Clock frequency adjustable from 4 to 16 kHz, see section 3.4.7 Derating by increasing the switching frequency.

U_{maxPU}	830 V
U_{onCH}	780 V – 800 V
U_{offCH}	740 V – 760 V
R_{2minRB}	22 Ω
P_{maxRB}	29.1 kW

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3.4.4 Size 3: SDS 5220A to SDS 5450A

Type	SDS 5220A	SDS 5370A	SDS 5450A
ID no.	55435	55436	55437
Recommended motor rating	22 kW	37 kW	45 kW
U_{1PU}	3×400 V, +32 % / -50 %, 50 Hz 3×480 V, +10 % / -58 %, 60 Hz		
$I_{1N,PU}$	3×37 A	3×62 A	3×76 A
f_{2PU}	0 – 700 Hz		
U_{2PU}	0 – 400 V		

Operation with synchronous servo motor

$I_{2N,PU}$	3×30 A	3×50 A	3×60 A
I_{2maxPU}	250 % for 2 s; 200 % for 5 s		
$f_{PWM,PU}$	8 kHz[a]		

a) Clock frequency adjustable from 4 to 16 kHz, see section 3.4.7 Derating by increasing the switching frequency.

Operation with asynchronous motor

$I_{2N,PU}$	3×44 A	3×70 A	3×85 A
I_{2maxPU}	180 % for 5 s; 150 % for 30 s		
$f_{PWM,PU}$	4 kHz[a]		

a) Clock frequency adjustable from 4 to 16 kHz, see section 3.4.7 Derating by increasing the switching frequency.

U_{maxPU}	830 V
U_{onCH}	780 V – 800 V
U_{offCH}	740 V – 760 V
R_{intRB}	30 Ω (PTC resistance; 100 W; max. 1 kW for 1 s; τ = 40 s)
R_{2minRB}	15 Ω
P_{maxRB}	42 kW

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3.4.5 Power loss data of the inverter according to EN 50598

Relative losses

Type	Nominal current $I_{2N,PU}$ [A]	Apparent power [kVA]	Absolute losses $P_{V,CU}$ a) [W]	(0/25)	(0/50)	(0/100)	(50/25)	(50/50)	(50/100)	(90/50)	(90/100)	IE class c)	Comparison d) [%]
				[%]									
SDS 5007A	4	0.9	<10	5.01	5.07	5.68	5.20	5.37	6.30	5.88	7.43	IE2	
SDS 5008A	2.3	1.6	<10	2.98	3.13	3.49	3.02	3.22	3.71	3.36	4.09	IE2	
SDS 5015A	4.5	3.1	12	1.71	1.86	2.24	1.75	1.97	2.51	2.16	3.04	IE2	
SDS 5040A	10	6.9	12	1.38	1.54	1.93	1.43	1.64	2.17	1.80	2.57	IE2	
SDS 5075A	16	11.1	12	0.95	1.12	1.66	0.99	1.23	1.98	1.41	2.52	IE2	
SDS 5110A	22	15.2	<15	0.80	0.97	1.49	0.84	1.06	1.75	1.21	2.19	IE2	
SDS 5150A	32	22.2	<15	0.70	0.87	1.40	0.74	0.97	1.66	1.11	2.08	IE2	
SDS 5220A	44	30.5	35	0.61	0.76	1.21	0.68	0.90	1.53	1.06	1.96	IE2	
SDS 5370A	70	48.5	35	0.53	0.69	1.18	0.59	0.82	1.49	0.97	1.89	IE2	
SDS 5450A	85	58.9	35	0.47	0.64	1.18	0.54	0.78	1.50	0.94	1.94	IE2	

Absolute losses P_V

Type	Nominal current $I_{2N,PU}$ [A]	Apparent power [kVA]	Absolute losses $P_{V,CU}$ a) [W]	(0/25)	(0/50)	(0/100)	(50/25)	(50/50)	(50/100)	(90/50)	(90/100)	IE class c)	Comparison d) [%]
				[W]									
SDS 5007A	4	0.9	<10	45.1	45.6	51.1	46.8	48.3	56.7	52.9	66.9	IE2	51.8
SDS 5008A	2.3	1.6	<10	47.7	50.1	55.8	48.3	51.5	59.3	53.8	65.4	IE2	40.2
SDS 5015A	4.5	3.1	12	52.9	57.6	69.3	54.4	61.0	77.9	67.1	94.1	IE2	39.6
SDS 5040A	10	6.9	12	95.3	106.1	133.3	98.6	113.2	149.9	123.9	177.0	IE2	37.1
SDS 5075A	16	11.1	12	104.9	124.0	184.6	110.3	136.6	219.8	156.0	279.8	IE2	35.8
SDS 5110A	22	15.2	<15	121.5	146.9	226.1	128.1	161.6	266.0	183.7	332.7	IE2	32.9
SDS 5150A	32	22.2	<15	154.7	192.8	311.3	164.6	214.6	369.3	245.9	462.1	IE2	38.3
SDS 5220A	44	30.5	35	187.5	232.2	368.7	207.7	273.9	466.8	323.0	597.8	IE2	32.1
SDS 5370A	70	48.5	35	256.6	332.3	570.8	287.9	397.0	721.5	471.0	915.9	IE2	33.9
SDS 5450A	85	58.9	35	277.8	376.9	692.3	317.4	459.0	886.1	554.6	1143.1	IE2	35.3

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a) Absolute losses for a power stage that is switched off
b) Operating points for relative motor stator frequency in % and relative torque current in %
c) IE class according to EN 50598
d) Comparison of the losses for the reference inverter related to IE2 in the nominal point (90, 100)

General conditions

The loss data applies to inverters without accessories.

The power loss calculation based on a three-phase supply voltage with 400 V_{AC} / 50 Hz.

The calculated data includes a supplement of 10 % according to EN 50598.

The power loss specifications refer to a clock frequency of 4 kHz.

The absolute losses for a power stage that is switched off refer to the 24 vdc power supply of the control electronics.

3.4.6 Power loss data of accessories

Type	Absolute losses P_V [W]
Safety module ASP 5001	1
Terminal module SEA 5001	< 2
Terminal module XEA 5001	< 5
Terminal module REA 5001	< 5
Fieldbus module CAN 5000	1
Fieldbus module DP 5000	< 2
Fieldbus module ECS 5000	< 2
Fieldbus module PN 5000	< 4
Brake module BRS 5001	< 1

Information
Also observe the absolute power loss of the encoder (usually < 3 W) as well as the brake for the design.

3.4.7 Derating by increasing the switching frequency

Based on the switching frequency $f_{PWM,PU}$, the following values of the output currents $I_{2N,PU}$ result. Remember that only 8 kHz and 16 kHz can be set for control type servo.

Output current $I_{2N,PU}$

Switching frequency	4 kHz	8 kHz	16 kHz
SDS 5007A	4.0 A	3.0 A	2.0 A
SDS 5008A	2.3 A	1.7 A	1.2 A
SDS 5015A	4.5 A	3.4 A	2.2 A
SDS 5040A	10.0 A	6.0 A	3.3 A
SDS 5075A	16.0 A	10.0 A	5.7 A
SDS 5110A	22.0 A	14.0 A	8.1 A
SDS 5150A	32.0 A	20.0 A	11.4 A
SDS 5220A	44.0 A	30.0 A	18.3 A
SDS 5370A	70.0 A	50.0 A	31.8 A
SDS 5450A	85.0 A	60.0 A	37.8 A

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3.5 Dimensions

3.5.1 Size 0 to 2: SDS 5007A to SDS 5150A

IGB
connection cable

Absolute
Encoder
Support
AES

EM 5000 /
BRS 5001

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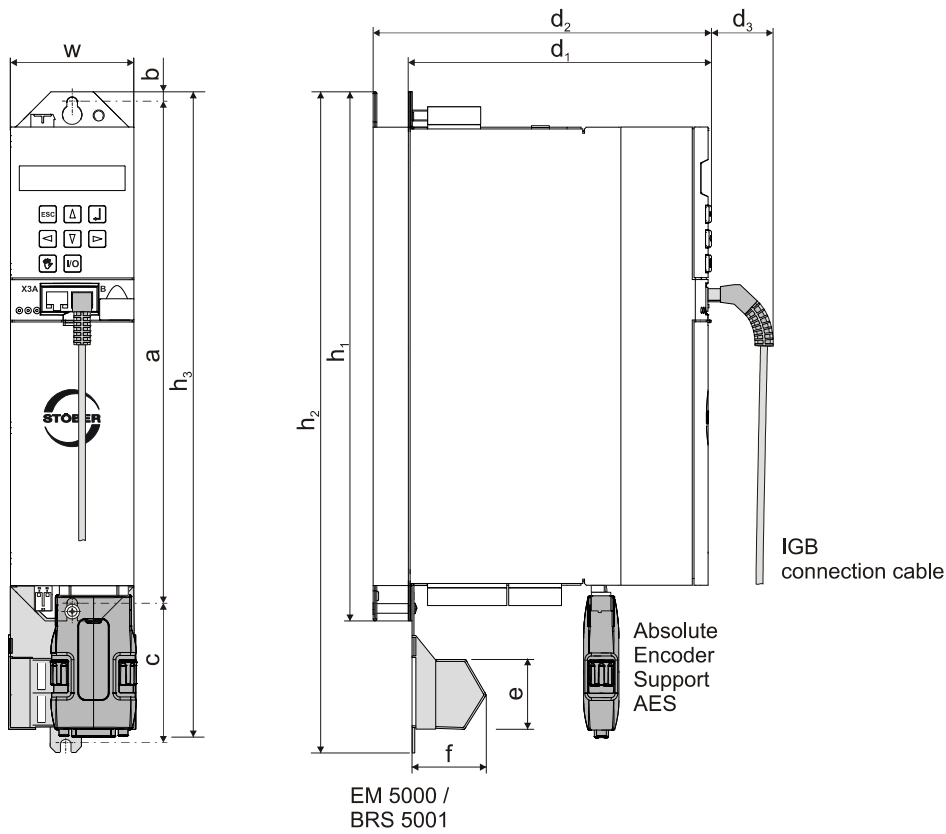
Dimensions [mm]				Size 0	Size 1	Size 2
Inverter	Height		h_1		300	
			h_2		$360^{a)}$ / $373^{b)}$	
			h_3 $^{c)}$		365	
	Width		w		70	105
	Depth		d_1	175	260	260
			d_2 $^{d)}$	193	278	278
			d_3		40	
EMC shroud	Height		e		$37.5^{e)}$ / $44^{f)}$	
	Depth		f		40	
Fastening holes	Vertical distance to upper edge		b		6	
	Vertical distance		a		283+2	
	Vertical distance		$c^{g)}$		79	

a) h_2 = Height incl. EMC shroud EM 5000

b) h_2 = Height incl. brake module BRS 5001

c) h_3 = Height incl. AES

d) d_2 = Depth incl. brake resistor RB 5000

e) e = Height of the EMC shroud EM 5000

f) e = Height of the brake module BRS 5001

g) c = Vertical distance at brake module BRS 5001

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3.5.2　Size 3: SDS 5220A to SDS 5450A
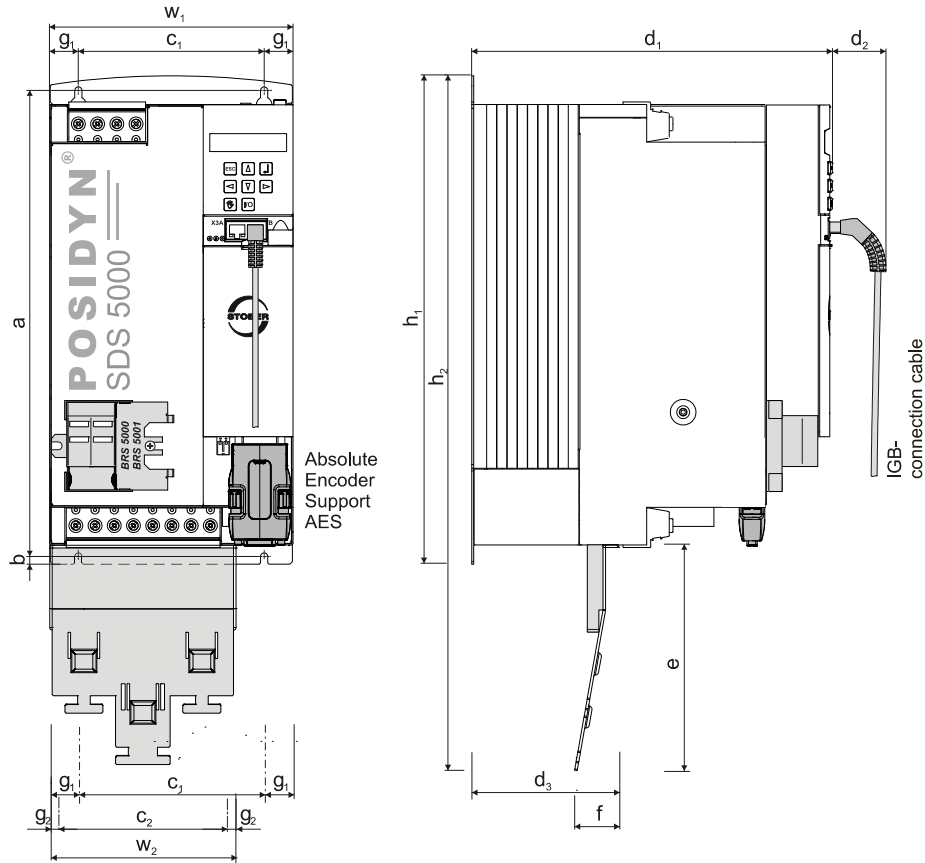
Dimensions [mm]				Size 3
Inverter	Height		h_1	382.5
			h_2 [a)]	540
	Width		w_1	194
	Depth		d_1	276
			d_2	40
EMC shroud	Height		e	174
	Width		w_2	147
	Depth		f	34
	Depth		d_3	113
Fastening holes	Vertical distance		a	365+2
	Vertical distance to bottom edge		b	6
	Horizontal distance		c_1 [b)]	150+0.2/-0.2
	Horizontal distance from the side edge		g_1 [c)]	20
	Horizontal distance		c_2 [d)]	132
	Horizontal distance from the side edge		g_2 [e)]	7.5

a) h_2 = height incl. EMC shroud EM6A3

b) c_1 = horizontal distance from the fastening holes of the inverter

c) g_1 = horizontal distance from the side edge of the inverter

d) c_2 = horizontal distance from the fastening holes of the EMC shroud EM6A3

e) g_2 = horizontal distance from the side edge of the EMC shroud EM6A3

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3.6 Brake resistors SDS 5xxxA

3.6.1 FZMU, FZZMU

Braking resistor – inverter assignment

Type	FZMU 400x65			FZZMU 400x65		
ID no.	49010	55445	55446	53895	55447	55448
SDS 5007A	X	—	—	—	—	—
SDS 5008A	X	—	—	—	—	—
SDS 5015A	X	—	—	—	—	—
SDS 5040A	—	—	—	X	—	—
SDS 5075A	—	—	—	X	—	—
SDS 5110A	—	X	—	—	X	—
SDS 5150A	—	X	—	—	X	—
SDS 5220A	—	—	X	—	—	X
SDS 5370A	—	—	X	—	—	X
SDS 5450A	—	—	X	—	—	X

The internal connections are wired with heat-resistant, silicon-insulated strands of wire on terminals. Also ensure a heat-resistant and stress-resistance design for the connection!

Conductor cross-section

Connection type	Conductor cross-section [mm^2]
Rigid	0.5 – 4.0
Flexible with cable end sleeve	0.5 – 2.5

Properties

Type	FZMU 400x65			FZZMU 400x65		
ID no.	49010	55445	55446	53895	55447	55448
Resistance [Ω]	100	22	15	47	22	15
Power [W]	600			1200		
Therm. time const. τ_{th} [s]	40			40		
Pulse power for < 1 s [kW]	18			36		
U$_{max}$ [V]	848			848		
Weight [kg]	Approx. 2.2			Approx. 4.2		
Protection class	IP20			IP20		
Test marks	c$\mathbf{UL}$us			c$\mathbf{UL}$us		

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Dimensions [mm]

Type	FZMU 400x65			FZZMU 400x65		
ID no.	49010	55445	55446	53895	55447	55448
L x D	400 × 65			400 × 65		
H	120			120		
K	6.5 × 12			6.5 × 12		
M	430			426		
O	485			450		
R	92			185		
U	64			150		
X	10			10		

FZMU   FZZM(U)

Drill pattern

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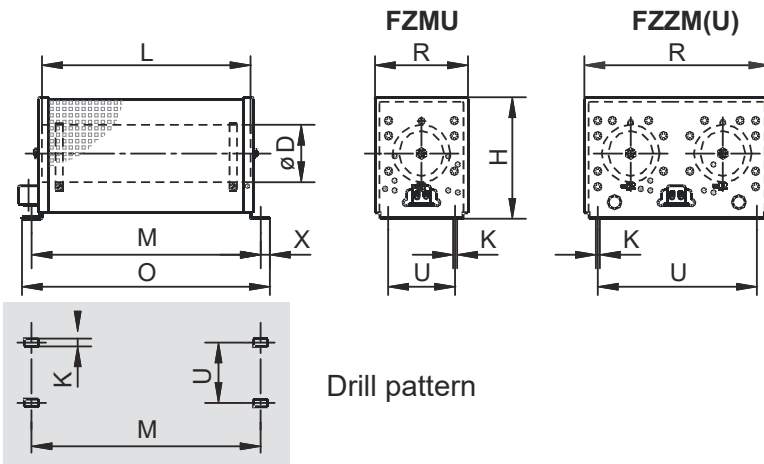
3.6.2 GVADU, GBADU

Braking resistor – inverter assignment

Type ID no.	GVADU 210x20 55441	GBADU 265x30 55442	GBADU 405x30 55499	GBADU 335x30 55443	GBADU 265x30 55444
SDS 5007A	X	X	X	—	—
SDS 5008A	X	X	X	—	—
SDS 5015A	X	X	X	—	—
SDS 5040A	X	X	X	X	—
SDS 5075A	—	—	—	X	—
SDS 5110A	—	—	—	—	X
SDS 5150A	—	—	—	—	X
SDS 5220A	—	—	—	—	X
SDS 5370A	—	—	—	—	X
SDS 5450A	—	—	—	—	X

Properties

Type ID no.	GVADU 210x20 55441	GBADU 265x30 55442	GBADU 265x30 55444	GBADU 335x30 55443	GBADU 405x30 55499
Resistance [Ω]	100	100	22	47	100
Power [W]	150	300	300	400	500
Therm. time const. τ_{th} [s]	60	60			
Pulse power for < 1 s [kW]	3.3	6.6	6.6	8.8	11
U_{max} [V]	848	848			
Cable design	Radox	FEP			
Cable length [mm]	500	500			
Cable cross-section [AWG]	18/19 (0.82 mm²)	14/19 (1.9 mm²)			
Weight [g]	300	950	950	1200	1450
Protection class	IP54	IP54			
Test marks	c**UL**us	c**UL**us			

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Dimensions [mm]

Type ID no.	GVADU 210x20 55441	GBADU 265x30 55442 55444	GBADU 335x30 55443	GBADU 405x30 55499
A	210	265	335	405
H	192	246	316	386
C	20	30	30	30
D	40	60	60	60
E	18.2	28.8	28.8	28.8
F	6.2	10.8	10.8	10.8
G	2	3	3	3
K	2.5	4	4	4
J	4.3	5.3	5.3	5.3
β	65°	73°	73°	73°

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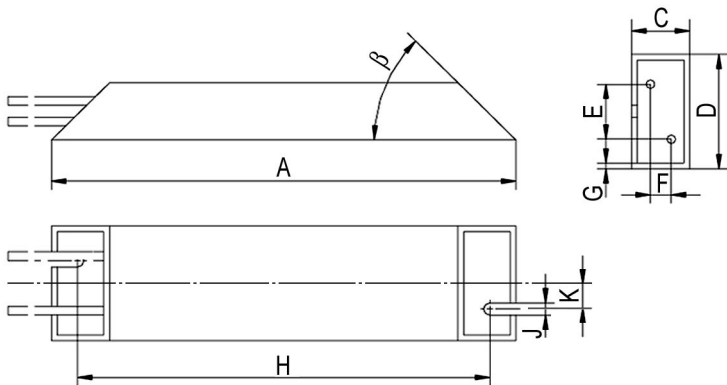
3.6.3 FGFKU

Braking resistor – inverter assignment

Type	FGFKU			
ID no.	55449	55450	55451	53897
SDS 5110A	X	—	—	—
SDS 5150A	X	—	—	—
SDS 5220A	—	X	X	X
SDS 5370A	—	X	X	X
SDS 5450A	—	X	X	X

Properties

Type	FGFKU			
ID no.	55449	55450	55451	53897
Resistance [Ω]	22	15	15	15
Power [W]	2500		6000	8000
Therm. time const. τ_{th} [s]	30		20	20
Pulse power for < 1 s [kW]	50		120	160
U_{max} [V]	848		848	848
Weight [kg]	Approx. 7.5		12	18
Test marks	cⓊus		cⓊus	cⓊus

Dimensions [mm]

Type	FGFKU		
ID no.	55449 55450	55451	53897
A	270	370	570
B	295	395	595
C	355	455	655

Drill pattern

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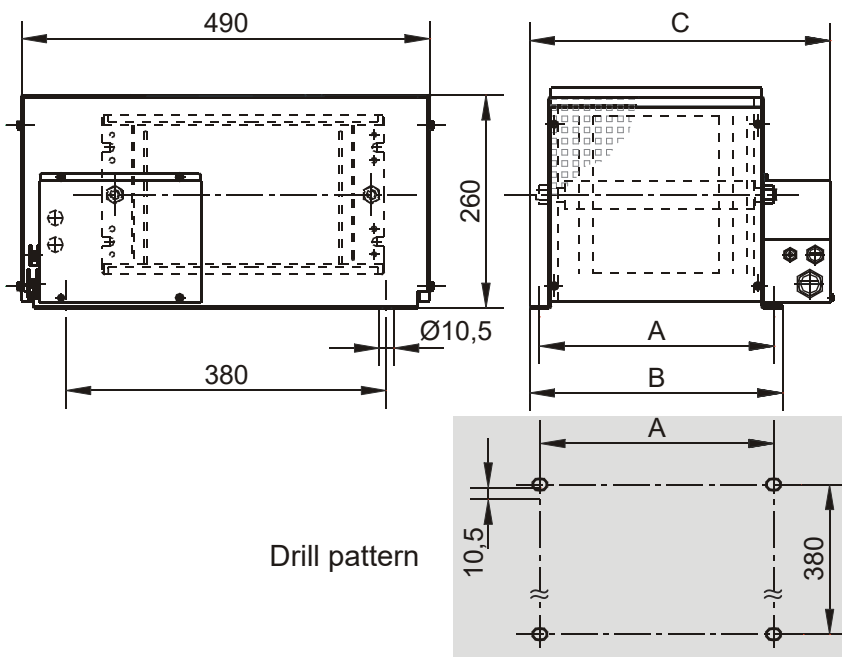
3.6.4 Bottom brake resistor RB 5000

Braking resistor – inverter assignment

Type ID no.	RB 5022 45618	RB 5047 44966	RB 5100 44965
SDS 5008A	—	—	X
SDS 5015A	—	—	X
SDS 5040A	—	X	X
SDS 5075A	—	X	—
SDS 5110A	X	—	—
SDS 5150A	X	—	—

Note the attachment to the inverter (section 4.2.1 Installing the bottom brake resistor and inverter)!

Properties

Type ID no.	RB 5022 45618	RB 5047 44966	RB 5100 44965
Resistance [Ω]	22	47	100
Power [W]	100	60	60
Therm. time const. τ_{th} [s]	8		
Pulse power for < 1 s [kW]	1.5	1.0	1.0
U_{max} [V]	800		
Weight [g]	approx. 640	approx. 460	approx. 440
Cable design	Radox		
Cable length [mm]	250		
Cable cross-section [AWG]	18/19 (0.82 mm²)		
Maximum torque for M5 threaded bolts [Nm]	5		
Protection class	IP40		
Test marks	c $\boldsymbol{\mathcal{R}\!\mathcal{U}}$ us		

Dimensions [mm]

Type ID no.	RB 5022 45618	RB 5047 44966	RB 5100 44965
Height	300	300	
Width	94	62	
Depth	18	18	
Drilling pattern corresponds to size	2	1	0 and 1

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3.7 Output derater

⚠️ **WARNING!**

Risk of burns! Fire hazard! Material damage!

Chokes can heat up to over 100 °C under permitted operating conditions.

▶ Take protective measures against accidental and intentional contact with the choke.

▶ Make sure that no flammable material is in the vicinity of the choke.

▶ Do not install chokes under or near the inverter.

⚠️ **WARNING!**

Fire hazard!

Using chokes outside of the nominal data (cable length, current, frequency, etc.) can cause the chokes to overheat.

▶ Always comply with the maximum nominal data when operating the chokes.

NOTICE

Danger of machine standstill!

The motor temperature sensor evaluation is faulting due to cable capacitances.

▶ If you do not use a cable from STOBER for a cable length over 50 m, you must wire the motor temperature sensor and the brake separately (maximum length: 100 m).

ℹ️ **Information**
The following technical data applies for a rotary field frequency of 200 Hz. For example, this rotary field frequency is achieved with a motor with 4 pole pairs and a nominal speed of 3000 rpm.
Always observe the specified derating for higher rotary field frequencies.
Also observe the dependency of the cycle frequency.

Type	TEP3720-0ES41	TEP3820-0CS41	TEP4020-0RS41
ID no.	53188	53189	53190
Voltage range	3 x 0 to 480 V		
Frequency range	0 to 200 Hz		
I_N at 4 kHz	4 A	17.5 A	38 A
I_N at 8 kHz	3.3 A	15.2 A	30.4 A
Max. permitted motor cable length with output derater	100 m		
Max. surrounding temperature $\vartheta_{amb,max}$	40 °C		
Design	Open		
Winding losses	11 W	29 W	61 W
Iron losses	25 W	16 W	33 W
Connections	Screw terminals		
Max. conductor cross-section	10 mm^2		
UL Recognized Component (CAN; USA)	Yes		
Test marks	c $\mathbf{\Re}$ us		

Projecting

Select the output chokes according to the rated currents of the motor and output chokes. In particular, observe the derating of the output choke for rotary field frequencies higher than 200 Hz.

You can calculate the rotary field frequency for your drive with the following formula:

$$f = n_N \cdot \frac{p}{60}$$

f   Rotary field frequency in Hz
n   Speed in rpm
p   Number of pole pairs
N   Nominal value

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Derating TEP3720-0ES41

I_N [A]
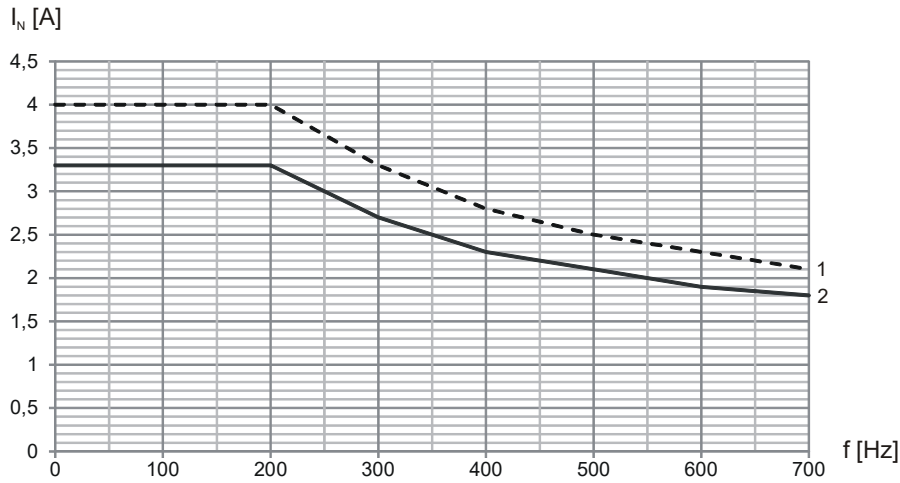
1   Cycle frequency 4 kHz
2   Cycle frequency 8 kHz

Derating TEP3820-0CS41

I_N [A]

1   Cycle frequency 4 kHz
2   Cycle frequency 8 kHz

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Derating TEP4020-0RS41

I_N [A]

1   Cycle frequency 4 kHz
2   Cycle frequency 8 kHz

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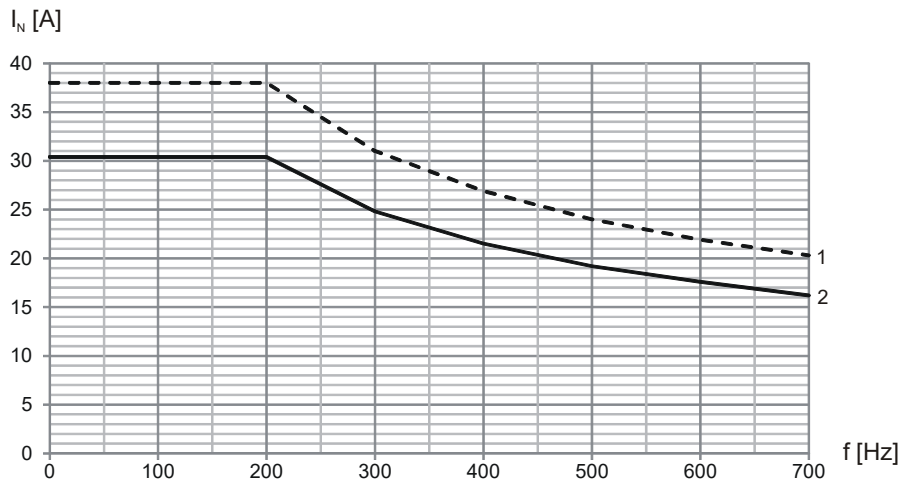
Dimensions	TEP3720-0ES41	TEP3820-0CS41	TEP4020-0RS41
Height h [mm]	Max. 153	Max. 153	Max. 180
Width w [mm]	178	178	219
Depth d [mm]	73	88	119
Vertical distance – fastening holes a1 [mm]	166	166	201
Vertical distance – fastening holes a2 [mm]	113	113	136
Horizontal distance – fastening holes b1 [mm]	53	68	89
Horizontal distance – fastening holes b2 [mm]	49	64	76
Drill holes – depth e [mm]	5.8	5.8	7
Drill holes – width f [mm]	11	11	13
Screw connection – M	M5	M5	M6
Weight [kg]	2.9	5.9	8.8
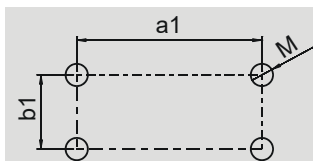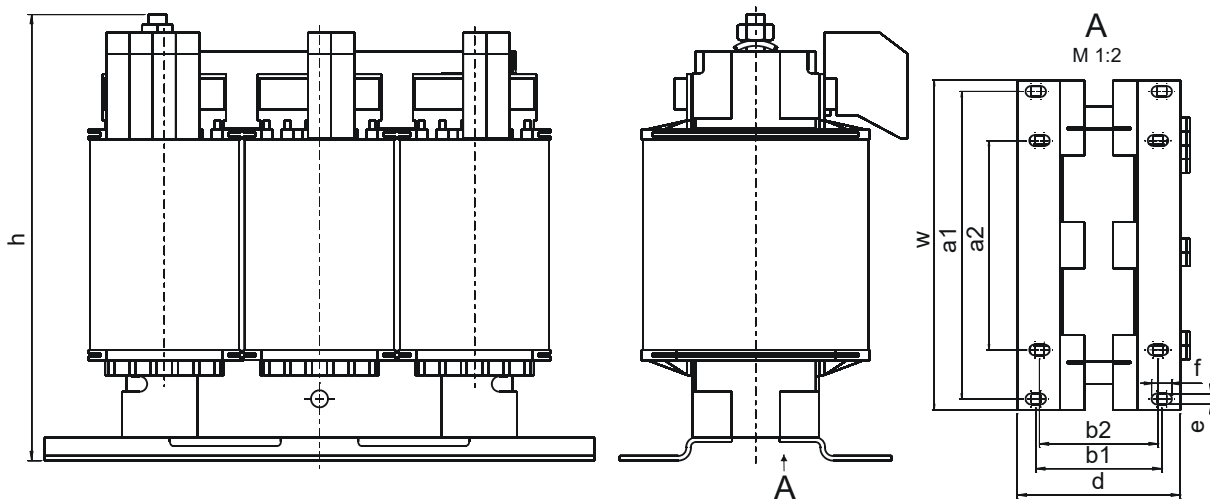
Mounting borings in acc. to DIN EN 60852-4

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4 Installation

This chapter will give you information about installation. This includes:

- Installation of the inverter in the switching cabinet
- Installation of accessories on or in the inverter

> ⚠ **WARNING!**
>
> **Danger of personal injury and material damage due to electric shock!**
>
> ▶ Always switch off all power supply voltage before working on the inverter! Note that the discharge time of the DC link capacitors is up to 6 minutes. You can only determine the absence of voltage after this time period.

4.1 Installation of the inverter in the switching cabinet

> **NOTICE**
>
> **Danger of property damage from incorrect installation of the devices!**
>
> ▶ It is essential to comply with the following installation instructions to avoid damage to the devices.

- The inverters must be installed in a control cabinet with at least protection class IP54.
- The installation location must be free of dust, corrosive vapors and all fluids (in accordance with pollution degree 2 as per EN 60204/EN 50178).
- The installation location must be free of atmospheric moisture.
- Prevent condensation, for example with anti-condensation heating elements.
- For reasons related to EMC, use mounting plates with a conductive surface (unpainted, etc.).
- Fasten the inverters onto the mounting plate with M5 screws.
- The inverters must be installed vertically:
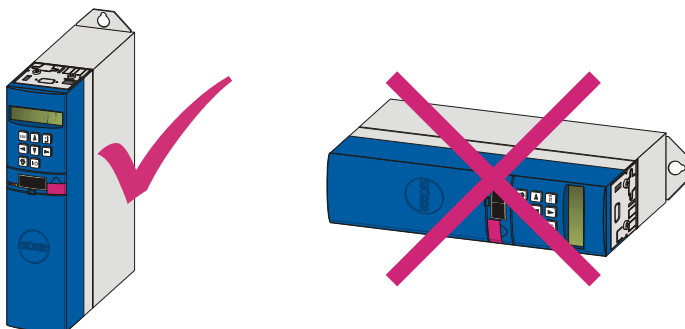
- Avoid installation above or in the immediate vicinity of heat-generating devices, e.g. output chokes or braking resistors:
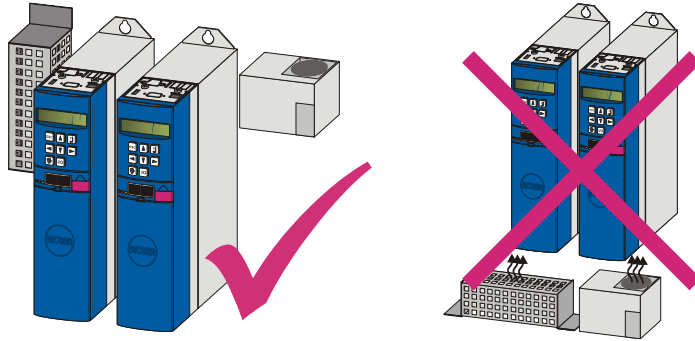
- To ensure there is sufficient air circulation in the control cabinet, observe the minimum clearances.
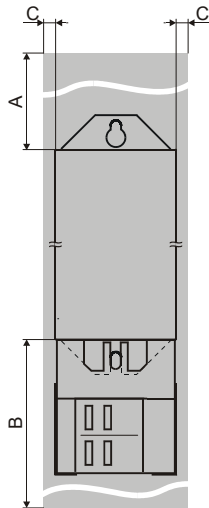
Min. clearance [dimensions in mm]	A Above	B Below	C On the side
Size 0 – size 2	100	100	5
... With EMC shroud or brake module	100	120	5
Size 3	100	100	5
... With EMC shroud	100	220	5

4.2 Accessories

4.2.1 Installing the bottom brake resistor and inverter

> ⚠ **WARNING!**
>
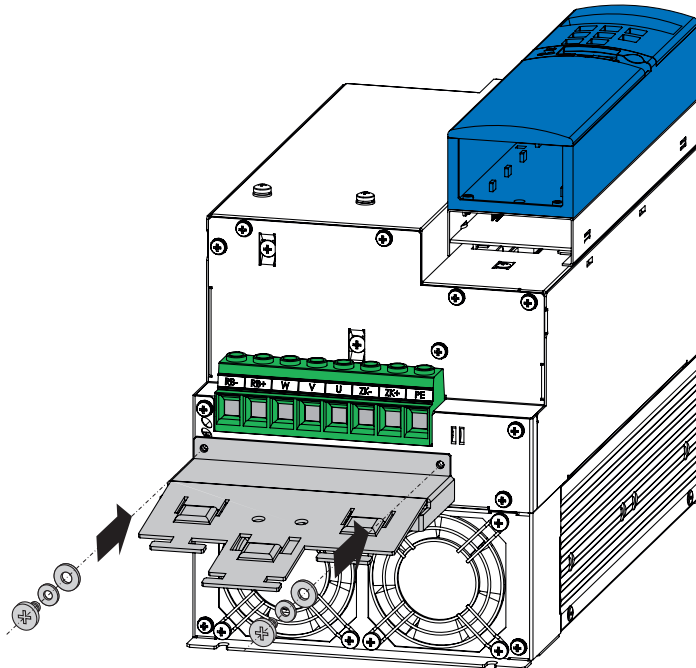> **Danger of personal injury and material damage due to electric shock!**
>
> ▶ Always switch off all power supply voltage before working on the inverter! Note that the discharge time of the DC link capacitors is up to 6 minutes. You can only determine the absence of voltage after this time period.

Requirements:
- You have tapped holes for M5 threaded bolts on the mounting plate in the control cabinet at the installation location, taking into consideration the different device dimensions.

You need:
- The M5 threaded bolts included with the bottom brake resistor.
- The screws and washers included with the submounting brake resistor.
- A PH2 Phillips screwdriver.
- An 8 mm hexagonal socket wrench.

Installation of the submounting brake resistor

1. Attach the bottom brake resistor to the mounting plate with the studs:
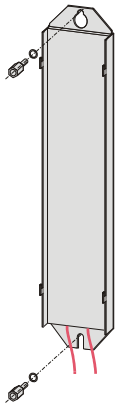
2. Place the device on the guides:
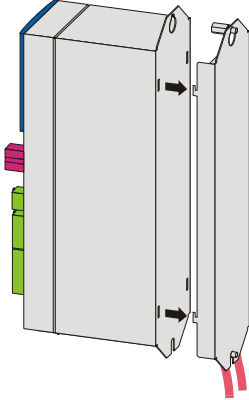
3. Press the device down on the guides:
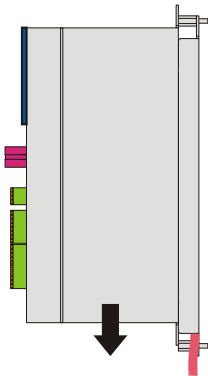
4. Attach the device to the studs with the screws and washers:
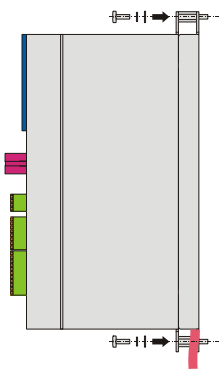
    ⇨ You have installed the submounting brake resistor.

5. Connect the braking resistor.
    Refer to the terminal description X21 for proper connection of the cable, see section 5.10.

6. Parameterize the braking resistor in the inverter.

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4.2.2 Installation of EMC shroud or brake module

4.2.2.1 Attaching EMC shroud EM 5000

For inverters sizes 0 to 2.

You can use the EM 5000 EMC shroud to connect the cable shield of the power cable.

Requirements:
• You have already installed the inverter in the control cabinet.

You need:
• A Phillips screwdriver for loosening the fastening screw.

Attaching EMC shroud EM 5000

1. Undo the lower fastening screw and washers of the inverter:
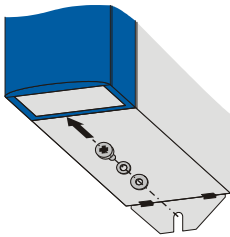
2. Insert the shroud into the openings of the inverter at a slight angle:
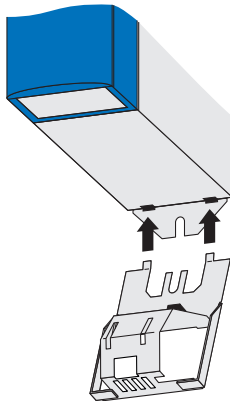
3. Press the back of the shroud either directly on the mounting plate or on the stud in the bottom:
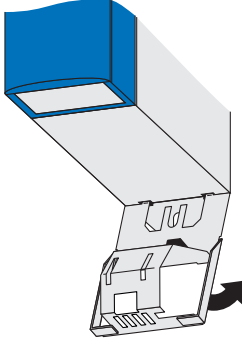
4. Attach the shroud to the inverter and mounting plate or studs with the fastening screw and washers:
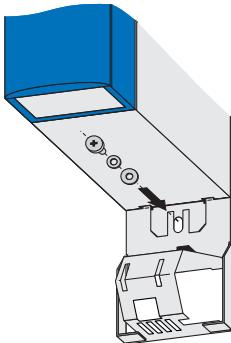
⇨ You have installed the shroud.

4.2.2.2   Attaching EMC shroud EM6A3

The larger EMC shroud EM6A3 is available for size 3 inverters for connecting the shield of the motor line.

⚠ **WARNING!**

Danger of personal injury and material damage due to electric shock!

▶ Always switch off all power supply voltage before working on the inverter! Note that the discharge time of the DC link capacitors is up to 6 minutes. You can only determine the absence of voltage after this time period.

For attachment you will need:
- A Phillips screwdriver.
- The two enclosed screws and washers (combination screws with toothed lock washer, M4x8).

Attaching the EMC shroud EM6A3 to an inverter (size 3)

Fasten the part onto the bottom of the inverter with the enclosed fastening screws in the tapped holes provided for that purpose (maximum tightening torque: 2.4 Nm).

4.2.2.3 Attaching brake module BRS 5001

⚠ **WARNING!**

Danger of personal injury and material damage due to electric shock!

▶ Always switch off all power supply voltage before working on the inverter! Note that the discharge time of the DC link capacitors is up to 6 minutes. You can only determine the absence of voltage after this time period.

You can use the BRS 5001 brake module to connect the cable shield of the power cable. The module also includes power electronics for the optional brake controller for one or two 24-V brakes.

The module includes monitoring for short circuit and broken cable to the connected brake and also for module overload and undervoltage.

The attachment of brake module BRS 5001 to inverters of size 3 is different to the attachment to inverters of size 0 to 2.

4.2.2.3.1 Size 0 to size 2

Requirements:
- You have already installed the inverter in the control cabinet.

You need:
- A Phillips screwdriver for loosening the fastening screw.

Attaching brake module BRS 5001

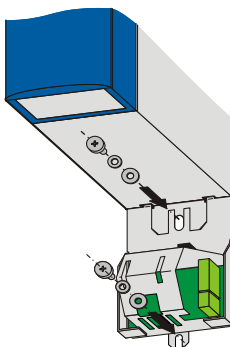1. Undo the lower fastening screw and washers of the inverter:
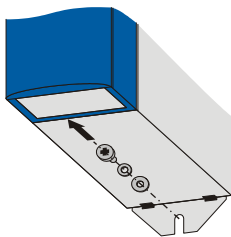
2. Insert the module into the openings of the inverter at a slight angle:
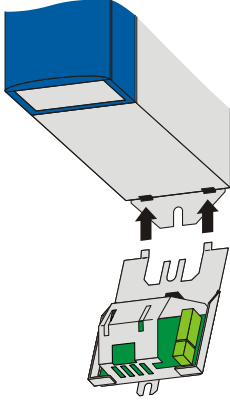
3. Press the back of the module either directly on the mounting plate or on the threaded bolt in the bottom:
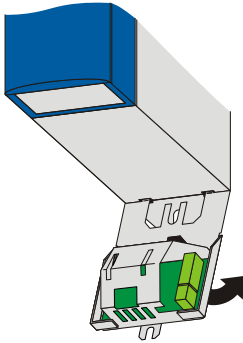
4. Attach the module to the inverter and mounting plate or threaded bolt with the fastening screw and washers. You can optionally secure the module below in addition with another fastening screw on the mounting plate:
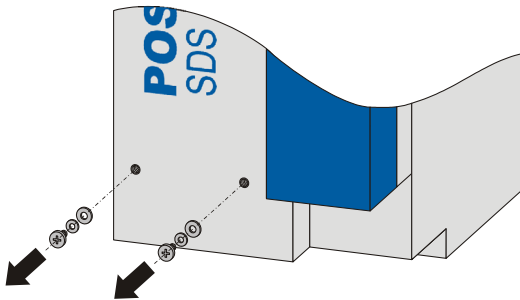
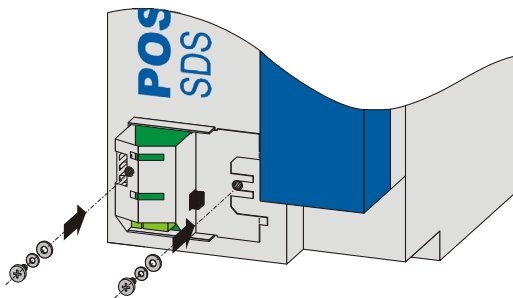⇨ You have now attached the accessory.

4.2.2.3.2   Attaching to size 3

You need:
- A Phillips screwdriver for loosening the fastening screw.

Attaching brake module BRS 5001

1. Undo the fastening screws and washers on the front of the inverter:

2. Place the component on the device and fasten it in place with the fastening screws and washers:

⇨ You have now attached the accessory.

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4.2.3   Installation of the terminal accessories

⚠️ **WARNING!**

Danger of personal injury and material damage due to electric shock!

▶ Always switch off all power supply voltage before working on the inverter! Note that the discharge time of the DC link capacitors is up to 6 minutes. You can only determine the absence of voltage after this time period.

NOTICE

Material damage due for example to electrostatic discharge!

▶ Take suitable protective measures when handling open printed circuit boards, for example clothing appropriate for ESD and an environment free of dirt and grease.

▶ Do not touch the contact surfaces.

To be able to connect binary and analog signals to the inverter, you need one of the following accessory parts:
• SEA 5001, ID no. 49576
• REA 5001, ID no. 49854
• XEA 5001, ID no. 49015

The installation is the same for the accessory parts.

If you want to continue to use a terminal module when replacing an inverter, note the following compatibility information for inverters from hardware version 200:

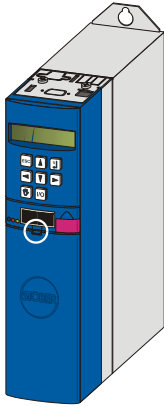| SEA 5000 / 5001	REA 5000	REA 5001	XEA 5000	XEA 5001
Yes	HW version 19 or higher for the accessories	Yes	No	HW version 11 or higher for the accessories

You need:
• A Phillips screwdriver.
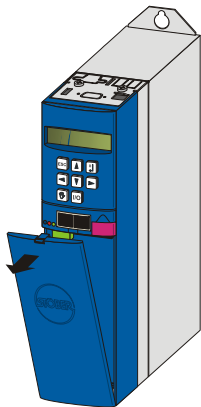• The screws pre-assembled on the accessories.

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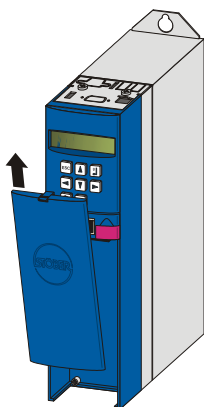**Installing SEA 5001, REA 5001 or XEA 5001 in a SDS 5000**

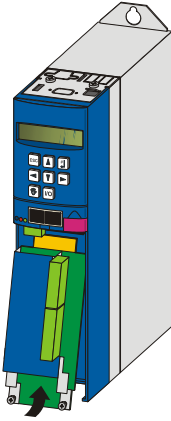1. Unlock the spring lock of the inverter cover:

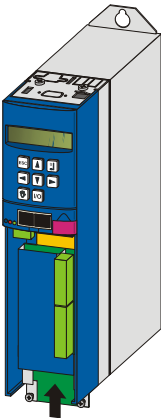2. Lift the upper end of the cover off the inverter:

3. Remove the cover upwards from the inverter:

4. Insert the accessory part at an oblique angle with the gold contacts forwards. The gold contacts must lie in front of the black terminal block.

5. Push the gold contacts in the black terminal block.

6. Fasten the accessory part on the inverter with the fastening screws:

⇨ You have now installed the accessory.

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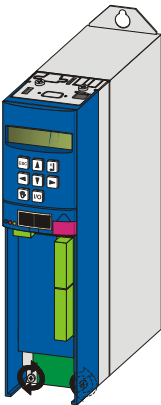
4.2.4 Installation of CANopen, PROFIBUS, EtherCAT or PROFINET accessories

> ⚠ **WARNING!**

Danger of personal injury and material damage due to electric shock!

▶ Always switch off all power supply voltage before working on the inverter! Note that the discharge time of the DC link capacitors is up to 6 minutes. You can only determine the absence of voltage after this time period.

> *NOTICE*

Material damage due for example to electrostatic discharge!

▶ Take suitable protective measures when handling open printed circuit boards, for example clothing appropriate for ESD and an environment free of dirt and grease.

▶ Do not touch the contact surfaces.

You will need the following accessories for the connection of CANopen or PROFIBUS. The accessory part is installed above the inverter's display.
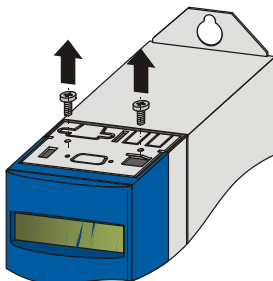
- CANopen: CAN 5000
- PROFIBUS: DP 5000

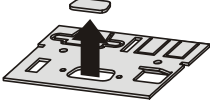You will need the following for installation of CAN 5000 or DP 5000.

- A TX10 Torx screwdriver.
- A pair of pliers.
- A hexagon socket wrench, 4.5 mm.
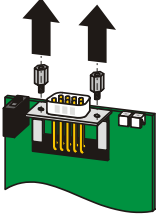
Installation of a CAN 5000 or DP 5000 in an inverter

1. Remove the mounting screws and take off the cover plate:
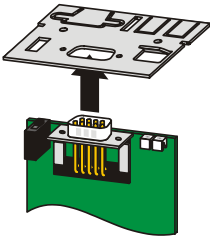
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2. Remove the metal plate punch-out with a pair of pliers:

3. Remove the screws from the option board:
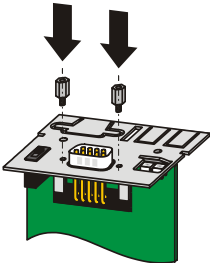
4. From below, thread the sub D plug connector of the PCB through the metal plate:
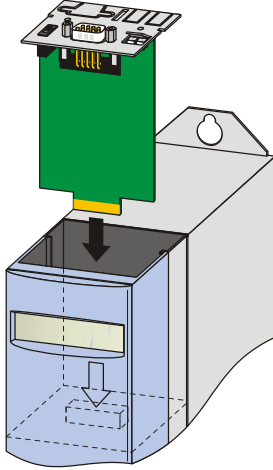
5. Secure the PCB to the metal plate with the screws which you removed in step 3:

6. Guide the option board into the inverter so that the gold contacts slide into the black connector:

7. Secure the metal plate to the inverter with the mounting screws:
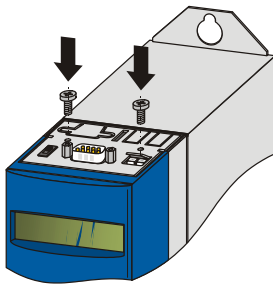
⇨ You have now installed the accessory.

To connect EtherCAT or PROFINET, you need the following accessory. The accessory is installed above the inverter display:

- EtherCAT: ECS 5000
- PROFINET: PN 5000

For installation you need:

- A Torx screwdriver TX10.
- A Phillips screwdriver.
- To install ECS 5000, the following metal plate that comes with the accessory:
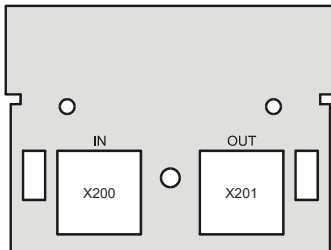
- To install PN 5000, the following metal plate that comes with the accessory:
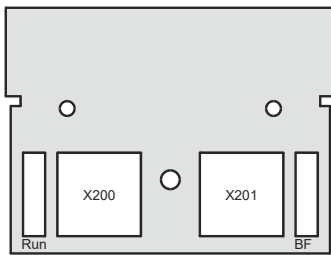
- The screw with the detent edge disk that is included with the accessory.

Installing ECS 5000 or PN 5000 in an inverter

1. Undo the fastening screws and take off the cover plate:

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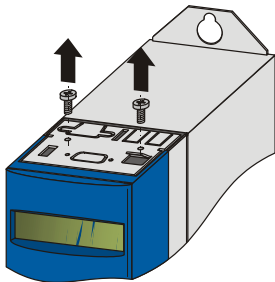
2. Guide the RJ45 connector of the circuit board from below through the plate that is included with the accessory:
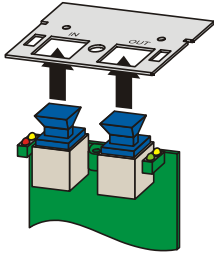
3. Fasten the plate on the circuit board with the screw with the detent edge disk that is included:
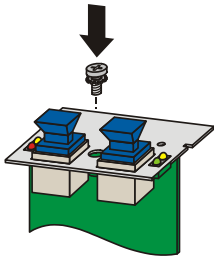
4. Guide the option board in the inverter so that the gold contacts are pushed in the black terminal block:
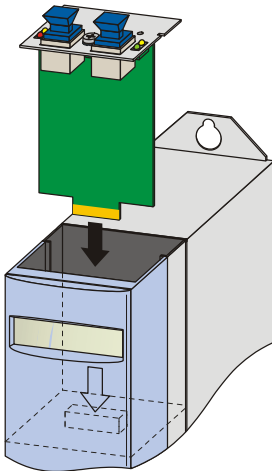
5. Fasten the plate to the inverter with the fastening screws:

⇨ You have now installed the accessory.

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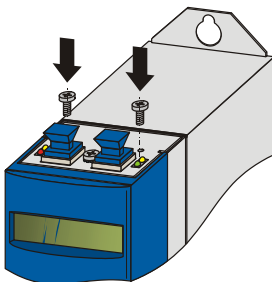
5 Connection

5.1 Overview of terminals

Front and top of device
(in the example with fieldbus accessory CAN 5000 and I/O terminal module SEA 5001)

Housing ground

X10 – 230V/400 V power

X12 ASP 5001

X11 – 24 V power

Fieldbus modules (accessories):
- CANopen CAN 5000 (X200)
- PROFIBUS DP 5000 (X200)
- EtherCAT ECS 5000 (X200, X201)
- PROFINET PN 5000 (X200, X201)

X3A, X3B PC, Integrated Bus

X1 enable, relay 1

I/O terminal modules (accessories):
- Standard SEA 5001 (X100, X101)
- Extended XEA 5001 (X100, X101, X102, X103)
- Resolver REA 5001 (X100, X101)

SEA 5001

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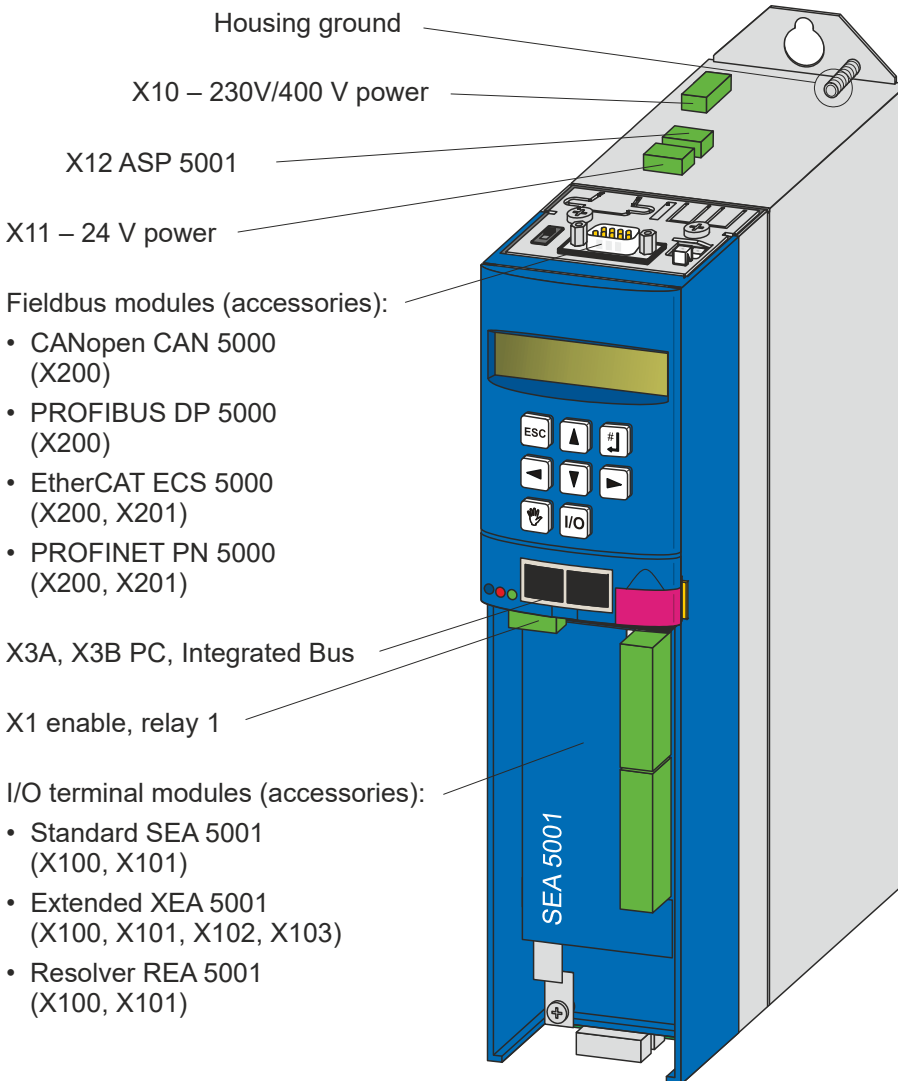
Bottom of the device
(in the example with brake module BRM 5001)

X4 Encoder

X5 Brake

X2 Motor temperature sensor

X22 DC link

X20 Motor

X21 Braking resistor

BRS 5001: X302

BRS 5001: X301

BRS 5001: X300
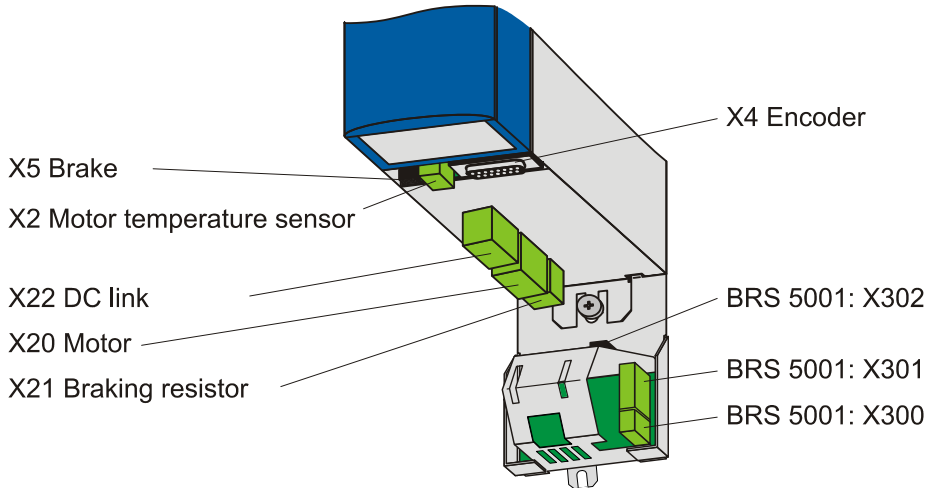
Size 3 – Front and top of device
(in the example with fieldbus module CAN 5000 and I/O terminal module SEA 5001)

X12 ASP 5001

X10 − 400 V power

X11 − 24 V power

X20 Motor,
DC link,
braking resistor

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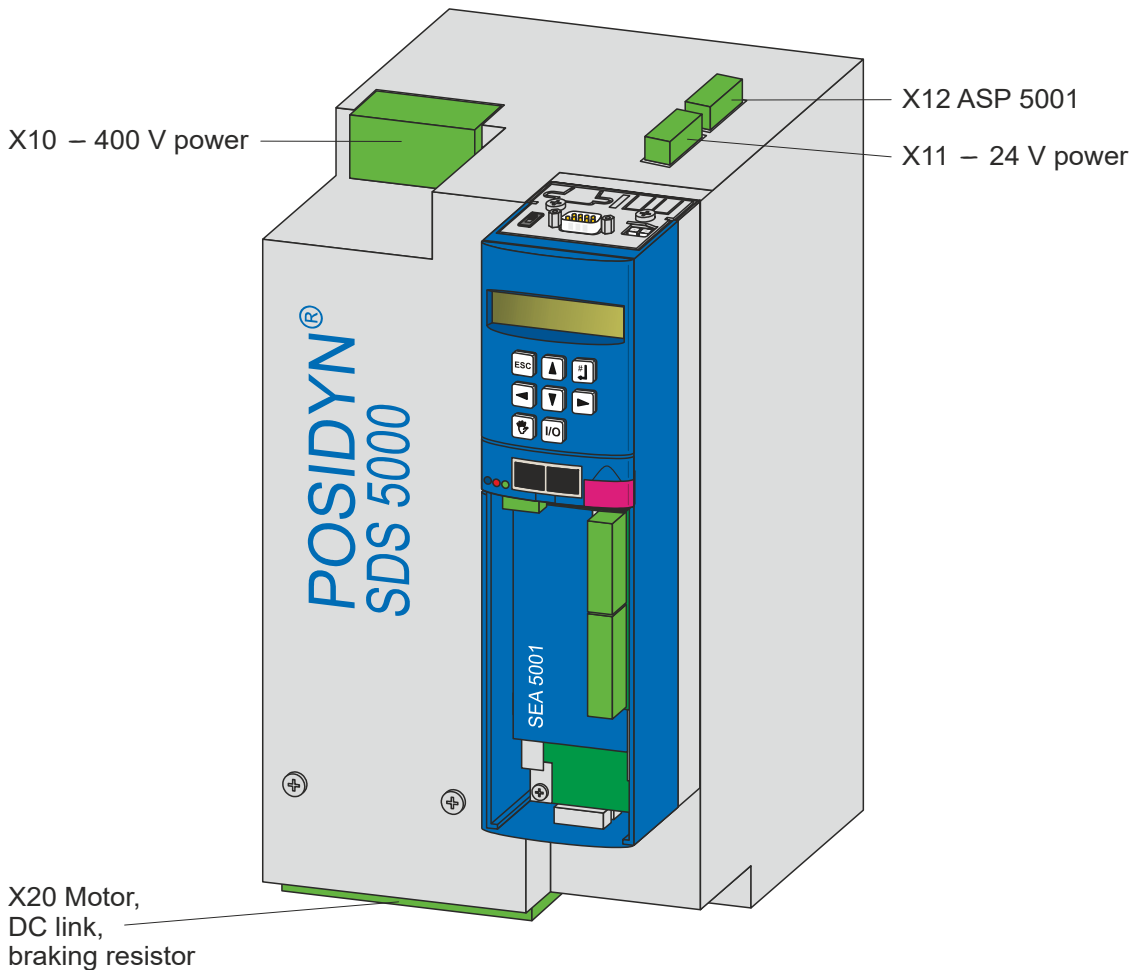
5.1.1   Fieldbus modules

Top of device with fieldbus module CANopen CAN 5000
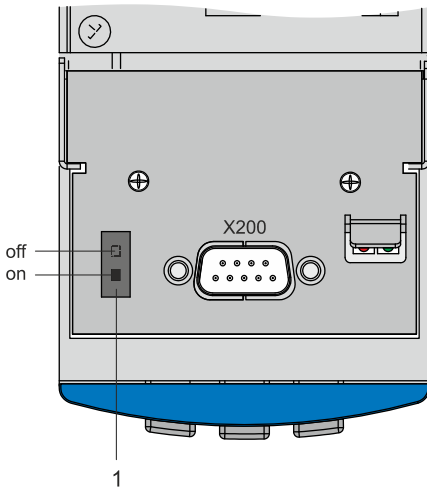
1   Internal terminating resistor 120 Ω switchable

Top of device with fieldbus module PROFIBUS DP 5000

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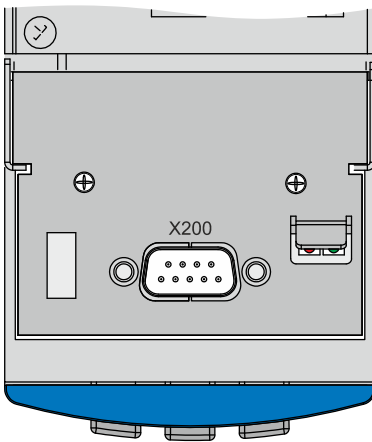
Top of device with fieldbus module EtherCAT ECS 5000

Top of device with fieldbus module PROFINET PN 5000

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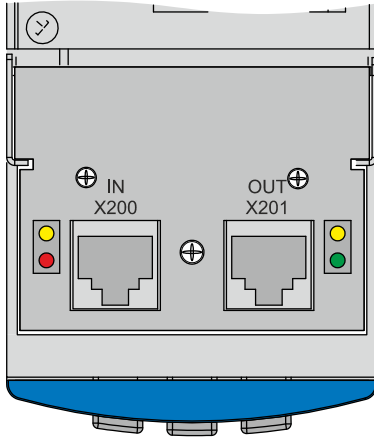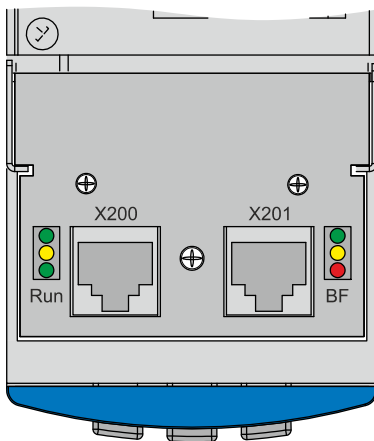
5.1.2 I/O terminal modules

Standard SEA 5001
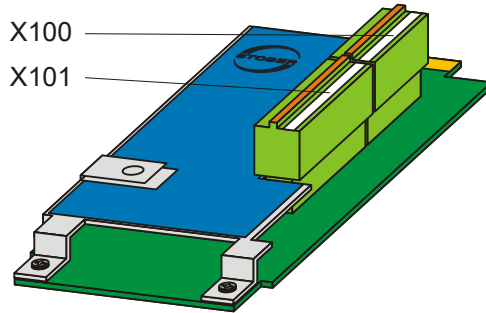
Extended XEA 5001

Resolver REA 5001

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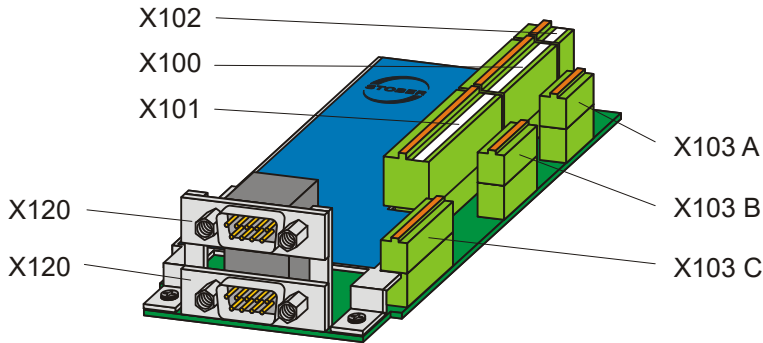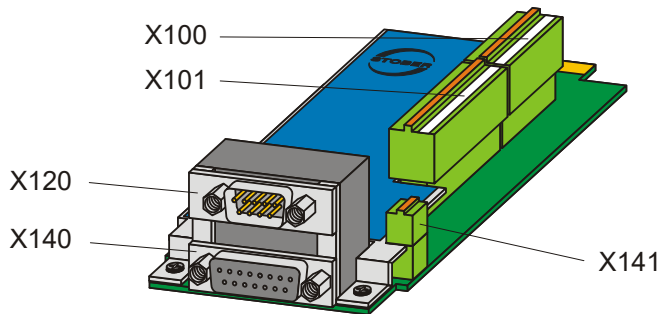
5.2 EMC connection
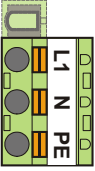
> **Information**
> In this section you can find general information on EMC-compliant installation. This involves recommendations. Depending on the application, ambient conditions as well as the legal requirements, measures beyond these recommendations may be required.
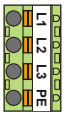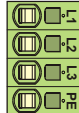
- Lay the power line, motor cable and signal lines separately from each other, e.g. in separate cable channels.
- Only use shielded cables as motor cables. Note also section 5.16 Cables.
- If the brake line is carried in the motor cable, the brake line must be separately shielded.
- Connect the shield of the motor cable with large contact areas and in the immediate vicinity of the inverter. For this purpose, use the EMC shroud EM 5000 or the brake module BRS 5001 for the sizes 0 to 2 or the EMC shroud EM6A3 for size 3.
- Shield the cable for connection to a braking resistor if it exceeds a length of 30 cm. In this case, connect the shield with large contact areas and in the immediate vicinity of the inverter.
- For motors with terminal boxes, connect the shield with large contact areas to the terminal box. For example, use EMC cable screw connections.
- Connect the shield of the control lines on one side with the reference ground of the source, e.g. the PLC or CNC.

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5.3 X10: 230 V/400 V power
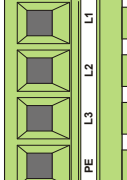
Terminal description – single-phase power connection Size 0

Pin		Designation	Function	Data
		—	Plastic dummy plug	—
		L1	Input voltage	230 V +20 %/-40 % 50/60 Hz
		N	Neutral conductor	—
		PE	Protective ground	—

Terminal description – three-phase power connection sizes 0, 1 and 2

Pin			Designation	Function	Data
Size 0	Size 1	Size 2	L1		3 x 400 V +32 %/-50 % 50 Hz or 3 x 480 V +10 %/-58 % 60 Hz
			L2	Input voltage	
			L3		
			PE	Protective ground	—

Terminal description – three-phase power connection – size 3

Pin		Designation	Function	Data
		L1		3 x 400 V +32 %/-50 % 50 Hz or3 x 480 V +10 %/-58 % 60 Hz
		L2	Input voltage	
		L3		
		PE	Protective ground	—

Minimum tightening torque M$_{min}$ – screw-type terminals

Size		Size 1		Size 2		Size 3	
Unit		[Nm]	[lb-in]	[Nm]	[lb-in]	[Nm]	[lb-in]
M$_{min}$		0.5	4.4	1.2	11	2.5	22

Maximum conductor cross-section of power terminals

Size	Size 0	Size 1	Size 2	Size 3
Maximum cross-section for conductor with ferrule [mm^2]	2.5	4	6	35

Other cable requirements

Technical Data	Size 0	Size 1	Size 2	Size 3
Insulation stripping length	10 mm	15 mm	18 mm	18 mm

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5.3.1 Line fuse

The device's cables and output are protected by means of line fuse. Various protective devices may be used for this purpose:
- Full range fuse (class "gG" in accordance with IEC class specification or "slow blow" in accordance with VDE)
- Miniature circuit breaker
  Use line circuit breaker with trigger characteristics C in accordance with EN 60898.
- Circuit breaker

Use fuses of class RK1 for UL-compliant applications (for example Bussmann KTS-R-xxA/600 V), CF, J, T or G. For devices of sizes 0 and 1 it is also possible to uses fuses of class CC.

Type	Input current $I_{1N,PU}$	Protection rating		
		Recommended	For UL-compliant use	For DC link connection in group 1
SDS 5007A	1 x 5.9 A	1 x 10 A	1 x 10 A	1 x 10 A
SDS 5008A	3 x 2 A	3 x 6 A	3 x 6 A	3 x 10 A
SDS 5015A	3 x 3.7 A	3 x 10 A	3 x 10 A	3 x 10 A
SDS 5040A	3 x 9.3 A	3 x 16 A	3 x 15 A	3 x 20 A
SDS 5075A	3 x 15.8 A	3 x 20 A	3 x 20 A	3 x 20 A
SDS 5110A	3 x 24.5 A	3 x 35 A	3 x 35 A	3 x 50 A
SDS 5150A	3 x 32.6 A	3 x 50 A	3 x 50 A	3 x 50 A
SDS 5220A[a]	3 x 37 A	3 x 50 A	3 x 50 A	3 x 80 A
SDS 5370A[a]	3 x 62 A	3 x 80 A	3 x 80 A	3 x 80 A
SDS 5450A[a]	3 x 76 A	3 x 80 A	3 x 80 A	3 x 80 A

a) operation with network commutation reactors and line fuses for operating class gG (full range fuses for cable and circuit protection to IEC 60269-2-1/DIN VDE 0636, part 201 NH fuses)

The inverters are only designed for use on supply current networks which can delivery at the most a maximum of symmetrical rated short circuit current at 480 Volts as per the following table:

Size	Max. symmetrical rated short circuit current
Size 0 and size 1	5000 A
Size 2	5000 A
Size 3	10000 A

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5.3.2 Residual current safety device

STOBER devices can be protected with a Residual Current protective Devices (RCD) to detect residual currents. Residual current protective devices prevent electrical accidents, especially ground fault through the body. They are generally distinguished according to their triggering limit and suitability for detecting different types of residual current.

Depending on the function, stray currents may occur when operating inverters. Stray currents are interpreted as residual currents by residual current protective devices and may therefore lead to false triggering. Depending on the relevant power supply connections, residual currents may occur with or without a DC current component. Because of this, you should take into consideration both the height and also the shape of the possible stray or residual current when selecting a suitable RCD.

⚠ **DANGER!**

Electric shock hazard!

The combination of single-phase inverters and residual current protective devices type A or AC can lead to false triggering of the RCDs.

Stray currents with a DC current component may occur in 3-phase inverters.

▶ Always protect single-phase inverters with *residual current protective devices type B, sensitive to all currents*, or with type F, sensitive to mixed currents.

▶ Always protect 3-phase inverters with *residual current protective devices type B, sensitive to all currents*.

False triggering – causes

Depending on stray capacitances and asymmetries, stray currents above 30 mA may occur during operation. Undesirable false triggering occurs under the following conditions:

• When inverters to the supply voltage.
  This false triggering can be rectified by using short-time delayed (super-resistant), selective (delayed switch-off) residual current protective devices or RCDs with increased trigger current (for example 300 or 500 mA).
• Due to higher frequency stray currents for long motor cables under normal operating conditions.
  This false triggering can be rectified for example using low-capacitance cables or output chokes.
• Due to unbalances in the supply network.
  This false triggering can be rectified e.g. using an isolating transformer.

ℹ **Information**

Check whether the use of residual current protective devices with increased trigger current as well as with short-time delayed or delayed switch-off trigger characteristics are permitted in your application.

Installation

⚠ **DANGER!**

Electric shock hazard!

Stray and residual currents with a DC current component can restrict the functionality of residual current protective devices types A and AC.

▶ Always follow the installation instructions for the protective devices you are using.

5.3.3 Housing ground

5.3.3.1 Size 0 to 2

Note the following information on the connection of the protective earth to ground the housing correctly:
- Note the assembly sequence on the M6 earth bolts (1):

  - 2 Contact disc
  - 3 Cable socket
  - 4 Washer
  - 5 Nut

  Contact disk, washer, and nuts are supplied with the inverter.
- Torque: 4 Nm
- Stray currents > 10 mA can arise in normal operation. To fulfill DIN EN 61800-5-1 and EN 60204-1, connect the earth bolts with a copper conductor according to the following table:
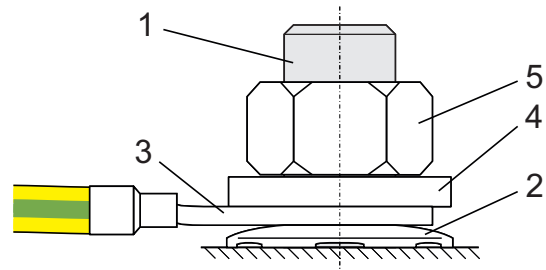
Cross-section A Feeder	Minimum cross-section A_P Earth conductor at earth bolts
$A \leq 2.5$ mm^2	2.5 mm^2
$2.5 < A \leq 16$ mm^2	A
$16 - 35$ mm^2	≥ 16 mm^2
> 35 mm^2	A/2

5.3.3.2 Size 3

Design the housing earth at interface X10 in at least mm^2 copper or 16 mm^2 aluminum.

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5.3.4 Forming

NOTICE

Material damage!

The DC link capacitors in devices of sizes 0, 1 and 2 can lose their electrical strength through long storage times. Considerable material damage can arise from a reduced electrical strength of the DC link capacitors when switching on.

▶ Use devices in storage annually or before startup.

Perform forming for stored devices.

Information

STOBER recommends connecting stored devices to the supply voltage according to the wiring shown for one hour every year. Please note that the inverters are designed exclusively for operation in TN networks.

The graphics below show the principle network connection for 3-phase and 1-phase devices.
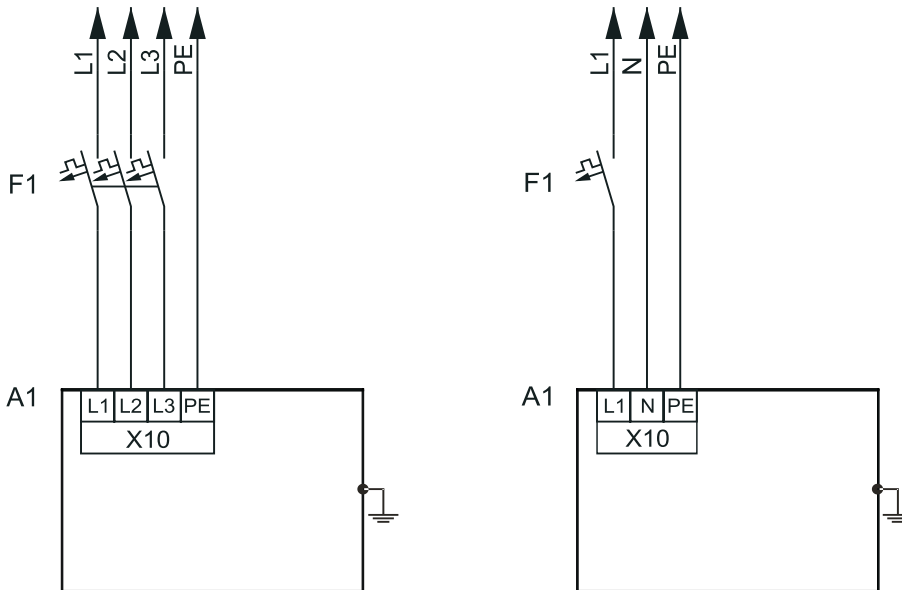
Legend

L1–L3 = lines 1 to 3
N = neutral conductor
PE = protective ground
F1 = fuse
A1 = inverter

If annual forming is not possible, form the stored devices before commissioning according to the wiring and voltage levels shown below.
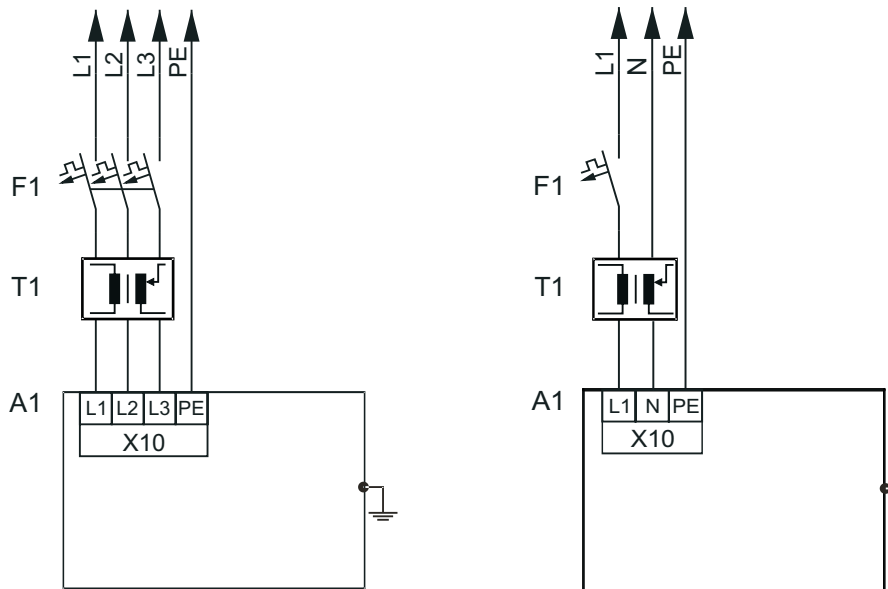
Legend

L1–L3 = lines 1 to 3

N = neutral conductor

PE = protective ground

F1 = fuse

T1 = variable transformer

A1 = inverter

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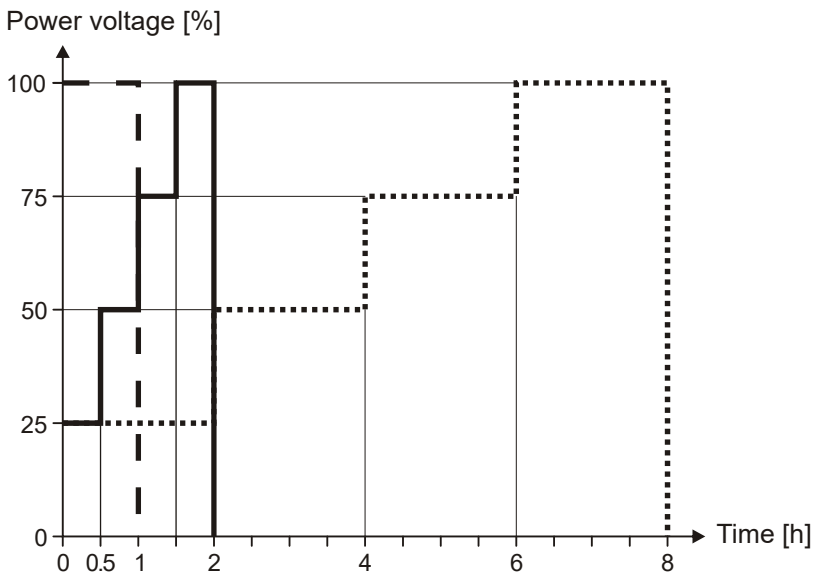
Power voltage [%]

– – Storage time 1 - 2 years:	Before enabling, apply voltage for one hour.
—— Storage time 2 - 3 years:	Before enabling, form as per curve.
····· Storage time ≥3 years:	Before enabling, form as per curve.
Storage time under 1 year:	No action required.

5.4   X11: 24 V power

Connection of 24 V to X11 is required for powering the control part.

NOTICE

Danger of damage to the device due to overload!

▶   If the 24 V power is looped through, a max. of four devices may be powered on one line.

> **Information**
>
> Remember that, with size 3 devices, the control unit is also powered via the DC link. If, with these inverters, only the 24 V power is switched off, the control electronics are initially still powered via the DC link and continue to run. This can cause problems if the control electronics evaluate the signals of devices which are powered externally and their power is switched off with the 24 V of the inverter (e.g., limit switch or encoder).

Terminal description size 0, size 1 and size 2

Pin		Designation	Function	Data
	+	+24 V	Auxiliary voltage (PELV) for supply of control electronics.	$U_{1CU} = 20.4 - 28.8$ V $I_{1maxCU} = 1.5$ A
	+	+24 V		
	–	GND	Reference potential for +24 V	—
	–	GND		

Terminal description size 3

Pin		Designation	Function	Data
	+	+24 V	Auxiliary voltage (PELV) for supply of control electronics.	$U_{1CU} = 20.4 - 28.8$ V $I_{1maxCU} = 1.5$ A
	–	GND	Reference potential for +24 V	—
	+	+24 V	Auxiliary voltage (PELV) for supply of control electronics.	$U_{1CU} = 20.4 - 28.8$ V $I_{1maxCU} = 1.5$ A
	–	GND	Reference potential for +24 V	—

Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	1.5
Flexible	1.5
Flexible with cable end, without plastic sleeve	1.5
Flexible with cable end, with plastic sleeve	0.5
2 leads with the same cross-section with double cable end	—

Example of connection
If the 24 V power is looped through, a max. of four devices may only be powered on one line. For conformity with UL, a 4 A fuse must be used on the 24 V incoming line. The fuse must be approved as per UL 248.

Size 0, size 1 and size 2

Size 3

WE KEEP THINGS MOVING
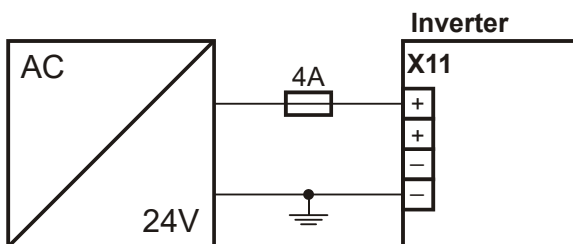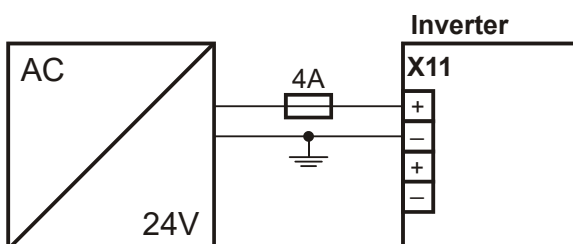
Example of the connection of two devices

WE KEEP THINGS MOVING
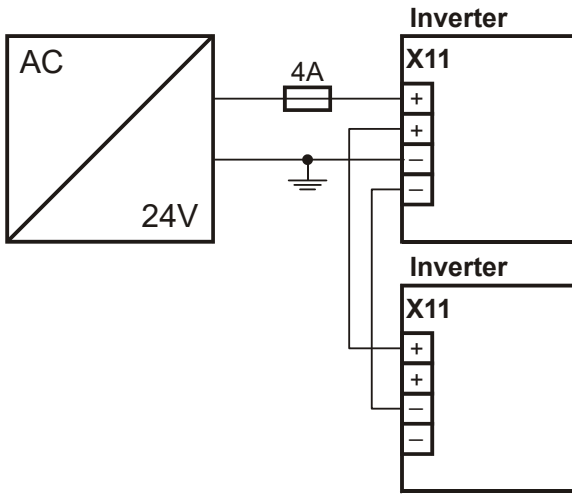
5.5 X1: Enable and relay 1

Use the enable signal to enable the power pack of the inverter. Starting with V 5.5-C, the function of relay 1 can be adjusted in parameter *F10*.

General specification	
Maximum cable length	30 m

Terminal description

Pin			Designation	Function	Data
	1		Contact 1	Relay 1	U_{max} = 30 V I_{max} = 1.0 A Life expectation (number of switching operations): • Mechanical min. 5 000 000 switching operations; • at 24 V/1A (ohm. load): 300 000 switching operations. Recommended fuse: max. 1 A (time lag)
	2		Contact 2		
	3		GND	Enable power board	High level ≥12 V Low level < 8 V I_{1max} = 16 mA U_{1max} = 30 V
	4		+ input		

Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	1.5
Flexible	1.5
Flexible with cable end, without plastic sleeve	1.5
Flexible with cable end, with plastic sleeve	0.5
2 leads with the same cross-section with double cable end	—
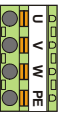
Example of connection

For a UL-compliant application, the use of a 1 A fuse before relay 1 is mandatory. The fuse must be approved as per UL 248.
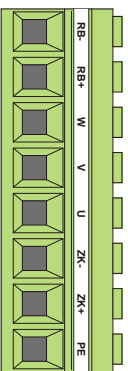
5.6 X20: Motor

Terminal description - size 0, size 1 and size 2

Pin			Designation	Function
Size 0	Size 1	Size 2	U	Motor connection, phase U
			V	Motor connection, phase V
			W	Motor connection, phase W
			PE	Protective ground

**Terminal description – size 3 (with braking resistor and DC link connection)**
Remember that with size 3 in addition to the motor the braking resistor and the DC link are also connected to terminal X20.

Pin	Designation	Function
	RB-	Braking resistor connection (see chapter X21: Braking Resistor)
	RB+	
	W	Motor connection, phase W
	V	Motor connection, phase V
	U	Motor connection, phase U
	ZK-	Reference potential for DC link
	ZK+	+ Potential of DC link
	PE	Protective ground

Minimum tightening torque M_{min} – screw-type terminals

Size	Size 1		Size 2		Size 3	
Unit	[Nm]	[lb-in]	[Nm]	[lb-in]	[Nm]	[lb-in]
M_{min}	0.5	4.4	1.2	11	2.5	22

Maximum conductor cross-section of power terminals

Size	Size 0	Size 1	Size 2	Size 3
Maximum cross-section for conductor with ferrule [mm^2]	2.5	4	6	35

Other cable requirements

Technical Data	Size 0	Size 1	Size 2	Size 3
Insulation stripping length	10 mm	15 mm	18 mm	18 mm

Maximum motor cable length

Size	0 to 2	3
Without output derater	50 m	100 m
With output choke	100 m	—

Connection without output choke

Observe the following points when connecting the motor without the output choke:

- Ground the shield of the motor cable on the shield contact on the inverter intended for this.
- Keep the exposed conductor as short as possible. All devices and circuits that are sensitive to EMC must be kept at a distance of at least 0.3 m.

Connection with output choke

Observe the following points when connecting the motor to the output choke:

- Ground the shield of the motor cable with large area contacts in the immediate vicinity of the output choke, for example with electrically conductive metal cable terminals on a grounded connection rail.
- Keep the exposed conductor as short as possible. All devices and circuits that are sensitive to EMC must be kept at a distance of at least 0.3 m.

The graphic below shows an example for the shielded connection of a motor with output choke (graphic: icotek GmbH).

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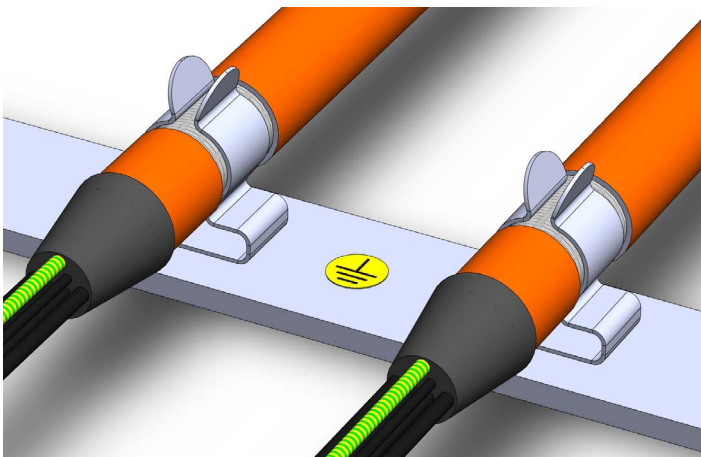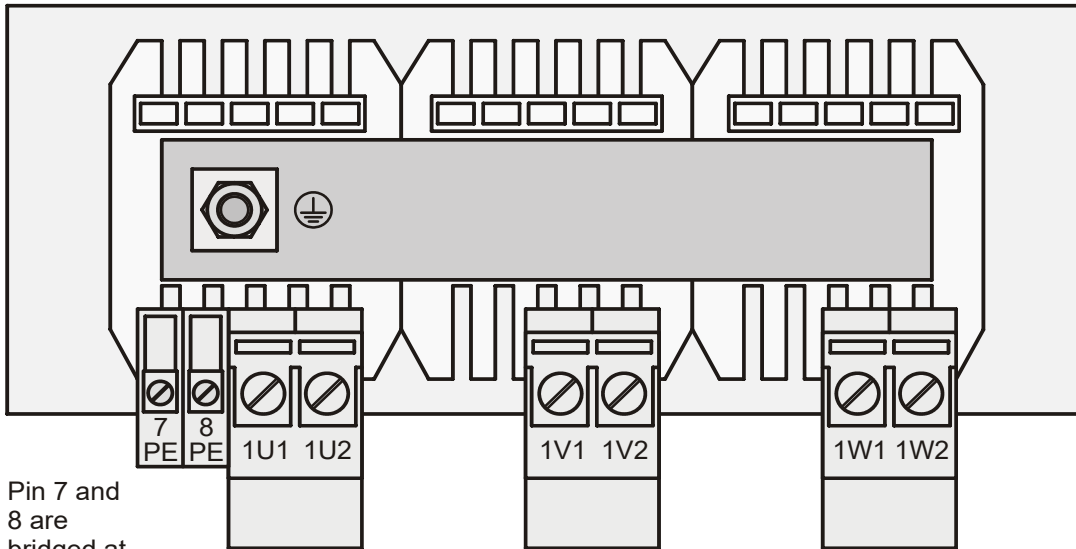
Pin 7 and 8 are bridged at the output derator

Example of connection

PES: HF shield connection via large-surface connection to PE

Inverter
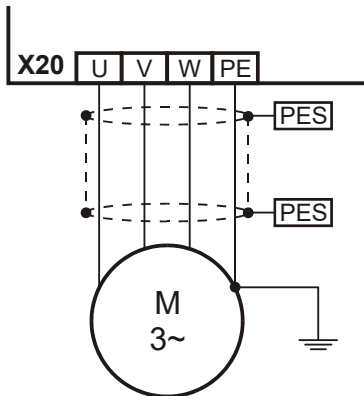
5.7 X12: ASP 5001 – Safe Torque Off

> **Information**
>
> If you want to use the safety function, you need option ASP 5001. It is imperative you read the operating instructions ASP 5001, see section 1.2 Further documentation, and integrate the safety technology in your safety circuit in accordance with the description given there. Note that for devices of size 3, the ASP 5001 option is fitted as standard.
> Connect the ASP 5001 option as per the following description if you are not using any safety technology.

> **Information**
>
> Please remember that the following description only applies to the ASP 5001. Go to applications@stoeber.de for the description of the ASP 5001.

Terminal description X12

Pin		Des.	Function	Data	Circuiting (If safety technology is not used!)
1		NC contact (break contact element)	Feedback contact; must be integrated in the safety circuit of the controller!	Note the specifications in the operating instructions ASP 5001, see section 1.2 Further documentation.	
2					
3		Relay coil+	Activation[a]	$U_1 = 20.4 – 28.8\ V_{DC}$ (PELV) $I_{1Typ} = 50\ mA$ $I_{1max} = 70\ mA$ Note the specifications in the operating instructions ASP 5001, see section 1.2 Further documentation.	
4		Relay coil-			

a) To conform with UL, a 4 A delayed fuse must be used in the 24 V feeder line. The fuse must be approved in accordance with UL 248.

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Maximum conductor cross-section

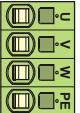| Connection type	Maximum conductor cross-section [mm^2]
Rigid	1.5
Flexible	1.5
Flexible with cable end, without plastic sleeve	1.5
Flexible with cable end, with plastic sleeve	0.5
2 leads with the same cross-section with double cable end	—

5.8   X2; X141: Motor temperature sensor

Connect the motor temperature sensor at terminal X2.

Motor temperature sensor connection
Motor windings are monitored thermally using the motor temperature sensors such as PTC thermistors, KTY temperature sensors or Pt temperature sensors.

PTC thermistors are thermistors whose resistance changes significantly with the temperature. When a PTC reaches its defined nominal response temperature, the resistance increases dramatically, by twice or more the original resistance to several kOhms. As PTC triplets are used, one thermistor monitors each phase of the motor winding. With 3 thermistors, all 3 phases are monitored which brings about effective motor protection.

On the other hand, KTY or Pt temperature sensors are temperature sensors with characteristic resistance curves that follow the temperature linearly. They therefore allow for analog measurements of motor temperatures. However, the measurements are limited to one phase of the motor winding, which also restricts motor protection considerably compared with PTC triplets.

> **Information**
> Note that the evaluation of a Pt1000 is only possible from firmware V 5.6-S. Before using a Pt or KTY sensor, note that motor protection is not ensured to the same extent as when monitoring with PTC triplet.

Motor temperature sensor lines in the resolver or EnDat cable (SDS 4000)
If you replace a SDS 4000 with a MDS or SDS 5000, the lines of the motor temperature sensor are carried in the previously used resolver or EnDat cable. To be able to continue using the cable, you will need the accessory part REA 5001 (see section 7 Accessories).

You can connect the EnDat cable directly to the REA 5001. You can connect the nine pole resolver cable using the resolver adapter included in the scope of delivery of the REA 5001 (see section 7 Accessories).

The signal of the motor temperature sensor is output on the REA 5001 to the interface X141. In this case connect X141 to X2.

> **Information**
> Note that evaluation of the temperature sensors is always active. If operation without temperature sensor is permitted, the connections must be bridged on X2. Otherwise a fault will be triggered when the device is switched on.

Terminal description X2

Pin		Function	Data
	1	1TP1/1K1+	Max. 2 PTC triplets (connected in series) or 1 KTY84-130 or 1 Pt1000
	2	1TP2/1K2-	

Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	2,5
Flexible	2,5
Flexible with cable end, without plastic sleeve	2,5
Flexible with cable end, with plastic sleeve	2,5
2 leads with the same cross-section with double cable end	1,5

Terminal description – X141

Pin		Function	Description
	1	1TP1/1K1+	Thermal motor protection signal, comes from X140 pin 7
	2	1TP2/1K2-	Thermal motor protection signal, comes from X140 pin 14

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Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	1,5
Flexible	1,5
Flexible with cable end, without plastic sleeve	1,5
Flexible with cable end, with plastic sleeve	0,75
2 leads with the same cross-section with double cable end	—

Example of connection of X2

Example of connection of X141 and X2
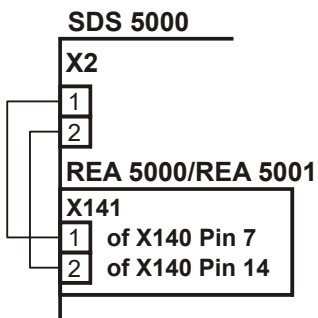
5.9 X5; X300 – X302: Motor holding brake

The inverter SDS 5000 can control one or two motor holding brakes. Usually brake 1 is the motor-internal brake and brake 2 the one in the motor adapter ServoStop. STÖBER Antriebstechnik GmbH + Co. KG offers the motor adapter ServoStop as an option for servo geared motors.

Requirement for the connection of motor holding brakes on the SDS 5000:
- Accessory part BRS 5001 (firmware V 5.6-N or later)
- Connection cable (X5, X302) included with the BRS 5001

> **Information**
> Remember that motor halting brakes of other manufacturers may not be connected to the BRS 5001 without first consulting STOBER.

> ⚠ **WARNING!**
>
> **Danger of personal injury and material damage due to electric shock!**
> ▶ Ensure sufficient strain relief for the power cable! Note that the option module does not provide the function of strain relief.

> **Information**
> Remember that you may only make the connection between X5 and X302 with the connection cable included with the BRS 5001.

> **Information**
> Remember that two LEDs are installed on the brake module. These LEDs indicate the status of the brake control:
> - LED on: brake output, energized (active)
> - LED off: brake output, not energized (inactive)

Terminal description X5 (inverter) and X302 (BRS 5001)

Pin		Designation	Function
6 5 4 / 3 2 1	1	1BD1	Controller Brake 1
	2	1BD2	Reference potential at pin 1, 2, 5 and 6
	3	Status1	Brake 1 feedback
	4	Status2	Brake 2 feedback
	5	2BD2	Reference potential at pin 1, 2, 5 and 6
	6	2BD1	Controller Brake 2

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Terminal description X300 (BRS 5001)

Pin		Designation	Function	Data
	+	24 V	Power input for brake controller	U_1 = 24 – 30 V I_{1max} = 7.5 A Fuse: up to max. 10 AT according to brakes used
	–	GND	Reference potential for 24 V	—

ℹ **Information**

Note that the 24-V power supply on X300 Pin + must always be at least 24 V. If the voltage falls below 24 V, a malfunction is triggered in the inverter.

Connect a controlled 24-V power supply to X300 Pin +.
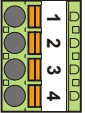
Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	2,5
Flexible	2,5
Flexible with cable end, without plastic sleeve	2,5
Flexible with cable end, with plastic sleeve	2,5
2 leads with the same cross-section with double cable end	1,5

Other cable requirements

Technical Data	
Insulation stripping length	10 mm

Terminal description X301 (BRS 5001)

Pin		Designation	Function	Data
	1	1BD1	Controller Brake 1	$I_2 \leq 3.6$ A: max. 15 operating cycles per min. $I_{2max} = 3.6$ A
	2	1BD2	Brake 1 reference potential	—
	3	2BD1	Controller Brake 2	$I_2 \leq 3.6$ A: max. 15 operating cycles per min. $I_{2max} = 3.6$ A
	4	2BD2	Brake 2 reference potential	—

Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	2,5
Flexible	2,5
Flexible with cable end, without plastic sleeve	2,5
Flexible with cable end, with plastic sleeve	2,5
2 leads with the same cross-section with double cable end	1,5

Other cable requirements

Technical Data	
Insulation stripping length	10 mm

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Brake connection with BRS 5001 for 24 V DC brakes
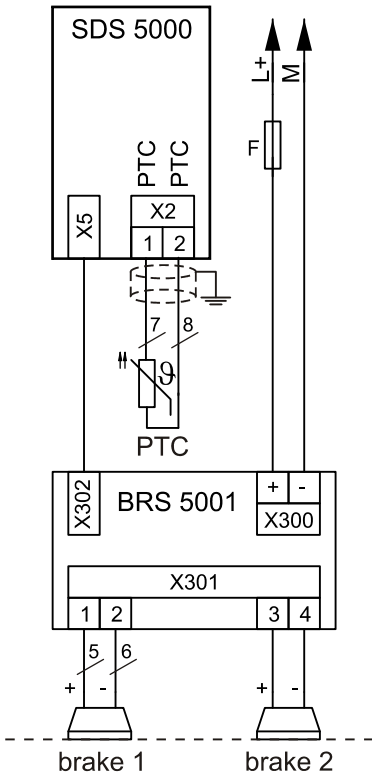
Indirect brake control
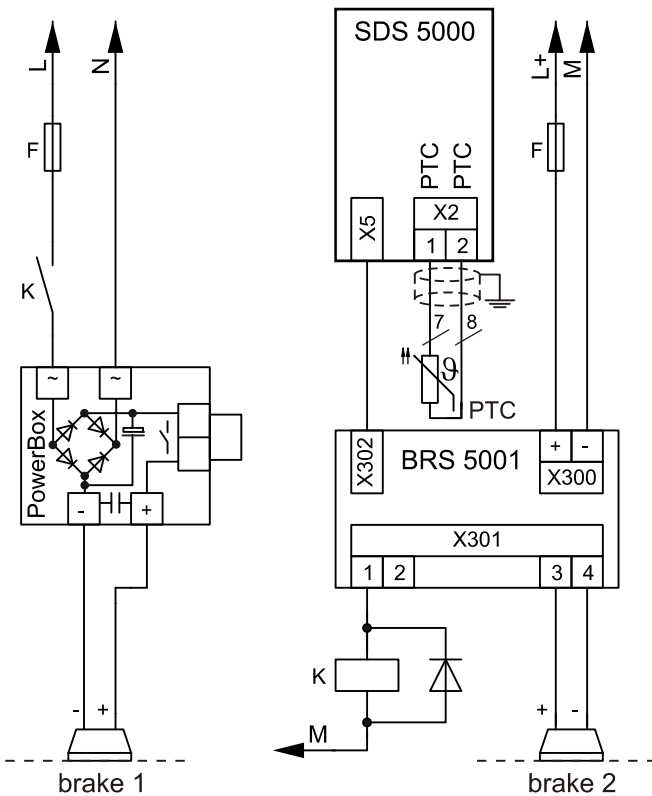
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5.10   X21: Braking resistor

An external braking resistor may be necessary during generating operation. For the technical data on the braking resistors, see chapter 3 Technical data. The braking resistor is connected to terminal X20 on size 3 versions (chapter 5.6 X20: Motor).

Terminal description – size 0 to size 2

Pin			Designation	Function
Size 0	Size 1	Size 2	RB	Connection of braking resistor
			RB	

Minimum tightening torque M$_{min}$ – screw-type terminals

Size	Size 1		Size 2	
Unit	[Nm]	[lb-in]	[Nm]	[lb-in]
M$_{min}$	0.5	4.4	1.2	11

Maximum conductor cross-section of power terminals

Size	Size 0	Size 1	Size 2	Size 3
Maximum cross-section for conductor with ferrule [mm^2]	2.5	4	6	35

Example of connection
Use a shielded cable for cables longer than 30 cm between braking resistor and device.

Inverter
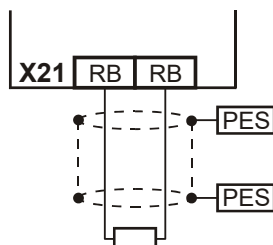
5.11 X22: DC link coupling

> **Information**
> Remember that the DC link coupling described here can only be used with the device families MDS 5000, SDS 5000 and FDS 5000.

When you have axes in your system which operate in combination and are continuously regenerative and motor-driven, the DC link coupling may offer advantages. The DC link coupling takes the excess power and offers it to other axes as drive power instead of converting it into heat via a braking resistor. Remember that you will need a braking resistor to absorb the power peaks when all drives in the DC link coupling brake at the same time.

> ⚠ **DANGER!**
>
> **Danger of device damage! When single-phase and three-phase devices are coupled, the single-phase devices will be destroyed.**
>
> ▶ Only use three-phase devices for the DC link coupling!

> *NOTICE*
>
> **Danger of device damage!**
>
> Because the failure of one device could damage other devices, failure of a device must cause the entire DC link compound system to be disconnected from the power supply.
>
> ▶ Make a note of the wiring and parameterization of relay 1 in Section Principal circuit diagram (X1.1 and X1.2).
>
> ▶ After a failure, replace all the devices in a group.

> **Information**
> Remember that the parameter *A38 DC power-input* must be set before the DC link coupling can function correctly:
> Group 1: *A38 = 0: inactive*
> Groups 2 and 3: *A38 = 1: active*
> See the description of the parameter.

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Terminal description X22 – size 0, size 1 and size 2

Pin			Designation	Function
Size 0	Size 1	Size 2	-U	Reference potential for DC link
			-U	
			+U	+ Potential of DC link
			+U	

Size 3: For connection to terminal X20, see 5.6 X20: Motor

Minimum tightening torque M_{min} – screw-type terminals

Size	Size 0		Size 1		Size 2	
Unit	[Nm]	[lb-in]	[Nm]	[lb-in]	[Nm]	[lb-in]
M_{min}	0.5	4.4	0.5	4.4	1.2	11

Maximum conductor cross-section of power terminals

Size	Size 0	Size 1	Size 2	Size 3
Maximum cross-section for conductor with ferrule [mm^2]	2.5	4	6	35

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Principal circuit diagram

The following figure shows the principle circuit diagram of the DC link connection. The inverters can be connected to each other in up to three groups. The possible combinations are shown in the table in the following section. The combination determines the types of line fuse and the DC link fuse.
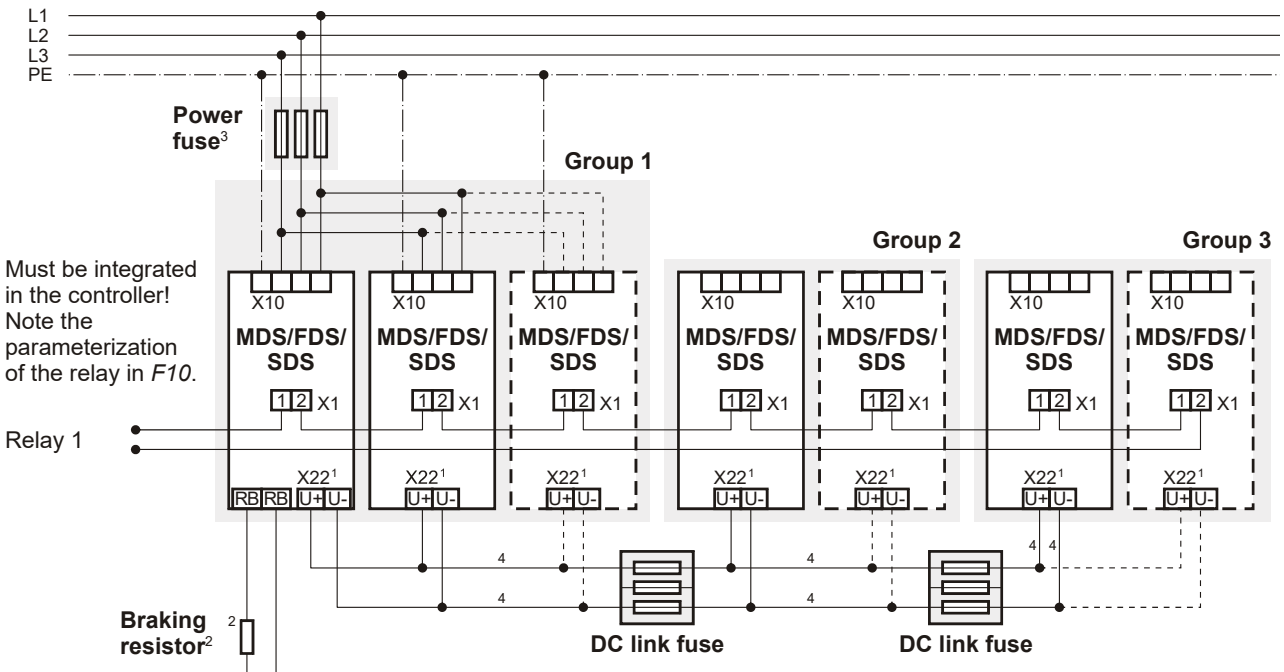
1   For MDS 5000 and SDS 5000, devices of size 3: X20, terminals ZK+, ZK-.
2   Dimension the braking resistor according to the braking output of the compound DC link system and the technical data of the device.
3   On this aspect, pay attention to section 5.3.
4   Dimension the conductor cross-sections of the DC link connection according to the requirements of your application. A reference point can be the maximum cross-section for the terminals X22 for size 0 to size 2 or X20 for size 3.

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Combinations

The following table shows the possible combinations for the DC link connection. There are a total of 15 combinations available.

Example: Combination no. 7:
With combination no. 7, you can combine an inverter of size 1 in group 1 with two devices of size 0 in group 2. Group 3 is not set up. The line fuse must have a rated current of 20 A. The groups are separated via the DC link fuse of type 1. Wait three minutes before switching on the devices of the DC link connection again.

	Group 1				DC link fuse	Group 2		DC link fuse	Group 3	t_{min} a)
Device family	MDS/FDS/SDS		MDS/SDS			MDS/FDS/SDS			MDS/FDS/SDS	
Size	Size 0	Size 1	Size 2	Size 3		Size 0	Size 1		Size 0	
Line fuse	10 A	20 A b)	50 A b)	80 A b)		—	—		—	
P_{2maxPU} c)	4 kW	10 kW	20 kW	45 kW		—	—		—	
Combination no.										
1	Max. 4	—	—	—	—	—	—	—	—	1
2	—	Max. 4	—	—	—	—	—	—	—	5
3	—	3	—	—	Type 1	2	—	—	—	5
4	—	3	—	—	Type 1	1	—	—	—	3
5	—	2	—	—	Type 1	2	—	—	—	3
6	—	2	—	—	Type 1	1	—	—	—	4
7	—	1	—	—	Type 1	2	—	—	—	3
8	—	—	Max. 3	—	—	—	—	—	—	2
9	—	—	3	—	Type 2	—	1	Type 1	2	2
10	—	—	3	—	Type 1	2	—	—	—	2
11	—	—	3	—	Type 2	—	1	—	—	2
12	—	—	2	—	Type 2	—	1	—	—	2
13	—	—	2	—	Type 2	—	1	Type 1	1	2
14	—	—	1	—	Type 2	1	—	—	—	2
15	—	—	—	Max. 3	—	—	—	—	—	1

a) Restart time

b) Note the list of line fuses for UL-compliant use in section 5.3.1 Line fuse

c) Maximum sum of drive power

Instead of delaying the process by the restart time, you can determine the restart time by evaluating the *E14* parameter. The parameter in all devices connected to the network must show that the load relay is open before the supply voltage may be switched on again. You can query the parameter via the fieldbus or binary output. If you are setting up a DC link connection only with devices from the SDS 5000 family or A-devices (HW version 200 or higher), you do not need to note the restart time.

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Fuses

⚠ **CAUTION!**

Danger of machine standstill! If a fuse element fails, the second fuse element will be damaged.

▶ Always replace the elements of a fuse in pairs.

Remember the following points during mounting and operation:
- Shield the DC link connections if the cables are longer than 20 cm. This prevents EMC problems.
- Use the two outer elements of the fuse holder to ensure adequate safe flashover distance.
- Use the following fuses to protect the DC link:

	Type 1	Type 2
Manufacturer	SIBA Sicherungs-Bau GmbH Borker Straße 22 D-44534 Lünen www.siba.de	
Size	10 x 38	
Operating class	gRL	
Rated voltage	AC 600 V	
Rated current	10 A	20 A
Power loss per element	1.6 W	3.5 W
Art. no. of fuse	6003434.10	6003434.20
Art. no. of fuse holder	5106304.3	

5.12   X100 – X103: Analog and binary signals

Below are the prerequisites for connecting analog and binary signals:
- SEA 5001
- REA 5001
- XEA 5001

⚠ **WARNING!**

Danger of faulty machine behavior due to EMC faults!

▶ Use exclusively cables up to 30 m in length for analog and binary inputs and outputs (AE, AA, BE, BA)!

ℹ **Information**
Note that the sampling time of the inputs and the refresh rate of the outputs correspond to the cycle time set in parameter *A150*.
For time critical functions such as a print mark control, a time stamp is also available for the binary inputs.
If BE encoders or BA encoder simulation is used, the sampling time and refresh rate is independent of the set cycle time (see section 5.13.4 BE encoder and BA encoder simulation).

Terminal description X100 – SEA 5001, REA 5001, XEA 5001

NOTICE

Machine movement by unexpected reference value

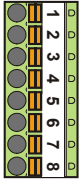The inverter detects a reference value setting of +5V for an unconnected analog input.

▶ Always operate the inverter with a connected analog input.

General specification	
Maximum cable length	30 m, shielded

Terminal description

Pin	Designation	Function	Data

1	AE1+	+ input of analog input AE1 resolution:
		• SEA 5001:
		  10 bit + sign
		  Offset < 100 mV
		  Tolerance < 50 mV
		• REA 5001 and XEA 5001:
		  15 bit + sign
		  Offset < 50 mV
		  Tolerance < 25 mV
			Reference: pin 3
			$U_1 = \pm 10$ V
			$R_{int} = 40$ kΩ
			U_{1max} against pin 3 = 30 V
			U_{1max} against protective ground 15 V
			U_{1max} against AGND = 30 V

2	AE1 shunt	Current input; shunt connection pin 2 is to be bridged with pin 1.	Reference: pin 3 $I_1 = \pm 20$ mA $R_{int} = 510$ Ω
3	AE1-	Inverted input of analog input AE1	U_{1max} against pin 1 = 30 V U_{1max} against protective ground = 15 V U_{1max} against AGND = 30 V

4	AE2+	+ input of the analog input AE2;
		Resolution:
		• SEA 5001, XEA 5001:
		  10 bit + sign
		  Offset < 100 mV
		  Tolerance < 50 mV
		• REA 5001:
		  15 bit + sign
		  Offset < 50 mV
		  Tolerance < 25 mV
			Reference: pin 5
			$U_1 = \pm 10$ V
			$R_{int} = 40$ kΩ
			U_{1max} against pin 5 = 30 V
			U_{1max} against protective ground = 15 V
			U_{1max} against AGND = 30 V

5	AE2-	Inverted input of analog input AE2	U_{1max} against protective ground = 15 V U_{1max} against AGND = 30 V
6	AA1	Analog output 1 Resolution: 11 bit + sign Offset < 100 mV Tolerance < 50 mV	Reference: pin 8 $I_{2max} = 10$ mA $R_{int} = 20$ Ω
7	AA2	Analog output 2 Resolution: 11 bit + sign Offset < 100 mV Tolerance < 50 mV	
8	AGND	Reference ground for analog signals	—
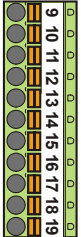
Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	1.5
Flexible	1.5
Flexible with cable end, without plastic sleeve	1.5
Flexible with cable end, with plastic sleeve	0.5
2 leads with the same cross-section with double cable end	—

Terminal description X101 – SEA 5001, REA 5001, XEA 5001

General specification	
Maximum cable length	30 m, shielded

Terminal description

Pin		Designation	Function	Data
	9	GND 18 V	Reference ground for pin 19	—
	10	DGND	Reference ground for pins 11 to 18	—
	11	BE1	Binary input	High level: 12 – 30 V Low level: 0 – 8 V $U_{1max} = 30$ V $I_{1max} = 16$ mA at U_{1max}
	12	BE2		
	13	BE3[a]		
	14	BE4[a]		
	15	BE5[a]		
	16	BA1	Binary output	$I_{2max} = 50$ mA at 45 °C, 40 mA at 55 °C
	17	BA2		
	18	24 V-In	24 vdc power supply • for XEA 5001 and • for binary outputs for SEA 5001 and REA 5001	Input range: 18 – 28.8 V
	19	18 V-Out	Auxiliary voltage 18 V	$U_2 = 16 – 18$ V $I_{2max} = 50$ mA

a) BE3, BE4 and BE5 can be used as an encoder input. Also note section 5.13.4 BE encoder and BA encoder simulation. On the REA 5001, these inputs can be switched by the sliding switch S0, S1 and S2 on the TTL level.

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Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	1.5
Flexible	1.5
Flexible with cable end, without plastic sleeve	1.5
Flexible with cable end, with plastic sleeve	0.5
2 leads with the same cross-section with double cable end	—

TTL/HTL switchover REA 5001

Switch	TTL/HTL conversion
S0	BE3
S1	BE4
S2	BE5

The identification of the switches and the assignment of the switch positions to the function (HTL/TTL) are shown on the PCB cover of the REA 5001.
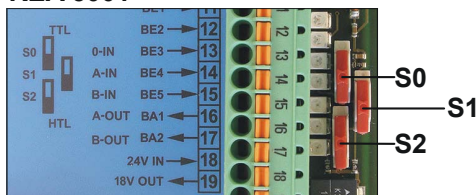
REA 5001

Terminal description X102 – XEA 5001

> **NOTICE**
>
> **Machine movement by unexpected reference value**
>
> The inverter detects a reference value setting of +5 V for an unconnected analog input.
>
> ▶ Always operate the inverter with a connected analog input.

General specification	
Maximum cable length	30 m, shielded

Terminal description

Pin		Designation	Function	Data
	1	AE3+	+ input of analog input AE3 Differential input voltage resolution: 10 bit + sign Offset < 100 mV Tolerance < 50 mV	Reference: pin 2 $U_1 = \pm 10$ V $R_{int} = 40$ kΩ U_{1max} against pin 2 = 30 V U_{1max} against protective ground 15 V U_{1max} against AGND = 30 V
	2	AE3-	Inverted input of analog input AE3	U_{1max} against pin 2 = 30 V U_{1max} against protective ground = 15 V U_{1max} against AGND = 30 V
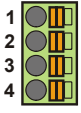
Maximum conductor cross-section

| Connection type	Maximum conductor cross-section [mm^2]
Rigid	1.5
Flexible	1.5
Flexible with cable end, without plastic sleeve	1.5
Flexible with cable end, with plastic sleeve	0.5
2 leads with the same cross-section with double cable end	—

Terminal description X103 A – XEA 5001

General specification	
Maximum cable length	30 m, shielded

Terminal description

Pin		Designation	Function	Data
	1	BA3		
	2	BA4	Binary output	I_{2max} = 50 mA
	3	BA5		
	4	BA6		

Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	1,5
Flexible	1,5
Flexible with cable end, without plastic sleeve	1,5
Flexible with cable end, with plastic sleeve	0,75
2 leads with the same cross-section with double cable end	—

Information

When the 24 V power fails, binary inputs BE6 to BE13 have signal status 0 (regardless of the physical signal state).

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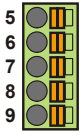
Terminal description X103 B – XEA 5001

General specification	
Maximum cable length	30 m, shielded

Terminal description

Pin		Designation	Function	Data
	5	BA7	Binary output	I_{2max} = 50 mA
	6	BA8		
	7	BA9		
	8	BA10		
	9	BE6	Binary input	Reference: Pin 10 of terminal X101 High level: 12 – 30 V Low level: 0 – 8 V U_{1max} = 30 V I_{1max} = 3 mA at U_{1max}

Maximum conductor cross-section
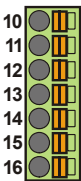
Connection type	Maximum conductor cross-section [mm^2]
Rigid	1,5
Flexible	1,5
Flexible with cable end, without plastic sleeve	1,5
Flexible with cable end, with plastic sleeve	0,75
2 leads with the same cross-section with double cable end	—

Terminal description X103 C – XEA 5001

General specification	
Maximum cable length	30 m, shielded

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Terminal description

Pin		Designation	Function	Data
	10	BE7		Reference: Pin 10 of terminal X101
	11	BE8		High level: 12 – 30 V
	12	BE9		Low level: 0 – 8 V
	13	BE10	Binary input	U_{1max} = 30 V
	14	BE11		I_{1max} = 3 mA at U_{1max}
	15	BE12		
	16	BE13		

Maximum conductor cross-section

Connection type	Maximum conductor cross-section [mm^2]
Rigid	1,5
Flexible	1,5
Flexible with cable end, without plastic sleeve	1,5
Flexible with cable end, with plastic sleeve	0,75
2 leads with the same cross-section with double cable end	—

Examples of connection

Potentiometer

Inverter

Current (0 - 20 mA, 4 - 20 mA)

Inverter

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Voltage (max. ± 10 V)

Inverter

X100		SEA 5001
1	AE1+	REA 5001
2	AE1-Shunt	XEA 5001
3	AE1-	
6	AA1	
7	AA2	
8	AGND	
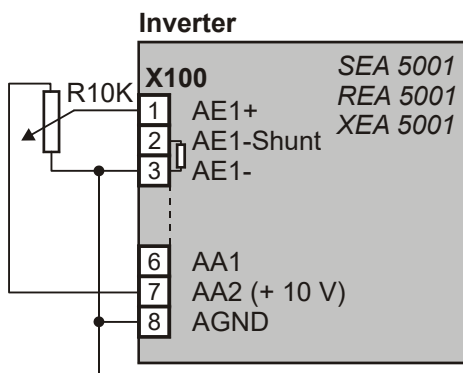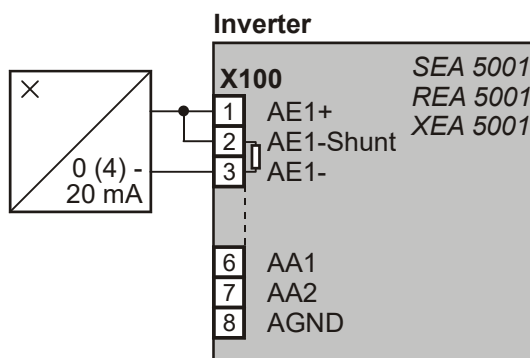
0 - 5 V
0 - 10 V
max. ± 10 V

Analog output voltage

Inverter

X100		SEA 5001
1	AE1+	REA 5001
2	AE1-Shunt	XEA 5001
3	AE1-	
6	AA1	
7	AA2	
8	AGND	

V

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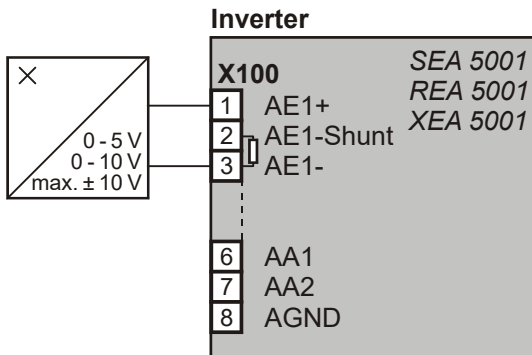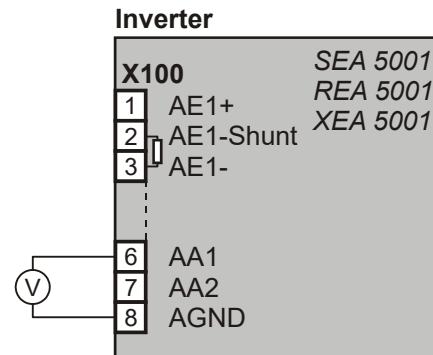
5.13 Encoder

> **ℹ Information**
>
> Remember that the encoder interfaces can usually evaluate or simulate several systems (e.g., EnDat and incremental encoder). In the parameters enter the particular system that you are connecting to an interface. Please consult the inverter operating manual in this case.

5.13.1 X4

> **NOTICE**
>
> **Danger of encoder destruction!**
>
> ▶ X4 may not be connected or disconnected when the device is on!

General specification	
U_2	5–16 V, see the encoder supply table below
I_{2max}	X4: 250 mA Sum X4, X120 and X140: 500 mA
I_{2min}	13 mA
Maximum cable length	100 m

Specification encoder EnDat 2.1 digital	
Encoder type	Single and multiturn, not suitable for linear measuring devices
switching frequency	2 MHz
Evaluation	Digital signals only; starting with HW 200 and firmware V 5.6-H, analog signals are tolerated on pins 1, 3, 9 and 11 (compatible with X140).

Specification encoder EnDat 2.2 digital	
Encoder type	Single and multiturn, not suitable for linear measuring devices
switching frequency	4 MHz
Evaluation	Digital signals only; starting with HW 200 and firmware V 5.6-H, analog signals are tolerated on pins 1, 3, 9 and 11 (compatible with X140).

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SSI encoder specification	
switching frequency	250 kHz
Sampling rate	250 µs Not permitted as motor encoder in servo mode
Code	Binary or Gray
Encoder type and format	Multiturn: 24 or 25 bits Single-turn13 bits short or 13 bits tree (13 bits of data in a 25-bit telegram)
Transfer	Double transmission, can be switched off

Incremental encoder specification	
Encoder type	Only TTL and HTL encoders with N channel may be connected to X4. Encoders without N channel generate a fault when at device start-up. If the use of an encoder without N channel is required, the encoder must be connected to X120. Observe the terminal description X120 for incremental signals for proper connection, see section 5.13.2 X120.
f_{max}	Evaluation: ≤ 1 MHz Simulation: < 250 kHz
Signal level	TTL and HTL

Calculation example – limit frequency f_{max}

... for an encoder with 2,048 pulses per revolution::

3,000 revolutions per minute (equivalent to 50 revolutions per second) * 2,048 pulses per revolution

= 102,400 pulses per second

= 102.4 kHz

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Encoder supply

U$_2$	Through	Remarks
5 V (unregulated)		Pin 12 (sense) not used
5 V (controlled at cable end)	Encoder sense line connected to pin 12 (sense)	STOBER synchronous servo motors EnDat 2.1/2.2 (standard)
5 V (controlled at X4)	Pin 12 (sense) bridged with pin 4 (UB+)	STOBER asynchronous motors TTL (for customer-specific solutions), without cable compensation
15 – 16 V	Pin 12 (sense) bridged with pin 2 (GND)	STOBER asynchronous motors HTL encoder: Bridge created in the cable plug that is connected to X4. SSI encoder: Bridge for UB+ is created in the bracket flange socket.
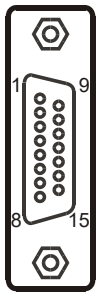
Terminal description X4 for encoder EnDat 2.1/2.2 digital and SSI encoder

Pin		Designation	Function
Socket	1	—	—
	2	GND	Reference for encoder supply to pin 4
	3	—	—
	4	U$_2$	Encoder supply
	5	DATA+	Differential input for DATA
	6	—	—
	7	—	—
	8	CLK+	Differential input for C:PCL
	9	—	—
	10	Sense-	Reference for sense signal to pin 12
	11	—	—
	12	Sense+	Sensor line for the supply voltage to adjust the encoder supply
	13	DATA-	Inverse differential input for DATA
	14	—	—
	15	CLK-	Inverse differential input for CLOCK

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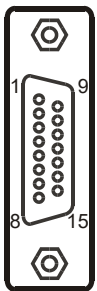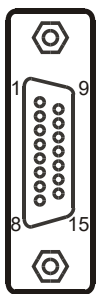
Terminal description X4 for HTL encoder

Pin		Designation	Function, data
Socket	1	B+	Differential input for B-track
	2	GND	Reference for encoder power on pin 4
	3	N+	Differential input for N-track
	4	U_2	Encoder power
	5	—	—
	6	A+	Differential input for A-track
	7	—	—
	8	—	—
	9	B-	Inverse, differential input for B-track
	10	N-	Inverse, differential input for N-track
	11	A-	Inverse, differential input for A-track
	12	Sense	Sensor lead for power supply to settle the encoder power
	13	—	—
	14	—	—
	15	—	—

Terminal description X4 for TTL encoders

Pin		Designation	Function, data
Socket	1	—	—
	2	GND	Reference for encoder supply to pin 4
	3	—	—
	4	U_2	Encoder supply
	5	B+	Differential input for B channel
	6	—	—
	7	N+	Differential input for N channel
	8	A+	Differential input for A channel
	9	—	—
	10	Sense-	Reference for sense signal to pin 12
	11	—	—
	12	Sense+	Sensor line for the supply voltage to adjust the encoder supply
	13	B-	Inverse, differential input for channel
	14	N-	Inverse, differential input for N channel
	15	A-	Inverse, differential input for A channel

5.13.2   X120

Prerequisite for using interface X120:

- REA 5001 or
- XEA 5001

> **Information**
> Interface X120 is a double interface on option board XEA 5001. The double interface makes it possible to distribute encoder signals to other inverters without a great amount of wiring work. This is why the two sub D connections have the same allocation.

General specification	
U_2	18 V, see encoder supply
I_{2max}	250 mA, sum X4, X120 and X140: 500 mA
Maximum cable length	50 m
Maximum number of subscribers	1 master and 31 subscribers
Terminating resistor	120 Ω

Specification SSI encoder (evaluation and simulation)	
switching frequency	592 kHz (motor encoder) or 250 kHz (position encoder)
Code	Binary or Gray
Encoder type	Multiturn: 24 or 25 bits Single-turn: 13 bit short or 13 Bit Tannenbaum
Transfer	Double transmission, can be switched off

Specification of incremental encoder and pulse train (evaluation and simulation)	
f_{max}	Evaluation: ≤ 1 MHz Simulation: < 250 kHz
Signal level	TTL

> **Calculation example – limit frequency f_{max}**
> **... for an encoder with** 2,048 pulses per revolution::
> 3,000 revolutions per minute (equivalent to 50 revolutions per second) * 2,048 pulses per revolution
> = 102,400 pulses per second
> = 102.4 kHz

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Encoder supply

Encoder supply	Bridge
Pin 8 (U$_2$)	Pin 1 (GND-Enc) to pin 9 (GND)
External	Pin 1 (GND-Enc) to GND of external supply

Terminal description X120 for SSI encoder

Pin		Designation	Function
Connector	1	GND-ENC	Reference potential for pin 4 to pin 7
	2	—	—
	3	—	—
	4	CLK-	Inverse differential input/output for CLOCK
	5	CLK+	Differential input/output for CLOCK
	6	DATA+	Differential input/output for DATA
	7	DATA-	Inverse differential input/output for DATA
	8	U$_2$	Encoder supply
	9	GND	Reference for pin 8

Information

Remember that all SSI slaves must be switched on/off simultaneously (24 V on X11 and X101.18). Switching individual stations during operation will cause other stations to malfunction.

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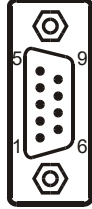**Terminal description of X120 for incremental encoder**

Pin		Designation	Function
Connector	1	GND-ENC	Reference potential for pin 2 to pin 7
	2	N+	Differential input/output for the N channel
	3	N-	Inverse differential input/output for the N channel
	4	A-	Inverse differential input/output for the A channel
	5	A+	Differential input/output for the A channel
	6	B+	Differential input/output for the B channel
	7	B-	Inverse differential input/output for the B channel
	8	U_2	Encoder supply
	9	GND	Reference for pin 8

Terminal description X120 for pulse train

Pin		Designation	Function
Connector	1	GND-ENC	Reference potential for pin 2 to pin 7
	2	—	—
	3	—	—
	4	Imp-	Inverse differential input/output for pulses
	5	Imp+	Differential input/output for pulses
	6	Direction+	Differential input/output for the direction
	7	Direction-	Inverse differential input/output for the direction
	8	U_2	Encoder supply
	9	GND	Reference for pin 8

Connection – topology

Only linear topology is permitted when two or more stations are coupled via interface X120. The signal lines must be terminated with resistors for the stations at either end of the coupling. The terminating resistors can be switched through via switches S3, S4 and S5 on accessory parts XEA 5001 and REA 5001.

Switch	TTL Encoder	SSI Encoder
S3	Zero	—
S4	A	CLK
S5	B	DATA
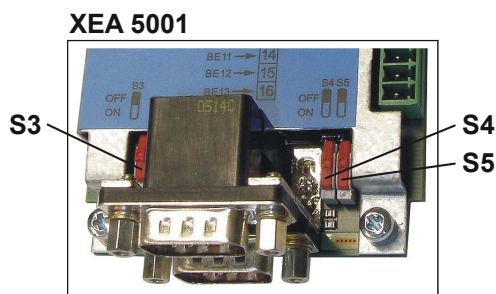
XEA 5001

REA 5001

Please note that the switches are installed in different positions on the REA 5001 and XEA 5001 accessories. Identification of the switches and assignment of the switch positions to the function (switched on/switched off terminal resistance) are shown on the PCB cover.

5.13.3   X140

Prerequisite for using interface X140:

- REA 5001

Resolver specification (evaluation)	
U_2	-10 V ... +10 V
I_2	80 mA
f_2	7 – 9 kHz
P_{max}	0.8 W
Transfer ratio	0.5 ± 5 %
Number of poles	2, 4 and 6
Phase shift	± 20 el.°
Maximum cable length	100 m

Specification of encoder EnDat 2.1 sin/cos (evaluation)	
U_2	5 – 16 V, see below table encoder supply EnDat
I_{2max}	250 mA, sum X4, X120 and X140 (EnDat): 500 mA
I_{2min}	30 mA
f_{max}	225 kHz
Encoder type	Single and multiturn, not suitable for linear measuring devices
Maximum cable length	100 m

Calculation example – limit frequency f_{max}

... for an encoder with 2,048 pulses per revolution::

3,000 revolutions per minute (equivalent to 50 revolutions per second) * 2,048 pulses per revolution

= 102,400 pulses per second

= 102.4 kHz

Encoder supply EnDat 2.1

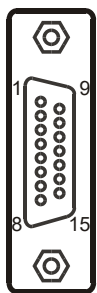| U_2	Through	Remarks
5 V (unregulated)		Pin 12 (sense) not used
5 V (controlled at cable end)	Encoder sense line connected to pin 12 (sense)	STOBER servo motors EnDat 2.1
5 V (controlled at X4)	Pin 12 (sense) bridged with pin 4 (UB+)	TTL (for customer-specific solutions)

> **Information**
> Note that the resolver interface at X140 is also used if a SDS 4000 is replaced where a motor with resolver at X40 was operated.
> In this case, you can continue to use the previously used encoder cable. The connection of the motor temperature sensor is carried in this cable. For this reason, observe the Chapter 5.8.
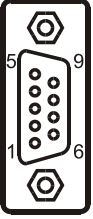
Terminal description X140 for resolver (REA 5001)

Pin[a)		Designation	Function
Socket	1	Sin+	Sin input
	2	GND	Reference to pin 6
	3	Cos+	Cos input
	4	—	—
	5	—	—
	6	ExcitationResolv	Resolver excitation signal
	7	1TP1/K1	Motor temperature sensor connection, if carried by the encoder cable; output at pin 1 of X141.
	8	—	—
	9	Sin-	Sin input (inverse)
	10	—	—
	11	Cos-	Cos input (inverse)
	12	—	—
	13	—	—
	14	1TP2/K2	Motor temperature sensor connection, if carried by the encoder cable; output at pin 2 of X141.
	15	—	—

a) View of sub-D

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Terminal description for resolver adapter (REA 5001)

Pin[a)		Designation	Function	Pin[b)	
Socket	1	—	—	—	Connector
	2	1TP1/K1	Motor temperature sensor connection, if carried by the encoder cable; output at pin 1 of X141.	7	
	3	Sin-	Sin input (inverse)	9	
	4	Cos-	Cos input (inverse)	11	
	5	GND	Reference to ExcitationResolv	2	
	6	1TP2/K2	Motor temperature sensor connection, if carried by the encoder cable; output at pin 2 of X141.	14	
	7	Sin+	Sin input	1	
	8	Cos+	Cos input	3	
	9	ExcitationResolv	Resolver excitation signal	6	

a) View of sub-D 9-pole for the connection of the SDS 4000-compatible resolver cable

b) view of sub-D 15-pole for the connection to the SDS 5000, terminal X140 (REA 5001)

Information

Note that the EnDat interface at X140 is used if a SDS 4000 is replaced and a motor with an absolute encoder at X41 was operated.

In this case, you can continue to use the previously used encoder cable. The connection of the motor temperature sensor is carried in this cable. For this reason, observe the Chapter 5.8.
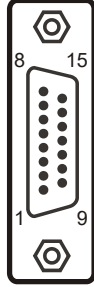
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Terminal description X140 for encoder EnDat 2.1 sin/cos (REA 5001)

Pin[a]		Designation	Function
Socket	1	Sin+	Sin input
	2	GND	Reference for encoder supply to pin 4
	3	Cos+	Cos input
	4	U_2	Encoder supply
	5	DATA+	Differential input for DATA
	6	—	—
	7	1TP1/K1	Connection motor temperature sensor is output to X141, pin 1 if carried by the encoder cable
	8	CLK+	Differential input for C:PCL
	9	Sin-	Inverse sin input
	10	Sense-	Reference for sense signal to pin 12
	11	Cos-	Inverse cos input
	12	Sense+	Sense signals for voltage control
	13	DATA-	Inverse differential input for DATA
	14	1TP2/K2	Connection motor temperature sensor is output to X141, pin 2 if carried by the encoder cable
	15	CLK-	Inverse differential input for CLOCK

a) View of sub-D

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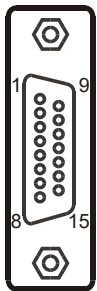
5.13.4   BE encoder and BA encoder simulation

Prerequisite for being able to evaluate or simulate an encoder on the binary interfaces:
- SEA 5001 or
- REA 5001 or
- XEA 5001

To evaluate single-ended incremental or pulse/directional signals, use binary inputs BE3, BE4 and BE5. If you would like to simulate them, use outputs BA1 and BA2.

General specification	
Maximum cable length	30 m
Signal level	HTL for SEA 5001 and XEA 5001
	TTL/HTL switchable for REA 5001

Evaluation – Incremental encoder and pulse train		
	HTL	**TTL**
High level	12 – 30 V	2 – 6 V
Low level	0 – 8 V	0 – 0.8 V
U_{1max}	30 V	6 V
I_{1max}	16 mA	13 mA
f_{max}	100 kHz	

Simulation – Incremental encoder and pulse train	
I_{2max}	50 mA for 45 °C, 40 mA for 55 °C
Eff. update rate	4 kHz
f_{max}	250 kHz
Extrapolation frequency	1 MHz

> **Calculation example – limit frequency f_{max}**
> **... for an encoder with** 2,048 pulses per revolution::
> 3,000 revolutions per minute (equivalent to 50 revolutions per second) * 2,048 pulses per revolution
> = 102,400 pulses per second
> = 102.4 kHz

Terminal description X101 – Incremental encoder and pulse train

| Pin		Designation	Function	Data
	9	GND 18 V	Reference ground for pin 19	—
	10	DGND	Reference ground for pins 11 to 18	—
	11	BE1	—	—
	12	BE2	—	
	13	BE3	Evaluation: Incremental encoder: N Pulse train: –	
	14	BE4	Evaluation: Incremental encoder: A Pulse train: frequency–	
	15	BE5	Evaluation: Incremental encoder: B Pulse train: direction	
	16	BA1	Simulation Incremental encoder: A Pulse train: frequency–	—
	17	BA2	Simulation Incremental encoder: B Pulse train: direction	
	18	24 V-In	24 vdc power supply - for XEA 5001 and - for binary outputs for SEA 5001 and REA 5001	Input range: 18 – 28.8 V
	19	18 V-Out	Auxiliary voltage 18 V	$U_2 = 16 - 18$ V $I_{2max} = 50$ mA
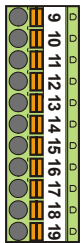
TTL/HTL switchover REA 5001

Switch	TTL/HTL conversion
S0	BE3
S1	BE4
S2	BE5

The identification of the switches and the assignment of the switch positions to the function (HTL/TTL) are shown on the PCB cover of the REA 5001.

REA 5001
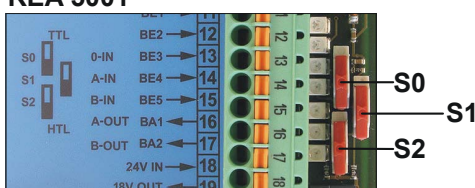
5.14   Fieldbus

5.14.1   X200: CANopen

Prerequisite for the CANopen link:

- CAN 5000

	Information
ℹ️	Please see the supplementary documentation of CANopen (see section 1.2 Further documentation)!

Terminal description X200

Pin		Designation	Function
Plug	1	—	—
	2	CAN-low	CAN-low line
	3	GND	Signal Ground
	4	—	—
	5	—	—
	6	CAN-low	CAN-low line connected internally with pin 2
	7	CAN-high	CAN-high line
	8	—	—
	9	CAN-high	CAN-high line connected internally with pin 7

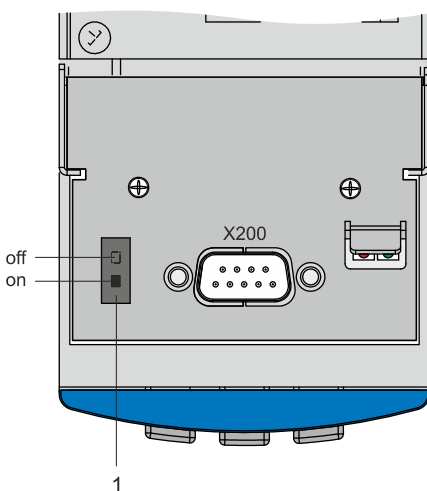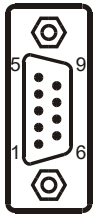Fig. 5-1Top of device with terminal X200

1   Internal terminating resistor 120 Ω switchable

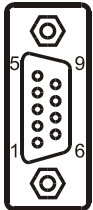## 5.14.2   X200: PROFIBUS

Prerequisite for the PROFIBUS link:

*   DP 5000

> **Information**
> Please see the supplementary documentation of PROFIBUS DP (see section 1.2 Further documentation)!

Terminal description X200

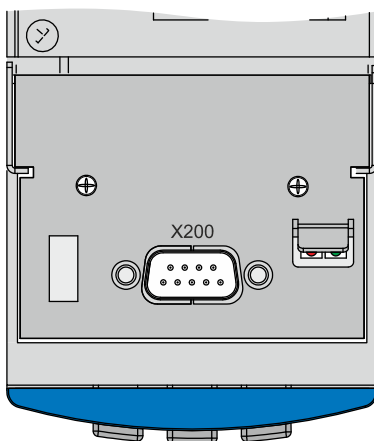| Pin		Designation	Function
socket	1	—	—
	2	—	—
	3	B	RxD / TxD-P (send/receive data +)
	4	RTS	Direction control for repeater +
	5	GND	Ground to + 5 V
	6	+5 V	Power for terminating resistors
	7	—	—
	8	A	RxD / TxD-N (send/receive data -)
	9	—	—

Fig. 5-2Top of device with terminal X200

5.14.3 X200, X201: EtherCAT

Prerequisite for the EtherCAT link:

- ECS 5000

> **Information**
> Please see the supplementary documentation of EtherCAT (see section 1.2 Further documentation)!

X200 and X201 terminal description

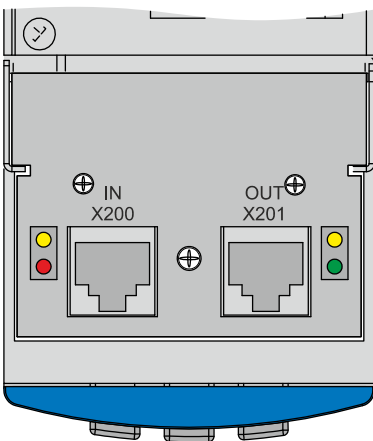| Pin		Designation	Function
	1	TxData+	EtherCAT communication
	2	TxData-	
	3	RecvData+	
	4	—	—
	5	—	—
	6	RecvData-	EtherCAT communication
	7	—	—
	8	—	—

Fig. 5-3Top of device with terminals X200 and X201

Cable specification

STOBER provides ready-made cables for the EtherCAT connection. These cables must be used to ensure proper functionality.

It is also possible to use cables with the following specification:

Plug wiring	Patch or crossover
Quality	CAT5e
Shielding	SFTP or PIMF

5.14.4　X200, X201: PROFINET

Requirement for the die PROFINET connection:

- PN 5000

> **ℹ Information**
> Observe the PROFINET operating manual (see section 1.2 Further documentation)!

Terminal description X200 and X201

The terminal configuration is determined by T 568-B.

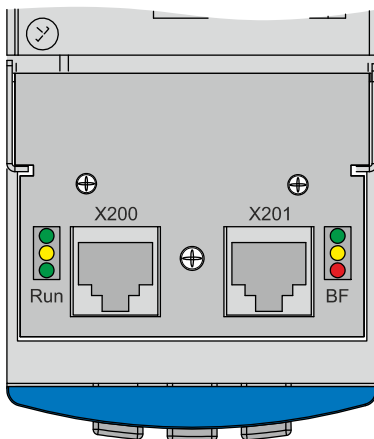| Pin		Designation	Function
	1	TxData +	PROFINET communication
	2	TxData -	
	3	RecvData +	
	4	—	Connect via RC-link with housing
	5	—	
	6	RecvData -	PROFINET communication
	7	—	Connect via RC-link with housing
	8	—	

Fig. 5-4Top of device with terminals X200 and X201

Observe the PROFINET installation guideline for the cable specification (PROFINET Order No. 8.071, identification: TC2-08-0001); you can obtain the document at www. profibus.com.

WE KEEP THINGS MOVING

5.15   X3A, X3B: PC, IGB

You can implement the functions of the IGB (Integrated Bus) with interface X3 located on the front of the inverter:
- Direct connection to the PC
- IGB Motionbus
- remote maintenance

Observe the operating manual SDS 5000, see section 1.2 Further documentation for setting up communication.

Terminal description X3A and X3B

Pin		Designation	Function
	1	Tx+	Ethernet communication
	2	Tx-	
	3	Rx+	
	4	—	Not used
	5	—	
	6	Rx-	Ethernet communication
	7	—	Not used
	8	—	

Cable specification

STOBER provides ready-made cables for
- direct connection PC - inverter and
- to set up the Integrated Bus.

These cables must be used to ensure proper functionality. Note also section 7 Accessories.

It is also possible to use cables with the following specification:

Plug wiring	Patch or crossover
Quality	CAT5e
Shielding	SFTP or PIMF

5.16   Cables

| ℹ	**Information**
	To ensure proper functionality of the drive we recommend using cables from STOBER that are coordinated with the system. In case of use of unsuitable connection cables, we reserve the right to reject claims under the warranty.

5.16.1   Power cable

Please observe the motor connection diagram that is delivered with every synchronous servo motor.

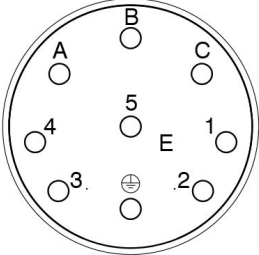Power cables are available depending on the plug size in the following designs:

- SpringTec quick lock for con.15
- SpeedTec quick lock for con.23 and con.40
- Screw technology for con.58
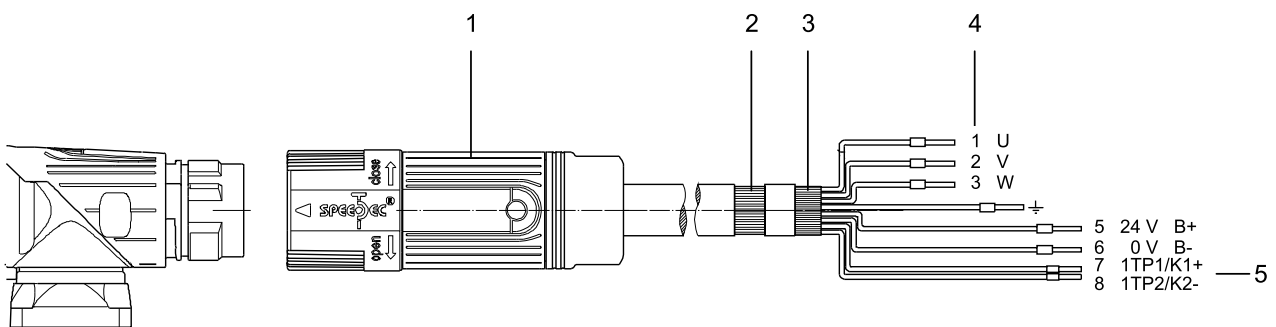
1   Plug connector (quick/screw lock)
2   Cable shield
3   Junction of all shields
4   Wire no.
5   Motor, brake temperature sensor

Synchronous servo motors of series ED/EK and EZ are equipped with circular plugs as standard and can be connected to inverters with the following power cables (the color specifications relate to the connection strands and are only significant for the motor-internal wiring).
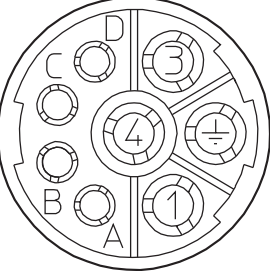
Power cable – connector size con.15

Bracket flange socket – motor	Pin	Signal	Motor-internal wire colors	Wire no.
	A	1U1	BK	1
	B	1V1	BU	2
	C	1W1	RD	3
	1	1TP1/1K1	BKBN	7
	2	1TP2/1K2	WHWH	8
	3	1BD1	RD	5
	4	1BD2	BK	6
	5	—	—	—
	⏚	PE	GNYE	⏚
	Housing	Shield	—	—

Dimensions – connector size con.15

Length [mm]	Diameter [mm]
42	18.7

Power cable – connector size con.23

Bracket flange socket – motor	Pin	Signal	Motor-internal wire colors	Wire no.
	1	1U1	BK	1
	3	1V1	RD	2
	4	1W1	BU	3
	A	1BD1	RD	5
	B	1BD2	BK	6
	C	1TP1/1K1	BKBN	7
	D	1TP2/1K2	WHWH	8
	⏚	PE	GNYE	⏚
	Housing	Shield	—	—

Dimensions – connector size con.23

Length [mm]	Diameter [mm]
78	26

Power cable – connector sizes con.40, con.58

Bracket flange socket – motor	Pin	Signal	Motor-internal wire colors	Wire no.
	R	1U1	BK	1
	V	1V1	BU	2
	W	1W1	RD	3
	+	1BD1	RD	5
	–	1BD2	BK	6
	1	1TP1/1K1	BKBN	7
	2	1TP2/1K2	WHWH	8
	⏚	PE	GNYE	⏚
	Housing	Shield	—	—

Dimensions – connector size con.40

Length [mm]	Diameter [mm]
99	46

Dimensions – connector size con.58

| Length [mm]	Diameter [mm]
146	63.5

WE KEEP THINGS MOVING

5.16.2 Encoder Cables

STOBER motors are equipped with encoder systems as standard.
Depending on the respective motor types, different encoder systems and associated plug connectors are used.
The following section describes the individual encoder systems, plug connectors and signal assignments.

5.16.2.1 Encoder EnDat 2.1/2.2 digital and SSI
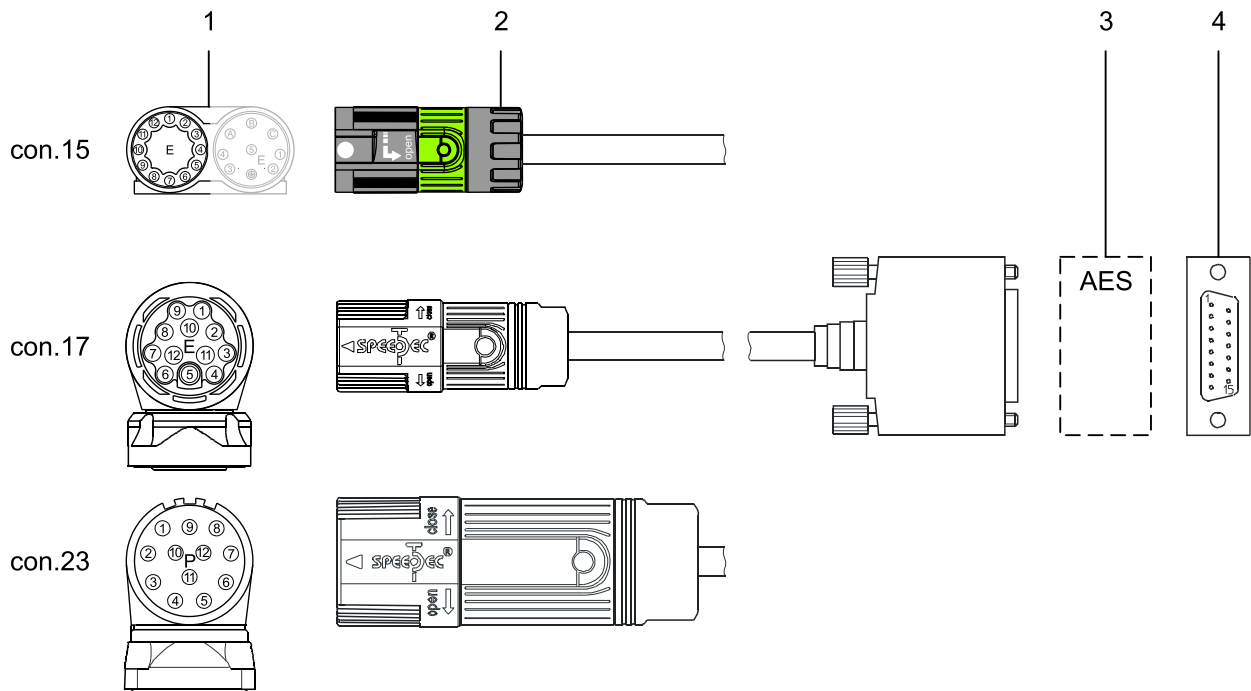
1   Bracket flange socket motor
2   STOBER encoder cable
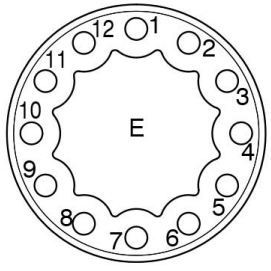3   Absolute Encoder Support
4   Sub-D (X4)

Digital absolute encoder EnDat 2.1/2.2 digital of series EBI, ECI, EQI, ECN or EQN can be combined with STOBER motors of series ED/EK and EZ. SSI encoders can also be connected to STOBER asynchronous motors.

The suitable encoder cables are described below.

Encoder cable – plug connector con.15

The voltage supply is buffered for the inductive EnDat 2.2 digital encoders "EBI 1135" and "EBI 135" with multiturn function. In this case, pin 2 and pin 3 are assigned to the backup battery U_{2BAT}. Note that the encoder cable must not be connected to X4 of the inverter but to the Absolute Encoder Support (AES) for these encoders.

| Motor | | Signal | Wire colors | | Sub-D (X4) |
Angle flange socket	Pin		Motor-internal	Encoder	Pin
	1	CLK+	VT	YE	8
	2	Sense	BU	PK	12
		U_{2BAT+} [a]			
	3	—	WH	GY	3
		U_{2BAT-} [a]			
	4	—	—	—	—
	5	DATA-	PK	BN	13
	6	DATA+	GY	WH	5
	7	—	—	—	—
	8	CLK-	YE	GN	15
	9	—	—	—	—
	10	GND	WHGN	BU	2
	11	—	—	—	—
	12	U_2	BNGN	RD	4
	Housing	Shield			

a) Only relevant for EBI encoders.

Dimensions – connector size con.15

Length [mm]	Diameter [mm]
42	18.7

WE KEEP THINGS MOVING

Encoder cable – plug connector con.17

The voltage supply is buffered for the inductive EnDat 2.2 digital encoders "EBI 1135" and "EBI 135" with multiturn function. In this case, pin 2 and pin 3 are assigned to the backup battery U_{2BAT}. Note that the encoder cable must not be connected to X4 of the inverter but to the Absolute Encoder Support (AES) for these encoders.

Motor		Signal	Wire colors		Sub-D (X4)
Angle flange socket	Pin		Motor-internal	Encoder	Pin
	1	CLK+	VT	YE	8
	2	Sense	BU	PK	12
		U_{2BAT+} [a]			
	3	—	WH	GY	3
		U_{2BAT-} [a]			
	4	—	—	—	—
	5	DATA-	PK	BN	13
	6	DATA+	GY	WH	5
	7	—	—	—	—
	8	CLK-	YE	GN	15
	9	—	—	—	—
	10	GND	WHGN	BU	2
	11	—	—	—	—
	12	U_2	BNGN	RD	4
	Housing	Shield			

a) Only relevant for EBI encoders.

Dimensions – connector size con.17

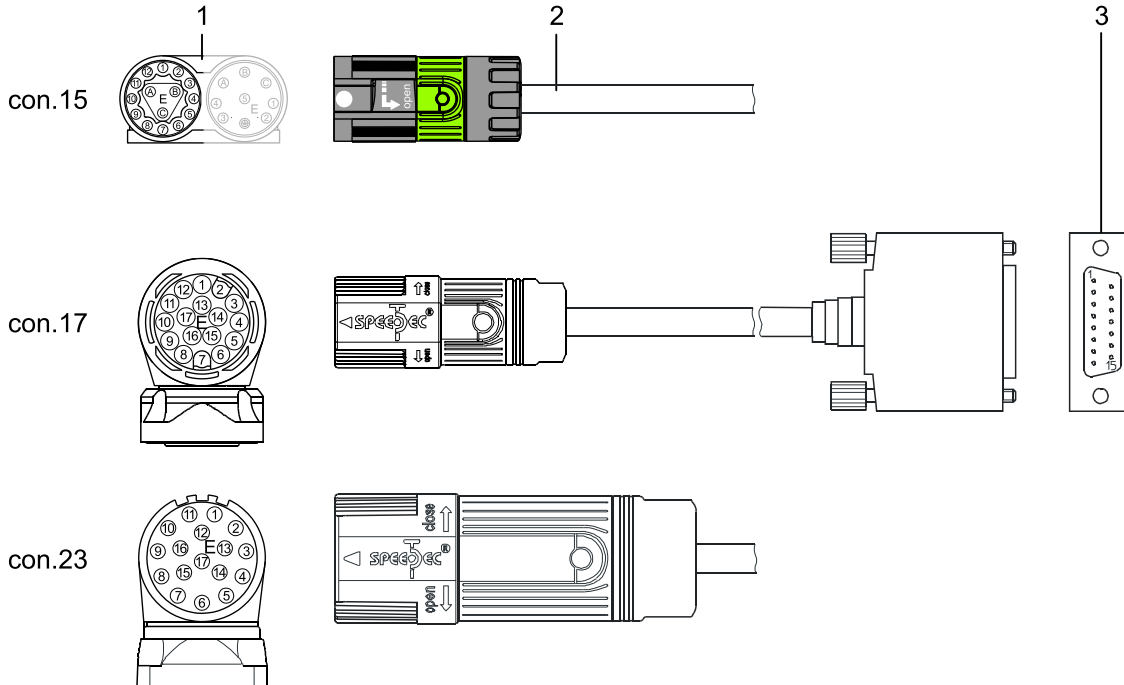| Length [mm]	Diameter [mm]
56	22

Encoder cable – plug connector con.23

Cable with plug connector con.23 in combination with EnDat 2.1/2.2 digital encoders can be connected to synchronous servo motors ED/EK; connect these with asynchronous motors in combination with SSI encoders.

Motor		Signal	Wire colors		Sub-D (X4)
Angle flange socket	Pin		Motor-internal	Encoder	Pin
	1	CLK+	VT	YE	8
	2	Sense	BNGN	PK	12
	3	—	—	—	—
	4	—	—	—	—
	5	DAT-	PK	BN	13
	6	DAT+	GY	WH	5
	7	—	—	—	—
	8	CLK-	YE	GN	15
	9	—	—	—	—
	10	GND	WHGN	BU	2
	11	—	—	—	—
	12	U_2	BNGN	RD	4
	Housing	Shield			

Dimensions – connector size con.23

Length [mm]	Diameter [mm]
58	26

WE KEEP THINGS MOVING

5.16.2.2 EnDat 2.1 sin/cos encoder

1   Bracket flange socket motor
2   STOBER encoder cable
3   Sub-D (X140)

Absolute encoder EnDat 2.1 sin/cos of series ECI, EQI, ECN or EQN can be combined with STOBER motors of series ED/EK and EZ.

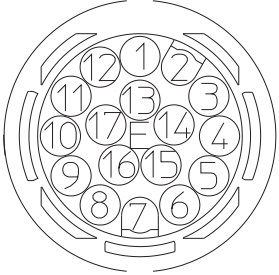The suitable encoder cables are described below.

Encoder cable – plug connector con.15

Motor Angle flange socket	Pin	Signal	Wire colors		Sub-D (X140) Pin
			Motor-internal	Encoder	
	1	Sense+	BU	GNRD	12
	2	Sense-	WH	GNBK	10
	3	U_2	BNGN	BNRD	4
	4	CLK+	VT	WHBK	8
	5	CLK-	YE	WHYE	15
	6	GND	WHGN	BNBU	2
	7	B+ (Sin+)	BUBK	RD	9
	8	B- (Sin-)	RDBK	OG	1
	9	DATA+	GY	GY	5
	10	A+ (Cos+)	GNBK	GN	11
	11	A- (Cos-)	YEBK	YE	3
	12	DATA-	PK	BU	13
	A	—	—	—	—
	B	—	—	—	—
	C	—	—	—	—
	Housing	Shield			

Dimensions – connector size con.15

Length [mm]	Diameter [mm]
42	18.7

WE KEEP THINGS MOVING

Encoder cable – plug connector con.17

Motor Angle flange socket		Signal	Wire colors		Sub-D (X140)
	Pin		**Motor-internal**	**Encoder**	**Pin**
	1	Sense+	BU	GNRD	12
	2	—	—	—	—
	3	—	—	—	—
	4	Sense-	WH	GNBK	10
	5	—	—	—	—
	6	—	—	—	—
	7	U_2	BNGN	BNRD	4
	8	CLK+	VT	WHBK	8
	9	CLK-	YE	WHYE	15
	10	GND	WHGN	BNBU	2
	11	—	—	—	—
	12	B+ (Sin+)	BUBK	RD	9
	13	B- (Sin-)	RDBK	OG	1
	14	DATA+	GY	GY	5
	15	A+ (Cos+)	GNBK	GN	11
	16	A- (Cos-)	YEBK	YE	3
	17	DATA-	PK	BU	13
	Housing	Shield			

Dimensions – connector size con.17

Length [mm]	Diameter [mm]
56	22

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Encoder cable – plug connector con.23

Cable with plug connector con.23 in combination with EnDat 2.1 Sin/Cos encoders can be connected to ED/ EK motors.

Motor Angle flange socket	Pin	Signal	Wire colors		Sub-D (X140) Pin
			Motor-internal	Encoder	
	1	Sense+	BU	GNRD	12
	2	—	—	—	—
	3	—	—	—	—
	4	Sense-	WH	GNBK	10
	5	—	—	—	—
	6	—	—	—	—
	7	U_2	BNGN	BNRD	4
	8	CLK+	VT	WHBK	8
	9	CLK-	YE	WHYE	15
	10	GND	WHGN	BNBU	2
	11	—	—	—	—
	12	B+ (Sin+)	BUBK	RD	9
	13	B- (Sin-)	RDBK	OG	1
	14	DAT+	GY	GY	5
	15	A+ (Cos+)	GNBK	GN	11
	16	A- (Cos-)	YEBK	YE	3
	17	DAT-	PK	BU	13
	Housing	Shield			

Dimensions – connector size con.23

Length [mm]	Diameter [mm]
58	26

WE KEEP THINGS MOVING
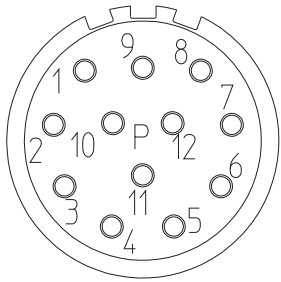
5.16.2.3 Encoder HTL

HTL incremental encoders can be combined with STOBER asynchronous motors.
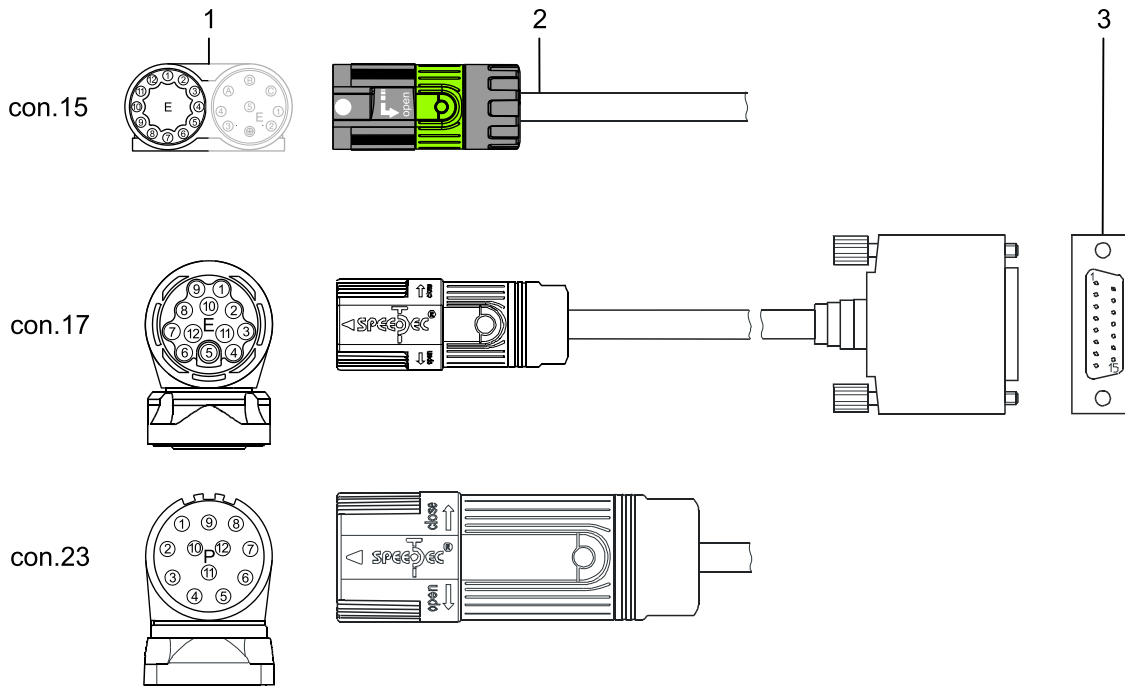The suitable encoder cable is described below.

Encoder cable – plug connector con.23

Motor Angle flange socket	Pin	Signal	Wire colors Motor-internal	Encoder	Sub-D (X4) Pin
	1	B-	PK	YE	9
	2	—	—	—	—
	3	N+	RD	PK	3
	4	N-	BK	GY	10
	5	A+	BN	BN	6
	6	A-	GN	WH	11
	7	—	—	—	—
	8	B+	GY	GN	1
	9	—	—	—	—
	10	GND	WH	BU	2
	11	—	—	—	—
	12	U_2	BN	RD	4
	Housing	Shield			

Dimensions – connector size con.23

Length [mm]	Diameter [mm]
58	26

5.16.2.4   Resolver

con.15

con.17

con.23
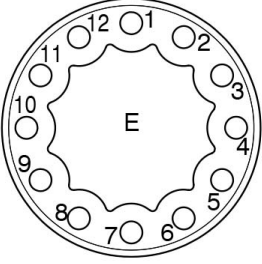
1   Bracket flange socket motor
2   STOBER encoder cable
3   Sub-D (X140)

Resolvers can be combined with STOBER motors of series ED/EK or EZ.
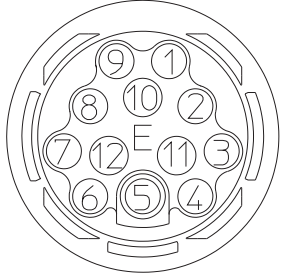The suitable resolver cables are described below.

WE KEEP THINGS MOVING

Encoder cable – plug connector con.15

Motor Angle flange socket	Pin	Signal	Wire colors Motor-internal	Encoder	Sub-D (X140) Pin
	1	S3 Cos+	BK	YE	3
	2	S1 Cos-	RD	GN	11
	3	S4 Sin+	BU	WH	1
	4	S2 Sin-	YE	BN	9
	5	—	—	—	Do not connect
	6	—	—	—	Do not connect
	7	R2 Ref+	YEWH	GY	6
	8	R1 Ref-	RDWH	PK	2
	9	—	—	—	—
	10	—	—	—	—
	11	—	—	—	—
	12	—	—	—	—
	Housing	Shield			

Dimensions – connector size con.15

Length [mm]	Diameter [mm]
42	18.7

Encoder cable – plug connector con.17
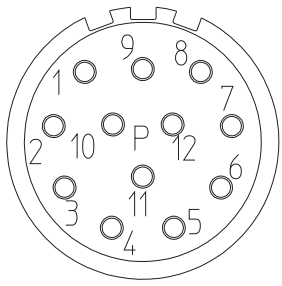
| Motor | | Signal | Wire colors | | Sub-D (X140) |
Angle flange socket	Pin		Motor-internal	Encoder	Pin
	1	S3 Cos+	BK	YE	3
	2	S1 Cos-	RD	GN	11
	3	S4 Sin+	BU	WH	1
	4	S2 Sin-	YE	BN	9
	5	—	—	—	Do not connect
	6	—	—	—	Do not connect
	7	R2 Ref+	YEWH	GY	6
	8	R1 Ref-	RDWH	PK	2
	9	—	—	—	—
	10	—	—	—	—
	11	—	—	—	—
	12	—	—	—	—
	Housing	Shield			

Dimensions – connector size con.17

Length [mm]	Diameter [mm]
56	22

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Encoder cable – plug connector con.23

Cable with plug connector con.23 in combination with resolvers can only be connected to synchronous servo motors ED/EK.

Motor		Signal	Wire colors		Sub-D (X140)
Angle flange socket	Pin		Motor-internal	Encoder	Pin
	1	S3 Cos+	BK	YE	3
	2	S1 Cos-	RD	GN	11
	3	S4 Sin+	BU	WH	1
	4	S2 Sin-	YE	BN	9
	5	—	—	—	Do not connect
	6	—	—	—	Do not connect
	7	R2 Ref+	YEWH	GY	6
	8	R1 Ref-	RDWH	PK	2
	9	—	—	—	—
	10	—	—	—	—
	11	—	—	—	—
	12	—	—	—	—
	Housing	Shield			

Dimensions – connector size con.23

Length [mm]	Diameter [mm]
58	26

Cable color – key

BK	BLACK	PK	PINK
BN	BROWN	RD	RED
BU	BLUE	VT	VIOLET
GN	GREEN	WH	WHITE
GY	GREY	YE	YELLOW
OG	ORANGE		

6 Examples of connections
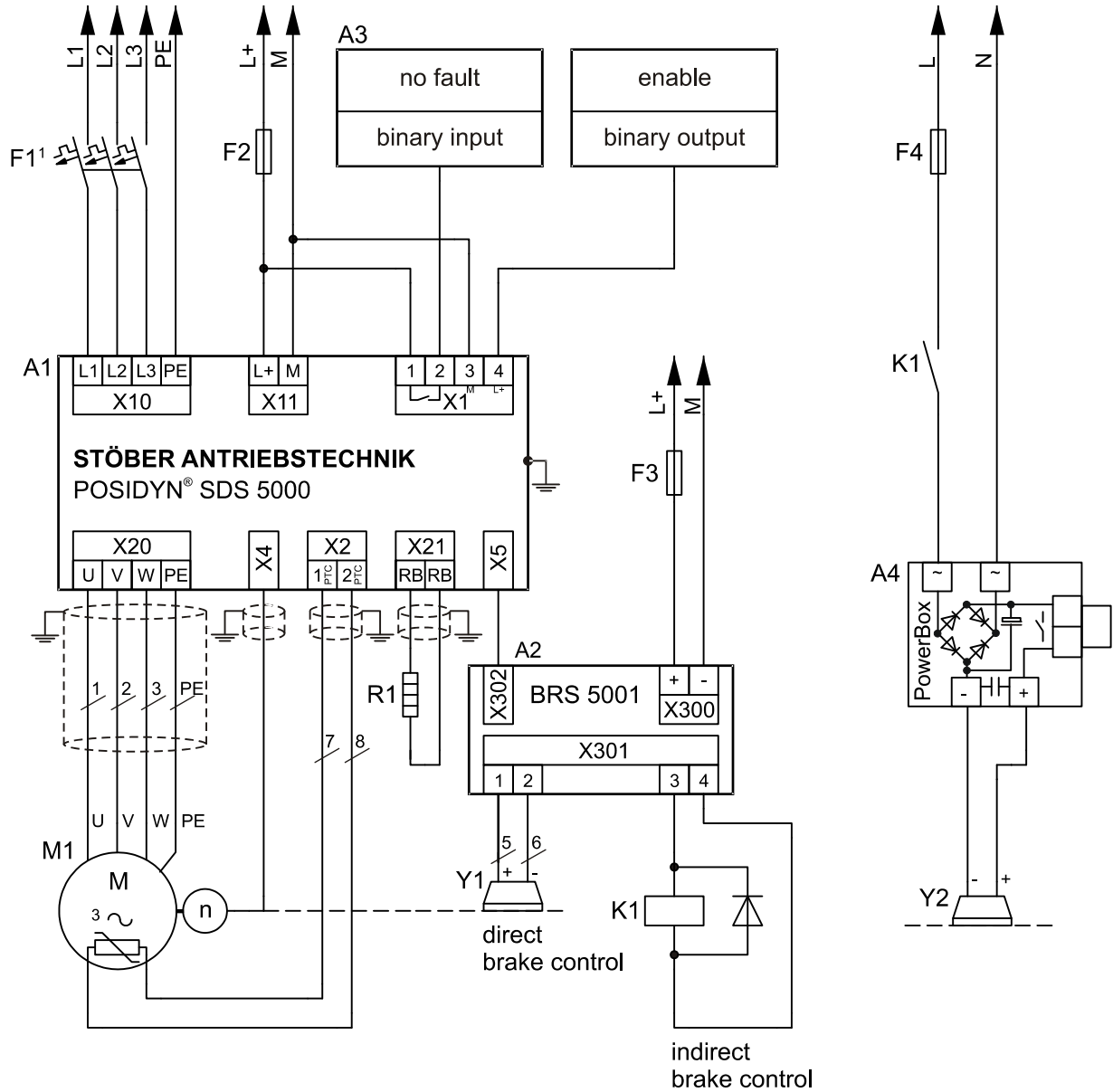
¹ circuit protection
  tripping characteristics C

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7 Accessories

I/O terminal module standard SEA 5001

ID no. 49576

Terminals:
- 2 analog inputs
- 2 analog outputs
- 5 binary inputs
- 2 binary outputs

I/O terminal module extended XEA 5001

ID no. 49015
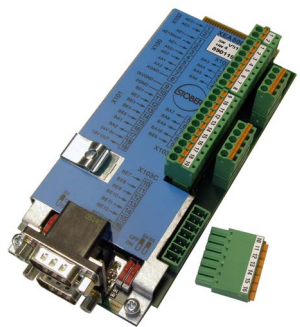
Terminals:
- 3 analog inputs
- 2 analog outputs
- 13 binary inputs
- 10 binary outputs

Encoder / interfaces:
- TTL incremental encoder (simulation and evaluation)
- Pulse train (simulation and evaluation)
- SSI encoder (simulation and evaluation)

SSI/TTL connection cable X120

ID no. 49482

For connection of the SSI interface X120 to the XEA 5001, 0.3 m in length.

I/O terminal module resolver REA 5001

ID no. 49854

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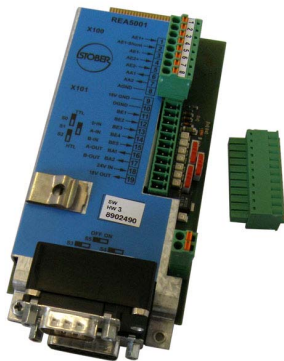
Terminals:
- 2 analog inputs
- 2 analog outputs
- 5 binary inputs
- 2 binary outputs

Encoder / interfaces:
- Resolver
- EnDat 2.1 sin/cos encoder
- TTL incremental encoder (simulation and evaluation)
- SSI encoder (simulation and evaluation)
- Pulse train (simulation and evaluation)
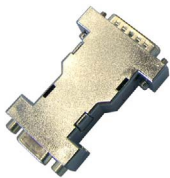
Resolver cables that were connected to an POSIDYN SDS 4000 can be connected via the resolver adapter (9-pin to 15-pin) included in the scope of delivery to terminal X140 of REA 5001.
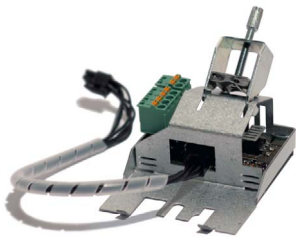
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> **Information**
> The brake module BRS 5001 is the follow-up model to BRS 5000. The new version is equipped with separate terminals for the connection of a motor holding brake and 24 vdc power supply as well as a screwable shield connection terminal.
> BRS 5001 requires firmware V 5.6-N or higher.

Brake module BRS 5001

ID no. 56519

Brake module for inverters of series SDS 5000.
Accessory part for direct control of up to two motor holding brakes (24 VDC) and (for inverters up to size 2) for connecting to the shield of the power cable.
Attachable on the basic housing.
Including connection cable for basic device and shield connection terminal.

Technical Data	
Power cable cross-section	1 to 10 mm²
Max. shield diameter	20 mm
Min. shield contact surface (isolated part of the power cable)	20 mm
Tightening torque	0.8 Nm

EMC shroud EM 5000

ID no. 44959
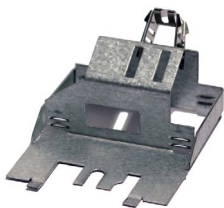
EMC shroud for sizes 0 to 2.
Accessory part for shield connection of the motor line.
Attachable on the basic housing.
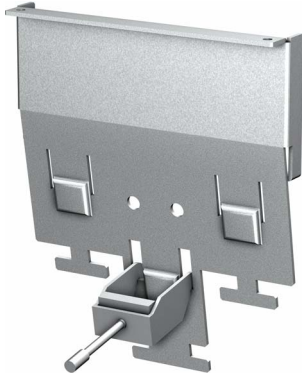Including shield connection terminal.

Technical Data	
Power cable cross-section	1 to 4 mm²
Max. shield diameter	12 mm
Min. shield contact surface (isolated part of the power cable)	15 mm

EMC shroud EM6A3

ID no. 135120

EMC shroud for size 3.
Accessory part for shield connection of the motor line.
Attachable on the basic housing.
Including shield connection terminal.
If necessary you can also connect the cable shield of the braking resistor and DC link connection on the shroud. Additional shield connection terminals are available as accessories for this purpose (ID no. 56521).

Technical Data	
Power cable cross-section	2.5 to 35 mm²
Max. shield diameter	35 mm
Min. shield contact surface (isolated part of the power cable)	20 mm
Tightening torque	1.5 – 1.8 Nm

4-way axis switcher POSISwitch AX 5000

ID no. 49578

Enables the operation of up to four servo motors on one inverter.

POSISwitch connection cable
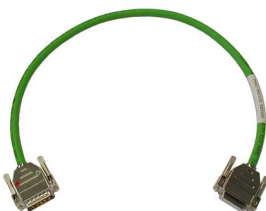
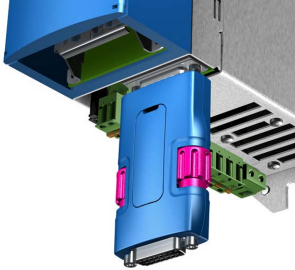Connection between inverter and POSISwitch AX 5000.

The following versions are available:

ID no. 45405: 0.5 m.
ID no. 45386: 2.5 m.

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Absolute Encoder Support AES

ID no. 55452

For buffering the power supply when using the inductive absolute value encoder EnDat 2.2 digital with battery-buffered Multiturn power stage, for example EBI1135, EBI135.
A battery is included.

Replaceable battery AES

ID no. 55453

Replaceable battery for Absolute Encoder Support AES.

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Fieldbus module CANopen DS-301 CAN 5000

ID no. 44574

Accessory part for connecting CAN bus.

Fieldbus module PROFIBUS DP-V1 DP 5000

ID no. 44575

Accessory module for connecting PROFIBUS DP-V1.

Fieldbus module EtherCAT ECS 5000

ID no. 49014

Accessory part for connecting EtherCAT (CANopen over EtherCAT).

EtherCAT cable

EtherNet patch cable, CAT5e, yellow.

The following versions are available:

ID no. 49313: approx. 0.2 m.
ID no. 49314: approx. 0.35 m.

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Fieldbus module PROFINET PN 5000

ID no. 53893

Accessory part for connecting PROFINET.

ASP 5001 – Safe Torque Off

Available with the standard version.
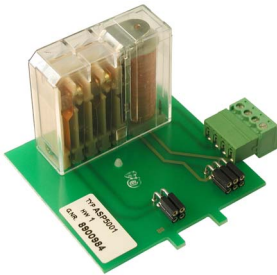
Option module for implementation of integrated safety function Safe Torque Off (STO).
The ASP 5001 may only be installed by STÖBER Antriebstechnik GmbH + Co. KG!
The ASP 5001 must be ordered with the basic device.

IGB connecting cable

To connect the interface X3 A or X3 B on the inverter front for IGB, CAT5e, magenta, connector angled at 45°.

The following versions are available:

ID no. 49855: 0.4 m.
ID no. 49856: 2 m.

PC connecting cable

ID no. 49857

To connect the X3 A or X3 B interface to PC, CAT5e, blue, 5m.

STÖBER

Hi-speed USB 2.0 Ethernet adapter

ID no. 49940

Adapter for connecting Ethernet to a USB connection.

Removable Data Storage Paramodule

Included in the standard design.

ID no. 55464

Memory module for configuration and parameters.

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