

Absolute Encoder CAS60---R4B User Manual

- A "magnetic detection mode", with excellent impact and vibration resistance.
- Multi-purpose, multi-functional, directly corresponds to the angle, length and speed measurement.
- Wide operating voltage, low current consumption.
- Clamping flange, servo flange or blind hollow shaft, the international standard structure.
- External resetting line to set the default location, easy installation, no need to find ZERO.

★**Please totally read the following instruction first for proper use of encoder.**

Parameter

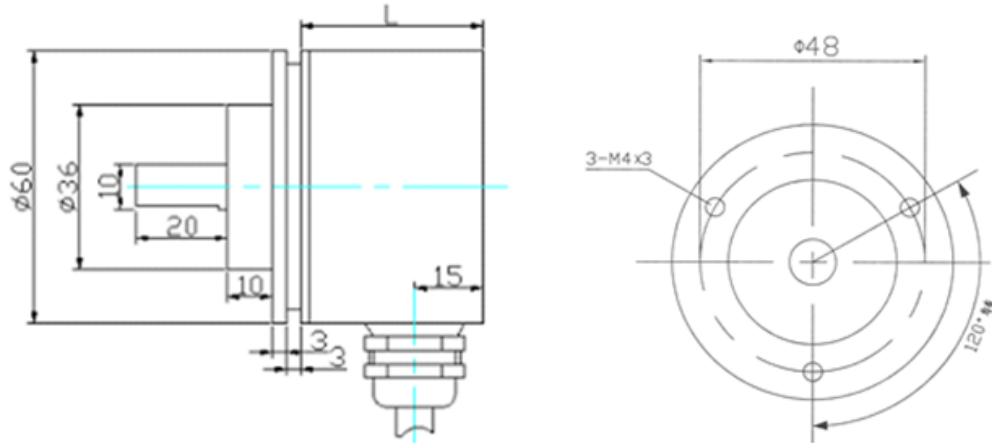
Operating Voltage	10-30Vdc polarity protection
Current Consumption	< 110mA (24V power supply) no load
Output Signal	RS485, you can set the length, angle, speed application output
Output load capacity	≤ 400 ohms, the standard 200-250 Ohm work
Linearity Resolution	1/32768 15bits
Operating Temperature	-25—80℃ Programming temperature range: 0℃~+70℃
Storage Temperature	-40—80℃
Protection class	IP67 for housing IP65 for shaft
Vibration & shock	20g, 10~2000Hz; 100g, 6ms
Permissible Rotation Rate	2400rpm
Output refresh cycle	<1.4ms
Connection Cable	1m 8-core shielded cable.
Overall Feature	Clamping flange or synchronous flange, metal enclosure, sealed dual-bearing structure (see attached drawing of overall dimension)
Shaft	Clamping flange shaft diameter 10mm, length 20mm, with D-flat, stainless steel, synchro flange shaft 6mm, length 10mm
Signal Conditioning	direction can be set; preset position, external set, such as external zero

Connection

Cable Output	
Cable Color	Signal Output
Brown	10—30Vdc Operating Voltage
White	0V GND
Green	RS485 Output A
Yellow	RS485 Output B
Pink	null
Blac	null
Blue	Programming permitted line
Gray	External Reset line

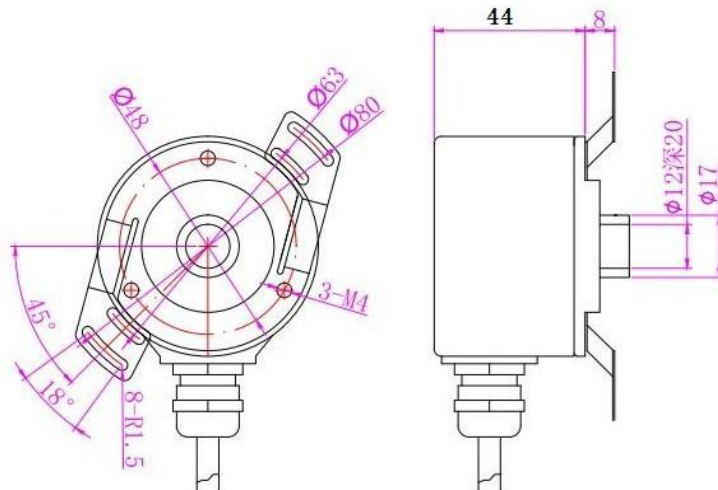
Installation dimensions (Unit: mm)

a. Clamping & synchro flange



b. Hollow shaft flange:

安装尺寸图:



Explanation: The horizontal axis represents the speed or the length (customizable), and the ordinate indicates the analog signal output

Custom RS485 communication protocol description:

Baud Rate: 4800bps 9600bps 19200bps 38400bps 115200bps.

Frame format: 8 data bits, 1 stop bit, no parity, no flow control.

The parameter of encoders is set by software instruction.

When the encoder is in active mode, That is the encoder automatically sends data to the host. Data length is 16 hexadecimal ASCII code format is: XAB> ± DATA ↵, as follow:

1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16
X	address	>	±	DATA											↵

Wherein, "X" is the leading letters, ">" is delimiters, "±" is the sign bit; "DATA" is the data, ASCII format, 10, from 0 to 9 constitute the range of -9,999,999,999 ~ +9,999,999,999. "↵" is carriage return (0D).



When the encoder is in passive mode, That is quiz mode. Host send inquiry instruction to the encoder, the instruction is four hexadecimal ASCII code format is: D + AB ↙.

“AB” is encoder address, range is 0~99.

1. Read data:

Host send: D + Address +0 D

Encoder return: X + address +> + sign + DATA+0 D

Example: Host sends 44 30 31 0D

Encoder return: 58 30 31 3E 2B 30 30 30 30 30 30 31 32 33 0D

2. Read parameters: (When blue wire connected high, is available)

Host sends: D +00 + A +0 D

Encoder return: X + address + a + direction + baud rate+ working condition + working mode +0 D

Example: Host sends: 44 00 41 0D

Encoder return: 58 30 31 61 06 03 11 09 0D

(Encoder address 01, clockwise to increase data value, baud rate 19200, reciprocating mode, passive mode)

3. Set Address: (When blue wire connected high, is available)

Host sends: D + address + B + new address +0 D

Encoder return: X + address + b + new address +0 D

Example: Host sends: 44 30 30 42 30 31 0D

Encoder return: 58 30 30 62 30 31 0D

(Modify the encoder address 00 to 01)

4. Setting direction: (When blue wire connected high, is available)

Host sends: D + address + C + new direction +0 D

Encoder return: X + address + c + +0 D new direction

Example: Host sends: 44 30 31 43 07 0D

Encoder return: 58 30 31 63 07 0D

(The CW to CCW)

5. Set the baud rate: (When blue wire connected high, is available)

Host sends: D + address + E + new baud +0 D

Encoder return: X + address + e + new baud +0 D

Example: Host sends: 44 30 31 45 03 0D

Encoder return: 58 30 31 65 03 0D

(Baud rate to 19200)

6. Set each circle Resolution: (When blue wire connected high, is available)

Host sends: D + Address + F + Resolution +0 D

Encoder return: X + address + f + resolution +0 D

Example: Host sends: 44 30 31 46 30 30 33 36 30 30 0D

Encoder return: 58 30 31 66 30 30 33 36 30 30 0D

(Set the resolution to 3600)

7. Set Passive Mode: (When blue wire connected high, is available)

Host sends: D + address + I + mode +0 D

Encoder return: X + address + i + mode +0 D

Example: Host sends: 44 30 31 49 09 0D

Encoder return: 58 30 31 69 09 0D

(Set to quiz mode)

8. Set the presetting value: (When blue wire connected high, is available)

Host sends: D + address + J + preset value +0 D

Encoder return: X + address + j + preset value +0 D

Example: Host sends: 44 30 31 4A 30 30 30 30 30 30 30 30 0D

Encoder return: 58 30 31 6A 30 30 30 30 30 30 30 30 0D

(Set presetting value to 0)

9. Encoder reset instruction: (When blue wire connected high, is available)

Host sends: D + address + L + M + sum parity +0 D

Encoder return: X + address + l + m +sum parity +0 D

Example: Host sends: 44 30 31 4C 4D sum verify 0D

Encoder return: 58 30 31 6C 6D sum check 0D

(The current position is reset to the default preset values)

10. Setting the operating mode: (When blue wire connected high, is available)

Host sends: D + address + N + mode +0 D mode

Encoder return: X + address + n + +0 D mode

Example: Host sends: 44 30 31 4E 11 0D

Encoder return: 58 30 31 6E 11 0D

(Working mode set: 10 is loop mode, 11 is reciprocating mode.)

11. Set reciprocating max value: (When blue wire connected high, is available)

Host sends: D + address + O + H + max value +0 D

Encoder return: X + address + o + H + max value+0 D

Example: Host sends: 44 30 31 4F 48 30 30 30 30 31 30 30 30 30 0D

Encoder return: 58 30 31 6E 48 30 30 30 30 31 30 30 30 30 0D

(Set max value to 100000)

12. Sets the maximum value of the loop: (When blue wire connected high, is available)

Host sends: D + address + P + L + max value +0 D

Encoder return: X + address + p + L + max value +0 D

Example: Host sends: 44 30 31 50 4C 30 30 30 30 31 30 30 30 30 0D

Encoder return: 58 30 31 70 4C 30 30 30 30 31 30 30 30 30 0D

(Set max value to 100000)

Parameters table:

ASCII 码	parameter	ASCII code	parameter
01	4800bps baud rate	07	CCW data increases
02	9600bps baud rate	08	Active mode
03	19200bps baud rate	09	passive mode
04	38400bps baud rate	10	Loop mode
05	115200bps baud rate	11	reciprocating mode
06	CW data increases		

Programming permitted line (blue wire) usage:

When setting mode, the blue wire and the brown wire connected together to the positive power supply, the white wire connected to power ground. In this case, the encoder communication speed is fixed to 19200bps.

When non-setting mode, that is work mode, we recommend the blue wire and the white line

connected together to the power ground.

RS485 communication considerations:

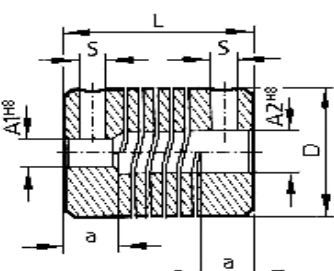
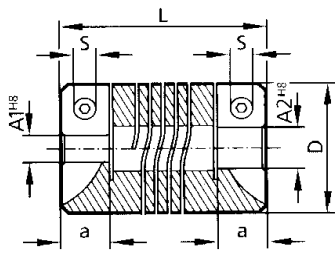
1. Communication speed and transmission distance is a contradiction. The higher the rate, the transmission distance is shorter, but more stable, and vice versa.
 2. External reset line (gray wire) used to reset the encoder current position to presetting value. When using, the gray wire should connected to high level (24V). But after the completion of the operation, It's better to connect gray wire to power ground to avoid interference.
 3. In the strong external electromagnetic interference, RS485 connection is best to use double-shielded cable.
 4. When multiple encoders connect host, because of the encoder have no parity, it is suggested that when the PC programming in time to distinguish between the various encoder data returned.
 5. When the system has a motor, encoder power supply should be isolated from other.
- Since RS485 circuit is a differential form, A, B are two signal lines with voltage, often times connect to ground or high level, RS485 circuit will cause damage

Ended coupling overall dimension and technical parameter

Attached: Recommended coupling:

- *Aluminium alloy integral style, with compact structure, durable, good rotation balance character.
- *Good anti-torsion rigidity, little detuning of shaft, high precision.
- * Absorb fine axial running, Eccentricity is allowed.
- * Puller bolt fixed style and hug fixed style



Style	F60022	F60067	Puller bolt fixed style overall dimension: F60022  S: M4	hug fixed style overall dimension: F60067  S: M4
D	24	24		
A1	6,8,10	6,8,10		
A2	8,10	10		
L	24	32		
A	7	8		
Max. radial deviation	±0.3	±0.35		
Max. axial deviation	±0.5	±0.5		
Max. angle deviation	±4°	±4°		
Max .speed rpm	8000	6000		