

Temposonics®

Magnetostrictive Linear Position Sensors

Temposonics® R-Series V EtherCAT® Operation Manual



I AM THE NEW GENERATION

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1. Introduction

1.1 Purpose and use of this manual

Before starting the operation of Temposonics® position sensors, read this documentation thoroughly and follow the safety information. Keep this manual for future reference!

The content of this technical documentation and its appendices is intended to provide information on mounting, installation and commissioning by qualified automation personnel ¹ or instructed service technicians who are familiar with the project planning and dealing with Temposonics® sensors.

1.2 Used symbols and warnings

Warnings are intended for your personal safety and for avoidance of damage to the described product or connected devices. In this documentation, safety information and warnings to avoid danger that might affect the life and health of operating or service personnel or cause material damage are highlighted by the pictogram defined below.

Symbol	Meaning
NOTICE	This symbol is used to point to situations that may lead to material damage, but not to personal injury.

2. Safety instructions

2.1 Intended use

This product may be used only for the applications defined under item 1 and only in conjunction with the third-party devices and components recommended or approved by MTS Sensors. As a prerequisite of proper and safe operation the product requires correct transport, storage, mounting and commissioning and must be operated with utmost care.

- The sensor systems of all Temposonics® series are intended exclusively for measurement tasks encountered in industrial, commercial and laboratory applications. The sensors are considered as system accessories and must be connected to suitable evaluation electronics, e.g. a PLC, IPC, indicator or other electronic control unit.

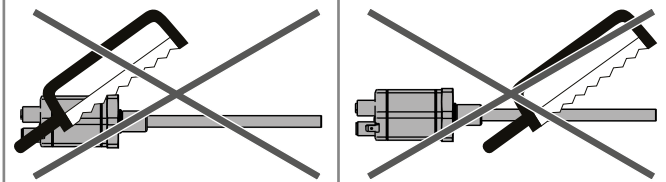
^{1/} The term "qualified technical personnel" characterizes persons who:

- are familiar with the safety concepts of automation technology applicable to the particular project
- are competent in the field of electromagnetic compatibility (EMC)
- have received adequate training for commissioning and service operations
- are familiar with the operation of the device and know the information required for correct operation provided in the product documentation

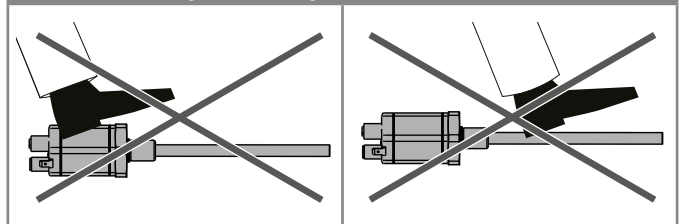
2.2 Foreseeable misuse

Foreseeable misuse	Consequence
Wrong sensor connection	The sensor will not work properly or can be damaged
Operate the sensor out of the operating temperature range	No signal output – the sensor can be damaged
Power supply is out of the defined range	Signal output is wrong / no signal output / the sensor will be damaged
Position measurement is influenced by an external magnetic field	Signal output is wrong
Cables are damaged	Short circuit – the sensor can be destroyed / sensor does not respond
Spacers are missing / installed in a wrong order	Error in position measurement
Wrong connection of ground / shield	Signal output is disturbed – the electronics can be damaged
Use of a magnet that is not specified by MTS Sensors	Error in position measurement

Do not alter the sensor.
→ The sensor might be damaged.



Do not step on the sensor.
→ The sensor might be damaged.



2.3 Installation, commissioning and operation

The position sensors must be used only in technically safe conditions. To maintain this condition and to ensure safe operation, installation, connection and service, work may be performed only by qualified technical personnel.

If danger of injury to persons or of damage to operating equipment is caused by sensor failure or malfunction, additional safety measures such as plausibility checks, limit switches, EMERGENCY STOP systems, protective devices etc. are required. In the event of trouble, shut down the sensor and protect it against accidental operation.

Safety instructions for commissioning

To maintain the sensor's operability, it is mandatory to follow the instructions given below.

1. Protect the sensor against mechanical damage during installation and operation.
2. Do not open or dismantle the sensor.
3. Connect the sensor very carefully and pay attention to the polarity of connections and power supply.
4. Use only approved power supplies.
5. Ensure the sensor is operating within the defined limits for supply voltage, environmental conditions, etc..
6. Check the function of the sensor regularly and provide documentation of the checks.
7. Before applying power, ensure that nobody's safety is jeopardized by starting machines.

2.4 Safety instructions for use in explosion-hazardous areas

The sensor is not suitable for operation in explosion-hazardous areas.

2.5 Warranty

MTS Sensors grants a warranty period for the Temposonics® position sensors and supplied accessories relating to material defects and faults that occur despite correct use in accordance with the intended application². The MTS Sensors obligation is limited to repair or replacement of any defective part of the unit. No warranty can be provided for defects that are due to improper use or above average stress of the product, as well as for wear parts. Under no circumstances will MTS Sensors accept liability in the event of offense against the warranty rules, no matter if these have been assured or expected, even in case of fault or negligence of the company. MTS Sensors explicitly excludes any further warranties. Neither the company's representatives, agents, dealers nor employees are authorized to increase or change the scope of warranty.

2.6 Return

For diagnostic purposes, the sensor can be returned to MTS Sensors or a repair facility explicitly authorized by MTS Sensors. Any shipment cost is the responsibility of the sender². For a corresponding form, see chapter "13. Appendix I" on page 43.

NOTICE

When returning sensors, place protective caps on male and female connectors of the sensor. For pigtail cables, place the cable ends in a static shielding bag for electrostatic discharge (ESD) protection. Fill the outer packaging around the sensor completely to prevent damage during transport.

^{2/} See also applicable MTS Sensors terms of sales and delivery on:
www.mtssensors.com

3. Identification

3.1 Order code of Temposonics® R-Series V RP5

1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20
R	P	5										D	5		1	U	1		1
a			b	c	d					e		f			g	h			

a	Sensor model		
R	P	5	Profile

b	Design
G	Magnet slider backlash free (part no. 253 421), suitable for internal linearization
L	Block magnet L (part no. 403 448)
M	U-magnet OD33 (part no. 251 416-2), suitable for internal linearization
N	Magnet slider longer ball-jointed arm (part no. 252 183), suitable for internal linearization
O	No position magnet
S	Magnet slider joint at top (part no. 252 182), suitable for internal linearization
V	Magnet slider joint at front (part no. 252 184), suitable for internal linearization

c	Mechanical options
A	Standard
V	Fluorelastomer seals for the sensor electronics housing

d	Stroke length				
X	X	X	X	M	0025...6350 mm
Standard stroke length (mm)		Ordering steps			
25... 500 mm		25 mm			
500...2500 mm		50 mm			
2500...5000 mm		100 mm			
5000...6350 mm		250 mm			
X	X	X	X	U	001.0...250.0 in.
Standard stroke length (in.)		Ordering steps			
1... 20 in.		1.0 in.			
20...100 in.		2.0 in.			
100...200 in.		4.0 in.			
200...250 in.		10.0 in.			

Non-standard stroke lengths are available; must be encoded in 5 mm/0.1 in. increments.

e	Number of magnets	
X	X	01...30 position(s) (1...30 magnet(s))

f	Connection type		
D	5	6	2 × M12 female connectors (5 pin), 1 × M8 male connector (4 pin)
D	5	8	2 × M12 female connectors (5 pin), 1 × M12 male connector (4 pin)

g	System
1	Standard

h	Output			
U	1	0	1	EtherCAT®, position, velocity and acceleration (1...30 positions)
U	1	1	1	EtherCAT®, position, velocity and acceleration internal linearization (1...30 positions)

NOTICE

- For the RP5, the magnet selected in **b** "Design" is included in the scope of delivery. For multi-position measurements with more than 1 magnet, order the other magnets separately.
- The number of magnets is limited by the stroke length. The minimum allowed distance between magnets (i.e. front face of one to the front face of the next one) is 75 mm (3 in.).
- Use magnets of the same type for multi-position measurement, e.g. 2 × U-magnet (part no. 251 416-2).
- If the option for internal linearization (U111) in **h** "Output" is chosen, select a suitable magnet.

3.2 Order code of Temposonics® R-Series V RH5

1	2	3	4	5	6	7	8	9	10	11	12	13	14	15	16	17	18	19	20
R	H	5										D	5		1	U	1		1
a			b	c	d					e		f			g	h			

a	Sensor model		
R	H	5	Rod

b	Design
B	Base unit (only for replacement)
J	Threaded flange M22×1.5-6g (rod Ø 12.7 mm), stroke length: 25...5900 mm (1...232 in.)
M	Threaded flange M18×1.5-6g (standard)
S	Threaded flange ¾"-16 UNF-3A (standard)
T	Threaded flange ¾"-16 UNF-3A (with raised-face)

c	Mechanical options
A	Standard
B	Bushing on rod end (only for design »M«, »S« & »T«)
M	Thread M4 at rod end (only for design »M«, »S« & »T«)
V	Fluorelastomer seals for the sensor electronics housing

d	Stroke length				
X	X	X	X	M	0025...7620 mm
Standard stroke length (mm)		Ordering steps			
25... 500 mm		5 mm			
500... 750 mm		10 mm			
750...1000 mm		25 mm			
1000...2500 mm		50 mm			
2500...5000 mm		100 mm			
5000...7620 mm		250 mm			
X	X	X	X	U	001.0...300.0 mm
Standard stroke length (in.)		Ordering steps			
1... 20 in.		0.2 in.			
20... 30 in.		0.4 in.			
30... 40 in.		1.0 in.			
40...100 in.		2.0 in.			
100...200 in.		4.0 in.			
200...300 in.		10.0 in.			

Non-standard stroke lengths are available; must be encoded in 5 mm/0.1 in. increments.

e	Number of magnets	
X	X	01...30 position(s) (1...30 magnet(s))

f	Connection type		
D	5	6	2 × M12 female connectors (5 pin), 1 × M8 male connector (4 pin)
D	5	8	2 × M12 female connectors (5 pin), 1 × M12 male connector (4 pin)

g	System
1	Standard

h	Output			
U	1	0	1	EtherCAT®, position, velocity and acceleration (1...30 positions)
U	1	1	1	EtherCAT®, position, velocity and acceleration internal linearization (1...30 positions)

NOTICE

- Specify number of magnets for your sensing application and order separately.
- The number of magnets is limited by the stroke length. The minimum allowed distance between magnets (i.e. front face of one to the front face of the next one) is 75 mm (3 in.).
- Use magnets of the same type for multi-position measurement, e.g. 2 × U-magnet (part no. 251 416-2).
- If the option for internal linearization (U111) in **h** "Output" is chosen, select a suitable magnet.

3.3 Nameplate

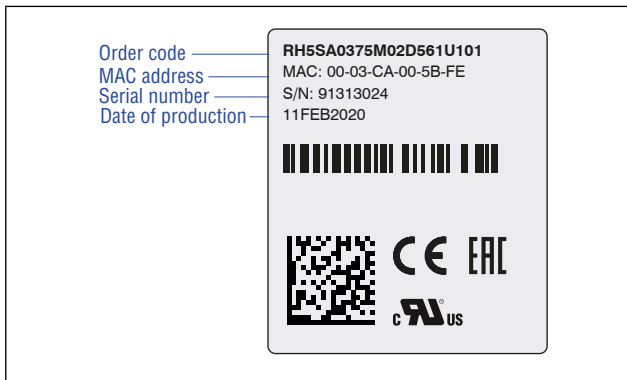


Fig. 1: Example of nameplate of a R-Series V RH5 sensor with EtherCAT® output

3.4 Approvals

- CE certified
- EAC certified
- ETG certified
- UL certified

3.5 Scope of delivery

RP5 (profile sensor):

- Sensor
- Position magnet
- 2 mounting clamps up to 1250 mm (50 in.) stroke length +
1 mounting clamp for each 500 mm (20 in.) additional stroke length

RH5 (rod sensor):

- RH5-B: Base unit, 3 socket screws M4
- RH5-J/M/S/T: Sensor, O-ring

4. Product description and commissioning

4.1 Functionality and system design

Product designation

- Position sensor Temposonics® R-Series V

Sensor model

- Temposonics® R-Series V RP5 (profile sensor)
- Temposonics® R-Series V RH5 (rod sensor)

Stroke length

- Temposonics® R-Series V RP5: 25...6350 mm (1...250 in.)
- Temposonics® R-Series V RH5: 25...7620 mm (1...300 in.)

Output signal

- EtherCAT®

Application

The Temposonics® position sensors are used for measurement and conversion of the length (position) variable in the fields of automated systems and mechanical engineering.

Principle of operation and system construction

The absolute, linear position sensors provided by MTS Sensors rely on the company's proprietary Temposonics® magnetostrictive technology, which can determine position with a high level of precision and robustness. Each Temposonics® position sensor consists of a ferromagnetic waveguide, a position magnet, a strain pulse converter and supporting electronics. The magnet, connected to the object in motion in the application, generates a magnetic field at its location on the waveguide. A short current pulse is applied to the waveguide. This creates a momentary radial magnetic field and torsional strain on the waveguide. The momentary interaction of the magnetic fields releases a torsional strain pulse that propagates the length of the waveguide. When the ultrasonic wave reaches the end of the waveguide it is converted into an electrical signal. Since the speed of the ultrasonic wave in the waveguide is precisely known, the time required to receive the return signal can be converted into a linear position measurement with both high accuracy and repeatability.

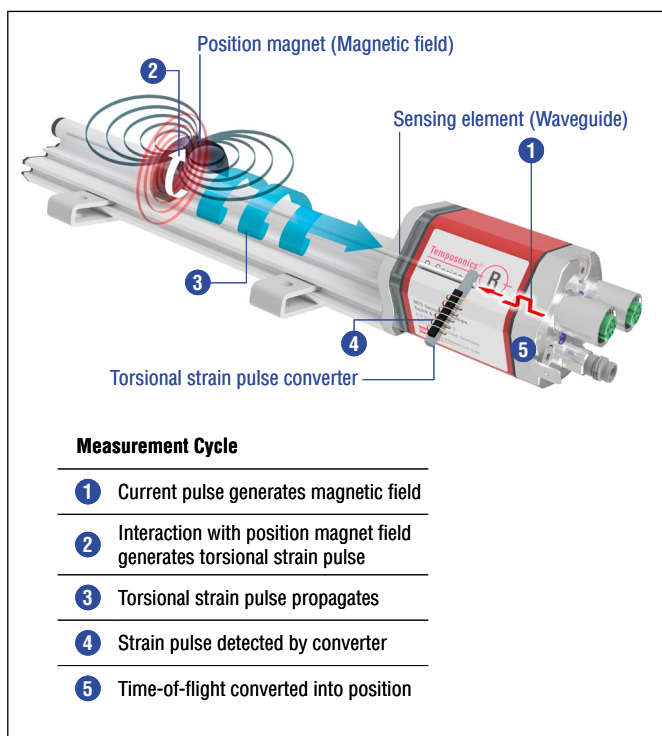


Fig. 2: Time-of-flight based magnetostrictive position sensing principle

Modular mechanical and electronic construction

- The sensor rod or profile protects the inner sensing element.
- The sensor electronics housing, a rugged aluminum construction, contains the complete electronic interface with active signal conditioning. Double shielding ensures high safety of operation and optimum EMC (Electromagnetic Compatibility).
- The external position magnet is a permanent magnet. Mounted on the mobile machine part, it travels along the sensor rod or profile and triggers the measurement through the sensor rod wall.
- The sensor can be connected directly to a control system. Its electronics generates a strictly position-proportional signal output between start and end position.

4.2 Styles and installation of Temposonics® R-Series V RP5

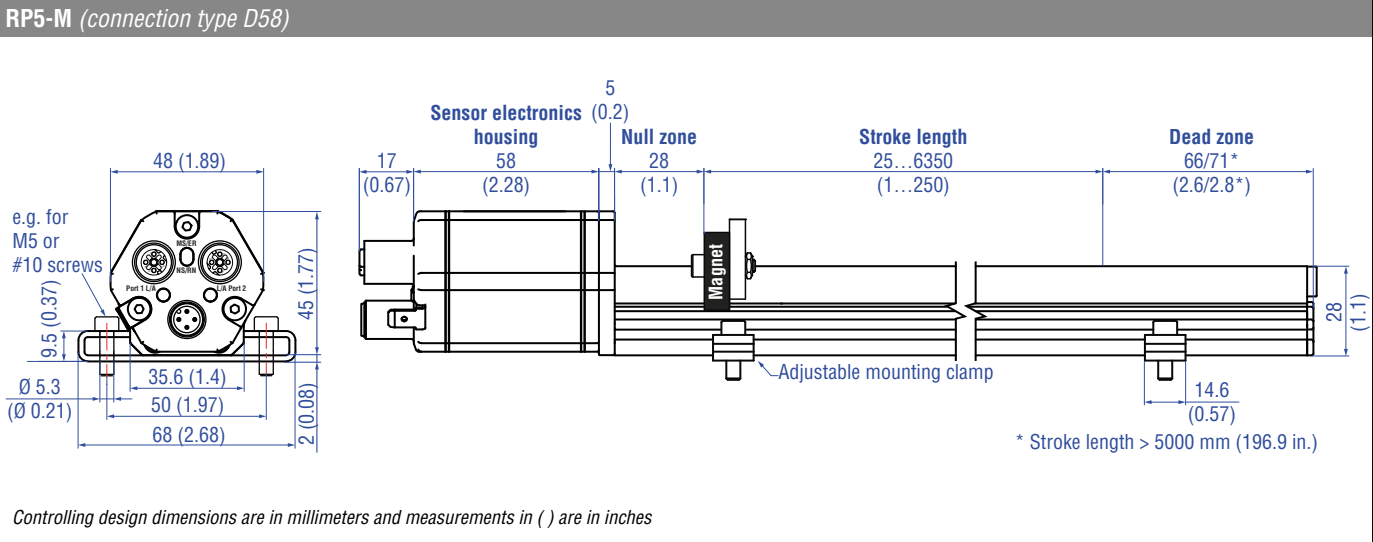


Fig. 3: Temposonics® RP5 with U-magnet

Installation of RP5

The position sensor can be installed in any position. Normally, the sensor is firmly installed and the position magnet is fastened to the mobile machine part. Thus it can travel along the sensor profile. The sensor is fitted on a flat machine surface using the mounting clamps (Fig. 4). A length-dependent number of these clamps are delivered with the sensor and must be distributed over the profile at regular distances. For fastening use M5×20 screws to DIN 6912 that should be tightened with a fastening torque of 5 Nm.

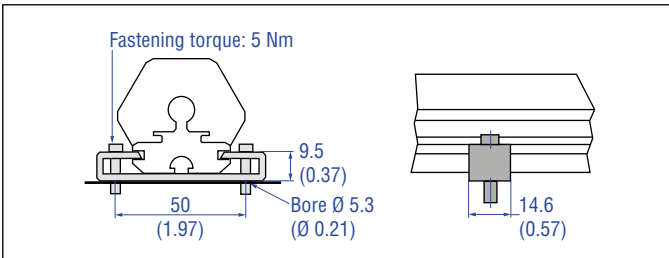


Fig. 4: Mounting clamps (part no. 400 802) with cylinder screw M5×20

Alternative:

If only limited space is available, the profile sensor can be mounted also via the T-rail in the profile bottom using a T-slot nut M5 (part no. 401 602) or a sliding block (Fig. 5).

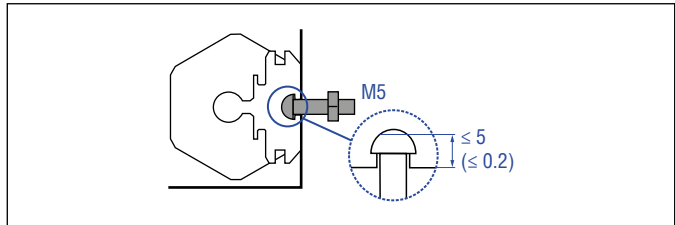
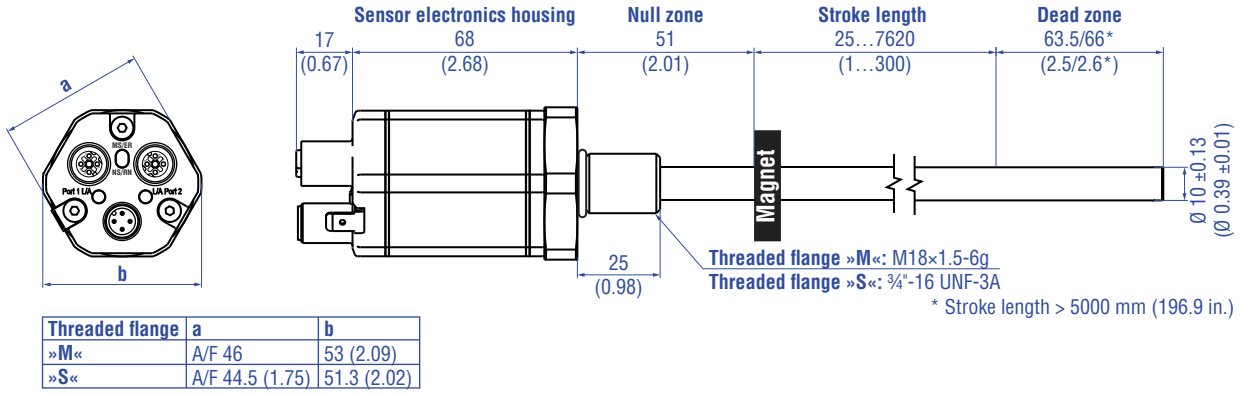


Fig. 5: T-slot nut M5 (part no. 401 602)

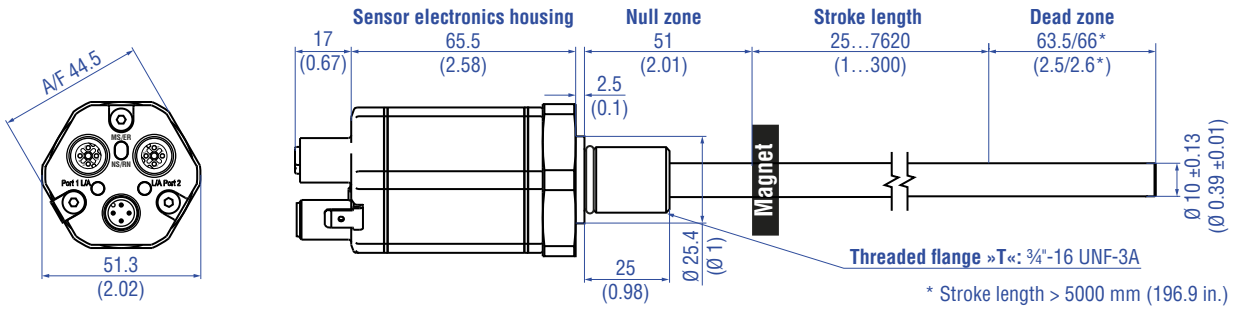
NOTICE
 Take care to mount the sensor in an axially parallel position to avoid damage to magnet and sensor.

4.3 Styles and installation of Temposonics® R-Series V RH5

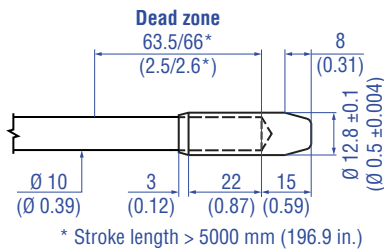
RH5-M/S-A/V – RH5 with threaded flange M18×1.5-6g or ¾"-16 UNF-3A (connection type D58)



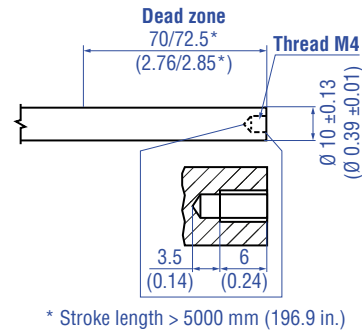
RH5-T-A/V – RH5 with threaded, raised face flange ¾"-16 UNF-3A (connection type D58)



Mechanical option »B«: Bushing on rod end for threaded flange M18×1.5-6g or ¾"×16 UNF-3A



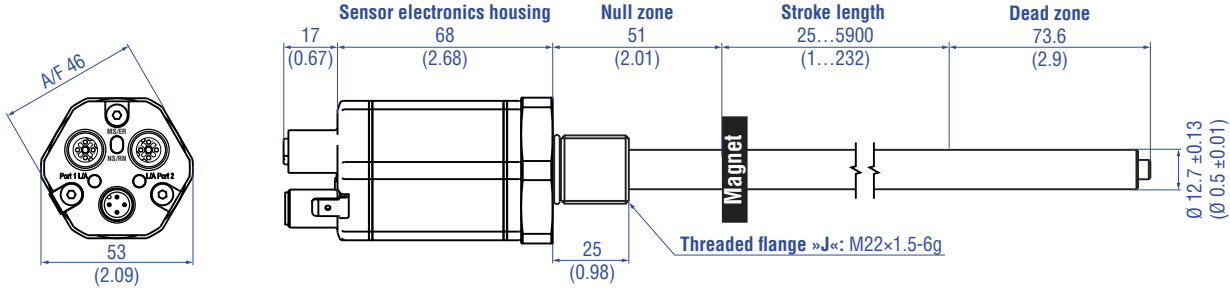
Mechanical option »M«: Thread M4 at rod end for threaded flange M18×1.5-6g or ¾"×16 UNF-3A



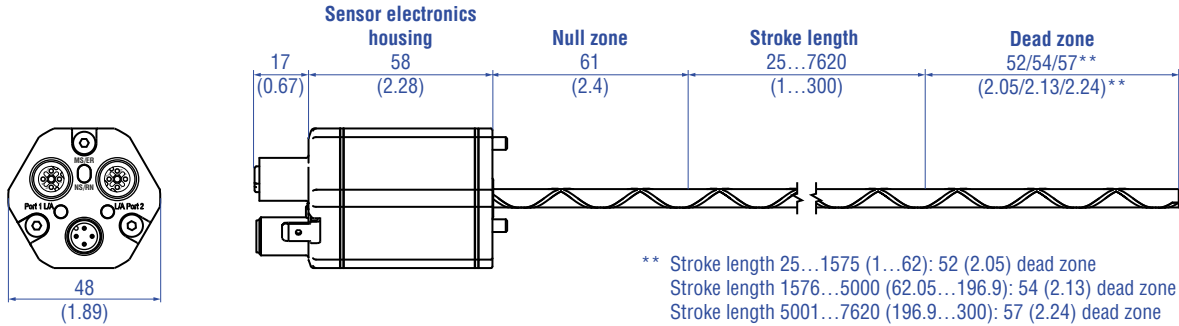
Controlling design dimensions are in millimeters and measurements in () are in inches

Fig. 6: Temposonics® RH5 with ring magnet, part 1

RH5-J-A/-V – RH5 with threaded flange M22×1.5-6g and Ø 12.7 mm rod (connection type D58)



RH5-B-A/-V – RH5 base unit for replacement



Controlling design dimensions are in millimeters and measurements in () are in inches

Fig. 7: Temposonics® RH5 with ring magnet, part 2

Installation of RH5 with threaded flange

Fix the sensor rod via threaded flange M18×1.5-6g, M22×1.5-6g or ¾"-16 UNF-3A.

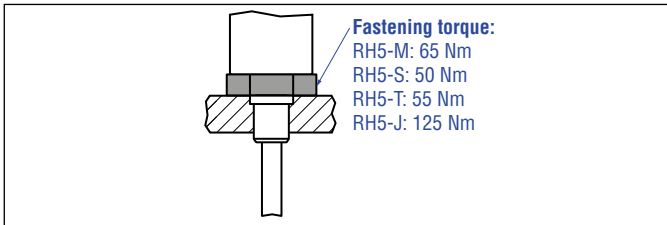


Fig. 8: Mounting example of threaded flange

Installation in a fluid cylinder

The rod-style version has been developed for direct stroke measurement in a fluid cylinder. Mount the sensor via threaded flange or a hex nut.

- Mounted on the face of the piston, the position magnet travels over the rod without touching it and indicates the exact position through the rod wall – independent of the hydraulic fluid.
- The pressure resistant sensor rod is installed into a bore in the piston rod.
- The base unit is mounted by means of only three screws. It is the only part that needs to be replaced if servicing is required, i.e. the hydraulic circuit remains closed. For more information see chapter "4.6 Replacement of sensor" on page 16.

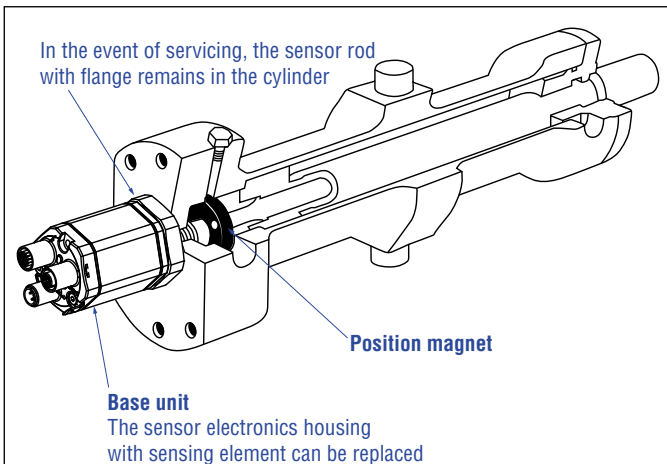


Fig. 9: Sensor in cylinder

Hydraulics sealing

There are two ways to seal the flange contact surface (Fig. 10):

1. A sealing by using an O-ring (e.g. 22.4 × 2.65 mm (0.88 × 0.1 in.), 25.07 × 2.62 mm (0.99 × 0.1 in.)) in a cylinder bottom groove.
2. A sealing by using an O-ring in the undercut.

For threaded flange (¾"-16 UNF-3A):

O-ring 16.4 × 2.2 mm (0.65 × 0.09 in.) (part no. 560 315)

For threaded flange (M18×1.5-6g):

O-ring 15.3 × 2.2 mm (0.60 × 0.09 in.) (part no. 401 133)

For threaded flange (M22×1.5-6g):

O-ring 19.2 × 2.2 mm (0.76 × 0.09 in.) (part no. 561 337)

In the case of threaded flange M18×1.5-6g or M22×1.5-6g, provide a screw hole based on ISO 6149-1 (Fig. 11). See ISO 6149-1 for further information.

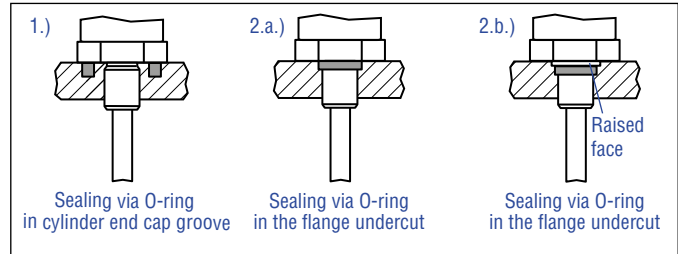


Fig. 10: Possibilities of sealing for threaded flange with flat face 1. + 2.a. (RH5-J/-M/-S) and with raised-face 2.b. (RH5-T)

- Note the fastening torque:
 - RH5-M: 65 Nm
 - RH5-S: 50 Nm
 - RH5-T: 55 Nm
 - RH5-J: 125 Nm
- Seat the flange contact surface completely on the cylinder mounting surface.
- The cylinder manufacturer determines the pressure-resistant gasket (copper gasket, O-ring, etc.).
- The position magnet should not grind on the sensor rod.
- The piston rod drilling (RH5-M/S/T-A/V with rod Ø 10 mm: ≥ Ø 13 mm (≥ Ø 0.51 in.); RH5-M/S/T-B with rod Ø 10 mm: ≥ Ø 16 mm (≥ Ø 0.63 in.); RH5-J-A/V with rod Ø 12.7 mm: ≥ Ø 16 mm (≥ Ø 0.63 in.)) depends on the pressure and piston speed.
- Adhere to the information relating to operating pressure.
- Protect the sensor rod against wear.

Notice for metric threaded flanges

Thread (d ₁ × P)	d ₂	d ₃	d ₄	d ₅ +0.1 0	L ₁ +0.4 0	L ₂	L ₃	L ₄	Z° ±1°
RH5-M-A/V									
M18×1.5-6g	55	≥ 13	24.5	19.8	2.4	28.5	2	26	15°
RH5-M-B									
M18×1.5-6g	55	≥ 16	24.5	19.8	2.4	28.5	2	26	15°
RH5-J-A/V									
M22×1.5-6g	55	≥ 16	27.5	23.8	2.4	28.5	2	26	15°

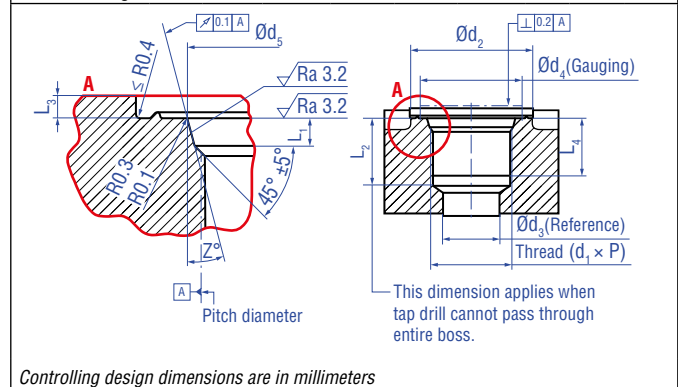


Fig. 11: Notice for metric threaded flange M18×1.5-6g/M22×1.5-6g based on DIN ISO 6149-1

4.4 Magnet installation

Typical use of magnets





Magnet	Typical sensors	Benefits
 Ring magnets	Rod model (RH5)	<ul style="list-style-type: none"> Rotationally symmetrical magnetic field
 U-magnets	Profile & rod models (RP5, RH5)	<ul style="list-style-type: none"> Height tolerances can be compensated, because the magnet can be lifted off
 Block magnets	Profile & rod models (RP5, RH5)	<ul style="list-style-type: none"> Height tolerances can be compensated, because the magnet can be lifted off
 Magnet sliders	Profile models (RP5)	<ul style="list-style-type: none"> The magnet is guided by the profile The distance between the magnet and the waveguide is strictly defined Easy coupling via the ball joint

Fig. 12: Typical use of magnets

Mounting ring magnets, U-magnets & block magnets

Install the magnet using non-magnetic material for mounting device, screws, spacers etc.. The magnet must not grind on the sensor rod. Alignment errors are compensated via the air gap.

- Permissible surface pressure: Max. 40 N/mm² (only for ring magnets and U-magnets)
- Fastening torque for M4 screws: 1 Nm; use washers, if necessary
- Minimum distance between position magnet and any magnetic material has to be 15 mm (0.6 in.) (Fig. 15).
- If no other option exists and magnetic material is used, observe the specified dimensions (Fig. 15).

NOTICE

Mount ring magnets and U-magnets concentrically. Mount block magnets centrally over the sensor rod or the sensor profile. The maximum permissible air gap must not be exceeded (Fig. 13/ Fig. 14). Take care to mount the primary sensor axis in parallel to the magnet path in order to avoid damage to the carriage, magnet and sensor rod.

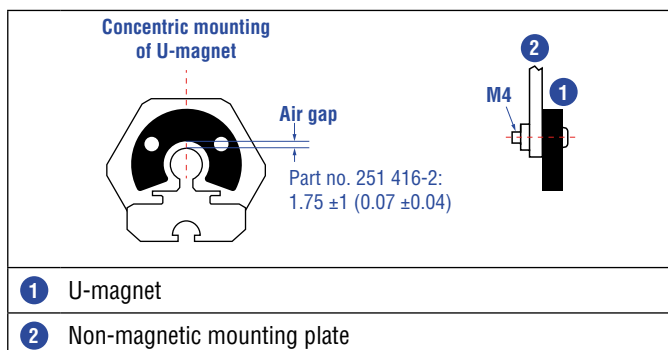


Fig. 13: Mounting of U-magnet (part no. 251 416-2)

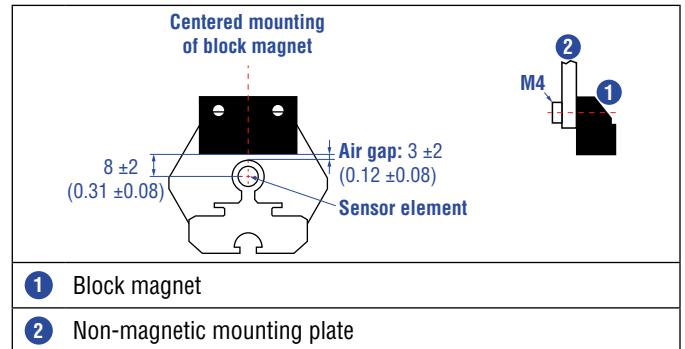


Fig. 14: Mounting of block magnet (part no. 403 448)

Magnet mounting with magnetic material

When using magnetic material the dimensions of Fig. 15 must be observed.

- If the position magnet aligns with the drilled piston rod
- If the position magnet is set further into the drilled piston rod, install another non-magnetic spacer (e.g. part no. 400 633) above the magnet.

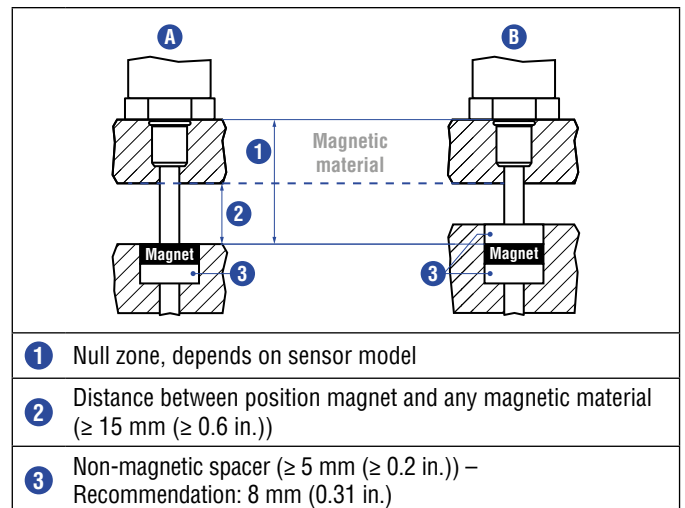


Fig. 15: Installation with magnetic material

Sensors with stroke lengths ≥ 1 meter (3.3 ft.)

Support horizontally installed sensors with a stroke length from 1 meter (3.3 ft.) mechanically at the rod end. Without using a support, the sensor rod bends over, and the rod and the position magnet may be damaged. A false measurement result is also possible. Longer rods require evenly distributed mechanical support over the entire length (e.g. part no. 561 481). Use an U-magnet (Fig. 16) for measurement.

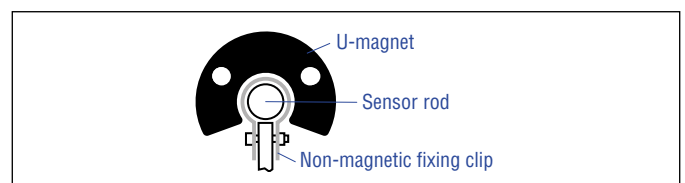


Fig. 16: Example of sensor support (part no. 561 481)

Controlling design dimensions are in millimeters and measurements in () are in inches

Start- and end positions of the position magnets

Consider the start and end positions of the position magnets during the installation. To ensure that the entire stroke length is electrically usable, the position magnet must be mechanically mounted as follows.

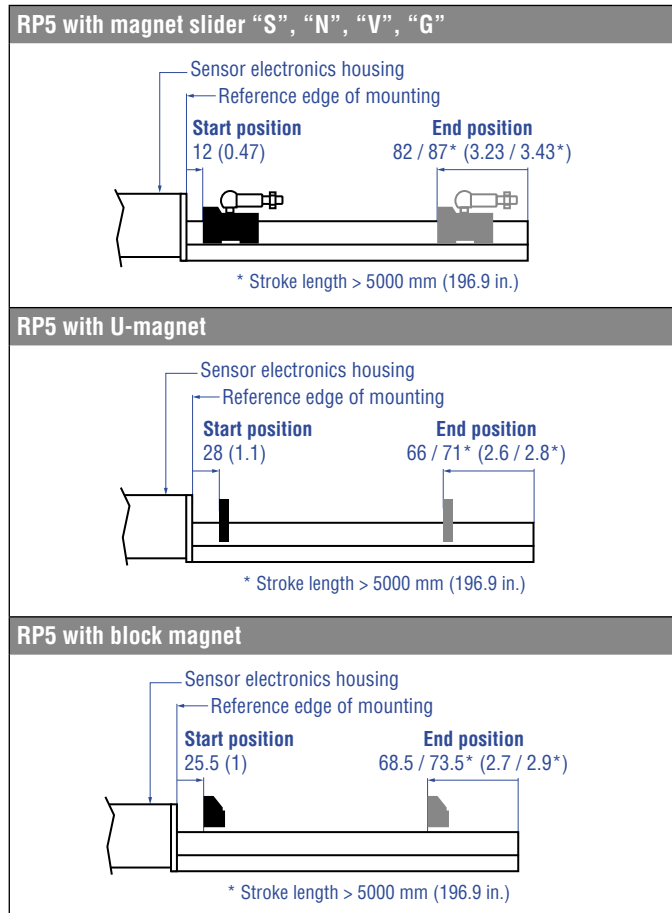


Fig. 17: Start- & end positions of magnets, part 1

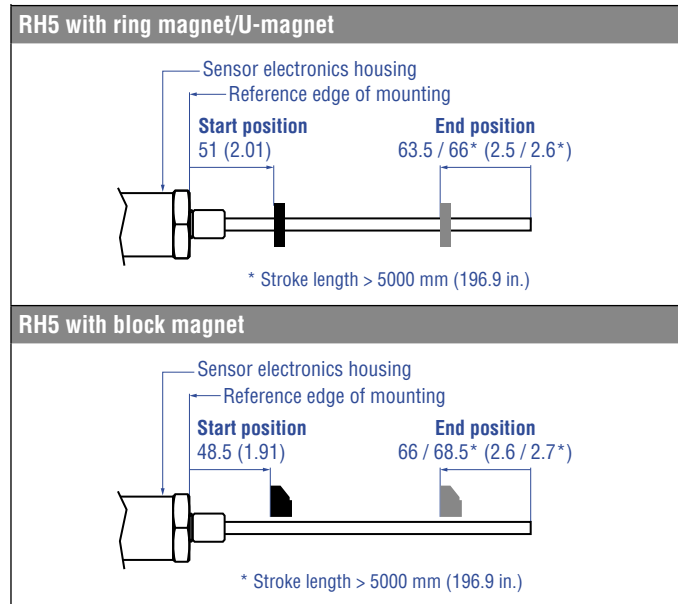


Fig. 18: Start- & end positions of magnets, part 2

NOTICE

On all sensors, the areas left and right of the active stroke length are provided for null and dead zone. These zones should not be used for measurement, however the active stroke length can be exceeded.

Multi-position measurement

The minimum distance between the magnets is 75 mm (3 in.).

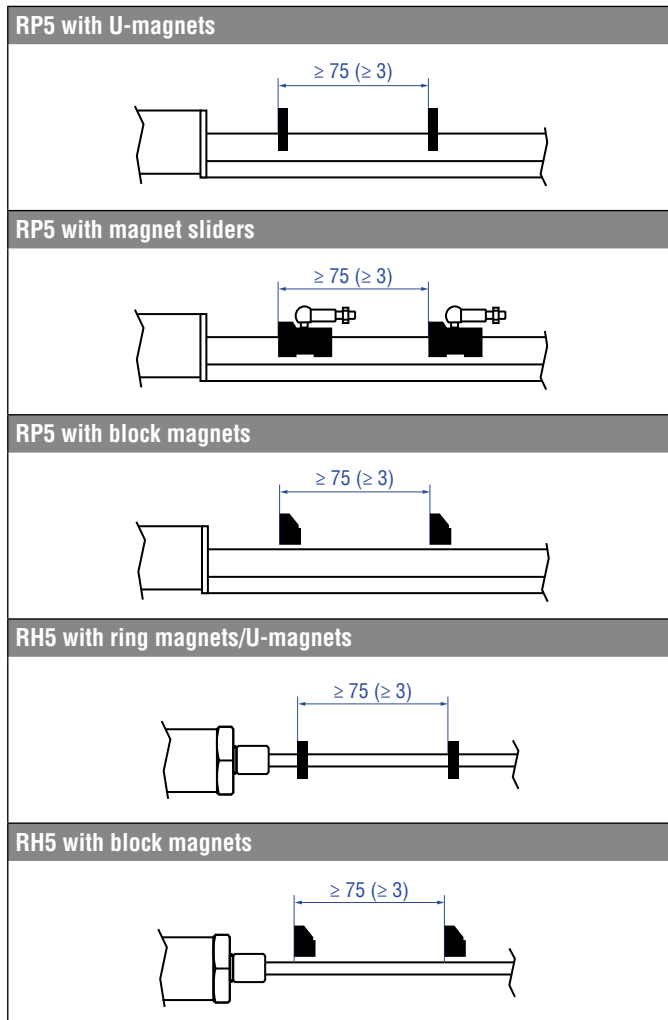


Fig. 19: Minimum distance for multi-position measurement

NOTICE

For multi-position measurement, use magnets of the same type e.g. 2 × U-magnet (part no. 251 416-2). Do not underscore the minimum distance between the magnets of 75 mm (3 in.) for multi-position measurement. Contact MTS Sensors if you need a magnet distance < 75 mm (3 in.).

4.5 Alignment of the magnet with the option “internal linearization”

The internal linearization offers improved linearity of the sensor. The option must be specified in the order code of the sensor. The internal linearization is set for the sensor during production.

A sensor with internal linearization is delivered with the magnet with which the sensor was calibrated during production. In order to achieve the best possible result, MTS Sensors recommends to operate the sensor with the supplied magnet.

For the internal linearization, the following magnets can be used:

- Ring magnet OD33 (part no. 253 620), only for RH5
- U-magnet OD33 (part no. 254 226)
- Ring magnet OD25.4 (part no. 253 621), only for RH5
- Magnet slider S (part no. 252 182), only for RP5
- Magnet slider N (part no. 252 183), only for RP5
- Magnet slider V (part no. 252 184), only for RP5
- Magnet slider G (part no. 253 421), only for RP5

The ring magnet and U-magnet will be marked for the internal linearization. During the installation, the magnets have to be aligned to the sensor electronics housing, see Fig. 20, Fig. 21 and Fig. 22.

For RH5 EtherCAT® sensors with ring magnet applies:

- Install the magnet until the marking on the magnet points to the sensor electronics housing.
- The marking on the magnet points to the same direction as the elongated status LED in the cap of the sensor electronics housing.

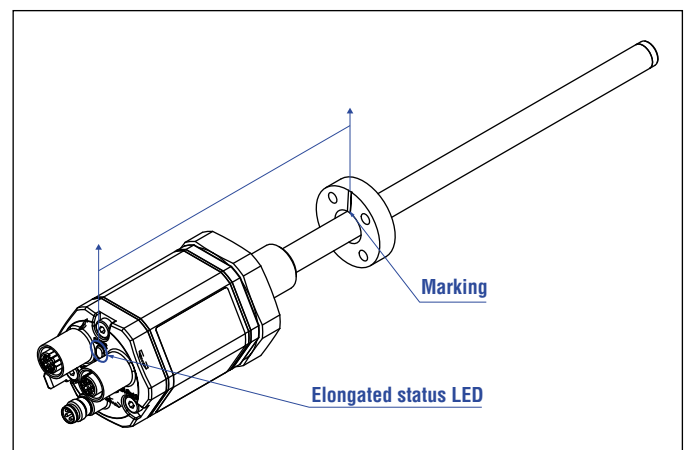


Fig. 20: Alignment of ring magnet for RH5 EtherCAT® with internal linearization

For RP5 EtherCAT® sensors with U-magnet applies:

- Install the magnet until the marking on the magnet points to the sensor electronics housing.
- The marking on the magnet points to the same direction as the elongated status LED in the cap of the sensor electronics housing.

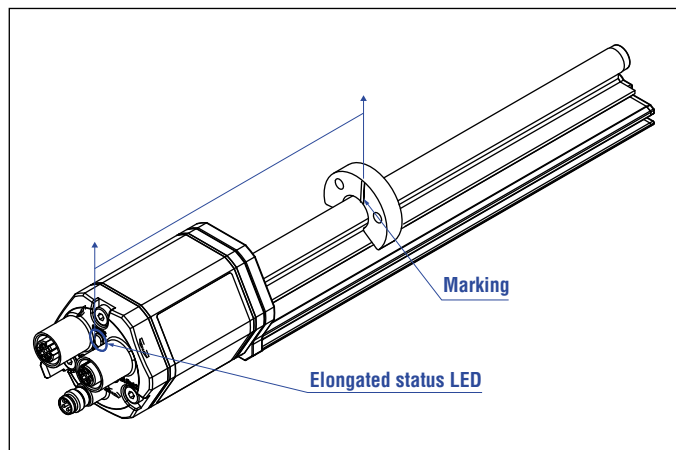


Fig. 21: Magnet alignment of U-magnet for RP5 EtherCAT® with internal linearization

For RP5 EtherCAT® sensors with magnet slider applies:

- ① Install the magnet sliders "S", "N" and "G" until the additional hole in the magnet points towards the sensor electronics housing.
- ② Install the magnet slider "V" until the joint points to the end of the profile.

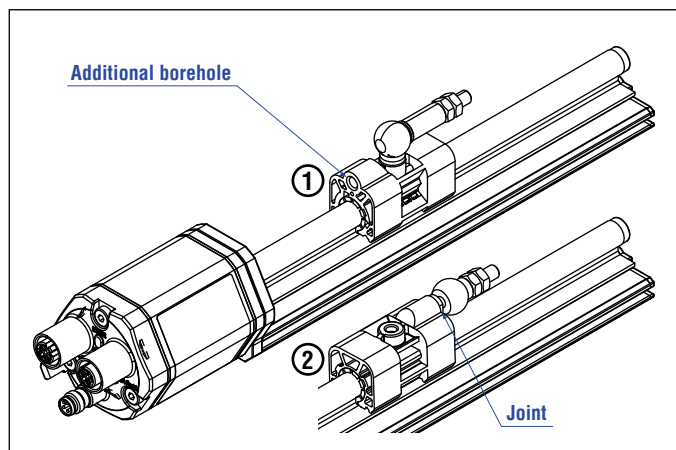


Fig. 22: Magnet alignment of magnet slider for RP5 EtherCAT® with internal linearization

The internal linearization of the sensor is carried out under the following conditions:

- Supply voltage +24 VDC ±0.5
- Operating time > 30 min
- No shock and no vibration
- Eccentricity of the position magnet to central axis of the sensor < 0.1 mm

NOTICE

The generated linearization might deviate from the linearity tolerances regarding different environmental conditions. In addition, the use of a different position magnet or more position magnets may cause differences.

4.6 Replacement of sensor

The base unit of the sensor model RH5-B is replaceable as shown in Fig. 23 and Fig. 24 for the sensor designs »M«, »S« and »T«. The sensor can be replaced without interrupting the hydraulic circuit.

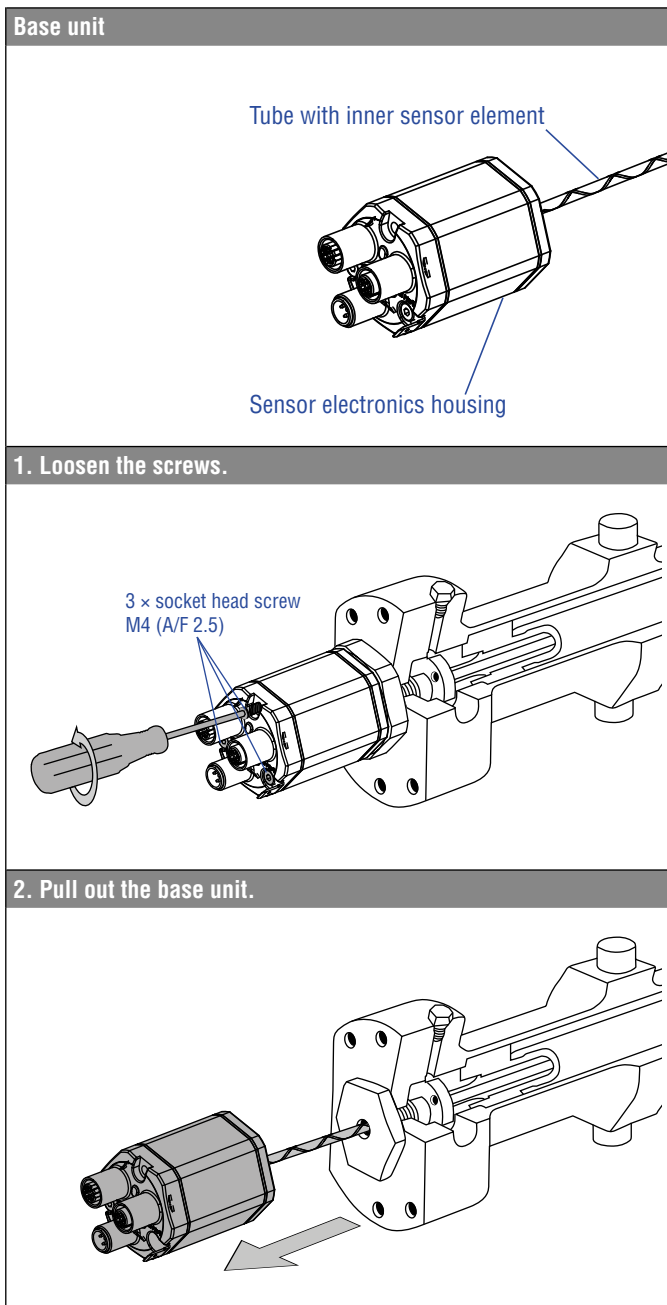


Fig. 23: Replacement of the base unit (e.g. RH5 sensor), part 1

3. Insert the new base unit.
Mount the ground lug on a screw.
Tighten the screws.

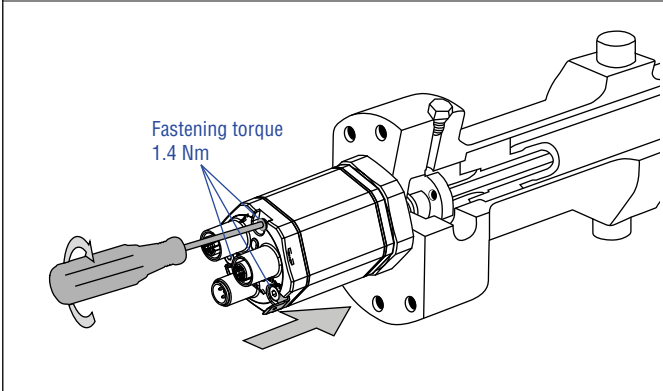


Fig. 24: Replacement of the base unit (e.g. RH5 sensor), part 2

NOTICE

- When replacing the base unit, make sure that no humidity enters the sensor tube. This may damage the sensor.
- Secure the base unit screws, e.g. using Loctite 243, before re-installing.
- If the R-Series V replaces a predecessor model of the R-Series, the plastic tube in the sensor rod must be removed.

4.7 Electrical connections

Placement of installation and cabling have decisive influence on the sensor's electromagnetic compatibility (EMC). Hence correct installation of this active electronic system and the EMC of the entire system must be ensured by using suitable metal connectors, shielded cables and grounding. Overvoltages or faulty connections can damage its electronics despite protection against wrong polarity.

NOTICE

1. Do not mount the sensors in the area of strong magnetic or electric noise fields.
2. Never connect/disconnect the sensor when voltage is applied.

Instructions for connection

- Use low-resistant twisted pair and shielded cables. Connect the shield to ground externally via the controller equipment.
- Keep control and signal cables separate from power cables and sufficiently far away from motor cables, frequency inverters, valve lines, relays, etc..
- Use only connectors with metal housing and connect the shielding to the connector housing.
- Keep the connection surface at both shielding ends as large as possible. Connect the cable clamps to function as a ground.
- Keep all non-shielded leads as short as possible.
- Keep the earth connection as short as possible with a large cross section. Avoid ground loops.
- With potential differences between machine and electronics earth connections, no compensating currents are allowed to flow across the cable shielding.

Recommendation:

Install potential compensating leads with large cross section, or use cables with separate double shielding, and connect only one end of the shield.

- Use only stabilized power supplies in compliance with the specified electrical ratings.

Grounding of profile and rod sensors

Connect the sensor electronics housing to machine ground. Ground sensor types RP5 and RH5 via ground lug as shown in Fig. 25. In addition you can ground the sensor type RH5 via thread.

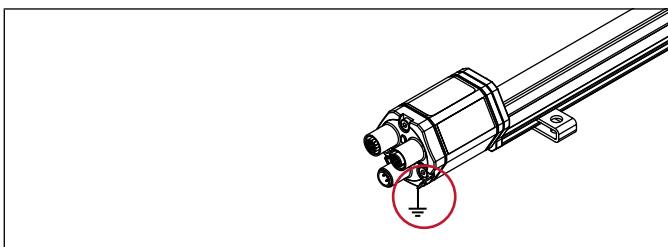


Fig. 25: Grounding via ground lug (e.g. RP5)

Connector wiring

Connect the sensor directly to the control system, indicator or other evaluating systems as follows:

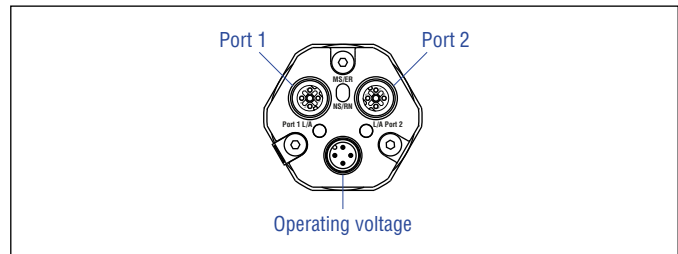
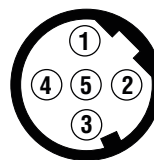


Fig. 26: Location of connections (e.g. D58 connector wiring)

D56

Port 1 – Signal

M12 female connector (D-coded)

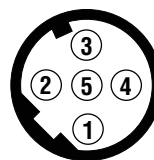


View on sensor

Pin	Function
1	Tx (+)
2	Rx (+)
3	Tx (-)
4	Rx (-)
5	Not connected

Port 2 – Signal

M12 female connector (D-coded)



View on sensor

Power supply

M8 male connector



View on sensor

Pin	Function
1	+12...30 VDC (±20 %)
2	Not connected
3	DC Ground (0 V)
4	Not connected

Fig. 27: Connector wiring D56

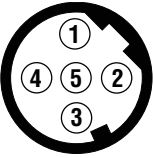


D58		
Port 1 – Signal		
M12 female connector (D-coded)	Pin	Function
 <p>View on sensor</p>	1	Tx (+)
	2	Rx (+)
	3	Tx (-)
	4	Rx (-)
	5	Not connected
Port 2 – Signal		
M12 female connector (D-coded)	Pin	Function
 <p>View on sensor</p>	1	Tx (+)
	2	Rx (+)
	3	Tx (-)
	4	Rx (-)
	5	Not connected
Power supply		
M12 male connector (A-coded)	Pin	Function
 <p>View on sensor</p>	1	+12...30 VDC (±20 %)
	2	Not connected
	3	DC Ground (0 V)
	4	Not connected

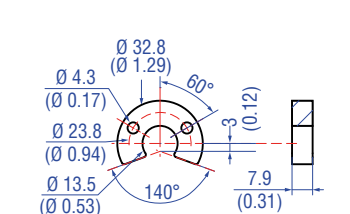
Fig. 28: Connector wiring D58

4.8 Frequently ordered accessories for RP5 design – Additional options available in our [Accessories Guide](#) 551 444

Position magnets

<p>Magnet slider S, joint at top Part no. 252 182</p> <p>Material: GRP, magnet hard ferrite Weight: Approx. 35 g Operating temperature: -40...+85 °C (-40...+185 °F)</p>	<p>Magnet slider V, joint at front Part no. 252 184</p> <p>Material: GRP, magnet hard ferrite Weight: Approx. 35 g Operating temperature: -40...+85 °C (-40...+185 °F)</p>	<p>Magnet slider N longer ball-joint arm Part no. 252 183</p> <p>Material: GRP, magnet hard ferrite Weight: Approx. 35 g Operating temperature: -40...+85 °C (-40...+185 °F)</p>	<p>Magnet slider G, backlash free Part no. 253 421</p> <p>Material: GRP, magnet hard ferrite Weight: Approx. 25 g Operating temperature: -40...+85 °C (-40...+185 °F)</p>

Position magnets

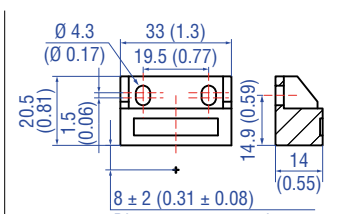


U-magnet OD33
Part no. 251 416-2

Material: PA ferrite GF20
Weight: Approx. 11 g
Surface pressure: Max. 40 N/mm²
Fastening torque for M4 screws: 1 Nm
Operating temperature:
-40...+105 °C (-40...+221 °F)

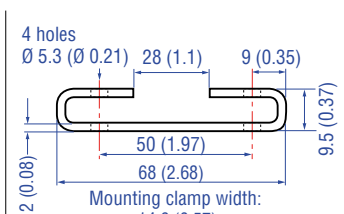
Marked version for sensors with inter-
nal linearization: Part no. 254 226

Mounting accessories



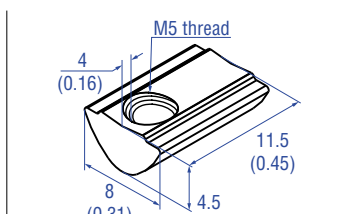
Block magnet L
Part no. 403 448

Material: Plastic carrier with hard ferrite
magnet
Weight: Approx. 20 g
Fastening torque for M4 screws: 1 Nm
Operating temperature:
-40...+75 °C (-40...+167 °F)
This magnet may influence the sensor
performance specifications for some
applications.



Mounting clamp
Part no. 400 802

Material: Stainless steel (AISI 304)

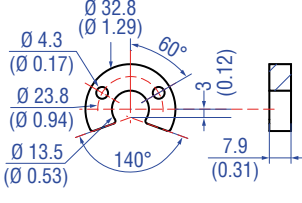
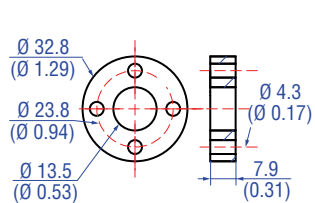
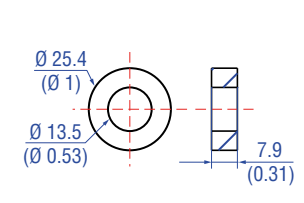
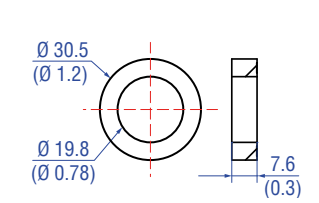


T-nut
Part no. 401 602

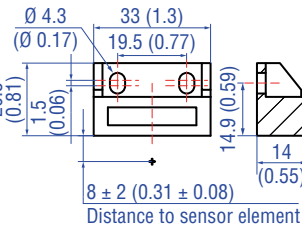
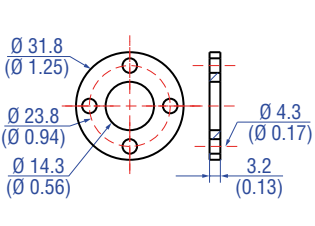
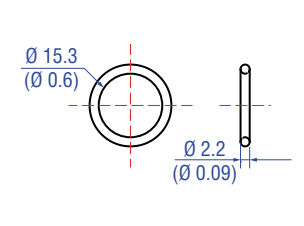
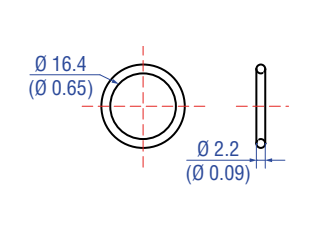
Fastening torque for M5 screw: 4.5 Nm

4.9 Frequently ordered accessories for RH5 design – Additional options available in our [Accessories Guide](#) 551 444

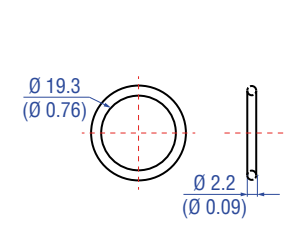
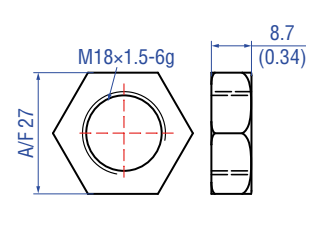
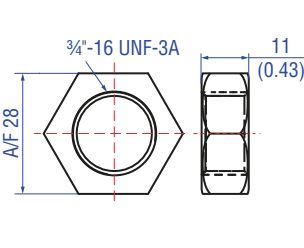
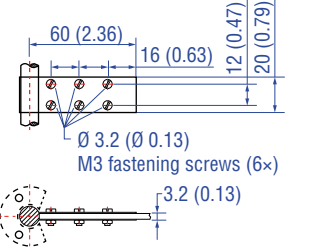
Position magnets

			
<p>U-magnet OD33 Part no. 251 416-2</p> <p>Material: PA ferrite GF20 Weight: Approx. 11 g Surface pressure: Max. 40 N/mm² Fastening torque for M4 screws: 1 Nm Operating temperature: -40...+105 °C (-40...+221 °F)</p> <p>Marked version for sensors with internal linearization: Part no. 254 226</p>	<p>Ring magnet OD33 Part no. 201 542-2</p> <p>Material: PA ferrite GF20 Weight: Approx. 14 g Surface pressure: Max. 40 N/mm² Fastening torque for M4 screws: 1 Nm Operating temperature: -40...+105 °C (-40...+221 °F)</p> <p>Marked version for sensors with internal linearization: Part no. 253 620</p>	<p>Ring magnet OD25.4 Part no. 400 533</p> <p>Material: PA ferrite Weight: Approx. 10 g Surface pressure: Max. 40 N/mm² Operating temperature: -40...+105 °C (-40...+221 °F)</p> <p>Marked version for sensors with internal linearization: Part no. 253 621</p>	<p>Ring magnet Part no. 402 316</p> <p>Material: PA ferrite coated Weight: Approx. 13 g Surface pressure: Max. 20 N/mm² Operating temperature: -40...+100 °C (-40...+212 °F)</p>

Position magnet Magnet spacer O-rings

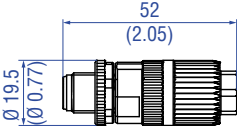
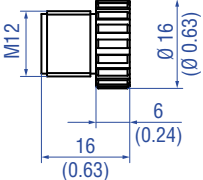
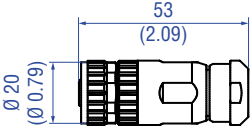
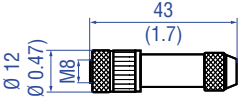
			
<p>Block magnet L Part no. 403 448</p> <p>Material: Plastic carrier with hard ferrite magnet Weight: Approx. 20 g Fastening torque for M4 screws: 1 Nm Operating temperature: -40...+75 °C (-40...+167 °F)</p> <p>This magnet may influence the sensor performance specifications for some applications.</p>	<p>Magnet spacer Part no. 400 633</p> <p>Material: Aluminum Weight: Approx. 5 g Surface pressure: Max. 20 N/mm² Fastening torque for M4 screws: 1 Nm</p>	<p>O-ring for threaded flange M18x1.5-6g Part no. 401 133</p> <p>Material: Fluoroelastomer Durometer: 75 ± 5 Shore A Operating temperature: -40...+204 °C (-40...+400 °F)</p>	<p>O-ring for threaded flange 3/4-16 UNF-3A Part no. 560 315</p> <p>Material: Fluoroelastomer Durometer: 75 ± 5 Shore A Operating temperature: -40...+204 °C (-40...+400 °F)</p>

O-ring Mounting accessories

			
<p>O-ring for threaded flange M22x1.5-6g Part no. 561 337</p> <p>Material: FPM Durometer: 75 Shore A Operating temperature: -20...+200 °C (-6...+392 °F)</p>	<p>Hex jam nut M18x1.5-6g Part no. 500 018</p> <p>Material: Steel, zinc plated</p>	<p>Hex jam nut 3/4-16 UNF-3A Part no. 500 015</p> <p>Material: Zinc plated</p>	<p>Fixing clip Part no. 561 481</p> <p>Application: Used to secure sensor rods (Ø 10 mm (Ø 0.39 in.)) when using an U-magnet or block magnet Material: Brass, non-magnetic</p>


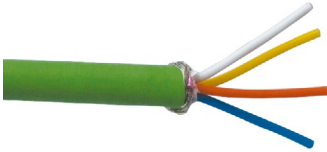


4.10 Frequently ordered accessories for EtherCAT® output – Additional options available in our [Accessories Guide](#)  [551 444](#)

Cable connectors*

			
<p>Signal connector M12 D-coded male (4 pin), straight Part no. 370 523</p>	<p>Signal connector M12 end cap Part no. 370 537</p>	<p>Power connector M12 A-coded female (5 pin), straight Part no. 370 677</p>	<p>Power connector M8 female (4 pin), straight Part no. 370 504</p>
<p>Material: Zinc nickel-plated Termination: Insulation-displacement Cable Ø: 5.5...7.2 mm (0.2...0.28 in.) Wire: 24 AWG – 22 AWG Operating temperature: –25...+85 °C (–13...+185 °F) Ingress protection: IP65/IP67 (correctly fitted) Fastening torque: 0.6 Nm</p>	<p>Female connectors M12 should be covered by this protective cap Material: Brass nickel-plated Ingress protection: IP67 (correctly fitted) Fastening torque: 0.39...0.49 Nm</p>	<p>Material: GD-Zn, Ni Termination: Screw Contact insert: CuZn Cable Ø: 4...8 mm (0.16...0.31 in.) Wire: 1.5 mm² Operating temperature: –30...+85 °C (–22...+185 °F) Ingress protection: IP67 (correctly fitted) Fastening torque: 0.6 Nm</p>	<p>Material: CuZn nickel plated Termination: Solder Cable Ø: 3.5...5 mm (0.14...0.28 in.) Wire: 0.25 mm² Operating temperature: –40...+85 °C (–40...+185 °F) Ingress protection: IP67 (correctly fitted) Fastening torque: 0.5 Nm</p>

Programming kit

Cables

			
<p>TempoLink kit for Temposonics® R-Series V Part no. TL-1-0-EM08 (D56) Part no. TL-1-0-EM12 (D58)</p>	<p>PUR signal cable Part no. 530 125</p>	<p>Signal cable with M12 D-coded male connector (4 pin), straight – M12 D-coded, male connector (4 pin), straight Part no. 530 064</p>	<p>Signal cable with M12 D-coded male connector (4 pin), straight – RJ45 male connector, straight Part no. 530 065</p>
<ul style="list-style-type: none"> • Connect wirelessly via Wi-Fi enabled device or via USB with the diagnostic tool • Simple connectivity to the sensor via 24 VDC power line (permissible cable length: 30 m) • User friendly interface for mobile devices and desktop computers • See product brief “TempoLink smart assistant” (document part no.: 551976) for further information 	<p>Material: PUR jacket; green Features: Cat 5, highly flexible, halogen free, energy chain capable, mostly oil & flame resistant Cable Ø: 6.5 mm (0.26 in.) Cross section: 2 × 2 × 0.35 mm² (22 AWG) Operating temperature: –20...+60 °C (–4...+140 °F)</p>	<p>Material: PUR jacket; green Features: Cat 5e Cable length: 5 m (16.4 ft) Cable Ø: 6.5 mm (0.26 in.) Ingress protection: IP65/IP67/IP68 (correctly fitted) Operating temperature: –30...+70 °C (–22...+158 °F)</p>	<p>Material: PUR jacket; green Features: Cat 5e Cable length: 5 m (16.4 ft) Cable Ø: 6.5 mm (0.26 in.) Ingress protection M12 connector: IP67 (correctly fitted) Ingress protection RJ45 connector: IP20 (correctly fitted) Operating temperature: –30...+70 °C (–22...+158 °F)</p>

*/ Follow the manufacturer’s mounting instructions

Controlling design dimensions are in millimeters and measurements in () are in inches

Cables



PVC power cable
Part no. 530 108

Material: PVC jacket; gray
Features: Shielded, flexible,
mostly flame resistant
Cable Ø: 4.9 mm (0.19 in.)
Cross section: 3 × 0.34 mm²
Bending radius: 10 × D
Operating temperature:
-30...+80 °C (-22...+176 °F)



Power cable with M8 female connector
(4 pin), straight – pigtail
Part no. 530 066 (5 m (16.4 ft.))
Part no. 530 096 (10 m (32.8 ft.))
Part no. 530 093 (15 m (49.2 ft.))

Material: PUR jacket; gray
Features: Shielded
Cable Ø: 8 mm (0.3 in.)
Operating temperature:
-40...+90 °C (-40...+194 °F)

5. Operation

5.1 Initial start-up

The position sensor R-Series V EtherCAT® transfers position, velocity and acceleration values via the EtherCAT® output. EtherCAT® means Ethernet for Control Automation Technology and is an Industrial Ethernet interface. It is managed by the EtherCAT Technology Group (ETG). The sensor and the corresponding ESI (EtherCAT Slave Information) file are certified by the ETG.

NOTICE

Observe during commissioning

1. Before initial switch-on, check carefully if the sensor has been connected correctly.
2. Position the magnet in the measuring range of the sensor during first commissioning and after replacement of the magnet.
3. Ensure that the sensor control system cannot react in an uncontrolled way when switching on.
4. Ensure that the sensor is ready and in operation mode after switching on. The Run status LED is green.
5. Check the preset span start and end values of the measuring range (see chapter 4.4) and correct them via the customer's control system, if necessary.

5.2 LED status

A diagnostic display on the lid of the sensor informs about the current status of the sensor. The R-Series V EtherCAT® is equipped with three LEDs:

- LED for status indication (condition indicator)
- LED for link activity of port 1 (port 1 L/A)
- LED for link activity of port 2 (port 2 L/A)

EtherCAT® LED status

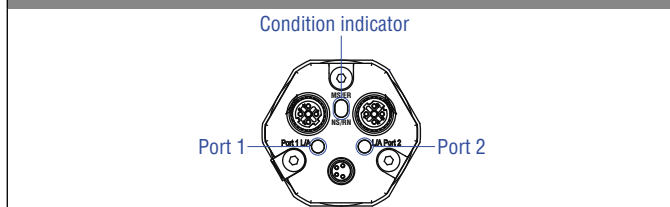
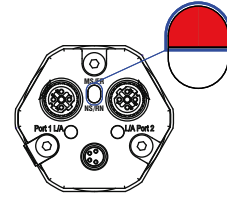


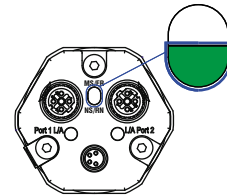
Fig. 29: LED status, part 1

Error status LED



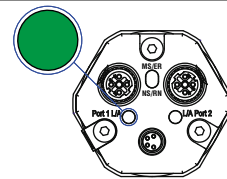
Red	Information
● ON	Critical error
◐ Flashing 1×	Slave drive state changed
◐ Flashing 2×	Watchdog timer error
◑ Blinking	Configuration error
○ OFF	Communication OK

Run status LED



Green	Information
● ON	OP mode
◐ Flashing 1×	SAFE-OP mode
◑ Blinking	PRE-OP mode
◑ Flickering	Booting process
○ OFF	INIT mode

Port 1 L/A (IN)



Green	Information
● ON	Link activity on port 1
◑ Blinking	Data transfer on port 1
○ OFF	Port closed

Fig. 30: LED status, part 2

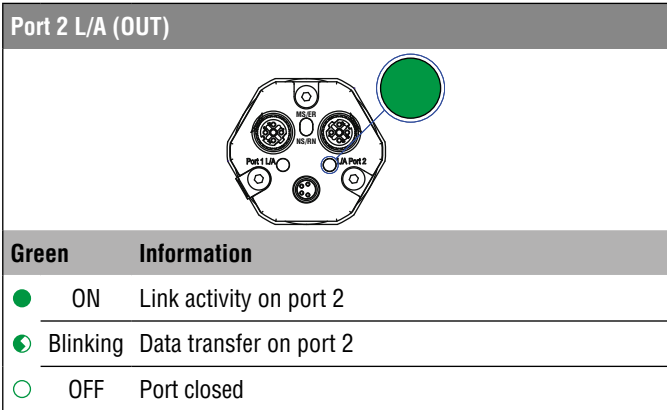


Fig. 31: LED status, part 3

5.3 Topologies and downstream devices

EtherCAT® supports flexible topologies when building a network. For example, line, star, ring and tree structures are possible. The two ports of the R-Series V EtherCAT® are coupled with each other inside the sensor. Therefore, a power failure of the sensor leads to the interruption of communication to the devices connected behind it. This can be avoided, for example, by extending a line structure to a ring structure.

6. Implementation and configuration of R-Series V EtherCAT® with TwinCAT 3

6.1 General information

This instruction describes as an example the implementation and configuration of a Temposonics® R-Series V sensor with EtherCAT® in TwinCAT 3 (The Windows Control and Automation Technology) from Beckhoff Automation GmbH & Co. KG. In principle, you can integrate the sensor into an EtherCAT® network using any EtherCAT®-compatible software and hardware.

NOTICE

Follow the information given in the controller operation manual.

6.2 Implementation of R-Series V EtherCAT® in TwinCAT 3

In order to integrate R-Series V EtherCAT® into TwinCAT 3, you must first provide the ESI file of the sensor for TwinCAT 3. An ESI file (EtherCAT Slave Information) describes the properties and functions of an EtherCAT® slave. The ESI file, which is based on XML, contains all relevant data that are important both for the implementation of the device in the controller and for data exchange during operation. The ESI file of the R-Series V EtherCAT® is packed in a zip file which is available for download on our homepage www.mtssensors.com. Download the ESI file and save it on your computer. To include the ESI file in TwinCAT, unpack the file and place the XML file in the TwinCAT 3 installation directory in the "Config\Io\EtherCAT" subdirectory. Then start TwinCAT 3.

If you have stored the ESI file in the installation directory when TwinCAT is already running, you can make the device description file known to TwinCAT later. To do this, select in the menu bar "File" the entry "EtherCAT Devices" → "Reload Device Descriptions" (Fig. 32).

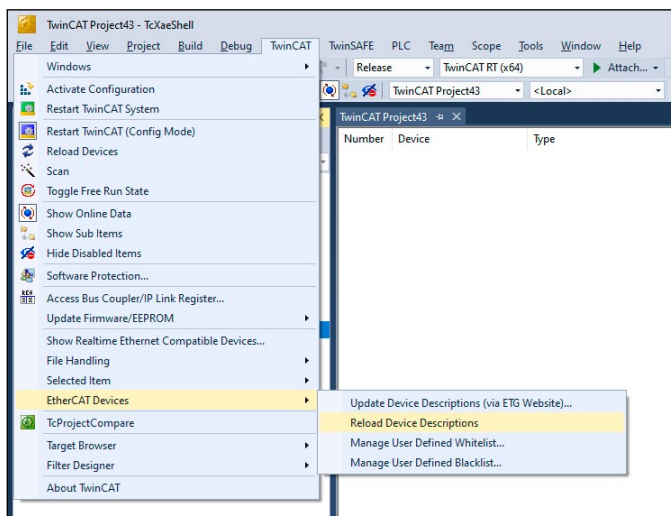


Fig. 32: Subsequent publication of device description files in TwinCAT 3

Fig. 33 shows the TwinCAT user interface in configuration mode (Config mode) after a project has been created and a master integrated. You can implement a slave such as the R-Series V EtherCAT® by selecting in the Solution Explorer in the tree the entry "I/O → Devices → Devices 1 (EtherCAT)". A right mouse click opens a menu. In this menu click the entry "Scan..." (Fig. 34). TwinCAT then searches for slaves in the network. In EtherCAT® this process is known as "Scan for boxes".

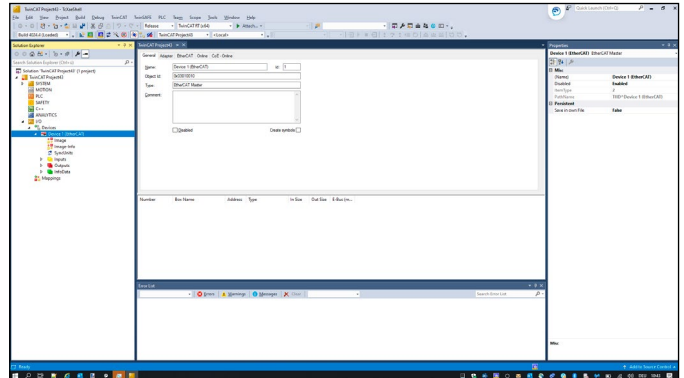


Fig. 33: TwinCAT 3 user interface in configuration mode after creating a project and including a master

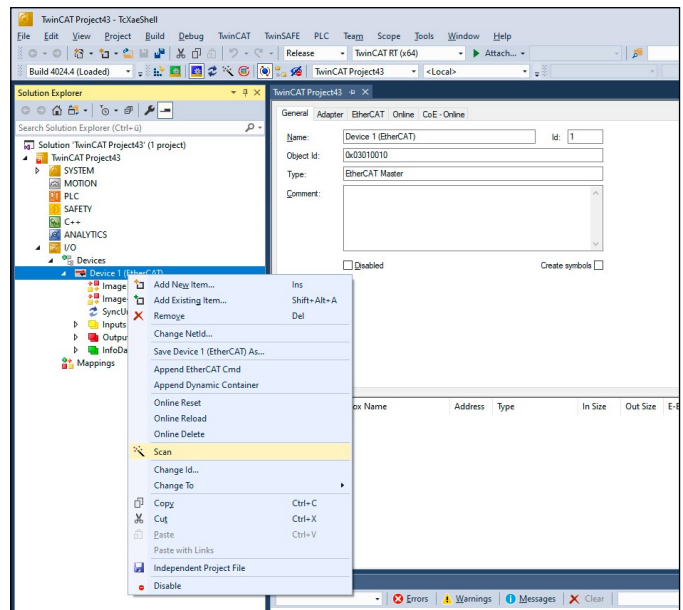


Fig. 34: Scan for boxes in the network

As shown in Fig. 35, the R-Series V EtherCAT® sensor is found in the network as "Box 1" with the name "MTS Temposonics V". If you have previously assigned the ESI file of the R-Series V EtherCAT® in the TwinCAT installation directory, TwinCAT can correctly assign this slave as "MTS Temposonics V".

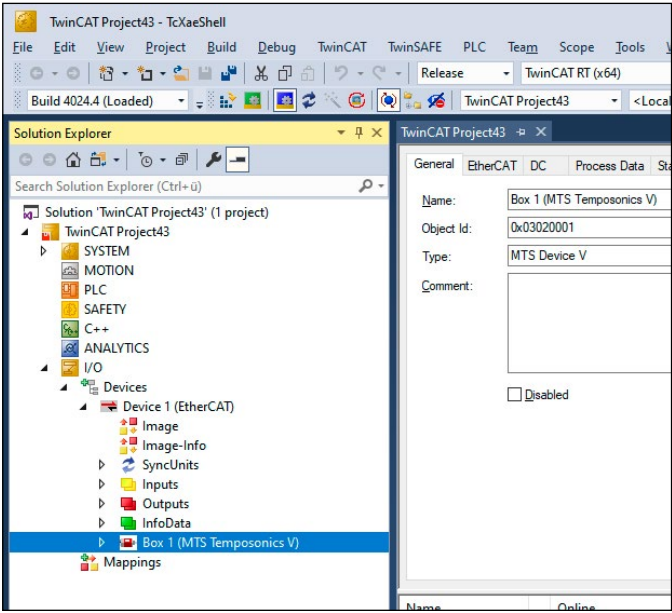


Fig. 35: R-Series V EtherCAT® found as “Box 1” in the network

In addition to adding a device through the “scan for boxes” process, you can also implement a device in another way. To do this, select in the Solution Explorer in the tree the entry “I/O → Devices → Devices 1 (EtherCAT)”. A right mouse click opens a menu. In this menu, click on the entry “Add new item”. The window “Insert EtherCAT Device” opens (Fig. 36). In this example, only the ESI file of the R-Series V EtherCAT® from MTS Sensors has been stored in the TwinCAT installation directory. Therefore, only this device with the name “MTS Device V” is displayed in this path. Select the “MTS Device V” device and confirm this by clicking the OK button.

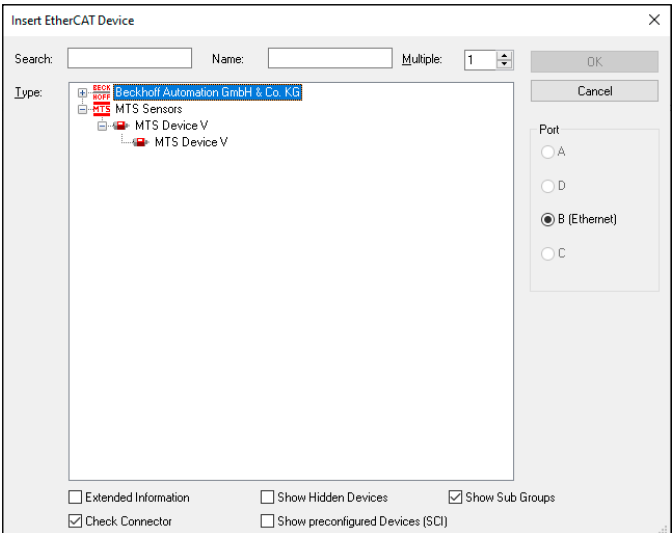


Fig. 36: The window “Insert EtherCAT Device” for implementing of devices

If you click on the added entry “Box 1 (MTS Temposonics V)” in the tree of the Solution Explorer, values of the sensor are displayed in the main window. Since the controller is not yet running, no values are requested from the sensor, so 0 is displayed (Fig. 37).

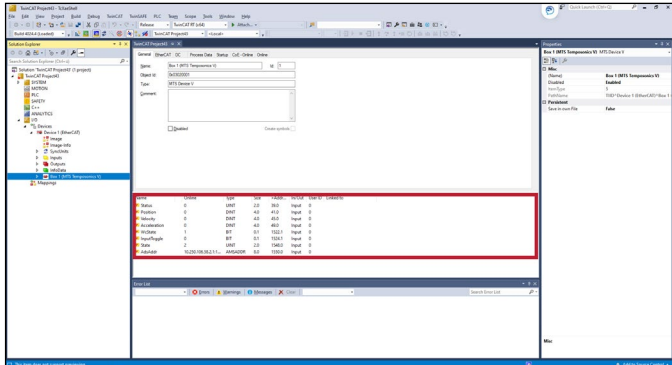


Fig. 37: Values of the R-Series V EtherCAT® displayed in the main window

To display current values, start the Free Run mode by clicking on the highlighted button in the upper menu bar (Fig. 38). Afterwards, current values of the sensor will be displayed in the main window. Among others, the following values are displayed when the position magnet is moved along the sensor rod/sensor profile:

- Status: current status of the magnet
- Position: current measured position of the position magnet on the rod/profile
- Velocity: current measured velocity of the position magnet on the rod/profile
- Acceleration: current measured acceleration of the position magnet on the rod/profile

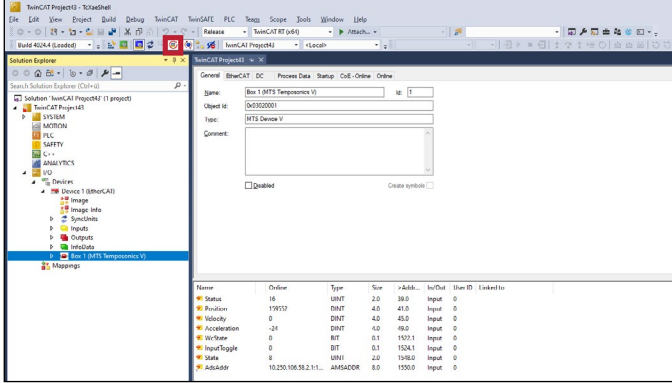


Fig. 38: Display of current values after starting the Free Run mode

If you expand the entry “Box 1” in the tree of the Solution Explorer, the variables for “Magnet 1” are displayed. In this example the sensor is operated with one magnet. For this magnet the following values are displayed as in the main window (Fig. 39):

- Status
- Position
- Velocity
- Acceleration

The WcState and InfoData values are described in the TwinCAT operation manual. The sensor is now implemented and ready for use.

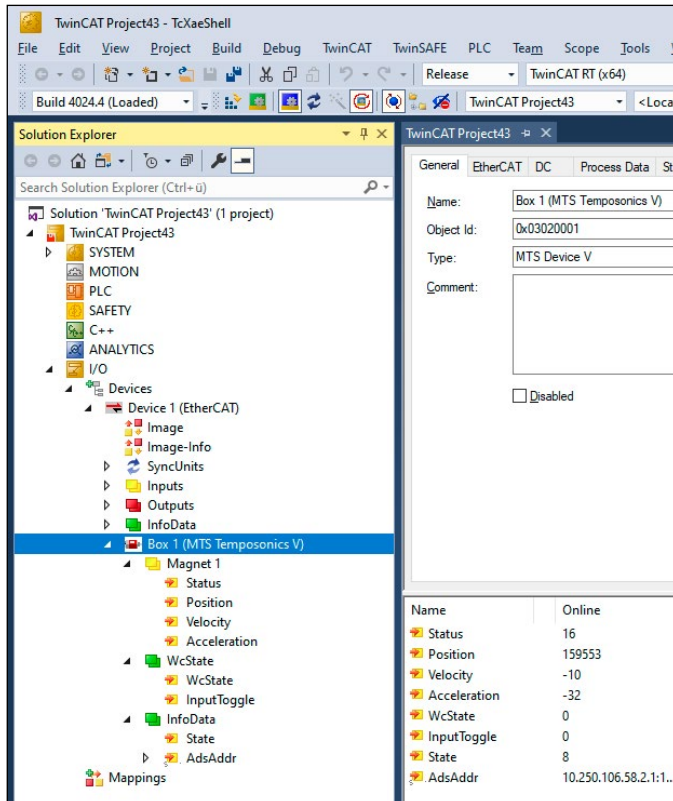


Fig. 39: Display variables of the R-Series V EtherCAT® in the solution explorer

If a multi-position measurement sensor (number of magnets > 1) is connected to the PLC, only the first magnet is initially displayed in the Solution Explorer. The other magnets must be enabled on the "Process Data" tab of the main window. This is described in the following section.

6.3 Configuration of R-Series V EtherCAT® in TwinCAT 3

Various tabs are available in the main window of the TwinCAT user interface for configuring the sensor:

The tab "General"

In the tab "General" the name of the device can be changed. For example, you can assign an application-specific name (Fig. 40).

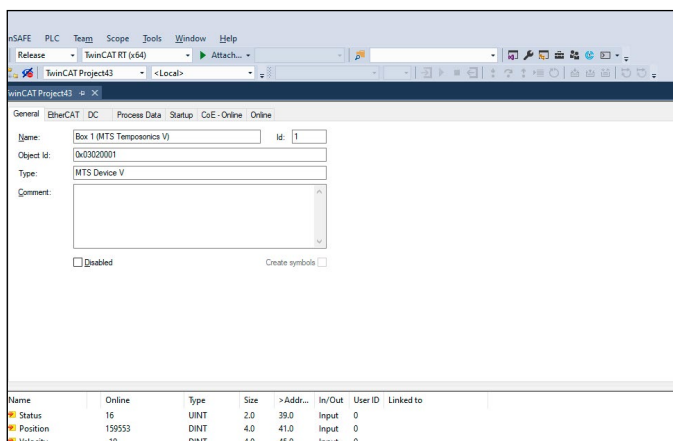


Fig. 40: The tab "General"

The tab "EtherCAT"

The tab "EtherCAT" shows EtherCAT® specific settings (Fig. 41).

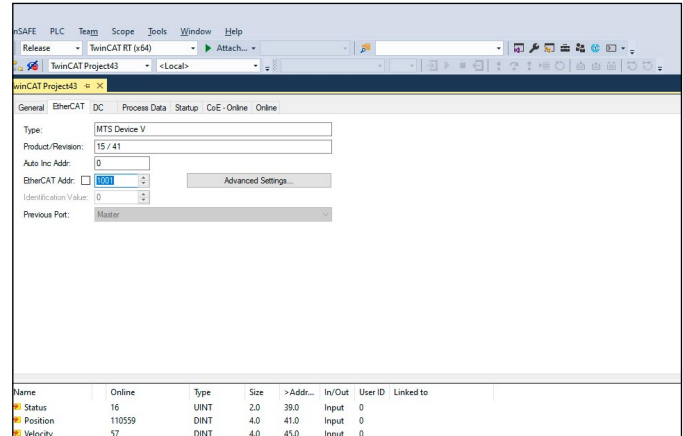


Fig. 41: The tab "EtherCAT"

The tab "DC"

In the tab "DC" you can set the mode in which the sensor should be operated in normal operation (Fig. 42):

- Synchronised on SyncManager event: The sensor is operated in SyncManager mode.
- Synchronised on DC sync event: The sensor is operated in distributed clock mode.

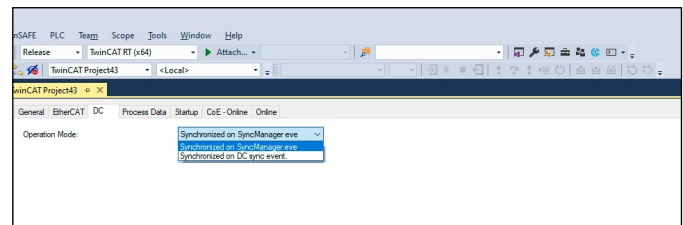


Fig. 42: The tab "DC"

The tab "Process Data"

The tab "Process Data" is used to configure process data of the sensor. As shown in Fig. 43, in this example the sensor is assigned to the Sync Manager "SM 3" and has a size of 14 bytes. The value of 14 bytes results from 2 bytes for the status and 4 bytes each for position, velocity and acceleration, as shown in the lower part of the main window. As shown in the "PDO Assignment" area, only the entry "0x1A00" is active. This is because the sensor is operated with one magnet. Accordingly, only "Magnet 1" is assigned to a Sync Manager in the "PDO List", in this case to "SM 3".

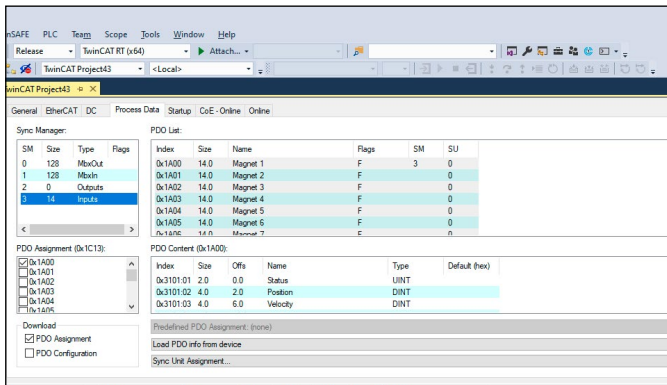


Fig. 43: The tab "Process Data"

For multi-position measurements, notice that only the first magnet in the "PDO Assignment" area is enabled by default. Additional magnets can be enabled by clicking on the other PDOs below the first one.

NOTICE
The sensor supports a maximum number of position magnets specified in the order code. If the sensor is operated with more magnets than specified in the order code, no values are displayed for the magnets above the maximum number in the order code. By default, only the first magnet is enabled on the sensor. To be able to use the other magnets in multi-position measurement, they must be enabled via the "PDO assignment" on the "Process Data" tab.

The tab "Startup"

The tab "Startup" shows which messages are exchanged between sensor and controller in the different startup phases (Fig. 44). You can use the "New" button to create additional messages to be exchanged in the startup phase. For more information see the TwinCAT operation manual.

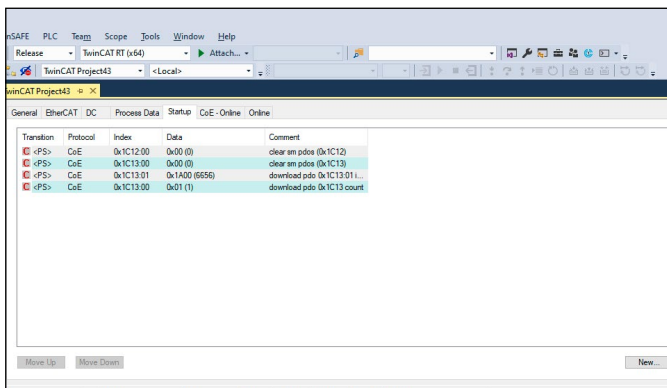


Fig. 44: The tab "Startup"

The tab "CoE - Online"

The R-Series V EtherCAT® supports the "CAN application protocol over EtherCAT® (CoE)" communication profile. Therefore, in the tab "CoE - Online" the parameters of the sensor are displayed with the respective values (Fig. 45). According to the name of this tab the object structure is similar to CAN. Parameters with the attribute ("Flag") RO can only be read, while parameters with the attribute ("Flag") RW can be read and adjusted. For a description of the parameters see chapter 8. Object dictionary of R-Series V EtherCAT® on page 36.

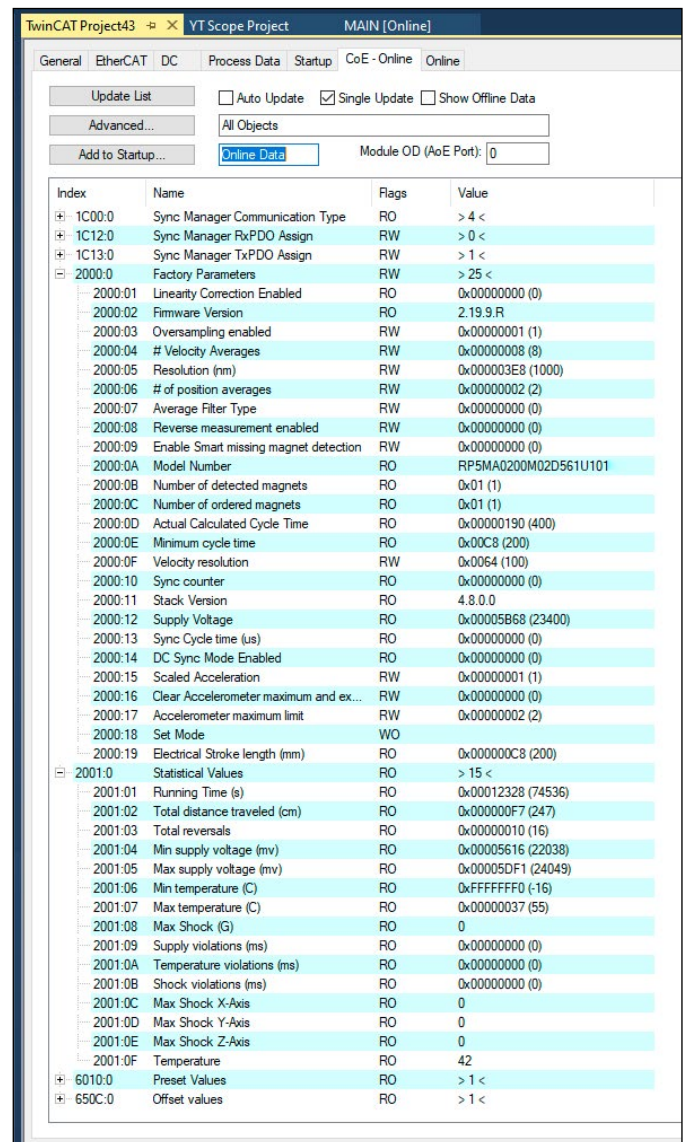


Fig. 45: The tab "CoE - Online"

The tab "Online"

In the tab "Online" you can set the sensor specifically in different modes and check the current status. (Fig. 46). For further information see the TwinCAT operation manual.

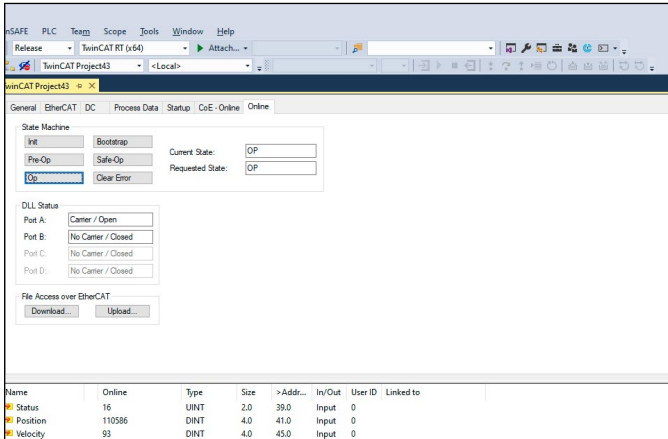


Fig. 46: The tab "Online"

For information on creating a program and transferring the program from the engineering environment to the runtime system see the TwinCAT operation manual.

7. Implementation and configuration of R-Series V EtherCAT® with TwinCAT 2

For the operation of the EtherCAT® Bus in this example, the following components are required:

- Temposonics® R-Series V with EtherCAT® interface
- EtherCAT® Slave Information (ESI) specification describes the structure of ESI files using the corresponding XML format
- This file is used to inform TwinCAT of characteristics and performance of the bus sensors.
- EtherCAT® Master (e.g. Industrial PC) with Windows OS
- EtherCAT® Master-Software 'TwinCAT System Manager'

The sensor is integrated into the bus system using the TwinCAT System Manager and ESI file from MTS. This file can be downloaded from www.mtssensor.com.

7.1 Configuration of Ethernet card

For this example, the TwinCAT software-based controller is used. Thus, an Ethernet card is needed for the master in order to use an EtherCAT® network. The EtherCAT® drivers must be installed and the appropriate Ethernet card activated before the data frame can be read. The status can be checked by opening the network at Windows Start button, Control Panel, Network Connections. The window shown at Fig. 47 is opened with a right click on the appropriate EtherCAT® LAN connection. Check that ECAT® Filter Driver and TwinCAT RT-Ethernet Intermediate Driver are activated and confirm with OK.

NOTICE

Some PLCs come pre-configured, so setting up the network port may not be required. For TwinCAT software based PLC, this is required.

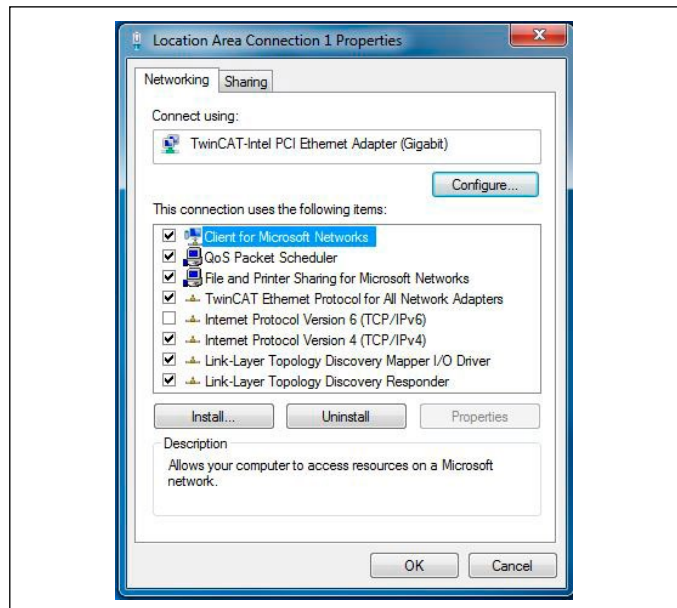


Fig. 47: Configure LAN drivers

7.2 Starting TwinCAT System Manager

Use TwinCAT System Manager to setup communication with EtherCAT® sensor.

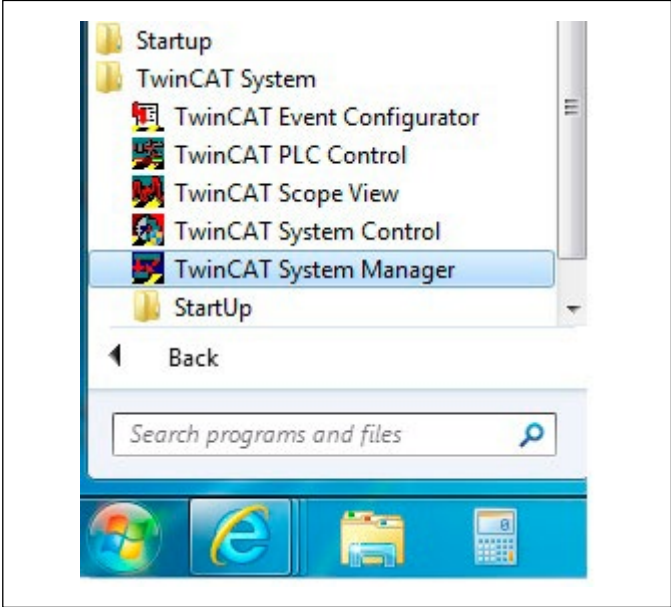


Fig. 48: Select TwinCAT System Manager

7.3 Adding the Ethernet card as an I/O device

On starting the TwinCAT System Manager the window shown at Fig. 49 is opened.

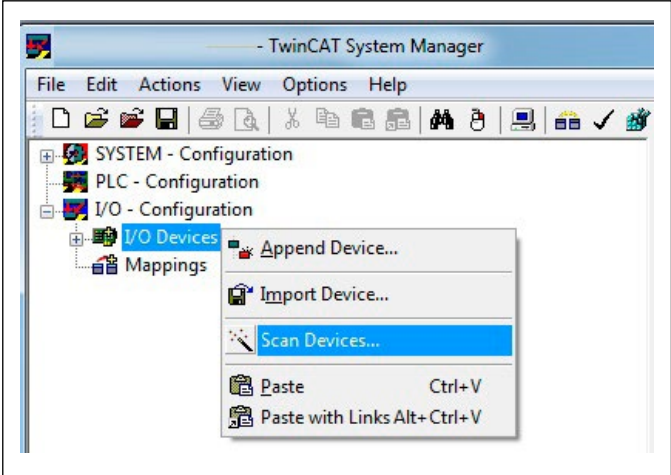


Fig. 49: Scan for Devices

An automatic search for a I/O Device (in this case the appropriate interface card) is initiated by a right click on "I/O Device" and then making "Scan Devices". The following dialogue box is opened (Fig. 50). Click on OK to search further.

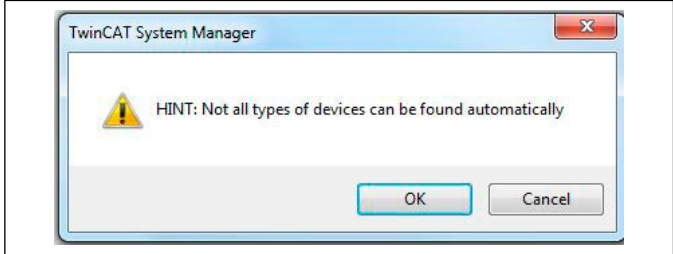


Fig. 50: Press OK to see available devices

A new menu is now opened showing the EtherCAT® interface card found and added to the file tree as I/O Device.

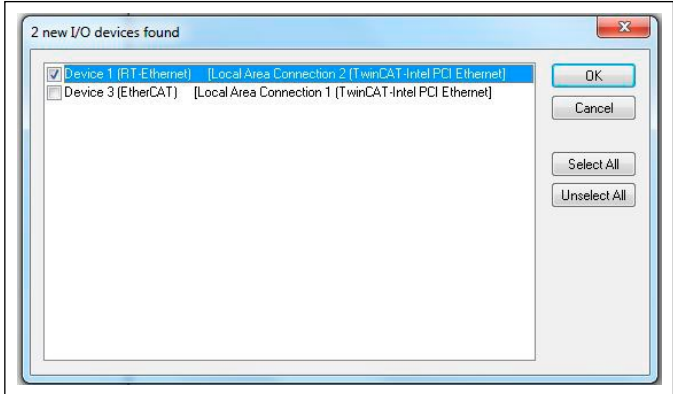


Fig. 51: Choose EtherCAT® Local Area Connection

Confirm with OK. A new dialogue box is opened (Fig. 52).

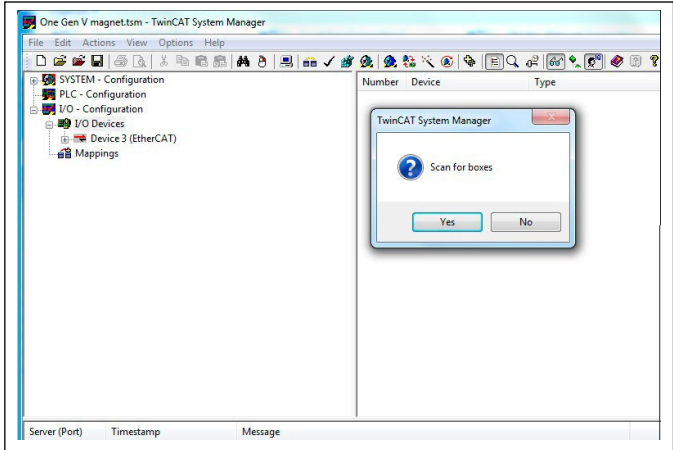


Fig. 52: Scan for boxes automatically

NOTICE

If you choose “Yes” the System Manager automatic search sensor(s) that can be connected to the EtherCAT® device. If “No” is selected, the sensor(s) must be added manually to the EtherCAT® device as described at manual addition.

7.4 Adding a sensor as a box

1. Automatic addition

The automatic search recognizes the sensor and a dialogue box is opened which asks whether the Free Run mode should be activated (Fig. 37). The sensor is added to corresponding I/O Device in the file system. The Free Run mode reports the position, velocity, and acceleration of the sensor – independent of whether a task is configured and activated. Yes tests the sensor/No closes the dialogue box.

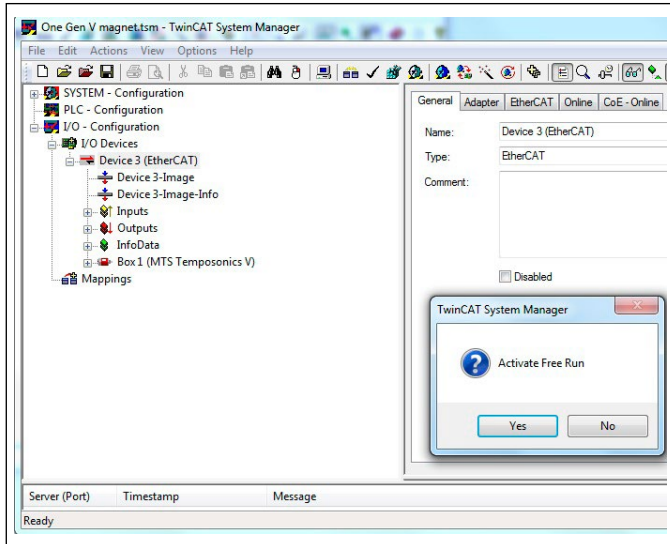


Fig. 53: Set to control to Free Run mode

2. Manual addition

Right click on the EtherCAT® symbol in the file tree in Fig. 53. In the new window which opens (not shown) select *Add Box*. Then open MTS Sensors in the window which opens next (Fig. 54) and select MTS Device V. Confirm with OK. The additional sensor is added to the file tree system.

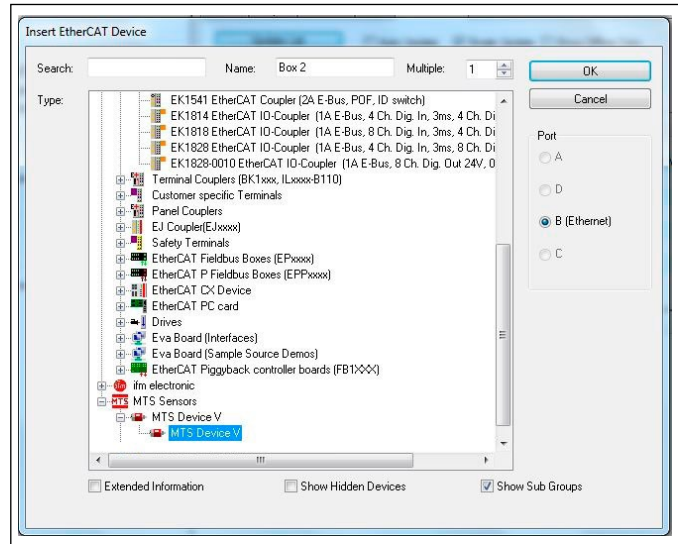



Fig. 54: Select MTS generation V sensor

Activate the button  (*Reload I/O Device*) in the tool bar in order to update the configuration. The Free Run mode activation window opens (Fig. 55). The Free Run reports the position, velocity and acceleration of the sensor – independent of whether a task is configured and activated. Yes tests the sensor. No closes the window.

7.5 Setting up and parameterizing the sensor

After adding the sensor as a box it can be set up and the parameters can be modified. Click on the box required in the file tree. The sensor set-up tabs are opened in the main window (Fig. 55).

1. General

The name and the ID of the sensor can be changed here.

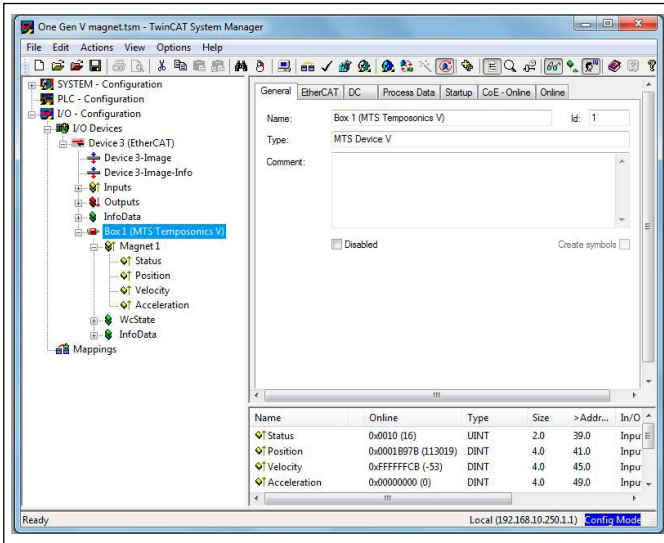


Fig. 55: Use General tab to update sensor info

2. EtherCAT

This tab includes the product no. and revision of the sensor. By clicking on advanced settings certain product numbers and revisions can be approved.

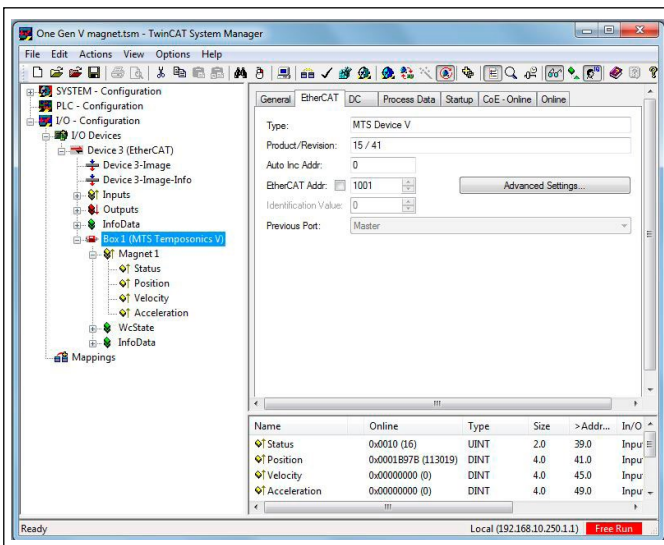


Fig. 56: EtherCAT tab used to identify product name and version

3. DC

The Distributed Clock (DC) mode which synchronizes the measurement cycle of the sensor by control unit, can be changed.

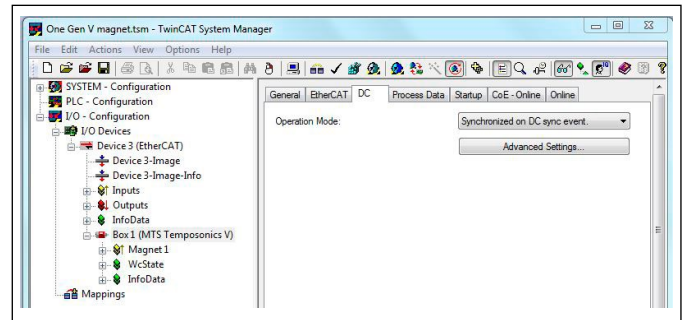


Fig. 57: Use General tab to update sensor info

To set the cycle time, click on "Advanced Settings". On the "Distributed Clock" page that appears, enable the usage of the distributed clock by adding a checkmark to the Enable value. Configure SYNC0 for the desired cycle time.

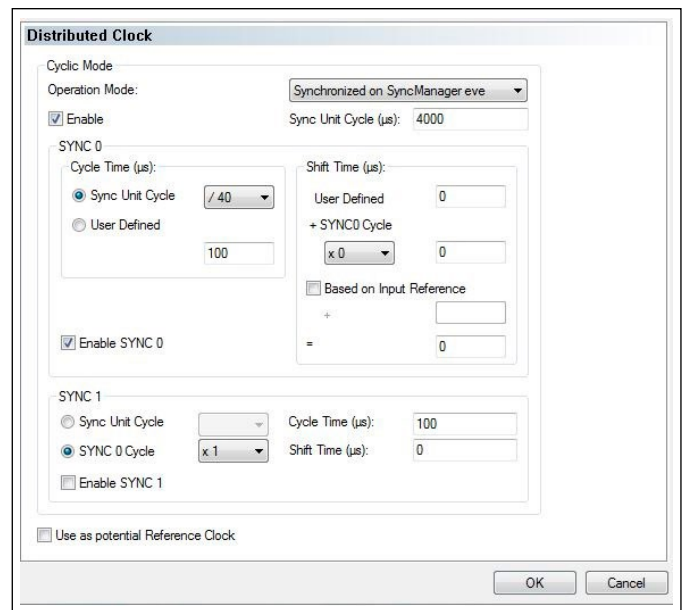


Fig. 58: Use to enable DC Sync mode

4. Startup

The *startup* tab can be used to insert mails which are transmitted to the sensor when starting up. After clicking on "New", a new mail can be prepared which is then transmitted to the sensor at the next start up (Fig. 59).

The transition in which the new mail is to be sent can be selected at the state machine. The transmission goes via a CoE protocol (CoE = CANopen application on layer over EtherCAT®). Startup enables a sensor to be replaced to meet different requirements without having to re-configure the new sensor.

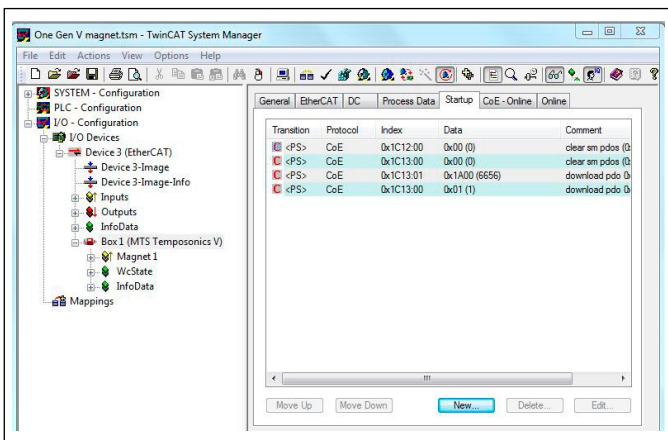


Fig. 59: Create new mail messages to send to the sensor

To select the number of magnets that will be monitoring, go to the *Process Data* tab and locate the "PDO Assignment" portion of the tab. There exists a complete list of the number of possible magnets that can be used based on the number of ordered magnets. The range of selectable magnets range from 0x1A00 to 0x1A1D. If one magnet is ordered, select 0x1A00. If two magnets are ordered, choose 0x1A00 and 0x1A01. Note: if you ordered two magnets and try to select more than two, all position, velocity, and acceleration data will return a value of 0.

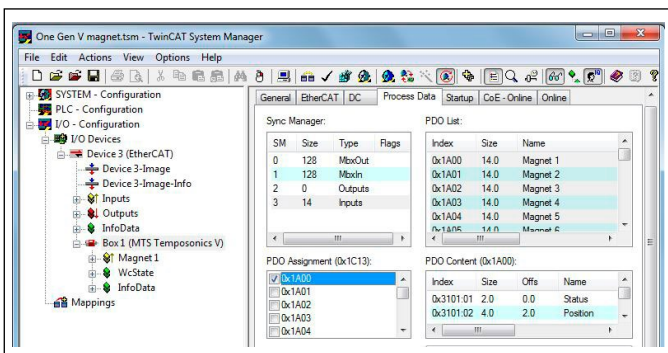


Fig. 60: Select the number of magnets used

5. CoE-Online

CoE lists the sensor's parameters. The flags column shows whether read (RO = read only) or read and write (RW) rights are available for the parameter. If rw rights are available the parameter can be changed by double clicking on the parameter and the alterations are sent to the sensor via the CoE-Mailbox.

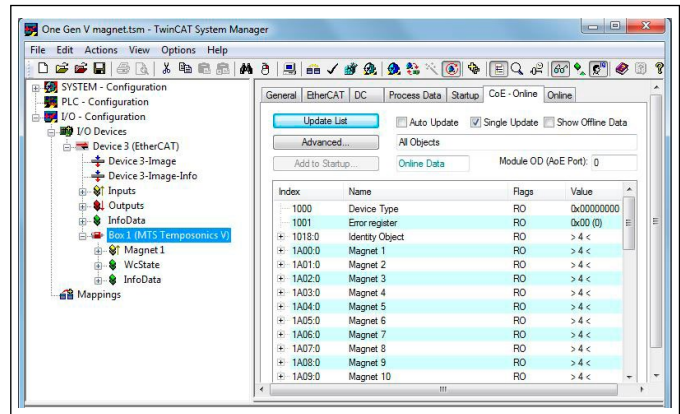


Fig. 61: Provides sensor parameter list

6. Online

The *online* tab shows the state machine of the sensor. The fields on the right show the current state and the requested state. By clicking on the buttons on the left a transition to a different sensor status can be requested.

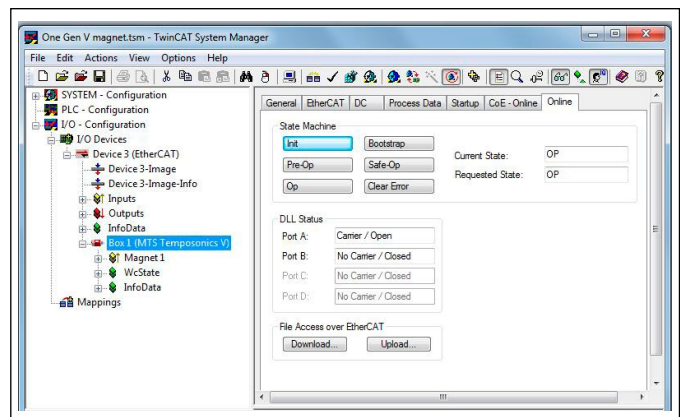


Fig. 62: View the state machine of current sensor

7.6 Sensor in operation

The sensor delivers input data into the process image in Free Run mode. On opening up the file system at *Inputs* the data is updated in the main window in the *Online* column (Fig. 63). The amount of data is dependent on the number of magnets. The status, position, velocity, and acceleration of each magnet is listed hexadecimally (decimally) in the online column.

1. Status

The status is a 2 byte number without prefix. Byte 1 is empty, Byte 2 shows the magnets and reports failures.

Example: 0x0010 Magnet No. 1 is OK

0x0018 Magnet No. 1 shows the failure bit

2. Position

The position is a 4 byte number without prefix. This value does not have a unit and must therefore be multiplied by the resolution in meters.

Example: Magnet No. 1 shows position value of 0x0000E998 (59800), a selected resolution of 1 μm results in a value of 59.8 mm.

3. Velocity

The velocity is shown as a 4 byte number with prefix. When the magnet moves away from the sensor head the speed value is positive and in the opposite direction it is negative. This value has no unit and must therefore be multiplied by $\mu\text{m}/\text{sec}$.

Example: Magnet No. 1 shows a speed value of 0x00030D4 (200000), a selected position resolution of 1 μm results in 200 mm/sec.

4. Acceleration

The acceleration for all selected magnets is available as well. In this case it is given with an additional 4 bytes. The prefix is independent of the direction of movement. A negative value depicts a deceleration of the magnet.

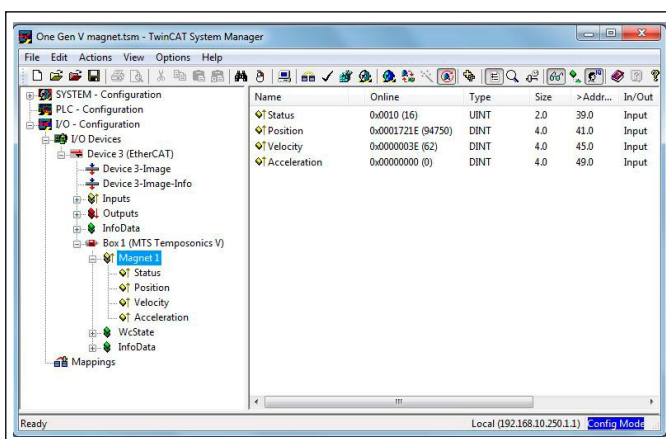


Fig. 63: View the state machine of current sensor

8. Object dictionary of R-Series V EtherCAT®

The R-Series V EtherCAT® supports the "CAN application protocol over EtherCAT® (CoE)" communication profile. The following tables describe the object dictionary relevant for R-Series V EtherCAT®.

Standard object					
Index	Subindex	Name	Attribute	Data type	Description
1000	00	Device type	RO	Unsigned32	Device type of the EtherCAT® slave

Table 1: The standard object

Error object					
Index	Subindex	Name	Attribute	Data type	Description
1001	00	Error register	RO	Unsigned8	The corresponding error bit is set in case of an error. If the error no longer exists, it is deleted automatically. <ul style="list-style-type: none"> • Value 0: No errors detected • Value 1: An error has been detected

Table 2: The error object

Identity object					
Index	Subindex	Name	Attribute	Data type	Description
1018	01	Vendor ID	RO	Unsigned32	Vendor ID (MTS Sensors)
	02	Product code	RO	Unsigned32	Product code of the sensor
	03	Revision	RO	Unsigned32	Revision number of the sensor
	04	Serial number	RO	Unsigned32	Serial number of the sensor

Table 3: The identity object

Magnet object					
Index	Subindex	Name	Attribute	Data type	Description
1A00-1A1D		Magnet 1...30	RO	Unsigned8	Number of magnets available on the sensor according to the number specified in the order code
	01	Status	RW	Unsigned16	Indicating the current status of the magnet and outputting errors or failures (Fig. 64)
	02	Position	RW	Unsigned32	Current position value of the magnet
	03	Velocity	RW	Unsigned32	Current velocity of the magnet. This value can be positive or negative depending on measurement direction (object 2000:08).
	04	Acceleration	RW	Unsigned32	Current acceleration of the magnet based on the magnet velocity. A positive value denotes acceleration and negative value denotes deceleration.

Table 4: The magnet object

The status of a magnet is indicated in a 16 bit word (Fig. 64). It applies:

- The first 7 bits are empty
- The following 5 bits **xxxxx** indicate the number of the magnet
- The bit 3 (the bit after the magnet number) indicates the status:
 - Bit value **y** = 0: No error
 - Bit value **y** = 1: Error detected: Magnet missing or too many magnets

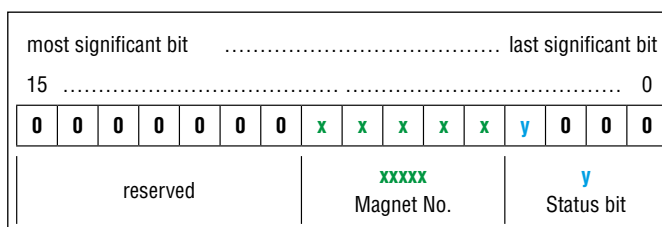


Fig. 64: Structure of the status object

Sync Manager Communication Type / Sync Manager RxPDO Assign / Sync Manger TxPDO Assign

These parameters are not relevant for the user and set by the EtherCAT® master in the network.

Accelerometer Data (for future use)

The sensor can optionally be equipped with an acceleration sensor. If the sensor is equipped with the accelerometer the following accelerometer data is available.

Accelerometer data					
Index	Subindex	Name	Attribute	Data type	Description
1B00	01	Status	RW	Unsigned32	The status value will update continuously when an accelerometer is present. If no accelerometer is present, the status will return a value of 65535.
	02	Axis X	RW	Signed32	X axis acceleration based on board orientation
	03	Axis Y	RW	Signed32	Y axis acceleration based on board orientation
	04	Axis Z	RW	Signed32	Z axis acceleration based on board orientation
	05	Combined X,Y,Z	RW	Signed32	Combined value determined from the three individual values Axis X, Axis Y and Axis Z
	06	Maximum of combined	RW	Signed32	Maximum value of the combined acceleration (subindex 05) so far
	07	Times limit exceeded	RW	Signed32	Indicates the number of times that the value Maximum of combined (subindex 06) has exceeded the accelerometer maximum limit (object 2000:17).

Table 5: The accelerometer data

Factory Parameters					
Index	Subindex	Name	Attribute	Data type	Description
2000	01	Linearity correction enabled	RO	Unsigned32	Indicating that the sensor was ordered with the internal linearization option. <ul style="list-style-type: none"> Value 0: Not Ordered Value 1: Ordered and enabled
	02	Firmware revision	RO	String	Firmware revision of the sensor
	03	Oversampling enabled	RW	Unsigned32	Enabling and disabling the extrapolation <ul style="list-style-type: none"> Value 0: Disabled Value 1: Enabled (default)
	04	# Velocity averages	RW	Unsigned32	Velocity Window Size: Setting the number of position values for determining the velocity of the position magnet. Possible values: 2...16 Default value: 8
	05	Resolution (nm)	RW	Unsigned32	Resolution of the position output in nm Possible values: 100...1,000,000 in steps of 100 nm Default value: 1000 nm (1 µm)
	06	# Position averages	RW	Unsigned32	Filter Window Size: Setting the number of position values for calculating the filter of the output value. Possible values: 2...16
	07	Average filter type	RW	Unsigned32	<ul style="list-style-type: none"> Value 0: No filter Value 1: FIR (finite impulse response) filter Value 2: IIR (infinite impulse response) filter
	08	Reverse mode enabled	RW	Unsigned32	Measuring direction <ul style="list-style-type: none"> Value 0: Measuring direction forward Value 1: Measuring direction reverse

Table 6: The factory parameters (part 1)

Factory Parameters					
Index	Subindex	Name	Attribute	Data type	Description
2000	09	Enable smart missing magnet detection	RW	Unsigned32	This parameter detects the number of the missing magnet on the sensor rod/sensor profile in case of a multi-position measurement. If this parameter is enabled, either the last measured position or 0 can be reported for the missing magnet. <ul style="list-style-type: none"> Value 0: Disabled; if a magnet is missing, an error is indicated for each magnet via the status bit (default) Value 1: Enabled; if a magnet is missing, an error is only indicated for the missing magnet via the status bit and the last measured position value is reported for this magnet Value 2: Enabled; if a magnet is missing, an error is only indicated for the missing magnet via the status bit and zero is reported as position value for this magnet Note: The status of the missing magnet is reported in the Magnet Object: Status.
	0A	Model number	RO	String	Order code of the sensor
	0B	Number of detected magnets	RO	Unsigned8	Current number of magnets detected on the sensor
	0C	Number of ordered magnets	RO	Unsigned8	Maximum number of magnets with which the sensor can be operated
	0D	Actual calculated cycle time	RO	Unsigned32	Cycle time of the sensor according to the stroke length
	0E	Minimum cycle time	RO	Unsigned16	Factory use only
	0F	Velocity resolution	RW	Unsigned16	Resolution of the velocity output in 0.1 µm/sec Default values: 100 (= 10 µm/sec)
	10	Sync counter	RO	Unsigned 32	If the EtherCAT® master runs in DC mode and the sensor is synchronized to the EtherCAT® master, this value is incremented. Note: DC sync model enabled (object 2000:14) is enabled
	11	Stack version	RO	String	Factory use only
	12	Supply voltage	RO	Unsigned32	Current power supply in mV
	13	Sync cycle time (µs)	RO	Unsigned32	Cycle time from the EtherCAT® master in synchronous mode (distributed clock mode). Note: The minimum cycle time of the sensor in distributed clock mode is 100 µs for up to 10 magnets and 250 µs for 11...30 magnets.
	14	DC sync mode enabled	RO	Unsigned32	Indicating that the EtherCAT® master is in distributed clock mode <ul style="list-style-type: none"> Value 0: Disabled Value 1: Enabled
	15	Scaled acceleration	RW	Unsigned32	Factory use only
	16	Clear accelerometer maximum and exceed count	RW	Unsigned32	Each exceeding of the Accelerometer maximum limit (object 2000:17) is counted. The number of exceeding can be cleared by setting this bit value to 1. Note: Only possible if the sensor is equipped with the optional accelerometer (for future use).
	17	Accelerometer maximum limit	RW	Unsigned32	The maximum limit of the measured accelerometer values. Each excess is counted in the parameter Times limit exceeded (object IB00:07). Note: Only possible if the sensor is equipped with the optional accelerometer (for future use).
	18	Set mode	WO	Unsigned32	Factory use only
	19	Electrical stroke length (mm)	RO	Unsigned32	Stroke length of the sensor

Table 7: The factory parameters (part 2)

Sensor statistics					
Index	Subindex	Name	Attribute	Data type	Description
2001	01	Running time (s)	RO	Unsigned32	Total operational time of the sensor in seconds
	02	Total distance traveled (cm)	RO	Unsigned32	Odometer: Total distance traveled by the position magnet in cm
	03	Total reversals	RO	Unsigned32	Magnet cycles: Total number of directional changes by the magnet
	04	Min supply voltage (mV)	RO	Unsigned32	Minimum input voltage so far in mV
	05	Max supply voltage (mV)	RO	Unsigned32	Maximum input voltage so far in mV
	06	Min temperature (C)	RO	Signed16	Minimum temperature inside the sensor electronics housing so far in °C
	07	Max temperature (C)	RO	Signed16	Maximum temperature inside the sensor electronics housing so far in °C
	08	Max shock (G)	RO	Unsigned32	Maximum shock so far measured by the integrated accelerometer Note: Only available if the sensor is equipped with the optional accelerometer (for future use).
	09	Supply violations (ms)	RO	Unsigned32	Input Voltage out of range: Duration of exceeding or falling below the permissible power supply range

Table 8: The sensor statistics

Sensor statistics					
Index	Subindex	Name	Attribute	Data type	Description
6010	01...1E	Preset for 1...30 magnets	RW	Unsigned32	With the preset, a value is entered for the current position which is to be output at this position in the future. The difference between the entered value and the currently measured position is calculated as an offset. The preset can be set for up to 30 magnets.
650C	01...1E	Offset for 1...30 magnets	RW	Unsigned32	The difference between the entered position value and the currently measured position is calculated as an offset.

Table 9: Preset and offset

9. TempoLink smart assistant with R-Series V EtherCAT®

TempoLink smart assistant supports the R-Series V EtherCAT®. The values listed in the object dictionary "Sensor Statistics" can be read out via TempoLink smart assistant. In addition, the current parameter settings can be viewed via the TempoLink smart assistant. This allows the sensor to be checked offline, i.e. without integration into a network. For further information see the TempoLink smart assistant operation manual (Document part number: 551986).

10. Maintenance and troubleshooting

10.1 Error conditions, troubleshooting

See chapter "5. Operation" on page 24.

10.2 Maintenance

The sensor is maintenance-free.

10.3 Repair

Repairs of the sensor may be performed only by MTS Sensors or a repair facility explicitly authorized by MTS Sensors.
For return see chapter "2.6 Return" on page 4.

10.4 List of spare parts

No spare parts are available for this sensor.

10.5 Transport and storage

The conditions of transport and storage of the sensor match the operating conditions mentioned in this document.

11. Removal from service/dismantling

The product contains electronic components and must be disposed of in accordance with the local regulations.

12. Technical data

12.1 Technical data Temposonics® R-Series V RP5

Output							
Interface	EtherCAT® Ethernet Control Automation Technology						
Data protocol	EtherCAT® 100 Base-Tx, Fast Ethernet						
Data transmission rate	100 MBit/s max.						
Measured value	Simultaneous position, velocity and acceleration for up to 30 magnets						
Measurement parameters							
Resolution: Position	0.5...1000 µm (selectable)						
Native cycle time	Stroke length	≤ 50 mm	≤ 715 mm	≤ 2000 mm	≤ 4675 mm	≤ 6350 mm	
	Cycle time	250 µs	500 µs	1000 µs	2000 µs	4000 µs	
Extrapolation cycle time	Number of magnets	≤ 10 magnets	11...30 magnets				
	Cycle time	100 µs	250 µs				
Linearity deviation ⁴	Stroke length	≤ 500 mm	> 500 mm				
	Linearity deviation	≤ ±50 µm	< 0.01 % F.S.				
	Optional internal linearity: Linearity tolerance (Applies for the first magnet for multi-position measurement)						
	Stroke length	25...300 mm	300...600 mm	600...1200 mm	1200...3000 mm	3000...5000 mm	5000...6350 mm
	typical	±15 µm	±20 µm	±25 µm	±45 µm	±85 µm	±95 µm
	maximum	±25 µm	±30 µm	±50 µm	±90 µm	±150 µm	±190 µm
Repeatability	< ±0.001 % F.S. (minimum ±2.5 µm)						
Hysteresis	< 4 µm typical						
Temperature coefficient	< 15 ppm / K typical						
Operating conditions							
Operating temperature	-40...+85 °C (-40...+185 °F)						
Humidity	90 % relative humidity, no condensation						
Ingress protection	IP67 (connectors correctly fitted)						
Shock test	150 g/11 ms, IEC standard 60068-2-27						
Vibration test	30 g/10...2000 Hz, IEC 60068-2-6 (excluding resonant frequencies)						
EMC test	Electromagnetic emission according to EN 61000-6-3						
	Electromagnetic immunity according to EN 61000-6-2						
	The sensor meets the requirements of the EU directives and is marked with CE						
Magnet movement velocity	Magnet slider: Max. 10 m/s; U-magnet: Any; block magnet: Any						
Design/Material							
Sensor electronics housing	Aluminum (painted), zinc die cast						
Sensor profile	Aluminum						
Stroke length	25...6350 mm (1...250 in.)						
Mechanical mounting							
Mounting position	Any						
Mounting instruction	Please consult the technical drawings on page 4						
Electrical connection							
Connection type	2 × M12 female connectors (5 pin), 1 × M8 male connector (4 pin) or 2 × M12 female connectors (5 pin), 1 × M12 male connector (4 pin)						
Operating voltage	12...30 VDC ±20 % (9.6...36 VDC)						
Power consumption	Less than 4 W typical						
Dielectric strength	500 VDC (DC ground to machine ground)						
Polarity protection	Up to -36 VDC						
Overvoltage protection	Up to 36 VDC						

12.2 Technical data Temposonics® R-Series V RH5

Output						
Interface	EtherCAT® Ethernet Control Automation Technology					
Data protocol	EtherCAT® 100 Base-Tx, Fast Ethernet					
Data transmission rate	100 MBit/s max.					
Measured value	Simultaneous position, velocity and acceleration for up to 30 magnets					
Measurement parameters						
Resolution: Position	0.5...1000 µm (selectable)					
Native cycle time	Stroke length	≤ 50 mm	≤ 715 mm	≤ 2000 mm	≤ 4675 mm	≤ 7620 mm
	Cycle time	250 µs	500 µs	1000 µs	2000 µs	4000 µs
Extrapolation cycle time	Number of magnets	≤ 10 magnets	11...30 magnets			
	Cycle time	100 µs	250 µs			
Linearity deviation ⁵	Stroke length	≤ 500 mm	> 500 mm			
	Linearity deviation	≤ ±50 µm	< 0.01 % F.S.			
	Optional internal linearity: Linearity tolerance (Applies for the first magnet for multi-position measurement)					
	Stroke length	25...300 mm	300...600 mm	600...1200 mm		
	typical	±15 µm	±20 µm	±25 µm		
	maximum	±25 µm	±30 µm	±50 µm		
Repeatability	< ±0.001 % F.S. (minimum ±2.5 µm)					
Hysteresis	< 4 µm typical					
Temperature coefficient	< 15 ppm/K typical					
Operating conditions						
Operating temperature	-40...+85 °C (-40...+185 °F)					
Humidity	90 % relative humidity, no condensation					
Ingress protection	IP67 (connectors correctly fitted)					
Shock test	150 g/11 ms, IEC standard 60068-2-27					
Vibration test	30 g/10...2000 Hz, IEC 60068-2-6 (excluding resonant frequencies)/					
	RH5-J: 15 g / 10...2000 Hz, IEC standard 60068-2-6 (excluding resonant frequencies)					
EMC test	Electromagnetic emission according to EN 61000-6-3					
	Electromagnetic immunity according to EN 61000-6-2					
	The sensor meets the requirements of the EU directives and is marked with CE					
Operating pressure	350 bar (5,076 psi)/700 bar (10,153 psi) peak (at 10 × 1 min) for sensor rod/RH5-J: 800 bar (11,603 psi)					
Magnet movement velocity	Any					
Design/Material						
Sensor electronics housing	Aluminum (painted), zinc die cast					
Sensor flange	Stainless steel 1.4305 (AISI 303)					
Sensor rod	Stainless steel 1.4306/1.4307 (AISI 304L)/RH5-J: Stainless steel 1.4301 (AISI 304)					
Stroke length	25...7620 mm (1...300 in.)/RH5-J: 25...5900 mm (1...232 in.)					
Mechanical mounting						
Mounting position	Any					
Mounting instruction	Please consult the technical drawings on page 4					
Electrical connection						
Connection type	2 × M12 female connectors (5 pin), 1 × M8 male connector (4 pin) or 2 × M12 female connectors (5 pin), 1 × M12 male connector (4 pin)					
Operating voltage	12...30 VDC ±20 % (9.6...36 VDC)					
Power consumption	Less than 4 W typical					
Dielectric strength	500 VDC (DC ground to machine ground)					
Polarity protection	Up to -36 VDC					
Overvoltage protection	Up to 36 VDC					

13. Appendix I

Safety Declaration

Dear Customer,

If you return one or several sensors for checking or repair, we need you to sign a safety declaration. The purpose of this declaration is to ensure that the returned items do not contain residues of harmful substances and / or that people handling these items will not be in danger.

MTS Sensors order number: _____ Sensor type(s): _____

Serial number(s): _____ Sensor length(s): _____

The sensor has been in contact with the following materials:

Do not specify chemical formulas.
Please include safety data sheets of the substances, if applicable.

In the event of suspected penetration of substances into the sensor, consult MTS Sensors to determine measures to be taken before shipment.

Short description of malfunction:

Corporate information

Company: _____

Address: _____

Contact partner

Name: _____

Phone: _____

E-mail: _____

We hereby certify that the measuring equipment has been cleaned and neutralized.
Equipment handling is safe. Personnel exposure to health risks during transport and repair is excluded.

Stamp

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Signature

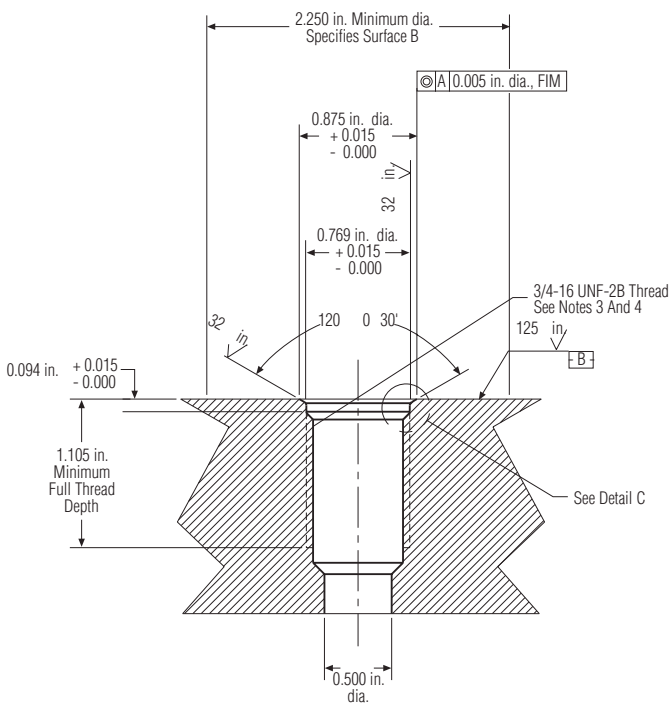
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Date

14. Appendix II

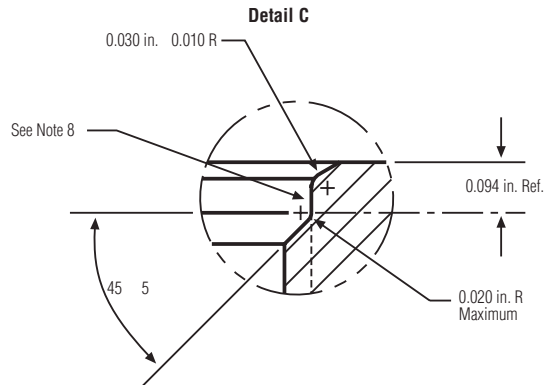
CYLINDER PORT DETAILS

PORT DETAIL (PD) FOR RH5-S:

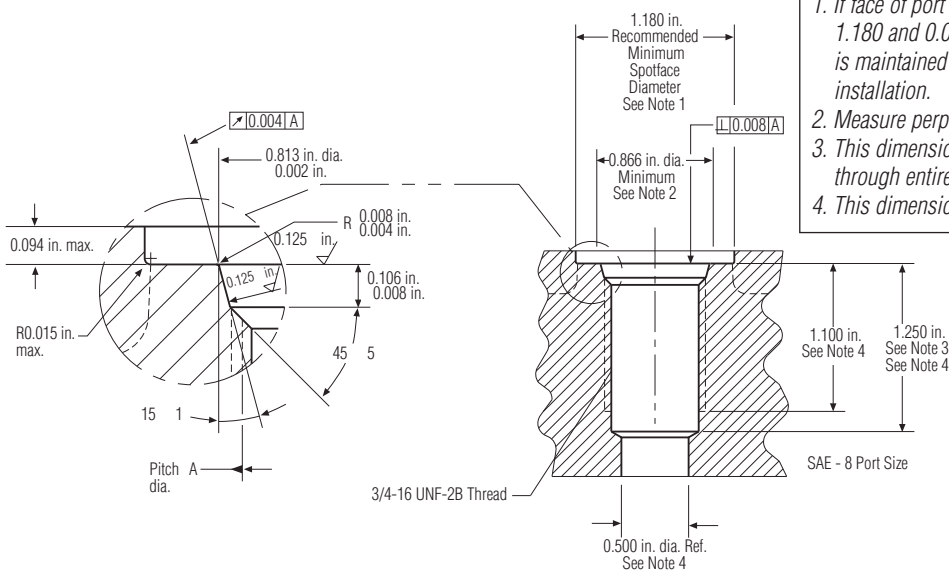


NOTES:

1. Dimensions and tolerances based on ANSI Y14.5-1982.
2. MTS has extracted all pertinent information from MS33649 to generate this document.
3. PD must be square with surface B within 0.005 FIM across 2.250 dia minimum.
4. PD must be concentric with 2.250 dia within 0.030 FIM and with 0.769 dia within 0.005 FIM.
5. Surface texture ANSI B46.1-1978
6. Use O-ring MTS part number 560315 for correct sealing.
7. The thread design shall have sufficient threads to meet strength requirements of material used.
8. Finish counter-bore shall be free from longitudinal and spiral tool marks. Annular tool marks up to 32 microinches maximum will be permissible.



PORT DETAIL (PD) FOR RH5-T:



NOTES:

1. If face of port is on a machined surface, dimensions 1.180 and 0.094 need not apply as long as R0.008/0.004 is maintained to avoid damage to the O-ring during installation.
2. Measure perpendicularity to A at this diameter.
3. This dimension applies when tap drill cannot pass through entire boss.
4. This dimension does not conform to SAE J1926/1.

15. Glossary

D

Distributed Clock

EtherCAT® uses a logical network of Distributed Clocks (DC) to synchronize the time on all local bus devices on the network. The EtherCAT® master usually selects the first Distributed Clock capable slave device as a Reference Clock, and then maintains a precise mapping of frame delays for all other slave devices in order to adjust their time to match the system time.

(→ Free Run, → Synchronous to SyncManager Event)

E

ESI

The properties and functions of an EtherCAT® device are described in an ESI file (**E**therCAT® **S**lave **I**nformation). The XML-based ESI file contains all relevant data that are important for the implementation of the device in the controller as well as for data exchange during operation. The ESI file of the R-Series V EtherCAT® is available on the homepage www.mtssensors.com.

EtherCAT®

EtherCAT® (**E**thernet for **C**ontrol **A**utomation **T**echnology) is an Industrial Ethernet interface and is managed by the EtherCAT® Technology Group (ETG). The R-Series V EtherCAT® and its corresponding ESI file are certified by the ETG.

Extrapolation

The native measurement cycle time of a sensor increases with the stroke length. With extrapolation, the sensor is able to report data faster than the native cycle time, independent of the stroke length of the sensor. Without extrapolation, if data is requested faster than the native cycle time, the last measured value is repeated.

F

FIR Filter

The FIR filter (**F**inite **I**mpulse **R**esponse) is used to smooth the measured position value before output. To determine the output value, only input values corresponding to the window (filter window size) are used for filter calculation. The output value is calculated from these input values in the form of a moving average value.

(→ IIR Filter)

Free Run

The sensor operates autonomously based on its own cycle and is not synchronized with the EtherCAT® cycle.

(→ Distributed Clock, → Synchronous to SyncManager Event)

I

IIR Filter

The IIR filter (**I**nfinite **I**mpulse **R**esponse) is used to smooth the measured position value before output. To determine the output value, the input values corresponding to the window (filter window size) are used for the filter calculation. The previous values are also taken into account when calculating the output value.

(→ FIR Filter)

Internal Linearization

The internal linearization offers an improved linearity for an overall higher accuracy of the position measurement. The internal linearization is set for the sensor during production.

M

Measuring Direction

When moving the position magnet, the position and velocity values increase in the measuring direction.

- Forward: Values increasing from sensor electronics housing to rod end/profile end
- Reverse: Values decreasing from sensor electronics housing to rod end/profile end

Multi-position measurement

During the measurement cycle, the positions of every magnet on the sensor are simultaneously reported. The velocity and acceleration are continuously calculated based on these changing position values as the magnets are moved.

O

Offset

A value which will be added or deducted to the actual position value. This leads to a shift of the measurement range start.

(→ Preset).

P

Preset

With the preset, a value is entered for the current position which is to be output at this position in the future. The difference between the entered value and the currently ensured position is calculated as an offset. (→ Offset)

R

RO

RO (**R**ead **O**nly) means that the value of the variable can only be read but is not modifiable.

RW

RW (**R**ead/**W**rite) means that the value of the variable can be read and written. The value of the variable is modifiable.

S

Synchronous to SyncManager Event

Besides the “Free Run” mode and the “Distributed Clock” DC mode, the sensor can be operated in the mode „Synchronous to SyncManager (SM) Event“. The SM event is triggered by the SyncManager when a passing frame is processed.

(→ Distributed Clock, → Free Run)

W

WO

WO (**W**rite **O**nly) means that the value can only be written.

T

TwinCAT

TwinCAT (**T**he **W**indows **C**ontrol and **A**utomation **T**echnology) is an automation solution from Beckhoff Automation GmbH & Co. KG for operating an EtherCAT® network.

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EtherCAT
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