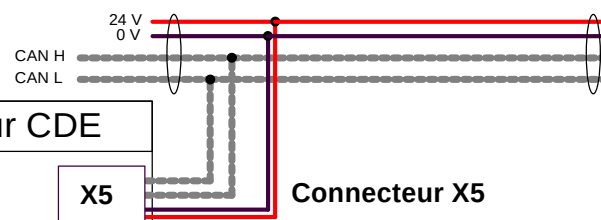


CAN Network



Pin-No.	Function
1	Wave terminating resistor 120 Ω internal for CAN by means of jumper between Pin 1 and Pin 2
2	CAN_LOW, CAN signal
3	CAN_GND, reference ground of CAN 24 V (Pin 9)
4	CAN_SYNC_LOW
5	Wave terminating resistor 120 Ω internal for CAN-SYNC by means of jumper between Pin 5 and Pin 3
6	CAN_GND, bridged with Pin 3
7	CAN_HIGH, CAN signal
8	CAN_SYNC_HIGH
9	CAN_+24 V (24 V ± 10%, 50 mA). This supply voltage is required for CAN operation.

Types de commande
Option A = CANopen
Option B = bit connect
Option C = personnalisé

+	24Vcc
+	0Vcc
[vers autre appareil]	

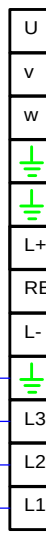
Cablage
230 V

X1



Cablage
400 V

X1

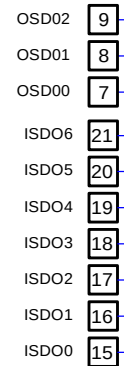


Variateur CDE

X5

Connecteur X5

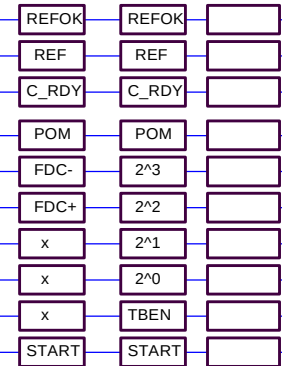
X2



opt.A

opt.B

opt.C



Connecteur X7

Connecteur X6

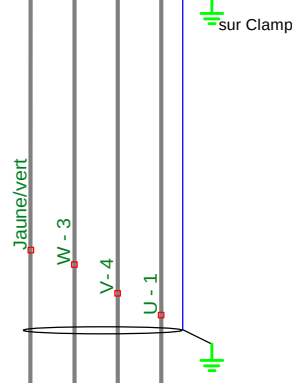
X7

X6

Pin-No.	Function
1	S2 / (Sine+)
2	S4 / (Sine-)
3	S1 / (Cosine+)
4	+5 V
5	PTC+, motor temperature monitoring
6	R1 / (REF+), resolver excitation
7	R2 / (REF-), resolver excitation, GND
8	S3 / (Cosine-)
9	PTC temperature monitoring

Pin-No.	Function TTL	SSI
1	A- (track A) ⁽¹⁾	do not use
2	A+ (track A) ⁽¹⁾	do not use
3		+5 V at 150 mA
4	do not use	DATA+ ⁽¹⁾ differential input RS485
5	do not use	DATA- ⁽¹⁾ differential input RS485
6	B- (track B) ⁽¹⁾	do not use
7		do not use
8		GND
9	R- (zero pulse) ⁽¹⁾	do not use
10	R+ (zero pulse) ⁽¹⁾	do not use
11	B+ (track B) ⁽¹⁾	do not use
12	Sensor + (±5 V supply). Cable length related voltage drops may occur in the sensor line. It is therefore recommended to connect the sensor line in order to counteract this effect.	
13	Sensor - (GND supply)	
14	do not use	CLK+ differential output, cycle signal
15	do not use	CLK- differential output, cycle signal

⁽¹⁾ The lines of tracks A, B, R and Data are internally connected with a 120 Ohm resistance.
Pin assignment for encoder interface X7, 15-pin D-Sub High Density, socket



Codeur

Resolver

+ sonde PTC

Phases moteur

Moteur Synchrone / Asynchrone

Title CDE340xx + Moteur Synchrone / Asynchrone		
Author GF		
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