HEIDENHAIN



Angle Encoders without Integral Bearing

August 2013





Information on
- Angle encoders with integral bearing
- Rotary encoders
- Encoders for servo drives
- Exposed linear encoders
- Linear encoders for numerically controlled machine tools
- HEIDENHAIN interface electronics
- HEIDENHAIN controls

is available on request as well as on the Internet at *www.heidenhain.de*.

This catalog supersedes all previous editions, which thereby become invalid. The basis for ordering from HEIDENHAIN is always the catalog edition valid when the contract is made.

Standards (ISO, EN, etc.) apply only where explicitly stated in the catalog.

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HEIDENHAIN angle encoders

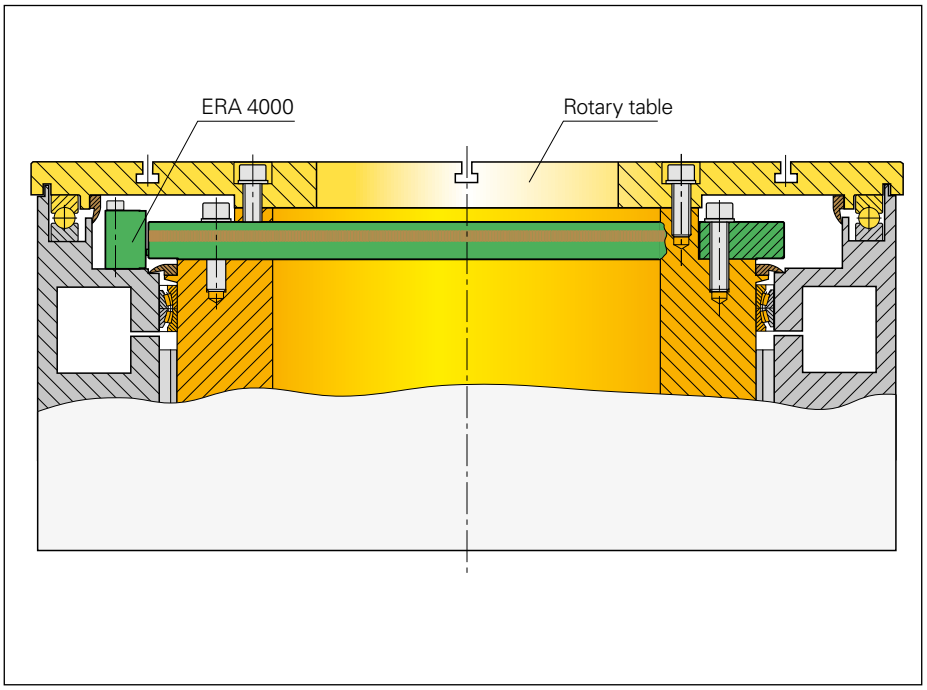
The term angle encoder is typically used to describe encoders that have an accuracy of better than ± 5″ and a line count above 10000.

These angle encoders are found in applications that require the **highly accurate measurement of angles** in the range of a few angular seconds, e.g. in rotary tables and swivel heads on machine tools, C axes on lathes, but also in measuring equipment and telescopes.

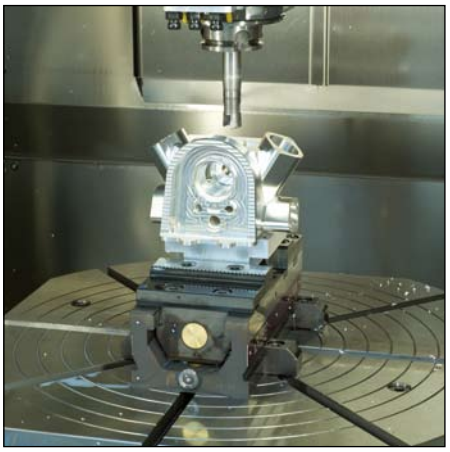
Other applications, such as scanners, positioning systems, printing units or beam deflection systems, require **high repeatability** and/or a **high angular resolution.** Encoders for such applications are likewise referred to as angle encoders.

In contrast, rotary encoders are used in applications where accuracy requirements are less stringent, e.g. in automation, electrical drives, and many other applications.

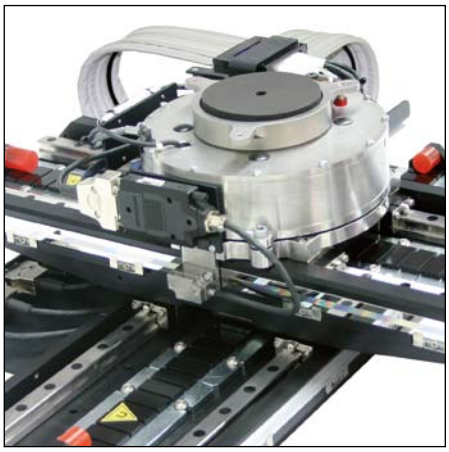
The tables on the following pages list different types of angle encoders to suit various applications and meet different requirements.



The **ERA 4000** angle encoder mounted onto the rotary table of a machine tool



Rotary table on a machine tool



X-Y-theta table



Large telescopes

Angle encoders without integral bearing
The angle encoders without integral bearing (modular angle encoders) **ERP, ERO** and **ERA** consist of two components—a scanning head and a graduation carrier, which must be aligned with each other during mounting. The eccentricity of the shaft as well as installation and adjustment therefore have a decisive effect on the achievable accuracy.



Modular angle encoders are available with various graduation carriers
- ERP/ERO: Glass circular scale with hub
- ERA 4000: Steel drum
- ERA 7000/8000: Steel tape

Angle encoders without integral bearing are designed for integration in machine elements or components. They are designed to meet the following requirements:
- Large hollow shaft diameters (up to 10 m with a scale tape)
- High shaft speeds
- No additional starting torque from shaft seals
- High reproducibility
- High adaptability to mounting space (versions with scale tape available as full circles or circle segments)

Because angle encoders without integral bearing are supplied without enclosure, the required degree of protection must be ensured through proper installation.

Selection guide on pages 6 to 9

Angle encoders with integral bearing
The angle encoders with integral bearing, **RCN, RON, RPN** and **ROD,** are complete, sealed systems. They are characterized by their simple mounting and uncomplicated adjustment. The integrated stator coupling (with the RCN, RON and RPN) or the separate shaft coupling (with the ROD) compensates axial motion of the measured shaft.



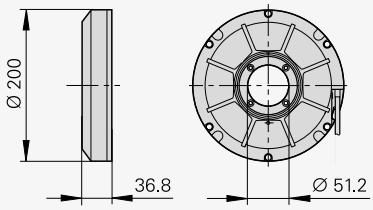
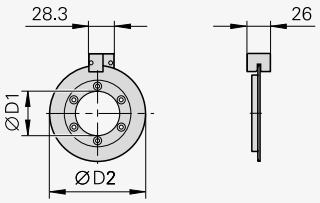
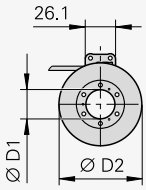
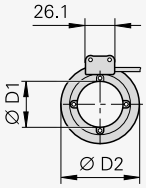
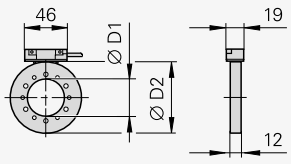
Angle encoders with integrated stator coupling therefore provide excellent dynamic performance because the coupling must absorb only that torque caused by friction in the bearing during angular acceleration of the shaft.

Other advantages:
- Compact size for limited installation space
- Hollow shaft diameters up to 100 mm to provide space for power lines, etc.
- Simple installation
- Large mounting tolerances

Selection guide on pages 10 to 13

You can find more detailed information on **angle encoders with integral bearing** on the Internet at *www.heidenhain.de* or in our separate catalog.

Selection guide
Angle encoders without integral bearing

Series	Version and mounting	Overall dimensions in mm	Diameter D1/D2	Accuracy of graduation	Mechanically permissible speed
Angle encoders with graduation on glass disk					
ERP 880	Phase-grating graduation on glass disk with hub; screwed onto front of shaft		–	± 0.9″	≤ 1 000 min^{-1}
ERP 4000	Phase-grating graduation on glass disk with hub; screwed onto front of shaft		D1: 8 mm D2: 44 mm	± 2″	≤ 300 min^{-1}
ERP 8000			D1: 50 mm D2: 108 mm	± 1″	≤ 100 min^{-1}
ERO 6000	METALLUR graduation on glass disk with hub; screwed onto front of shaft		D1: 25/95 mm D2: 71/150 mm	± 3″/ ± 2″	≤ 1 600 min^{-1}/ ≤ 800 min^{-1}
ERO 6100	Chrome graduation on glass; screwed onto front of shaft		D1: 41 mm D2: 70 mm	± 10″	≤ 3 500 min^{-1}
Angle encoders with graduation on steel scale drum					
ERA 4x80	Scale drum with centering collar; screwed onto front of shaft		D1: 40 mm to 512 mm D2: 76.5 mm to 560.46 mm	± 5″ to ± 2″	≤ 10 000 min^{-1} to ≤ 1 500 min^{-1}
ERA 4282	Scale drum for increased accuracy; screwed onto front of shaft		D1: 40 mm to 270 mm D2: 76.5 mm to 331.31 mm	± 4″ to ± 1.7″	≤ 10 000 min^{-1} to ≤ 2 500 min^{-1}

[1] Through integrated interpolation

	Interface	Signal periods per revolution	Reference marks	Model	Page
	~ 1 V_{PP}	180000	One	**ERP 880**	**34**
	~ 1 V_{PP}	131072	None	**ERP 4080**	**36**
	~ 1 V_{PP}	360000	None	**ERP 8080**	
	~ 1 V_{PP}	9000/ 18000	One	**ERO 6080**	**38**
	⊓⊔ TTL	45000 to 900000[1)]	One	**ERO 6070**	
	~ 1 V_{PP}	4096	One	**ERO 6180**	**40**
	~ 1 V_{PP}	12000 to 52000	Distance-coded	**ERA 4280C**	**42**
		6000 to 44000		**ERA 4480C**	
		3000 to 13000		**ERA 4880C**	
	~ 1 V_{PP}	12000 to 52000	Distance-coded	**ERA 4282C**	**46**



ERP 880



ERP 4080



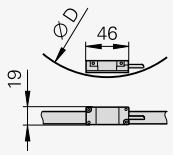
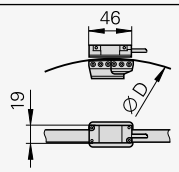
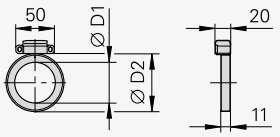
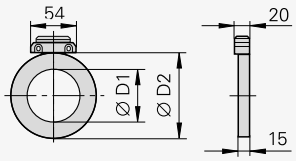
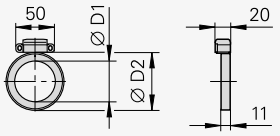
ERO 6080



ERA 4000

Selection guide

Angle encoders without integral bearing and modular encoders

Series	Version and mounting	Overall dimensions in mm	Diameter D1/D2	Accuracy of graduation	Mechanically permissible speed
Angle encoders with graduation on steel tape					
ERA 7000	Steel scale tape for internal mounting, full circle version[1]; scale tape is tensioned on the outside circumference		458.62 mm to 1146.10 mm	± 3.9″ to ± 1.6″	≤ 250 min^{-1} to ≤ 220 min^{-1}
ERA 8000	Steel scale tape for external mounting, full circle version[1]; scale tape is tensioned on the outside circumference		458.11 mm to 1145.73 mm	± 4.7″ to ± 1.9″	Approx. ≤ 45 min^{-1}
Modular encoders with magnetic graduation					
ERM 2200	Steel scale drum with MAGNODUR graduation; screwed onto front of shaft		D1: 70 mm to 380 mm D2: 113.16 mm to 452.64 mm	± 7″ to ± 2.5″	≤ 14000 min^{-1} to ≤ 3000 min^{-1}
ERM 200	Steel scale drum with MAGNODUR graduation; screwed onto front of shaft		D1: 40 mm to 410 mm D2: 75.44 mm to 452.64 mm	± 11″ to ± 3.5″	≤ 19000 min^{-1} to ≤ 3000 min^{-1}
ERM 2400	Steel scale drum with MAGNODUR graduation; fastened by clamping		D1: 40/55 mm D2: 64.37/75.44 mm	± 17″ to ± 9″	≤ 33000 min^{-1} to ≤ 27000 min^{-1}
ERM 2900			D1: 40 mm to 100 mm D2: 58.6 mm to 120.96 mm	± 68″ to ± 33″	≤ 47000 min^{-1} to ≤ 16000 min^{-1}

[1] Segment versions upon request

	Interface	Signal periods per revolution	Reference marks	Model	Page
	~ 1 V_{PP}	36000 to 90000	Distance-coded	**ERA 7480C**	**48**
	~ 1 V_{PP}	36000 to 90000	Distance-coded	**ERA 8480C**	**52**
	~ 1 V_{PP}	1800 to 7200	One	**ERM 2280**	Catalog: *Magnetic Modular Encoders*
	⊓⊔ TTL	600 to 3600	One	**ERM 220**	
	~ 1 V_{PP}			**ERM 280**	
	~ 1 V_{PP}	512 to 600	One	**ERM 2485**	
	~ 1 V_{PP}	192 to 400	One	**ERM 2984**	



ERA 7480



ERA 8480

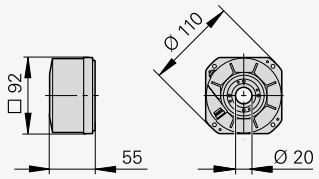
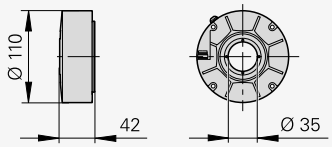
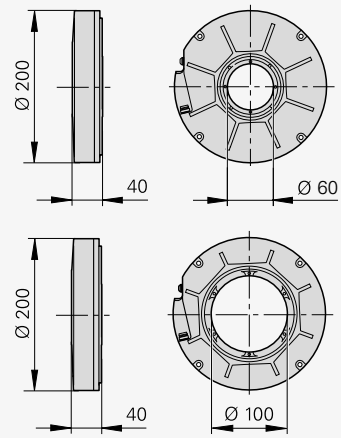
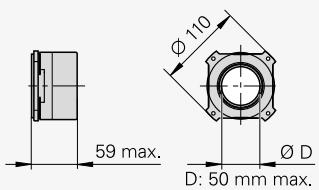


ERM 2200



ERM 280

Selection guide
Absolute angle encoders with integral bearing

Series	Overall dimensions in mm	System accuracy	Mechanically permissible speed	Position values per revolution	Interface
With integrated stator coupling					
RCN 2000		± 5″	≤ 1 500 min^{-1}	67 108 864 ≙ 26 bits	EnDat 2.2/02 EnDat 2.2/22 Fanuc 05 Mit 03-4
		± 2.5″		268 435 456 ≙ 28 bits	EnDat 2.2/02 EnDat 2.2/22 Fanuc 05 Mit 03-4
RCN 5000		± 5″	≤ 1 500 min^{-1}	67 108 864 ≙ 26 bits	EnDat 2.2/02 EnDat 2.2/22 Fanuc 05 Mit 03-4
		± 2.5″		268 435 456 ≙ 28 bits	EnDat 2.2/02 EnDat 2.2/22 Fanuc 05 Mit 03-4
RCN 8000		± 2″	≤ 500 min^{-1}	536 870 912 ≙ 29 bits	EnDat 2.2/02 EnDat 2.2/22 Fanuc 05 Mit 03-4
		± 1″			EnDat 2.2/02 EnDat 2.2/22 Fanuc 05 Mit 03-4
With mounted stator coupling					
ECN 200		± 10″	≤ 3000 min^{-1}	33 554 432 ≙ 25 bits	EnDat 2.2/02 EnDat 2.2/22
				8 388 608 ≙ 23 bits	Fanuc 02 Mit 02-4

	Incremental signals	Signal periods per revolution	Model	For more information
	~ 1 V_{PP}	16384	**RCN 2380**	Catalog: *Angle Encoders with Integral Bearing*
	–	–	**RCN 2310**	
	–	–	**RCN 2390F**	
	–	–	**RCN 2390M**	
	~ 1 V_{PP}	16384	**RCN 2580**	
	–	–	**RCN 2510**	
	–	–	**RCN 2590F**	
	–	–	**RCN 2590M**	
	~ 1 V_{PP}	32768	**RCN 5380**	
	–	–	**RCN 5310**	
	–	–	**RCN 5390F**	
	–	–	**RCN 5390M**	
	~ 1 V_{PP}	32768	**RCN 5580**	
	–	–	**RCN 5510**	
	–	–	**RCN 5590F**	
	–	–	**RCN 5590M**	
	~ 1 V_{PP}	32768	**RCN 8380**	
	–	–	**RCN 8310**	
	–	–	**RCN 8390F**	
	–	–	**RCN 8390M**	
	~ 1 V_{PP}	32768	**RCN 8580**	
	–	–	**RCN 8510**	
	–	–	**RCN 8590F**	
	–	–	**RCN 8590M**	
	~ 1 V_{PP}	2048	**ECN 225**	Catalog: *Angle Encoders with Integral Bearing*
	–	–	**ECN 225**	
	–	–	**ECN 223F**	
	–	–	**ECN 223M**	



RCN 2000



RCN 5000



RCN 8000
Ø 60 mm

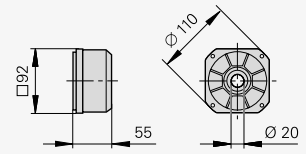
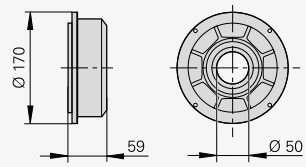
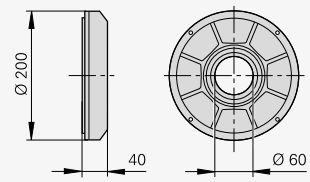
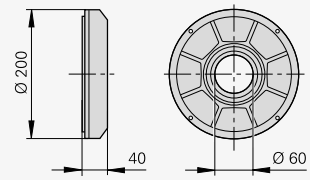
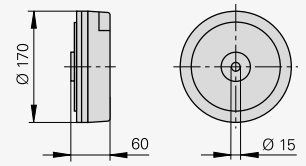
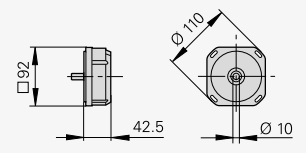
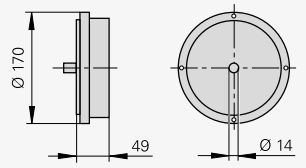


RCN 8000
Ø 100 mm



ECN 200
Ø 50 mm

Selection guide
Incremental angle encoders with integral bearing

Series	Overall dimensions in mm	System accuracy	Mechanically permissible speed	Interface
With integrated stator coupling				
RON 200		± 5″	≤ 3000 min^{-1}	⊓⊔TTL
				⊓⊔TTL
				∿ 1 V_{PP}
		± 2.5″		∿ 1 V_{PP}
RON 700		± 2″	≤ 1000 min^{-1}	∿ 1 V_{PP}
				∿ 1 V_{PP}
RON 800 **RPN 800**		± 1″	≤ 1000 min^{-1}	∿ 1 V_{PP}
				∿ 1 V_{PP}
RON 900		± 0.4″	≤ 100 min^{-1}	∿ 11 μA_{PP}
For separate shaft coupling				
ROD 200		± 5″	≤ 10000 min^{-1}	⊓⊔TTL
				⊓⊔TTL
				∿ 1 V_{PP}
ROD 700		± 2″	≤ 1000 min^{-1}	∿ 1 V_{PP}
ROD 800		± 1″	≤ 1000 min^{-1}	∿ 1 V_{PP}

[1] After integrated interpolation

	Signal periods per revolution	Model	For more information
	18000[1)]	**RON 225**	Catalog: *Angle Encoders with Integral Bearing*
	180000/90000[1)]	**RON 275**	
	18000	**RON 285**	
	18000	**RON 287**	
	18000	**RON 785**	
	18000/36000	**RON 786**	
	36000	**RON 886**	
	180000	**RPN 886**	
	36000	**RON 905**	
	18000[1)]	**ROD 220**	Catalog: *Angle Encoders with Integral Bearing*
	180000[1)]	**ROD 270**	
	18000	**ROD 280**	
	18000/36000	**ROD 780**	
	36000	**ROD 880**	



RON 285



RON 786



RON 905



ROD 280



ROD 780

Measuring principles
Measuring standard

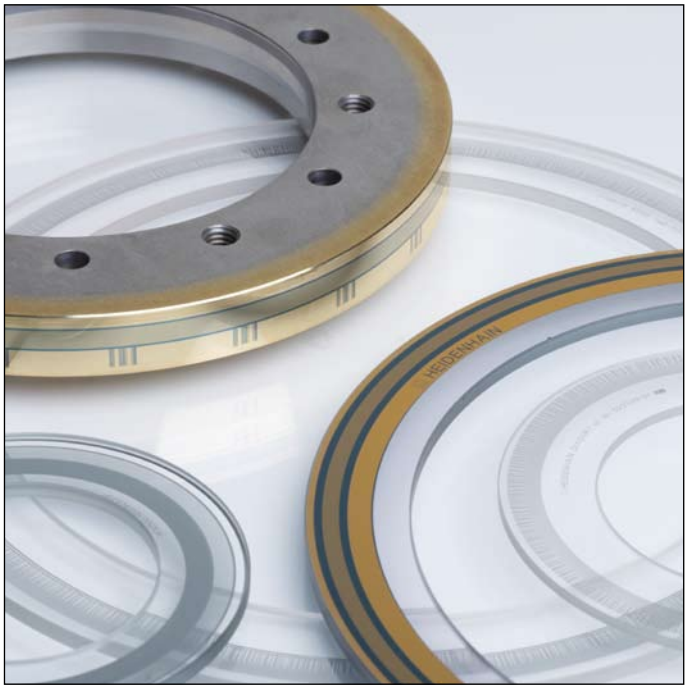
HEIDENHAIN encoders incorporate measuring standards of periodic structures known as graduations. These graduations are applied to a glass or steel substrate. Glass scales are used primarily in encoders for speeds up to 10000 min^{-1}. Steel drums are used for higher speeds—up to 20000 min^{-1}. The scale substrate for large diameters is a steel tape.

HEIDENHAIN manufactures the precision graduations in specially developed, photolithographic processes.

- AURODUR: matte-etched lines on gold-plated steel tape with typical graduation period of 40 µm
- METALLUR: contamination-tolerant graduation of metal lines on gold, with typical graduation period of 20 µm
- DIADUR: extremely robust chromium lines on glass (typical graduation period of 20 µm) or three-dimensional chrome structures (typical graduation period of 8 µm) on glass
- SUPRADUR phase grating: optically three dimensional, planar structure; particularly tolerant to contamination; typical graduation period of 8 µm and finer
- OPTODUR phase grating: optically three dimensional, planar structure with particularly high reflectance, typical graduation period of 2 µm and finer

These processes permit very fine grating periods and are characterized by a high definition and homogeneity of the line edges. Together with the photoelectric scanning method, this high edge definition is a precondition for the high quality of the output signals.

The master graduations are manufactured by HEIDENHAIN on custom-built high-precision ruling machines.



Circular graduations of angle encoders

Incremental measuring method

With the **incremental measuring method**, the graduation consists of a periodic grating structure. The position information is obtained **by counting** the individual increments (measuring steps) from some point of origin. Since an absolute reference is required to ascertain positions, the measuring standard is provided with an additional track that bears a **reference mark**. The absolute position on the scale, established by the reference mark, is gated with exactly one measuring step. The reference mark must therefore be scanned to establish an absolute reference or to find the last selected datum.

In some cases, this may require rotation by up to nearly 360°. To speed and simplify such "reference runs," many encoders feature **distance-coded reference marks**—multiple reference marks that are individually spaced according to a mathematical algorithm. The subsequent electronics find the absolute reference after traversing two successive reference marks—meaning only a few degrees of traverse (see nominal increment I in the table).

Encoders with distance-coded reference marks are identified by a "C" behind the model designation (e.g. ERA 4200C).

With distance-coded reference marks, the **absolute reference** is calculated by counting the signal periods between two reference marks and using the following formula:

$$\alpha_1 = (\text{abs A} - \text{sgn A} - 1) \times \frac{I}{2} + (\text{sgn A} - \text{sgn D}) \times \frac{\text{abs } M_{RR}}{2}$$

where:

$$A = \frac{2 \times \text{abs } M_{RR} - I}{GP}$$

Where:

α_1 = Absolute angular position of the first traversed reference mark to the zero position in degrees

abs = Absolute value

sgn = Sign function ("+1" or "–1")

M_{RR} = Measured distance between the traversed reference marks in degrees

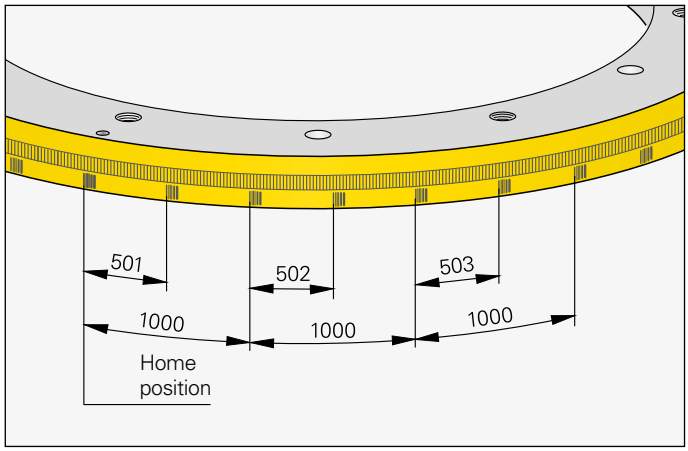
I = Nominal increment between two fixed reference marks (see tables)

GP = Grating period ($\frac{360°}{\text{Line count}}$)

D = Direction of rotation (+1 or –1). Proper rotation (indicated in the mating dimensions) equals +1.

ERA 7480C, ERA 8480C

Line count z	Number of reference marks	Nominal increment I
36000	72	10°
45000	90	8°
90000	180	4°



Schematic representation of a circular graduation with distance-coded reference marks (ERA 4480 with 20000 lines as example)

ERA 4000C

Line count for grating period 20 µm	40 µm	80 µm	Number of reference marks	Nominal increment I
–	–	3000	6	120°
8192	4096	4096	8	90°
–	–	5000	10	72°
12000	6000	–	12	60°
–	–	7000	14	51.429°
16384	8192	8192	16	45°
20000	10000	10000	20	36°
24000	12000	12000	24	30°
–	–	13000	26	27.692°
28000	14000	–	28	25.714°
32768	16384	–	32	22.5°
40000	20000	–	40	18°
48000	24000	–	48	15°
52000	26000	–	52	13.846°
–	38000	–	76	9.474°
–	44000	–	88	8.182°

Scanning the measuring standard
Photoelectric scanning

Most HEIDENHAIN encoders operate using the principle of photoelectric scanning. Photoelectric scanning of a measuring standard is contact-free, and as such, free of wear. This method detects even very fine lines, no more than a few microns wide, and generates output signals with very small signal periods.

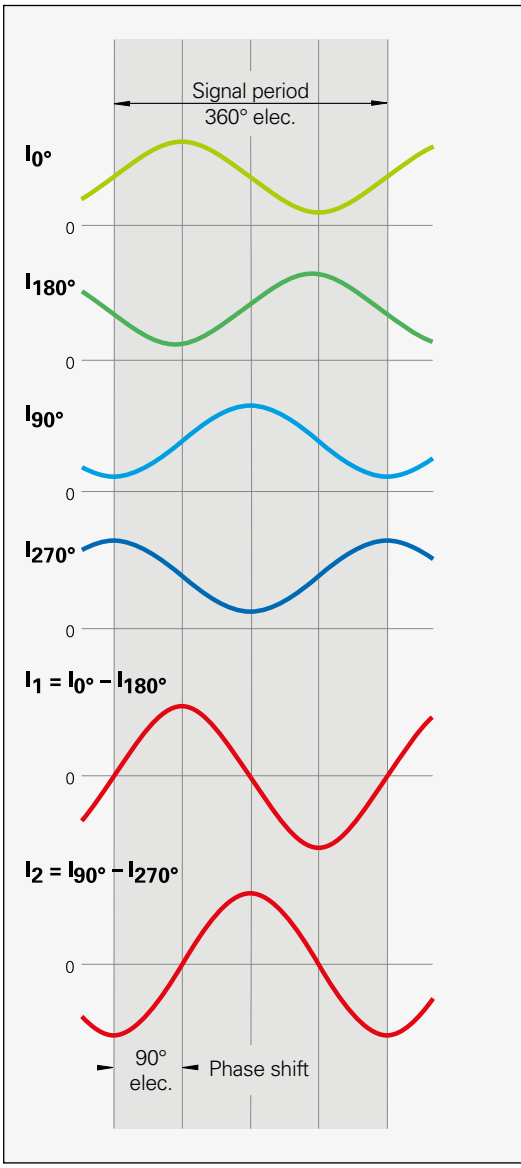
The finer the grating period of a measuring standard is, the greater the effect of diffraction on photoelectric scanning. HEIDENHAIN uses two scanning principles with angle encoders:

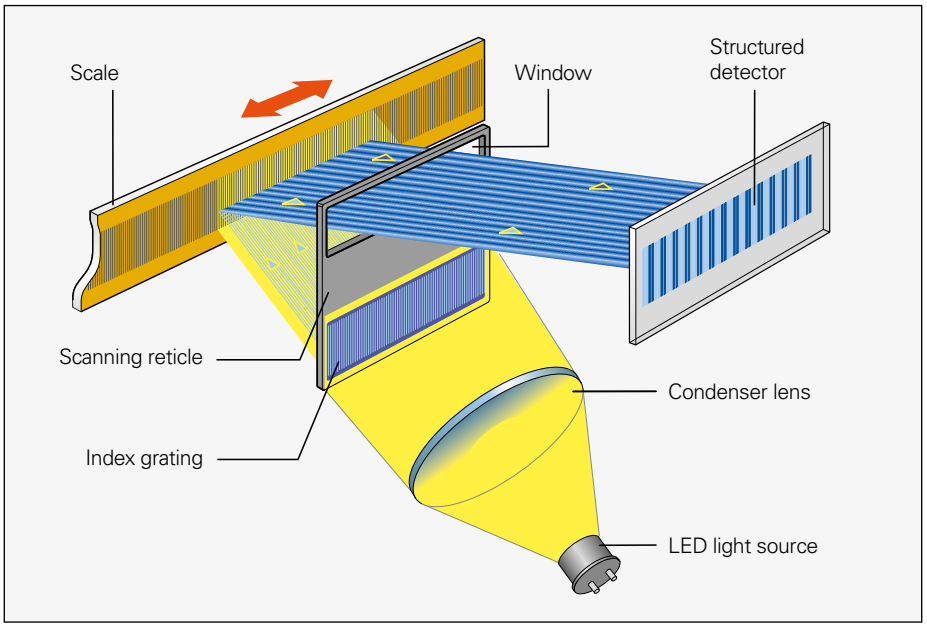
- The **imaging scanning principle** for grating periods from 10 µm to approx. 70 µm.
- The **interferential scanning principle** for very fine graduations with grating periods of 4 µm and finer.

Imaging scanning principle
Put simply, the imaging scanning principle functions by means of projected-light signal generation: two graduations with equal grating periods—the circular scale and the scanning reticle—are moved relative to each other. The carrier material of the scanning reticle is transparent, whereas the graduation on the measuring standard may be applied to a transparent or reflective surface.
When parallel light passes through a grating, light and dark surfaces are projected at a certain distance. An index grating with the same grating period is located here. When the two gratings move relative to each other, the incident light is modulated. If the gaps in the gratings are aligned, light passes through. If the lines of one grating coincide with the gaps of the other, no light passes through.

Photovoltaic cells convert these variations in light intensity into electrical signals. The specially structured grating of the scanning reticle filters the light to generate nearly sinusoidal output signals. The smaller the period of the grating structure is, the closer and more tightly toleranced the gap must be between the scanning reticle and circular scale. Practical mounting tolerances for encoders with the imaging scanning principle are achieved with grating periods of 10 µm and larger.

The ERA angle encoders, for example, operate according to the imaging scanning principle.

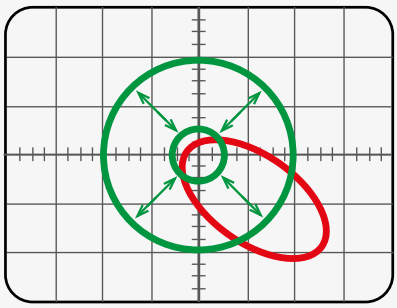




Photoelectric scanning in accordance with the imaging principle with a steel scale and single-field scanning

The sensor generates four nearly sinusoidal current signals ($I_{0°}$, $I_{90°}$, $I_{180°}$ and $I_{270°}$), electrically phase-shifted to each other by 90°. These scanning signals do not at first lie symmetrically about the zero line. For this reason the photovoltaic cells are connected in a push-pull circuit, producing two 90° phase-shifted output signals $\mathbf{I_1}$ and $\mathbf{I_2}$ in symmetry with respect to the zero line.

In the X/Y representation on an oscilloscope the signals form a Lissajous figure. Ideal output signals appear as a centered circle. Deviations in the circular form and position are caused by position error within one signal period (see *Measuring Accuracy*) and therefore go directly into the result of measurement. The size of the circle, which corresponds to the amplitude of the output signal, can vary within certain limits without influencing the measuring accuracy.



X/Y representation of the output signals

Interferential scanning principle

The interferential scanning principle exploits the diffraction and interference of light on a fine graduation to produce signals used to measure displacement.

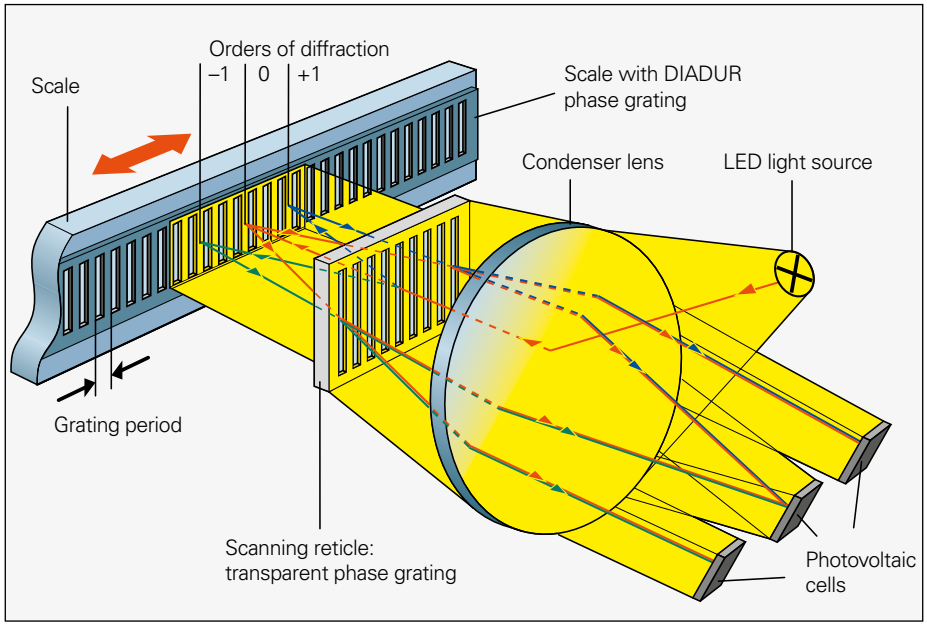
A step grating is used as the measuring standard: reflective lines 0.2 µm high are applied to a flat, reflective surface. In front of that is the scanning reticle—a transparent phase grating with the same grating period as the scale.

When a light wave passes through the scanning reticle, it is diffracted into three partial waves of the orders –1, 0, and +1, with approximately equal luminous intensity. The waves are diffracted by the scale such that most of the luminous intensity is found in the reflected diffraction orders +1 and –1. These partial waves meet again at the phase grating of the scanning reticle where they are diffracted again and interfere. This produces essentially three waves that leave the scanning reticle at different angles. Photovoltaic cells convert this alternating light intensity into electrical signals.

A relative motion of the scanning reticle to the scale causes the diffracted wave fronts to undergo a phase shift: when the grating moves by one period, the wave front of the first order is displaced by one wavelength in the positive direction, and the wavelength of diffraction order –1 is displaced by one wavelength in the negative direction. Since the two waves interfere with each other when exiting the grating, the waves are shifted relative to each other by two wavelengths. This results in two signal periods from the relative motion of just one grating period.

Interferential encoders function with average grating periods of 4 µm and finer. Their scanning signals are largely free of harmonics and can be highly interpolated. These encoders are therefore especially suited for high resolution and high accuracy. Even so, their generous mounting tolerances permit installation in a wide range of applications.

The ERP angle encoders, for example, operate according to the interferential scanning principle.



Photoelectric scanning in accordance with the interferential scanning principle and single-field scanning

Measuring accuracy

The accuracy of angular measurement is mainly determined by
- the quality of the graduation,
- the stability of the graduation carrier,
- the quality of the scanning process,
- the quality of the signal processing electronics,
- the eccentricity of the graduation to the bearing,
- the error of the bearing, and
- the coupling to the measured shaft.

These factors of influence are comprised of encoder-specific error and application-dependent issues. All individual factors of influence must be considered in order to assess the attainable total accuracy.

Encoder-specific error

The encoder-specific error is given in the Specifications:
- Accuracy of graduation
- Position error within one signal period

Accuracy of graduation

The accuracy of the graduation ± a results from its quality. This includes
- the homogeneity and period definition of the graduation,
- the alignment of the graduation on its carrier,
- *for encoders with massive graduation carriers:* the stability of the graduation carrier, in order to also ensure accuracy in the mounted condition, and
- *for encoders with steel scale tape:* the error due to irregular scale-tape expansion during mounting, as well as the error at the scale-tape butt joints of full-circle applications.

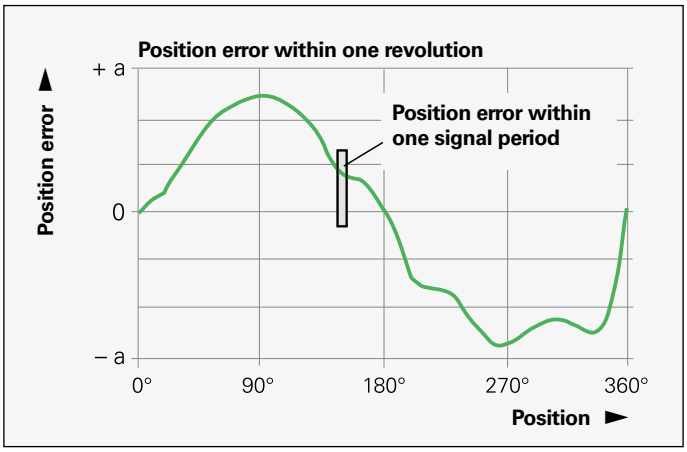
The accuracy of the graduation ± a is ascertained under ideal conditions by using a series-produced scanning head to measure position error at positions that are integral multiples of the signal period.

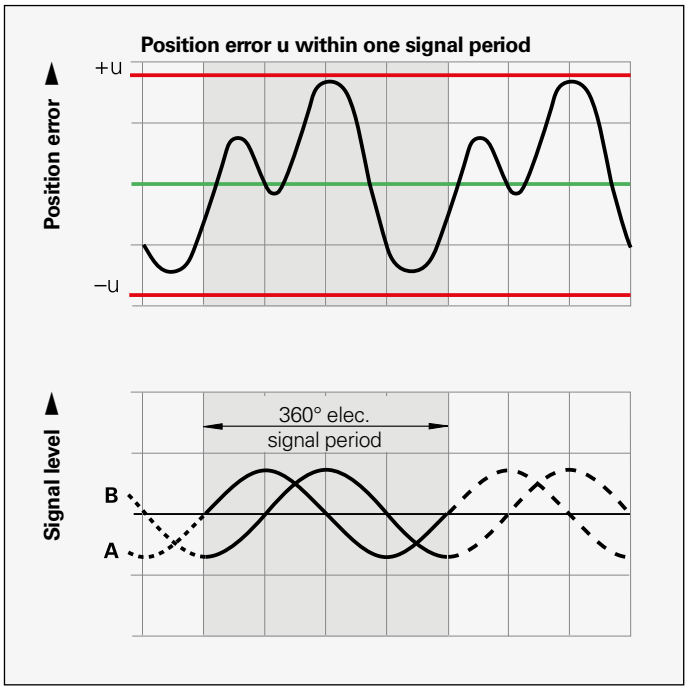
Position error within one signal period

The position error within one signal period ± u results from the quality of the scanning and—for encoders with integrated pulse-shaping or counter electronics—the quality of the signal-processing electronics. For encoders with sinusoidal output signals, however, the errors are determined by the signal processing electronics of the subsequent electronics.

The following individual factors influence the result:
- The length of the signal period
- The homogeneity and period definition of the graduation
- The quality of scanning filter structures
- The characteristics of the detectors
- The stability and dynamics of further processing of the analog signals

These factors of influence are to be considered when specifying position error within one signal period.





Position error within one signal period ± u *is specified in percent of the signal period. For modular angle encoders without integral bearing the value is typically better than ± 1 % of the signal period (ERP 880: ± 1.5 %). You will find the values in the Specifications.*

Position errors within one signal period already become apparent in very small angular motions and in repeated measurements. They especially lead to speed ripples in the speed control loop.

Application-dependent error

The mounting and adjustment of the scanning head, in addition to the given encoder-specific error, normally have a significant effect on the accuracy that can be achieved by **encoders without integral bearings**. Of particular importance are the mounting eccentricity of the graduation and the radial runout of the measured shaft. The application-dependent error values must be measured and calculated individually in order to evaluate the total accuracy.

In contrast, the specified system accuracy for encoders with integral bearing already includes the error of the bearing and the shaft coupling. (See the *Angle Encoders with Integral Bearing* catalog.)

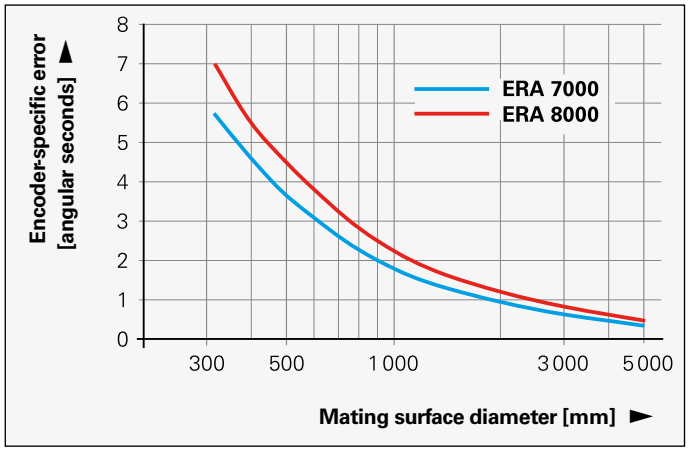
Errors due to eccentricity of the graduation to the bearing

Under normal circumstances, the graduation will have a certain eccentricity relative to the bearing once the disk/hub assembly, scale drum or steel scale tape is mounted. In addition, dimensional and form deviations of the customer's shaft can result in added eccentricity. The following relationship exists between the eccentricity e, the graduation diameter D and the measuring error Δφ (see illustration below):

$$\Delta\varphi = \pm 412 \cdot \frac{e}{D}$$

Δφ = Measuring error in " (angular seconds)
e = Eccentricity of the scale drum to the bearing in µm (1/2 the radial deviation)
D = Mean graduation diameter in mm
M = Center of graduation
φ = "True" angle
φ' = Scanned angle

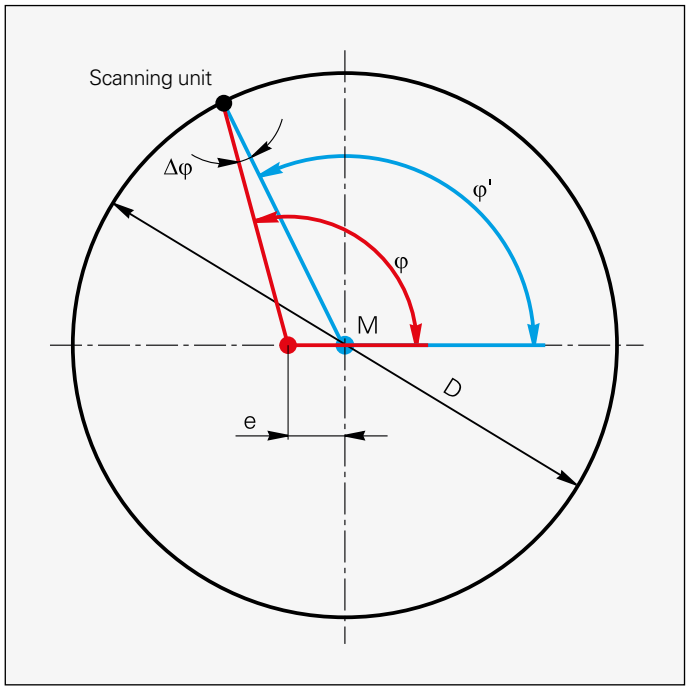
Encoder-specific error of ERA 7000 and ERA 8000



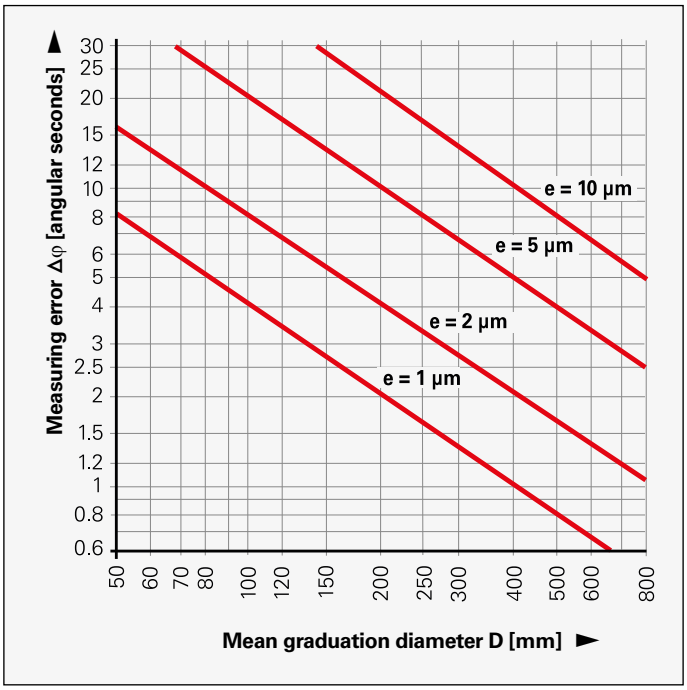
Mean graduation centerline diameter D for:

ERP 880	D = 126 mm
ERP 4000	D = 40 mm
ERP 8000	D = 104 mm
ERO 6000	D = 64 mm or 142 mm
ERO 6100	D = 64 mm
ERA 4000	D ≙ drum outside diameter
ERA 7000	D ≙ diameter of tape
ERA 8000	mating surface

Eccentricity of the graduation to the bearing



Resultant measuring error Δφ for various eccentricity values e as a function of mean graduation diameter D



Error due to radial runout of the bearing
The equation for the measuring error Δφ is also valid for radial deviation of the bearing if the value e is replaced with the eccentricity value, i.e. half of the radial deviation (half of the displayed value). Bearing compliance to radial shaft loading causes similar errors.

Deformation of the graduation resulting from mounting
The profile, reference surfaces, position of the graduation relative to the mounting surface, mounting holes, etc. of the scale drums and disk/hub assemblies are all designed so that the mounting and operation only marginally influence the accuracy of the encoders.

Shape and diameter error of the bearing surface (for ERA 7000 and ERA 8000)
Shape errors of the bearing surface can impair the attainable system accuracy.

In the segment solutions, the additional angular error Δφ occurs when the nominal scale-tape bearing-surface diameter is not exactly maintained:

$$\Delta\varphi = (1 - D'/D) \cdot \varphi \cdot 3600$$

where
Δφ = Segment deviation in angular seconds
φ = Segment angle in degrees
D = Nominal scale-tape carrier diameter
D′ = Actual scale-tape carrier diameter

This error can be eliminated if the line count per 360° z′ valid for the actual scale-tape carrier diameter D′ can be entered in the control. The following relationship is valid:

$$z' = z \cdot D'/D$$

where z = Nominal line count per 360°
z′ = Actual line count per 360°

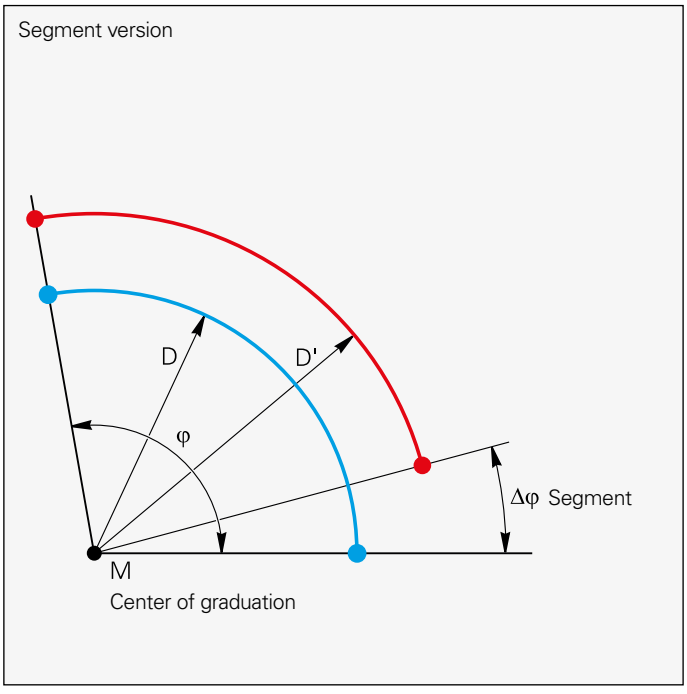
The angle actually traversed in segment versions should be measured with a comparative encoder, such as an angle encoder with integral bearing.

Compensation possibilities
The mounting eccentricity of the graduation and the radial runout of the measured shaft cause a large share of the application-dependent errors. A common and effective method of eliminating these errors is to mount two or even more scanning heads at equal distances around the graduation carrier. The subsequent electronics mathematically combine the individual position values.

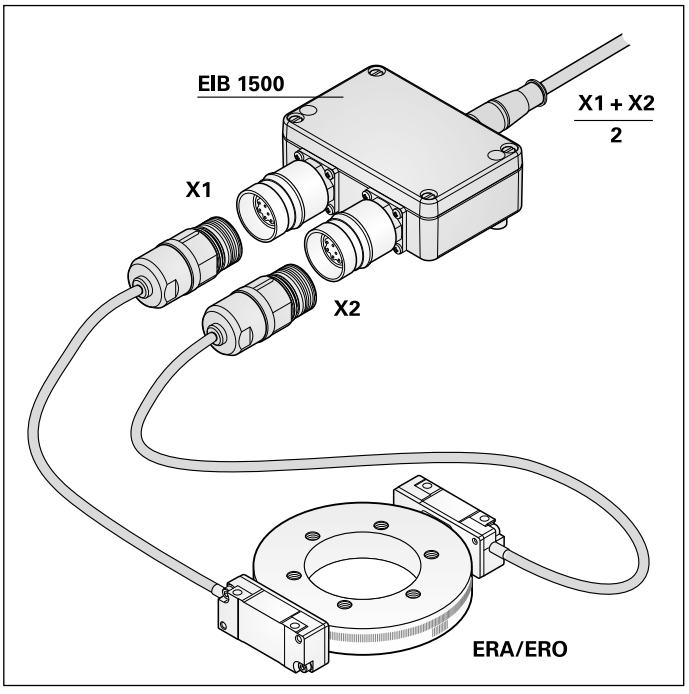
The EIB 1500 from HEIDENHAIN is an electronics unit suitable for mathematically combining the position values from two scanning heads in real time, without impairing the control loop (see *Evaluation and display units*).

The accuracy improvement actually attained by this in practice strongly depends on the installation situation and the application. In principle, all eccentricity errors (reproducible errors due to mounting errors, non-reproducible errors due to radial eccentricity of the bearing) as well as all uneven harmonics of the graduation error are eliminated.

Angular error due to variations in scale-tape carrier diameter



Position calculation of two scanning heads in order to compensate for eccentricity and radial runout



Calibration chart

For its ERP, ERO and ERA 4000 angle encoders, HEIDENHAIN prepares individual calibration charts and ships them with the encoder.

The **calibration chart** documents the graduation accuracy including the graduation carrier. It is ascertained through a large number of measuring points during one revolution. All measured values lie within the graduation accuracy listed in the specifications.

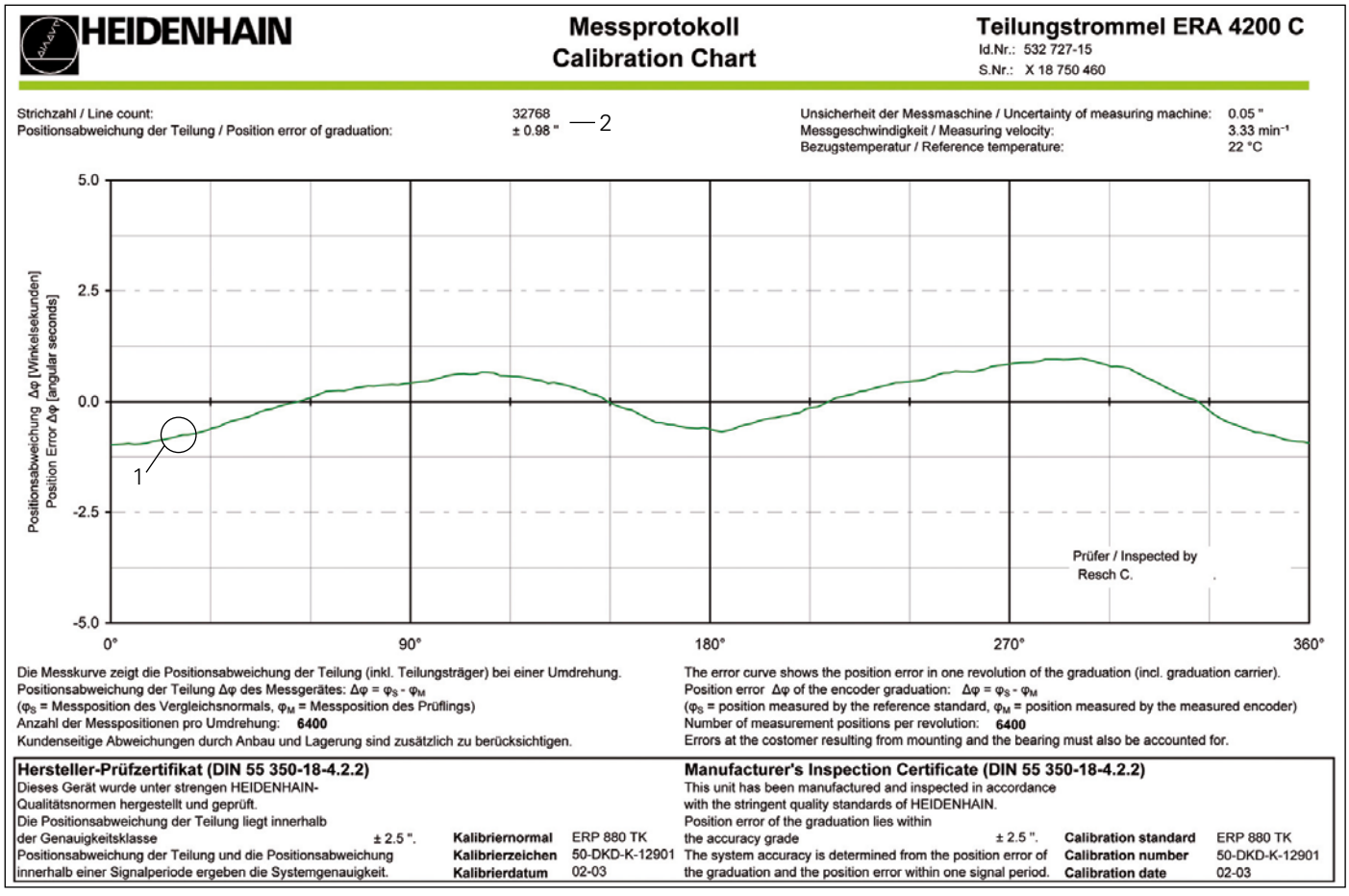
The deviations are ascertained at constant temperatures (22 °C) during the final inspection and are indicated on the calibration chart.

The **calibration standard** indicated in the manufacturer's inspection certificate documents and guarantees traceability to recognized national and international standards.

The accuracy data of the calibration chart do not include the position error within one signal period and any error resulting from mounting.

For testing and calibration purposes, angle encoders without integral bearing with massive graduation carriers are mounted at HEIDENHAIN exactly the same way as in the application later. This ensures that it possible to exactly apply the accuracy determined at HEIDENHAIN to the machine.

Calibration chart example:
ERA 4200C scale drum
1 Graphic representation of the graduation error
2 Result of calibration



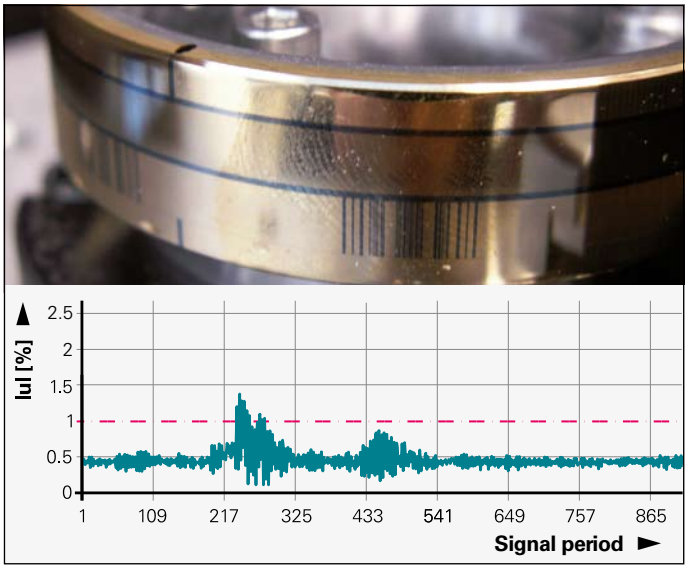
Reliability

Exposed angle encoders without integral bearing from HEIDENHAIN are optimized for use on fast, precise machines. In spite of the exposed mechanical design they are highly tolerant to contamination, ensure high long-term stability, and are quickly and easily mounted.

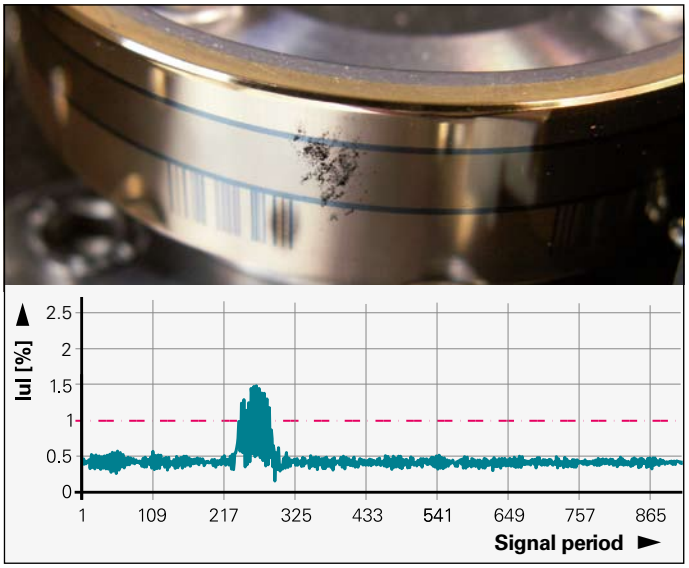
Lower sensitivity to contamination
Both the high quality of the grating and the scanning method are responsible for the accuracy and reliability of the encoders. Encoders from HEIDENHAIN operate with **single-field scanning.** Only one scanning field is used to generate the scanning signals. Local contamination on the measuring standard (e.g. fingerprints or oil accumulation) influences the light intensity of the signal components, and therefore of the scanning signals, in equal measure. The output signals do change in their amplitude, but not in their offset and phase position. They remain highly interpolable, and the position error within one signal period remains small.

The **large scanning field** additionally reduces sensitivity to contamination. In many cases this can prevent encoder failure. Even if the contamination from printer's ink, PCB dust, water or oil is up to 3 mm in diameter, the encoders continue to provide high-quality signals. The position errors within one revolution remain far below the specified accuracy.

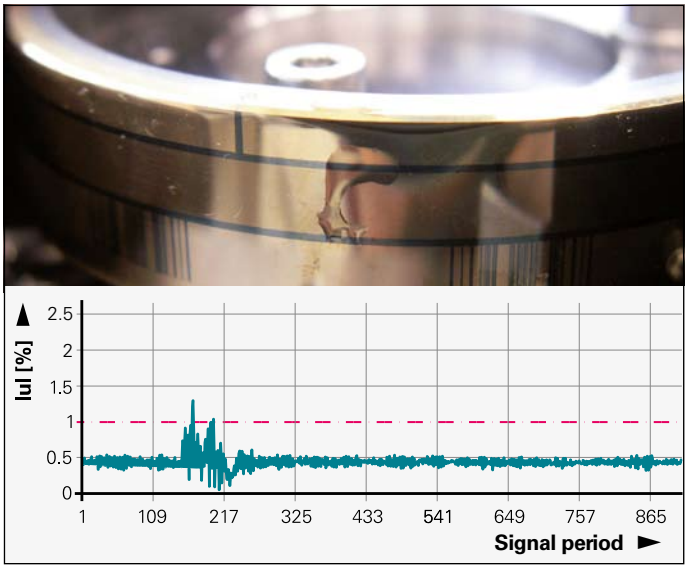
The figures at right show the results of contamination tests with ERA 4000 encoders. The maximum position errors within one signal period |u| are indicated. Despite significant contamination, the specified value of ± 1 % is exceeded only slightly.



Contamination by fingerprint



Contamination by toner dust

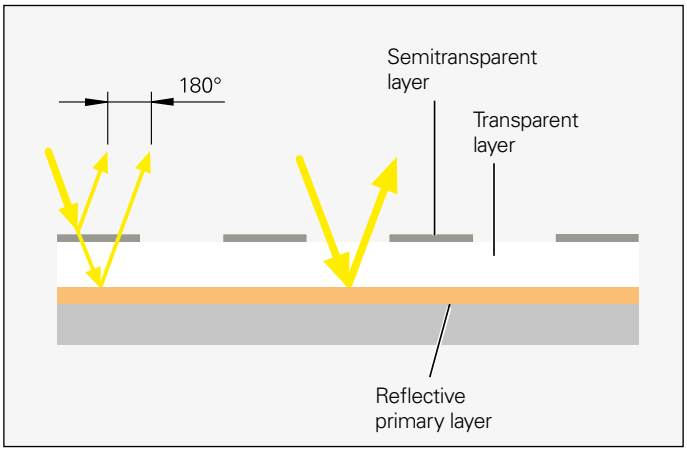


Contamination by water drops

Durable measuring standards
By the nature of their exposed design, the measuring standards of angle encoders without integral bearing are less protected from their environment. HEIDENHAIN therefore always uses tough gratings manufactured in special processes.

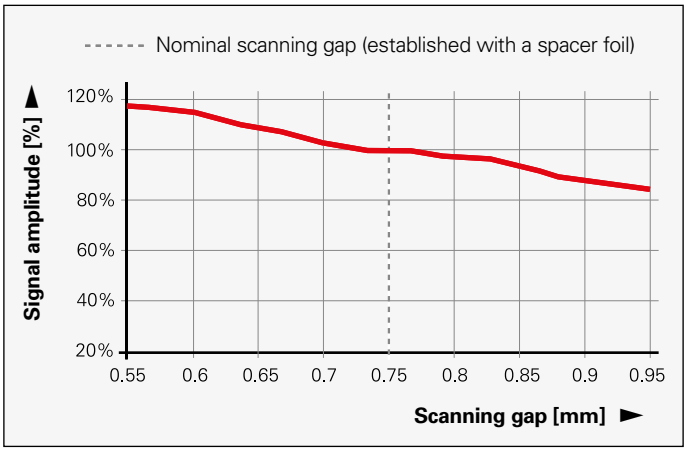
In the DIADUR process, hard chrome structures are applied to a glass or steel carrier.

In the METALLUR process a reflective gold layer is covered with a thin layer of glass. On this layer are lines of chromium only several nanometers thick, which are semitransparent and act as absorbers. Measuring standards with METALLUR graduations have proven to be particularly robust and insensitive to contamination because the low height of the structure leaves practically no surface for dust, dirt or water particles to accumulate.



Composition of a METALLUR graduation

Application-oriented mounting tolerances
The mounting tolerances of angle encoders without integral bearing from HEIDENHAIN have only a slight influence on the output signals. In particular, a variation in the scanning gap between the graduation carrier and scanning head causes only negligible change in the signal amplitude, and barely affect the position error within one signal period. This behavior is substantially responsible for the high reliability of angle encoders from HEIDENHAIN.



Influence of the scanning gap on the signal amplitude for ERA 4000

Mechanical design types and mounting
General information

Angle encoders without integral bearing consist of a scanning head and a graduation carrier. The graduation carrier can either be a scale tape or a massive component, such as a scale drum or disk/hub assembly. The motion of the scanning head and graduation relative to each other is determined solely via the machine bearing. For this reason the machine must be designed from the very beginning to meet the following prerequisites:

- The **bearing** must be designed such that the mounting tolerances of the encoders are maintained and the accuracy requirements expected for the axis are fulfilled (see *Specifications*) during mounting as well as operation.
- The **mounting surface** for the graduation carrier must meet the demands of the respective encoder regarding flatness, roundness, eccentricity and the diameter.
- To facilitate **adjustment** of the scanning head to the graduation, it should be fastened to a bracket or using appropriate fixed stops.

All angle encoders without integral bearing with **massive graduation carriers** are designed so that the specified accuracy can actually be achieved in the application. The mounting methods and alignment strategies ensure the highest possible reproducibility.

Centering the graduation
Since graduations from HEIDENHAIN have a very high degree of accuracy, the attainable overall accuracy is predominantly affected by mounting errors (mainly eccentricity errors). Various possibilities for centering, depending on the encoder and mounting method, are possible for minimizing the eccentricity errors in practice.

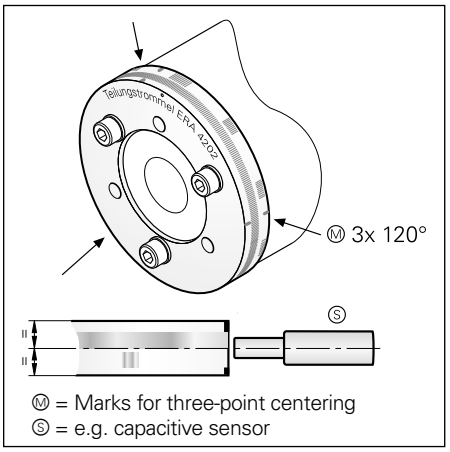
1. Centering collar
The graduation carrier is pushed or shrunk onto the shaft. However, this very simple strategy requires a very exact shaft geometry.

2. Three-point centering
The graduation carrier is centered over three positions at 120° increments marked on the carrier. That way, any roundness errors of the surface on which the carrier is being centered do not affect the exact alignment of the axis center point.

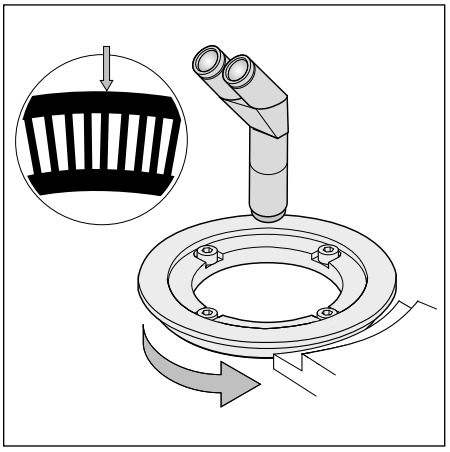
3. Optical centering
Graduation carriers made from glass are often centered with the aid of a microscope. This method uses the clear and unambiguous reference edges or centering rings on the graduation carriers.

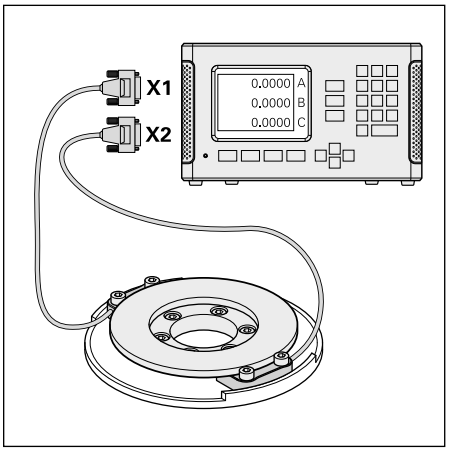
4. Centering with two scanning heads
This strategy is suited for all angle encoders without integral bearing with massive graduation carriers. Since HEIDENHAIN graduations typically have long-range error characteristics, and the graduation or position value itself is used as reference here, this is the most exact of all centering strategies.

Scanning heads
Since final assembly of the angle encoders without integral bearing takes place on the machine, exact mounting of the scanning head is necessary once the graduation carrier has been mounted. For exact alignment of the scanning head to the scale, it must in principle be aligned and adjustable in five axes (see illustration). This adjustment is greatly facilitated by the design of the scanning heads, with the corresponding mounting strategy and large mounting tolerances. For example, mounting of the scanning heads for ERA encoders is reduced to using the included spacer foil to set to scanning gap correctly.

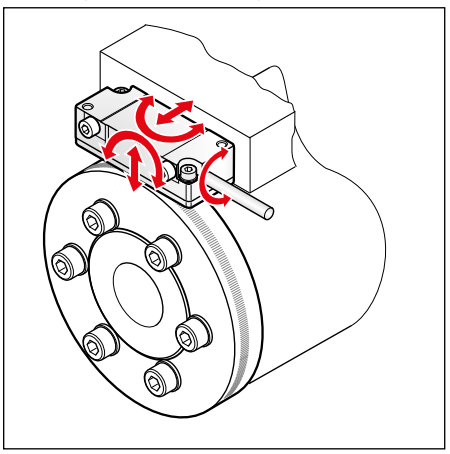


Three-point centering


Optical centering



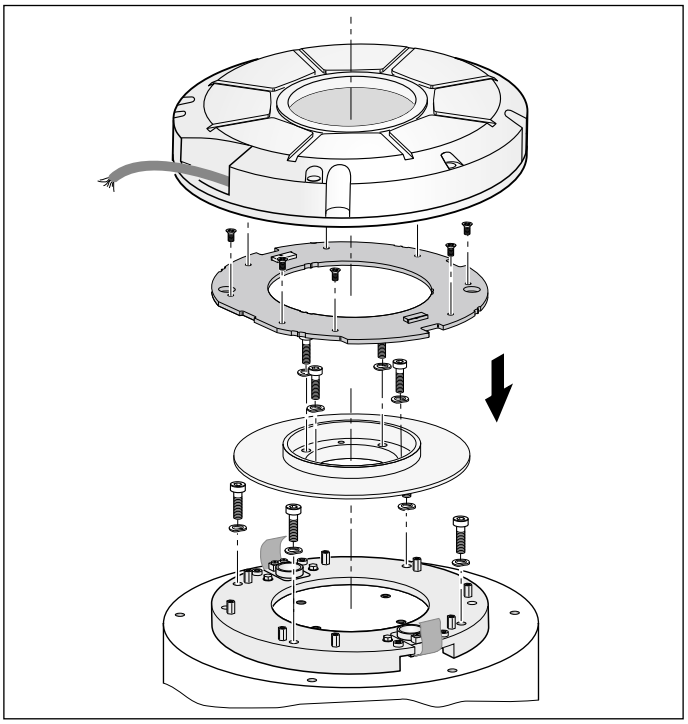
Centering with two scanning heads



ERP 880

The ERP 880 modular angle encoder consists of the following components: scanning unit, disk/hub assembly, and PCB. Cover caps for protection from contact or contamination can be supplied as accessories.

Mounting the ERP 880
First the scanning unit is mounted on the stationary machine part with an alignment accuracy to the shaft of ± 1.5 µm. Then the disk/hub assembly is screwed onto the front of the shaft, and is also aligned with a maximum eccentricity of ± 1.5 µm to the scanning unit. Then the PCB is attached and connected to the scanning unit. Fine adjustment takes place with "electrical centering" using the PWM 9 (see *HEIDENHAIN measuring equipment*) and an oscilloscope. A cover cap can protect the ERP 880 from contamination.



Mounting the ERP 880 (in principle)

IP 40 cover cap
With sealing ring for IP 40 protection
Cable, 1 m, with male coupling, 12-pin
ID 369774-01

IP 64 cover cap
With shaft sealing ring for IP 64 protection
Cable, 1 m, with male coupling, 12-pin
ID 369774-02



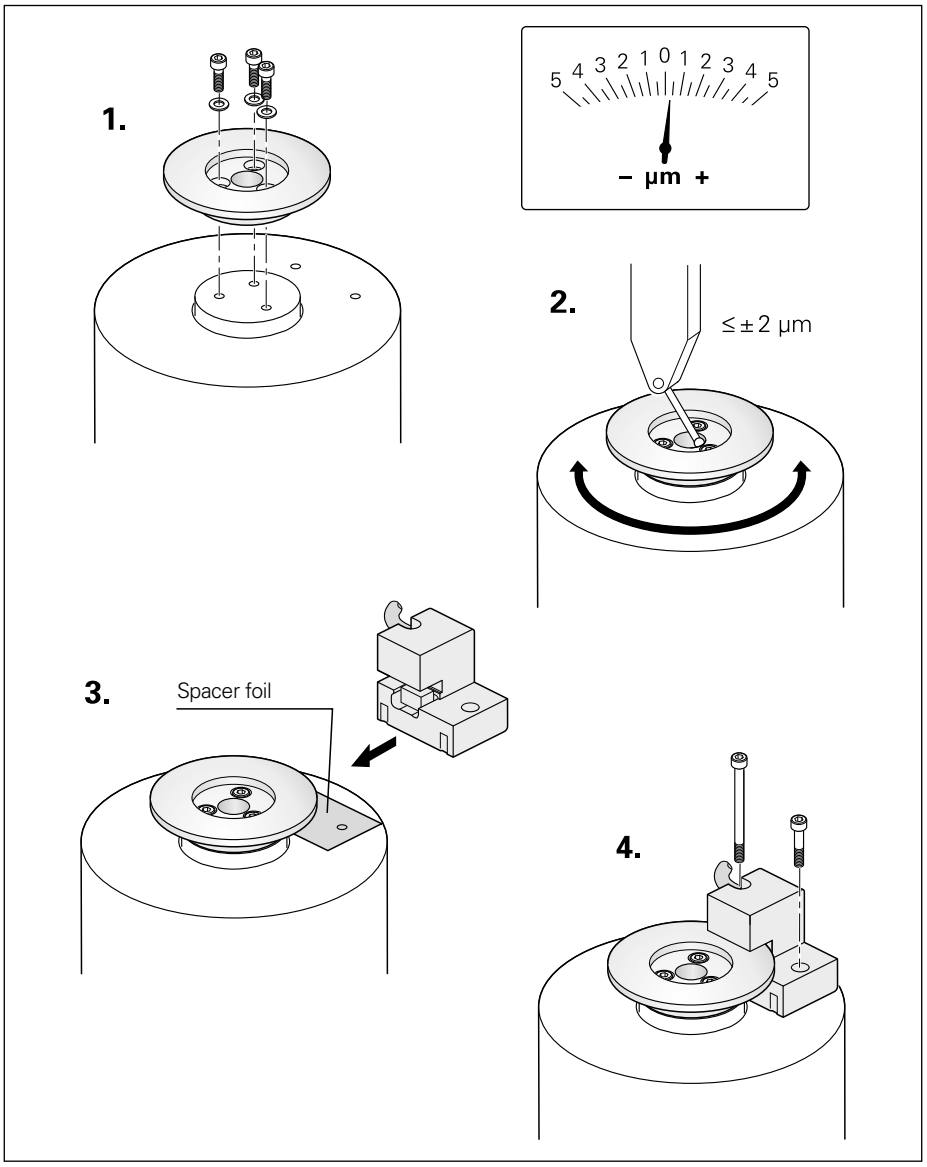
Mechanical design types and mounting
ERP 4080/ERP 8080

The ERP 4080 and ERP 8080 modular angle encoders are intended for measuring tasks requiring utmost precision and resolution. They use interferential scanning of a phase grating, and consist of a scanning head and a disk/hub assembly.

Determining the axial mounting tolerance
To attain the greatest possible accuracy, it is important to ensure that the wobble of the shaft and the wobble of the disk/hub assembly do not add to each other. The positions of the maximum and minimum wobble of the hub are marked. The wobble of the shaft must be measured and the maximum and minimum positions determined. The disk/hub assembly is then mounted such that the remaining wobble is minimized.

Mounting the disk/hub assembly
The disk/hub assembly is slid onto the drive shaft, centered using the inside diameter of the hub, and fastened with screws. The circular scale can be centered using a dial indicator on the inside diameter of the hub, or optically using the centering circle integrated in the circular scale, or electrically with the aid of a second, diametrically opposed scanning head.

Mounting the scanning head
The scanning head is fastened with two screws (or with the mounting aid) and the appropriate spacer foils on the mounting surface so that it can be moved slightly. The scanning head is adjusted electronically with the aid of the PWM 9 or PWT 18 (see *HEIDENHAIN measuring equipment*) by moving the scanning head within the mounting holes until the output signals reach an amplitude of ≥ 0.9 V_{PP}.



Accessories
Mounting aid
For adjusting the scanning head
ID 622976-02

Adapter for length gauges
For measuring the mounting tolerances
ID 627142-01

Spacer foils
For axial position adjustment

10 µm	ID 619943-01
20 µm	ID 619943-02
30 µm	ID 619943-03
40 µm	ID 619943-04
50 µm	ID 619943-05
60 µm	ID 619943-06
70 µm	ID 619943-07
80 µm	ID 619943-08
90 µm	ID 619943-09
100 µm	ID 619943-10

Set (one foil per gap from 10 µm to 100 µm): ID 619943-11

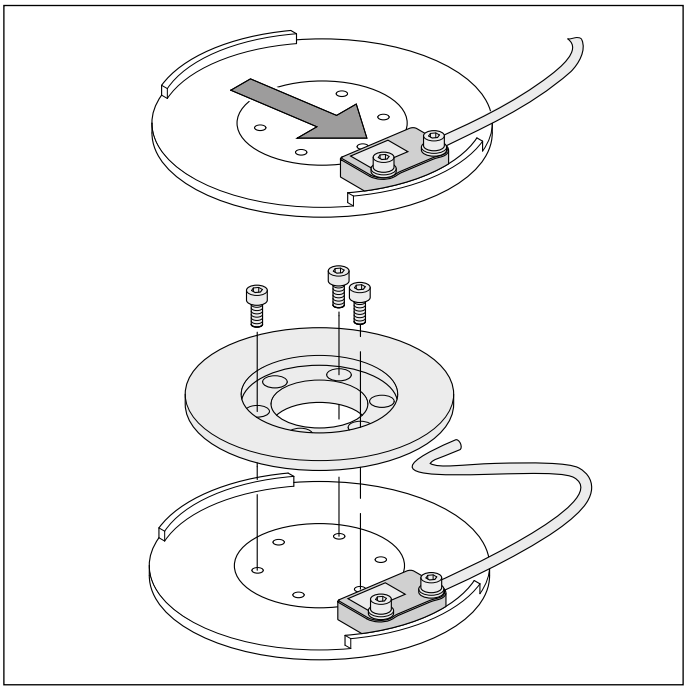
ERO 6000, ERO 6100

The ERO 6000 and ERO 6100 modular angle encoders consist of a scanning head and a disk/hub assembly. These are positioned and adjusted relative to each other on the machine.

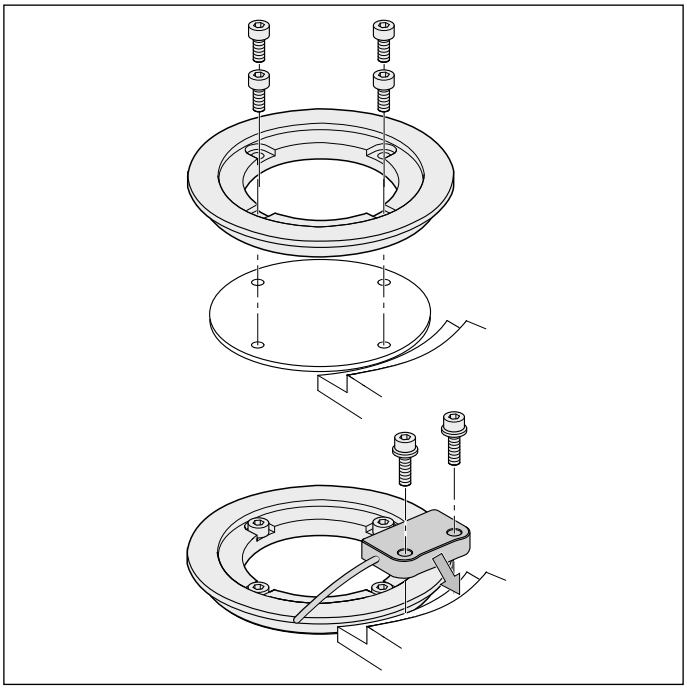
Mounting the ERO 6000
A mating surface with fixed stop and defined inside diameter is advantageous for simple mounting of the scanning head. The scanning head is pressed against this mounting surface and secured with two screws. No further alignment is necessary. Then the disk/hub assembly is screwed onto the front of the shaft, and centered either mechanically via three-point centering or electrically. The scanning gap between the scanning head and graduated disk is already defined by the mounting surface, so no further adjustment is necessary here either.

Mounting the ERO 6100
The disk/hub assembly is mounted on the shaft axially and centered optically. A mounting bracket with stop edge and defined inside diameter, and that can be adjusted axially, is advantageous for simple mounting of the scanning head. The scanning head is pressed against the stop surfaces of the mounting bracket and then secured with two screws. The included spacer foil is used to correctly set the scanning gap between the scanning head and graduated disk, and the mounting bracket is then secured.

The output signals are checked with the PWT. An APE 381 interface electronics unit is necessary for the ERO 6x80 (see *HEIDENHAIN measuring equipment*).



Mounting the ERO 6000



Mounting the ERO 6100

Mechanical design types and mounting
ERA 4000 series

The ERA 4000 modular angle encoders are supplied as two components: the scale drum and the scanning head.

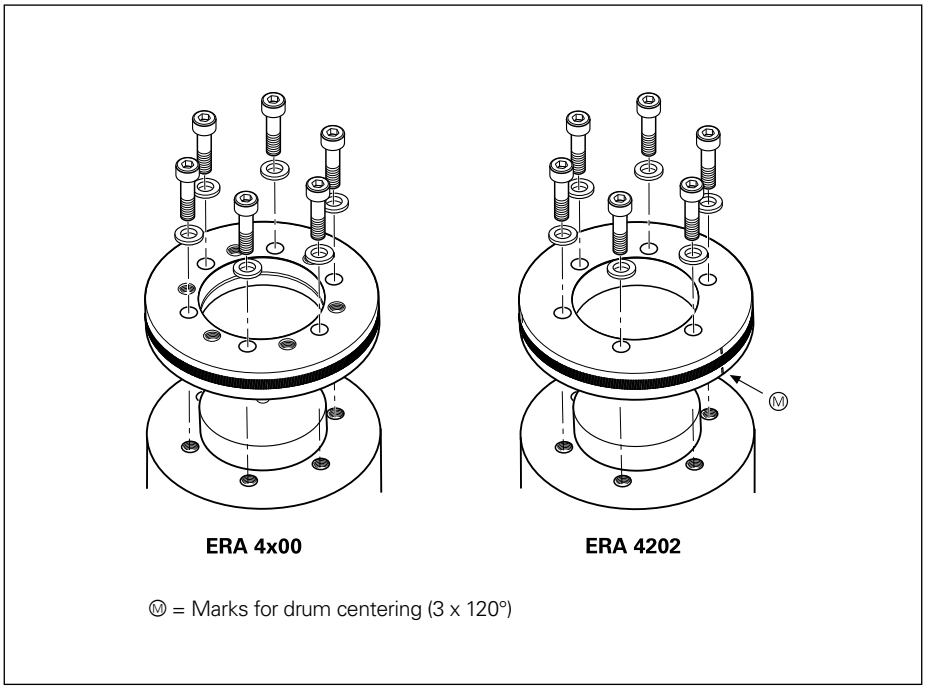
The **scanning heads** of the ERA 4000 series feature very compact dimensions. The **scale drums** of the ERA 4000 are available in different versions to suit the particular application. The ERA 4x80 versions are available with various grating periods depending on the accuracy requirements. The appropriate scanning heads are shown in the table at right. Special design measures are required to protect the ERA from contamination. The ERA 4480 angle encoders are also available for various drum diameters with a protective cover. A special scanning head (with compressed-air inlet) is needed for versions with protective cover. The protective cover suited to the scale drum diameter must be ordered separately.

Application	Scale drum	Grating periods	Model	Appropriate scanning head
High shaft speeds	Centering collar	20 µm	ERA 4200	ERA 4280
		40 µm	ERA 4400	ERA 4480
		80 µm	ERA 4800	ERA 4880
Increased positioning accuracy and high shaft speeds	Three-point centering	20 µm	ERA 4202	ERA 4280

Special design features of the ERA modular angular encoders assure comparatively fast mounting and easy adjustment.

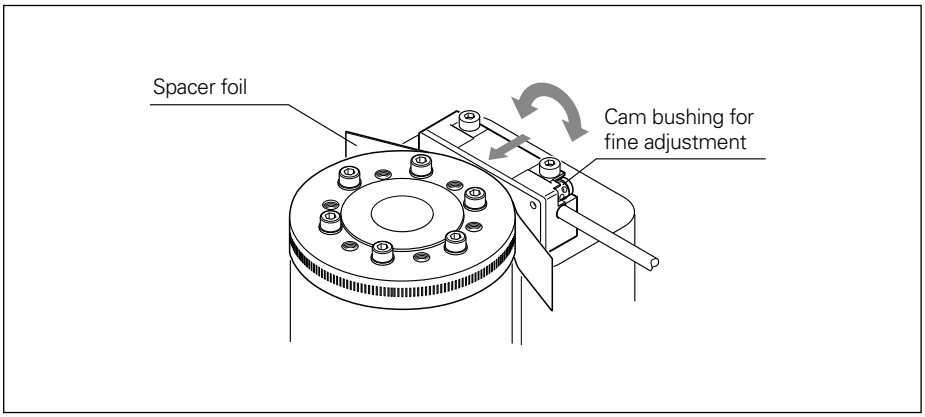
Mounting the ERA 4x00 scale drum
The scale drum is slid onto the drive shaft and fastened with screws. The scale drum is centered via the centering collar on its inner circumference. The drum does not need to be adjusted. HEIDENHAIN recommends a slight oversize of the shaft on which the scale drum is to be mounted. For mounting, the scale drum may be slowly warmed on a heating plate over a period of approx. 10 minutes to a maximum temperature of 100 °C.

Mounting the ERA 4202 scale drum
The scale drum is centered over three positions at 120° increments on its circumference and fastened with screws. The benefits of three-point centering and the solid design of the scale drum make it possible to attain a very high accuracy when the encoder is mounted, with relatively little mounting effort. The positions for centering are marked on the scale drum.



Mounting the scale drums

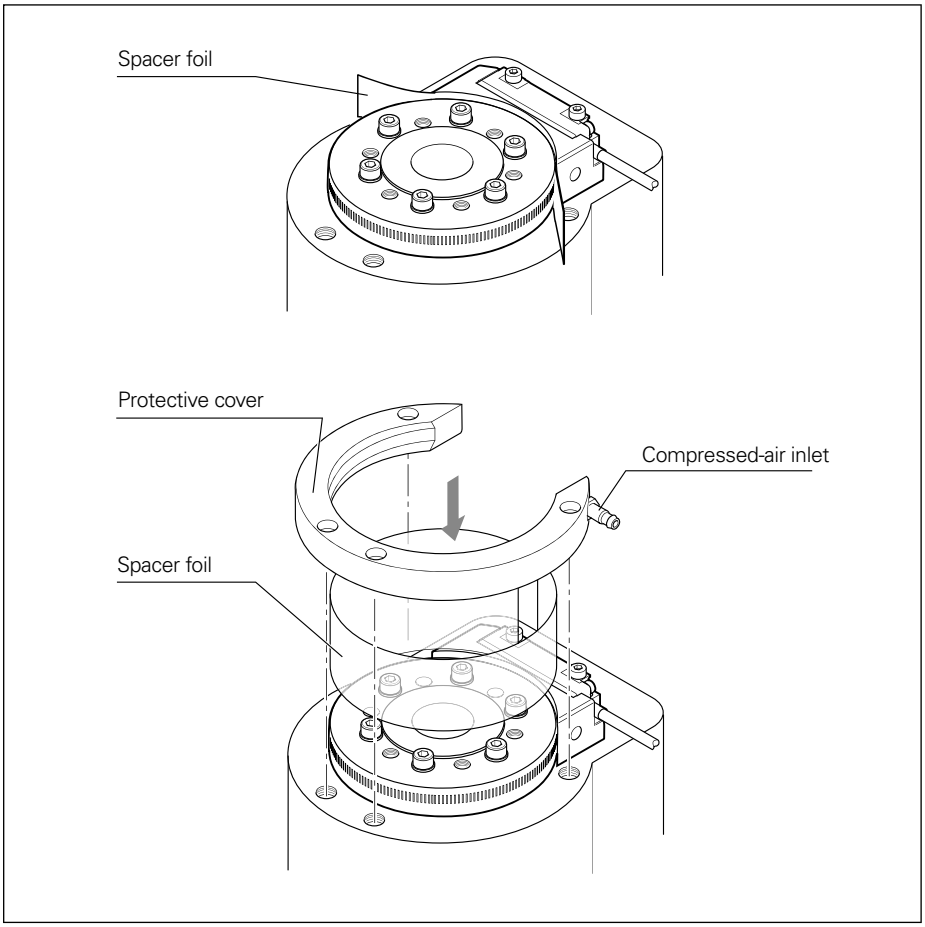
Mounting the scanning head
In order to mount the scanning head, the spacer foil is held against the circumference of the scale drum. The scanning head is pressed against the foil and fastened. The foil is then removed. ERA 4000 encoders with 20 µm grating period also feature a cam bushing for fine adjustment of the scanning field.



Mounting the scanning head

Mounting the protective cover
The ERA 4480 modular angle encoders with protective cover are available in various diameters. This cover provides additional protection against contamination when compressed air is applied.

The scale drum and the scanning unit are mounted as described above. The separate spacer foil supplied with the protective cover is placed around the scale drum. It protects the scale drum when mounting the protective cover, and ensures that a constant scanning gap is maintained. Then the protective cover is slid onto the scale drum and secured. The spacer foil is removed. For information about the compressed-air inlet see *General mechanical information*.



Mounting an ERA 4480 with protective cover

Mechanical design types and mounting
ERA 7000 and ERA 8000 series

The ERA 7000 and ERA 8000 series of angle encoders consist of a scanning unit and a one-piece steel scale tape. The steel scale tape is available up to a length of 30 m. The tape is mounted on

- the **inside diameter** (ERA 7000 series) or
- the **outside diameter** (ERA 8000 series)

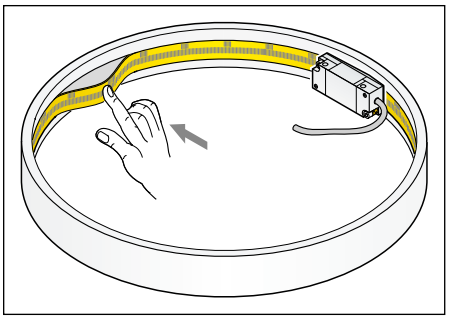
of a machine element.

The ERA 74x0C und ERA 84x0C angle encoders are designed for **full-circle applications.** Thus, they are particularly suited to hollow shafts with large inside diameters (from approx. 400 mm) and to applications requiring an accurate measurement over a large circumference, e.g. large rotary tables, telescopes, etc.

In applications where there is no full circle, or measurement is not required over 360°, **circle segments** are available.

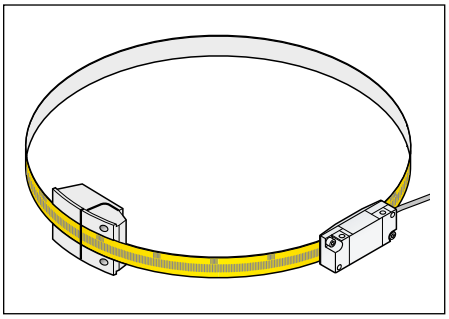
Mounting the scale tape for full-circle applications

ERA 74x0C: An **internal slot** with a specified diameter is required as scale tape carrier. The tape is inserted starting at the butt joint and is clicked into the slot. The length is cut so that the tape is held in place by its own force.



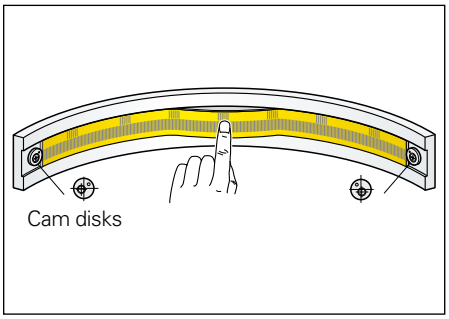
ERA 84x0C: The scale tape is supplied with the halves of the tensioning cleat already mounted on the tape ends. An **external slot** is necessary for mounting. A recess must also be provided for the tensioning cleat. After the scale tape has been inserted, it is fastened aligned along the slot edge and tensioned using the tensioning cleat.

The scale tape ends are manufactured so exactly that only minor signal-form deviations can occur in the area of the butt joint. To make sure that the scale tape does not move within the slot, it is fixed with adhesive at multiple points in the area of the butt joint.

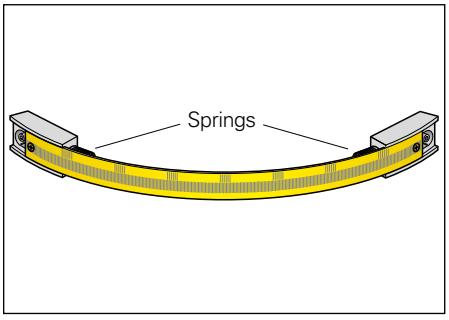


Mounting the scale tape for circle segments

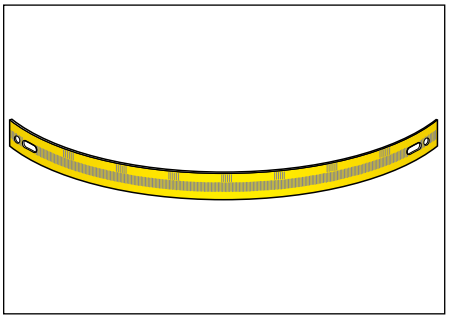
ERA 74x1C: An internal slot with a specified diameter is required. The two cam disks fixed in this slot are adjusted so that the scale can be snapped into the slot under pressure.



ERA 84x1C: The scale tape is supplied with premounted end pieces. An external slot with recesses for the bearing pieces is required for placing the scale tape. The end pieces are fitted with tension springs, which create an optimal bearing preload for increasing the accuracy of the scale tape, and evenly distribute the expansion over the entire length of the scale tape.



ERA 84x2C: An external slot or one-sided axial stop is recommended for placing the scale tape. The scale tape is supplied without tensioning elements. It must be preloaded with a spring balance, and secured using the two oblong holes.



Determining the mating diameter
In order to guarantee the correct functioning of the distance-coded reference marks, the circumference must be a multiple of 1 000 grating periods. The association between the mating diameter and the line count can be seen in the table.

Specification of segment angle
For segment versions the angle available as measuring range must be a multiple of 1 000 grating periods. Also, the circumference of the theoretical full circle must be a multiple of 1 000 grating periods, since this often simplifies integration with the numeric control.

Mounting the scanning head
In order to mount the scanning head, the spacer foil is held against the circumference of the scale drum. The scanning head is pressed against the foil and fastened. The foil is then removed. In addition, the scanning field can be finely adjusted via a cam bushing.

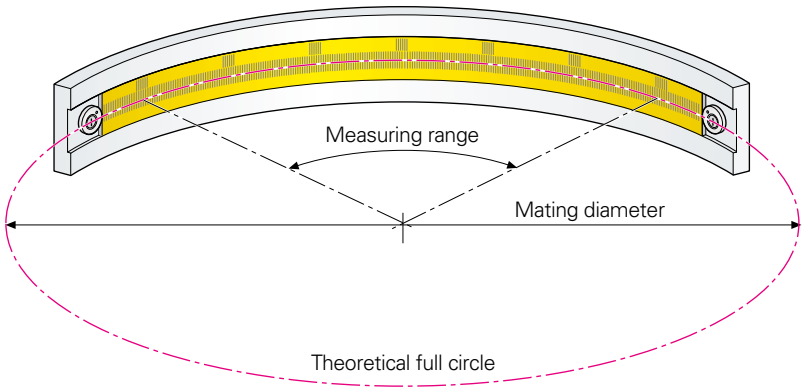
Checking the output signals at the butt joint
In order to check whether the scale tapes of the ERA 74x0C and ERA 84x0C have been mounted correctly, the output signals should be checked at the butt joint—before the adhesive has hardened.

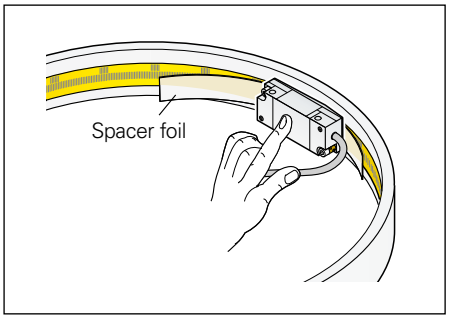
The quality of the output signals can be checked using HEIDENHAIN's PWT phase-angle testing unit. When the scanning head is moved along the scale tape, the PWT graphically displays the quality of the signals as well as the position of the reference mark.

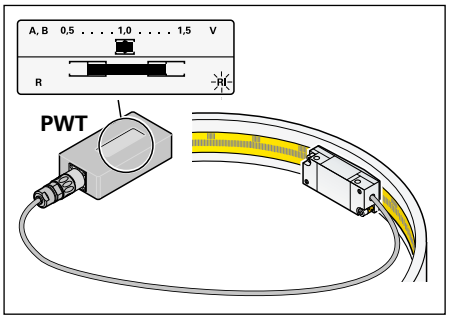
The PWM 9 phase angle measuring unit calculates a quantitative value for the deviation of the actual output signals from the ideal signal (see *HEIDENHAIN measuring equipment*).

	Mating diameter in mm	**Measuring range in degrees for segment versions**
ERA 7000C	n · 0.01273112 +0.3	n_1 · 4.583204 : (D–0.3)
ERA 8000C	n · 0.0127337 -0.3	n_1 · 4.584121 : (D+0.3)

n = line count of full circle; n_1 = line count of measuring range
D = mating diameter [mm]







General mechanical information

Protection
For angle encoders **without integral bearing,** the necessary protection against contamination and contact must be ensured during installation through design measures such as additional labyrinth seals.

Unless otherwise indicated, all RCN, RON, RPN and ROD angle encoders **with integral bearing** meet protection standard IP 67 according to EN 60529 or IEC 60529 for the housing and cable outlet, and IP 64 at the shaft inlet.

Some versions of the ERA 4480 angle encoders up to a drum inside diameter of 180 mm are available with an optional protective cover. Connection to a source of compressed air slightly above atmospheric pressure provides additional protection against contamination.

The compressed air introduced directly onto the encoders must be cleaned by a micro filter, and must comply with the following quality classes as per **ISO 8573-1** (2010 edition):

- Solid contaminants: **Class 1**

Particle size	Number of particles per m^3
0.1 µm to 0.5 µm	≤ 20000
0.5 µm to 1.0 µm	≤ 400
1.0 µm to 5.0 µm	≤ 10

- Max. pressure dewpoint: **Class 4** (pressure dewpoint at 3 °C)
- Total oil content: **Class 1** (max. oil concentration: 0.01 mg/m^3)

For optimum supply of sealing air to the angle encoders with integral bearing, the required air flow is 1 to 4 l/min per encoder. Ideally the air flow is regulated by the HEIDENHAIN connecting pieces with integrated throttle (see *Accessories*). At an inlet pressure of approx. $1 \cdot 10^5$ Pa (1 bar), the throttles ensure the prescribed volume of airflow.

Accessory:
DA 400 compressed air unit
ID 894602-01

DA 400
HEIDENHAIN offers the DA 400 compressed-air filter system for purifying the compressed air. It is designed specifically for the introduction of compressed air into encoders.

The DA 400 consists of three filter stages (prefilter, fine filter and activated carbon filter) and a pressure regulator with pressure gauge. The pressure gauge and the automatic pressure switch (which is available as an accessory) effectively monitor the sealing air.

The compressed air introduced into the DA 400 must fulfill the requirements of the following purity classes as per DIN/ISO 8573-1 (2010 edition):

- Particles: **Class 5**

Particle size	Number of particles per m^3
0.1 µm to 0.5 µm	Not specified
0.5 µm to 1.0 µm	Not specified
1.0 µm to 5.0 µm	≤ 100000

- Max. pressure dewpoint: **Class 6** (pressure dewpoint at 10 °C)
- Total oil content: **Class 4** (max. oil concentration: 5 mg/m^3)



The following components are necessary for connection to angle encoders:

Connecting piece, straight
with throttle and gasket
ID 226270-xx

Connecting piece, straight, short
with throttle and gasket
ID 275239-xx

M5 coupling joint, swiveling
with seal
ID 207834-xx

For more information, ask for our *DA 400* Product Information sheet.

Temperature range
The angle encoders are inspected at a **reference temperature** of 22 °C. The system accuracy given in the calibration chart applies at this temperature.
The **operating temperature range** indicates the ambient temperature limits between which the angle encoders will function properly.
The **storage temperature range** of –30 °C to +80 °C is valid as long as the unit remains in its packaging (ERP 4080/ERP 8080: 0 °C to 60 °C).

Protection against contact
After encoder installation, all rotating parts must be protected against accidental contact during operation.

Acceleration
Angle encoders are subject to various types of acceleration during operation and mounting.
- The indicated maximum values for **vibration** are valid according to EN 60068-2-6.
- The maximum permissible acceleration values (semi-sinusoidal shock) for **shock and impact** are valid for 6 ms (EN 60068-2-27).
  Under no circumstances should a hammer or similar implement be used to adjust or position the encoder.

Shaft speeds
The maximum permissible shaft speeds for the ERA 4000 angle encoders series were determined according to the FKM guideline. This guideline serves as mathematical attestation of component strength with regard to all relevant influences and it reflects the latest state of the art. The requirements for fatigue strength (10 million reversals of load) were considered in the calculation of the permissible shaft speeds. Because installation has a significant influence, all requirements and directions in the specifications and mounting instructions must be followed for the shaft-speed data to be valid.

Expendable parts
Encoders from HEIDENHAIN are designed for a long service life. Preventive maintenance is not required. However, they contain components that are subject to wear, depending on the application and manipulation. These include in particular cables with frequent flexing.

Other such components are the bearings of encoders with integral bearing, shaft sealing rings on rotary and angle encoders, and sealing lips on sealed linear encoders.

System tests
Encoders from HEIDENHAIN are usually integrated as components in larger systems. Such applications require **comprehensive tests of the entire system** regardless of the specifications of the encoder.

The specifications shown in this brochure apply to the specific encoder, not to the complete system. Any operation of the encoder outside of the specified range or for any other than the intended applications is at the user's own risk.

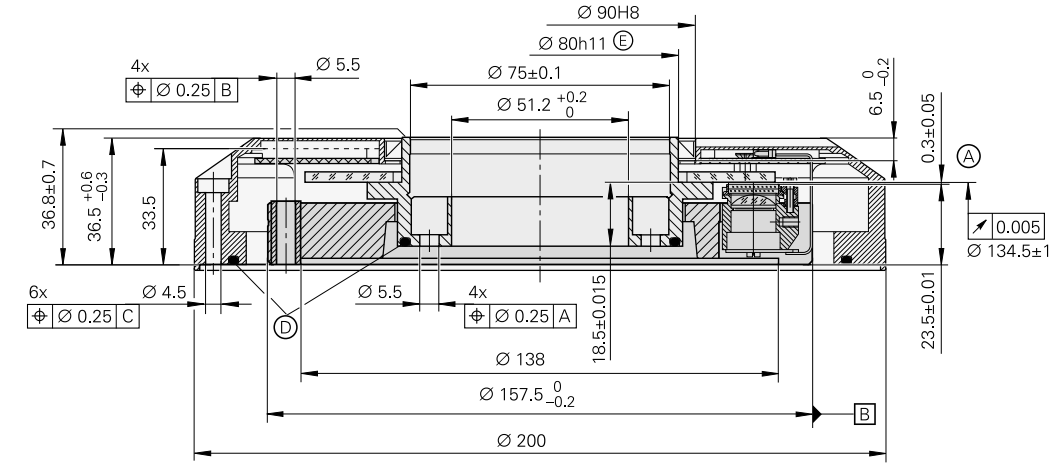
Mounting
Work steps to be performed and dimensions to be maintained during mounting are specified solely in the mounting instructions supplied with the unit. All data in this catalog regarding mounting are therefore provisional and not binding; they do not become terms of a contract.

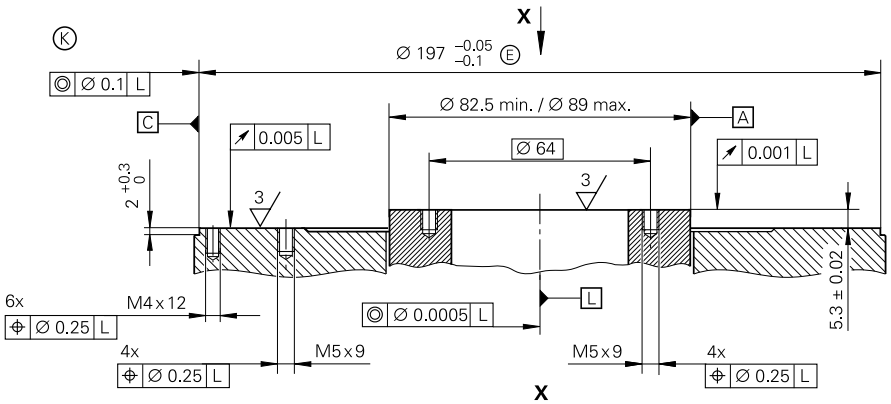
DIADUR, AURODUR and METALLUR are registered trademarks of DR. JOHANNES HEIDENHAIN GmbH, Traunreut.

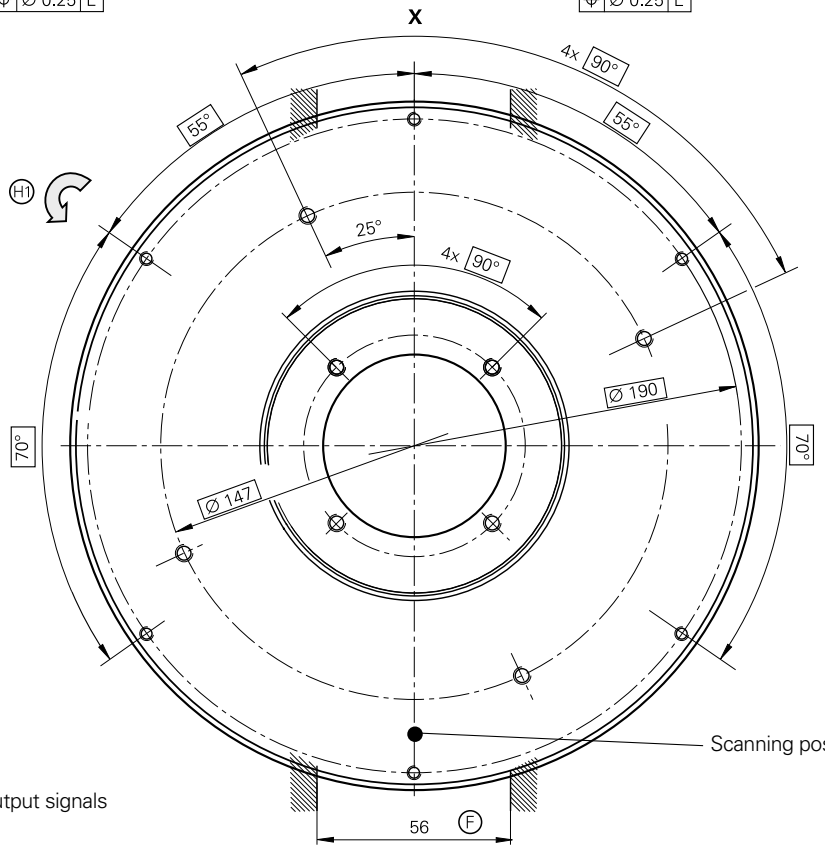
ERP 880

Incremental angle encoder for very high accuracy
- **High resolution**
- **Protective cover as accessory**









mm

Tolerancing ISO 8015
ISO 2768 - m H
< 6 mm: ±0.2 mm

Cable radial, also usable axially
Ⓐ = Disk-to-scanning-reticle gap
Ⓛ = Axis of bearing rotation
Ⓚ = Required mating dimensions
Ⓕ = Space needed for service
Ⓓ = Seal
Ⓗ1 = Direction of shaft rotation for output signals as per the interface description

	ERP 880		
Measuring standard	DIADUR phase grating on glass		
Signal periods	180 000		
Accuracy of graduation	± 0.9″		
Position error per signal period[1)]	± 0.1″		
Reference marks	One		
Hub inside diameter	51.2 mm		
Mech. permissible speed	≤ 1 000 min^{-1}		
Moment of inertia of rotor	$1.2 \cdot 10^{-3}$ kgm^2		
Permissible axial motion of measured shaft	≤ ± 0.05 mm		
Interface	⌒ 1 V_{PP}		
Cutoff frequency –3 dB –6 dB	≥ 800 kHz ≥ 1.3 MHz		
Electrical connection	*With cover:* Cable 1 m, with M23 coupling *Without cover:* Via 12-pin PCB connector (adapter cable ID 372164-xx)		
Cable length	≤ 150 m (with HEIDENHAIN cable)		
Voltage supply	5 V DC ± 0.5 V		
Current requirement	≤ 250 mA (without load)		
Vibration 55 to 2 000 Hz **Shock** 6 ms	≤ 50 m/s^2 (EN 60 068-2-6) ≤ 1 000 m/s^2 (EN 60 068-2-27)		
Operating temperature	0 °C to 50 °C		
Protection* EN 60 529	*Without cover:* IP 00	*With cover:* IP 40	*With cover and rotary shaft seal:* IP 64
Starting torque	–		0.25 Nm
Weight	3.0 kg	3.1 kg incl. cover	

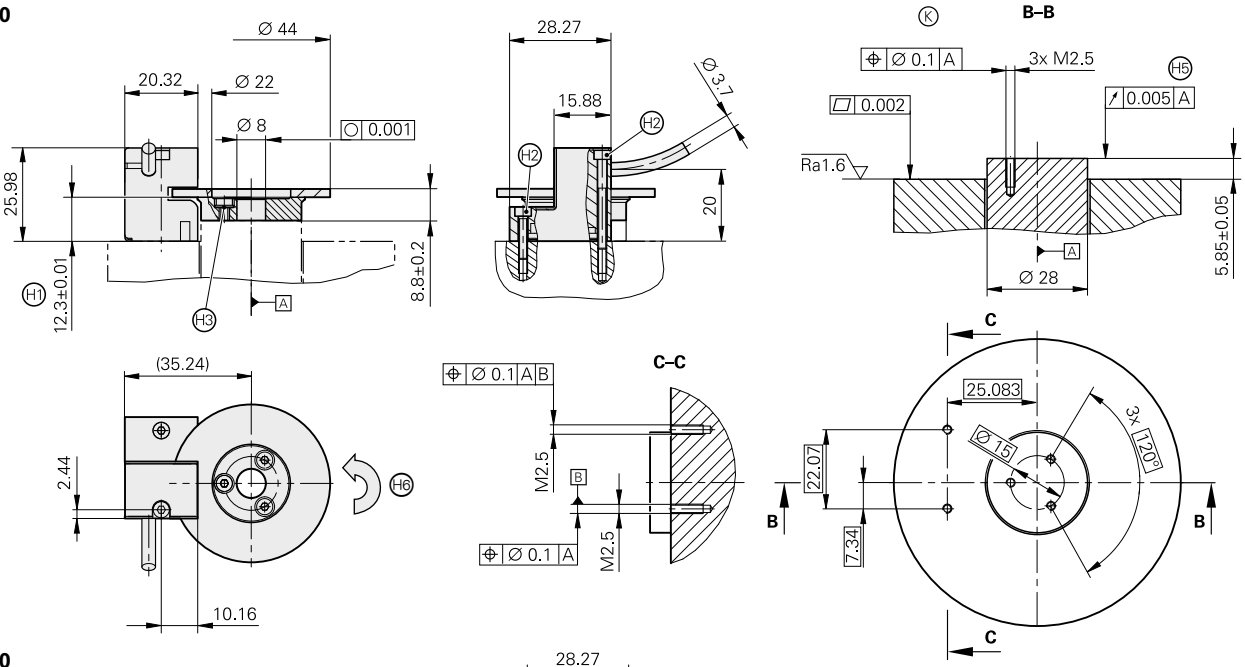
***** Please select when ordering
[1)] The position error within one signal period and the accuracy of the graduation result together in the encoder-specific error; for additional error through mounting and the bearing of the measured shaft, see *Measuring accuracy*

ERP 4080/ERP 8080

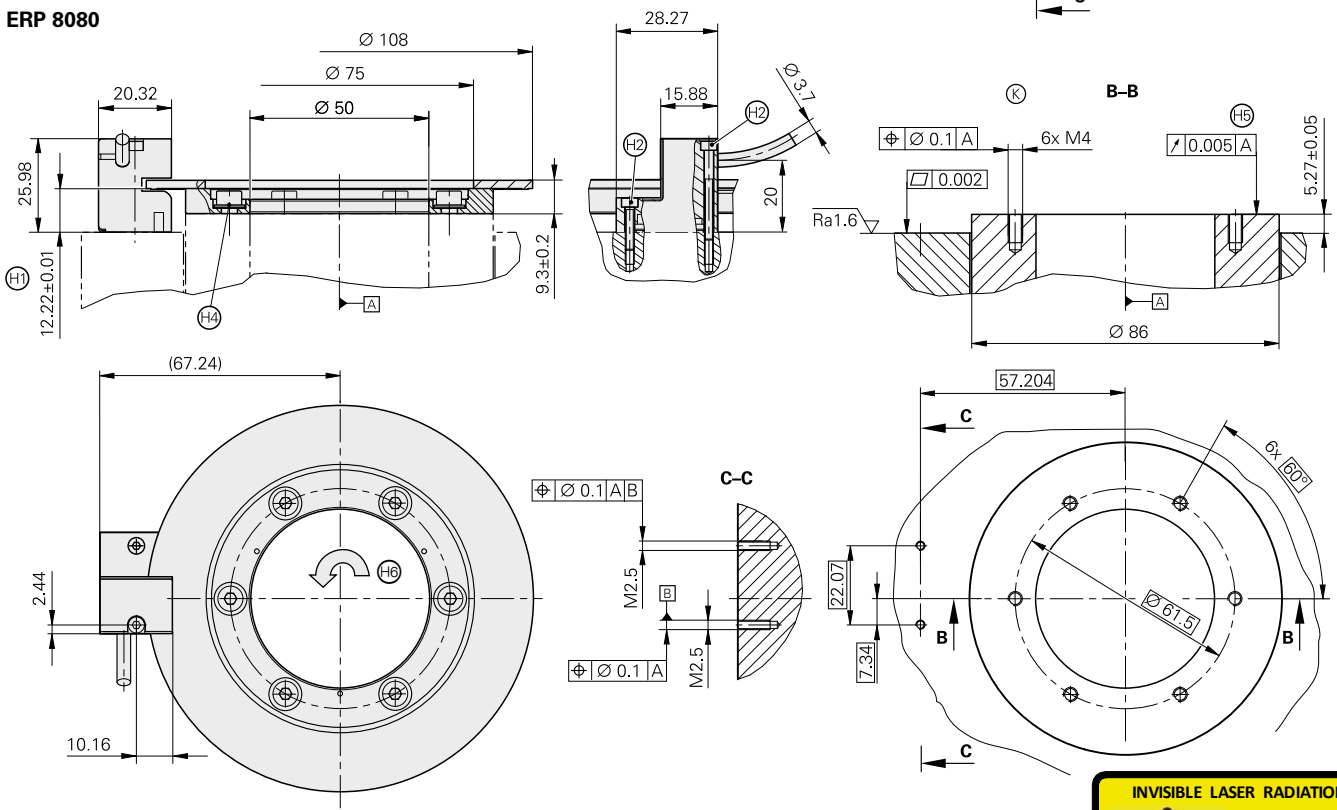


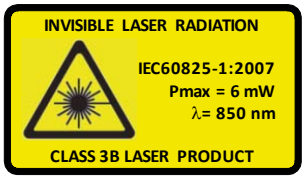
Incremental angle encoder for high accuracy
- **Highest resolution**
- **Consists of scanning head and disk/hub assembly**

ERP 4080



ERP 8080





mm

Tolerancing ISO 8015
ISO 2768 - m H
< 6 mm: ±0.2 mm

Ⓐ = Bearing
Ⓚ = Required mating dimensions
Ⓗ1 = Mounting clearance set with spacer foil
Ⓗ2 = Cylinder head screw ISO 4762–A2–M2.5
Ⓗ3 = Cylinder head screw ISO 4762–A2–M2.5 and washer ISO 7089–2.5–140HV–A2
Ⓗ4 = Cylinder head screw ISO 4762–A2–M4 and washer ISO 7089–4–140HV–A2
Ⓗ5 = Mounting surface not convex
Ⓗ6 = Direction of shaft rotation for output signals as per the interface description

Scanning head	AK ERP 4080	AK ERP 8080
Interface	⌒ 1 V_{PP}	
Cutoff frequency –3 dB	≥ 250 kHz	
Electrical connection	Cable 1 m, with D-sub connector (15-pin)	
Cable length	≤ 30 m (with HEIDENHAIN cable)	
Voltage supply	5 V DC ± 0.25 V	
Current requirement	≤ 150 mA (without load)	
Laser	*Scanning head and graduated disk mounted:* Class 1 *Scanning head not mounted:* Class 3B *Laser diode used:* Class 3B	
Vibration 55 to 2000 Hz **Shock** 6 ms	≤ 50 m/s^2 (EN 60068-2-6) ≤ 500 m/s^2 (EN 60068-2-27)	
Operating temperature	15 °C to 40 °C	
Weight (approx.)	33 g (without cable)	

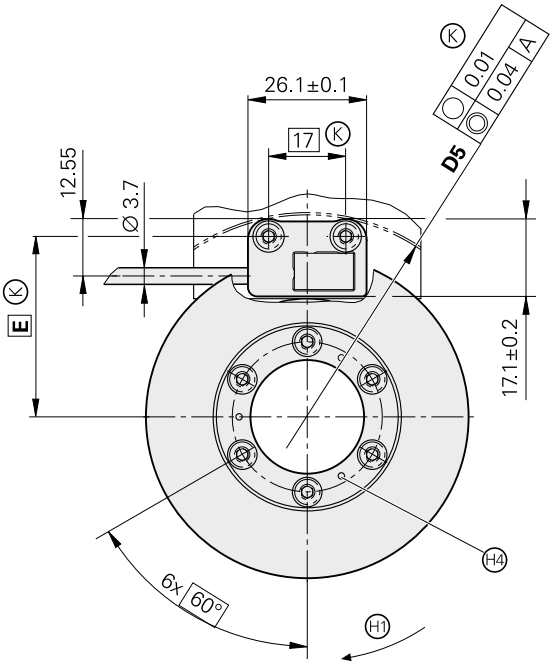
Graduated disk	TKN ERP 4080	TKN ERP 8080
Measuring standard	Phase-grating graduation on glass	
Signal periods	131072	360000
Accuracy of graduation	± 2″	± 1″
Position error per signal period[1]	± 0.1″	± 0.05″
Reference marks	None	
Hub inside diameter	8 mm	50 mm
Mech. permissible speed	≤ 300 min^{-1}	≤ 100 min^{-1}
Moment of inertia of rotor	$5 \cdot 10^{-6}$ kgm^2	$250 \cdot 10^{-6}$ kgm^2
Permissible axial motion of measured shaft	≤ ± 0.01 mm (including wobble)	
Protection EN 60529	IP 00 (for clean room application)	
Weight (approx.)	36 g	180 g

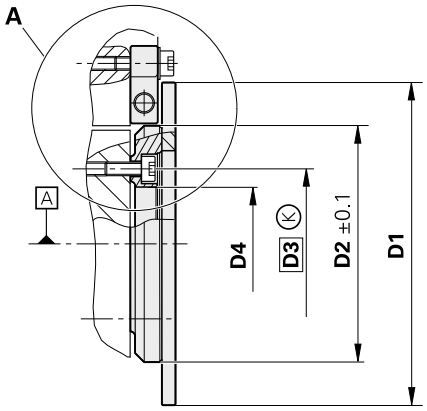
[1] The position error within one signal period and the accuracy of the graduation result together in the encoder-specific error; for additional error through mounting and the bearing of the measured shaft, see *Measuring accuracy*

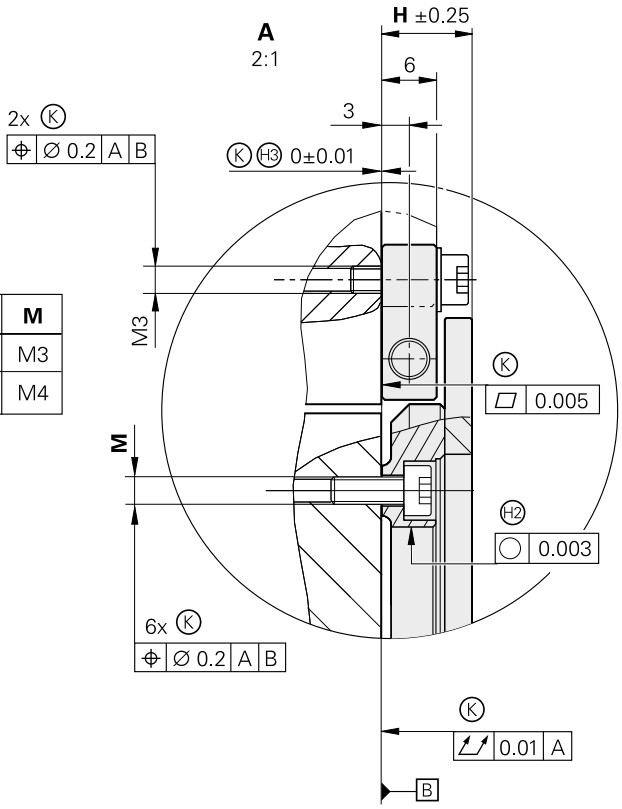
ERO 6000 series



Incremental angle encoder for high accuracy
- **Compact design**
- **Low weight, low moment of inertia**
- **Consists of scanning head and disk/hub assembly**







D1	D2	D3	D4	D5	E	H	M
Ø 71	Ø 52	Ø 33	Ø 25H6	Ø 88.9H6	39.7	9.9	M3
Ø 150	Ø 130	Ø 107	Ø 95 $^{+0.015}_{0}$	Ø 166H6	78.7	10.2	M4

Tolerancing ISO 8015
ISO 2768 - m H
< 6 mm: ±0.2 mm

A = Bearing
K = Required mating dimensions
H1 = Positive direction of rotation
H2 = Centering collar
H3 = Mounting tolerance between mounting surface of scanning head and disk/hub assembly
H4 = Marks for centering the circular scale (3 x 120°)

Scanning head	AK ERO 6080	AK ERO 6070		
Interface	∿ 1 V_{PP}	⊓⊔ TTL x 5	⊓⊔ TTL x 10	⊓⊔ TTL x 50
Reference mark signal	Square-wave pulse			
Integrated interpolation*	–	5-fold	10-fold	50-fold
Cutoff frequency –3 dB	≥ 200 kHz	–	–	–
Scanning frequency	–	≤ 200 kHz	≤ 100 kHz	≤ 25 kHz
Edge separation a	–	≥ 0.220 µs	≥ 0.220 µs	≥ 0.175 µs
Electrical connection	Cable 3 m with male D-sub connector (15-pin), interface electronics for ERO 6070 in the connector			
Cable length	≤ 30 m			
Voltage supply	5 V DC ± 0.25 V			
Current requirement	< 100 mA (without load)	< 200 mA (without load)		
Vibration 55 to 2000 Hz **Shock** 6 ms	200 m/s² 400 m/s²			
Operating temperature	0 °C to 50 °C			
Weight (approx.) Scanning head Connector Cable	6 g (without cable) 32 g 22 g/m	6 g (without cable) 140 g 22 g/m		

Graduated disk	TKN ERO 6000	
Measuring standard	METALLUR graduation on glass	
Signal periods*	9000	18000
Accuracy of graduation	± 3″	± 2″
Position error per signal period[1)]	± 2″	± 1″
Reference marks	One	
Hub inside diameter	25 mm	95 mm
Circular scale outside diameter	71 mm	150 mm
Mech. permissible speed	≤ 1600 min^{-1}	≤ 800 min^{-1}
Moment of inertia	44 x 10^{-6} kgm^2	1.1 x 10^{-3} kgm^2
Permissible axial motion	≤ 0.1 mm	
Protection EN 60529	IP 00	
Weight (approx.)	84 g	323 g

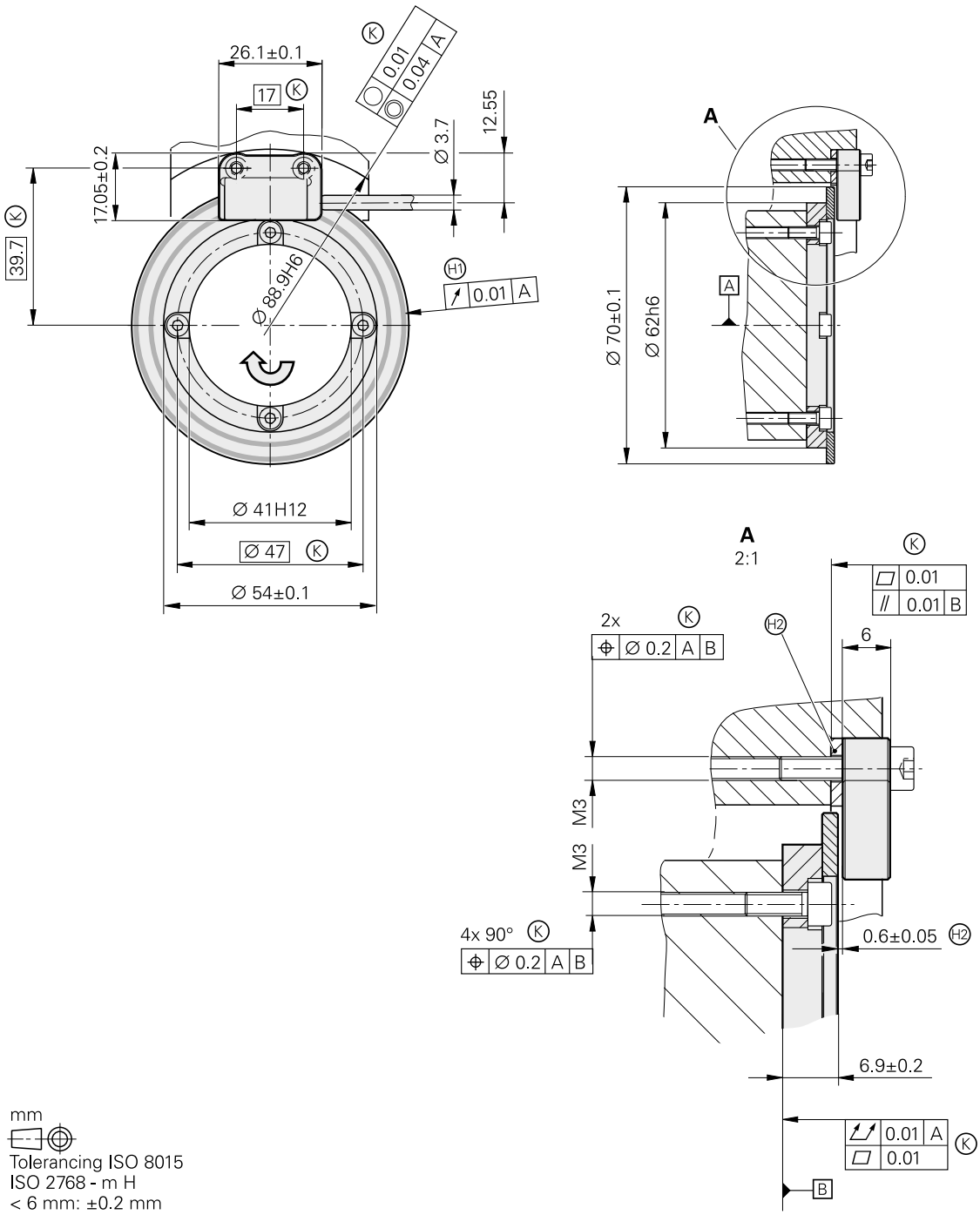
***** Please select when ordering

[1)] The position error within one signal period and the accuracy of the graduation result together in the encoder-specific error; for additional error through mounting and the bearing of the measured shaft, see *Measuring accuracy*

ERO 6180

Incremental angle encoder
- **Compact design**
- **Low weight, low moment of inertia**
- **Consists of scanning head and disk/hub assembly**





mm
Tolerancing ISO 8015
ISO 2768 - m H
< 6 mm: ±0.2 mm

Ⓐ = Bearing
Ⓚ = Required mating dimensions
Ⓗ1 = Centering of the circular scale with hub by the customer via the graduation
Ⓗ2 = Scanning gap adjustment by means of a shim
Direction of scanning unit motion for output signals in accordance with interface description

Scanning head	AK ERO 6180
Interface	⁓ 1 V_{PP}
Reference mark signal	Square-wave pulse
Cutoff frequency –3 dB	≥ 200 kHz
Electrical connection	Cable 3 m with D-sub connector (male, 15-pin)
Cable length	≤ 30 m
Voltage supply	5 V DC ± 0.25 V
Current requirement	< 100 mA (without load)
Vibration 55 to 2000 Hz **Shock** 11 ms	≤ 200 m/s^2 (EN 60068-2-6) ≤ 400 m/s^2 (EN 60068-2-27)
Operating temperature	0 °C to 50 °C
Weight (approx.) Scanning head Connector Cable	6 g (without cable) 32 g 22 g/m

Graduated disk	TKN ERO 6100
Measuring standard	Chromium graduation on glass
Signal periods	4096
Accuracy of graduation	± 10″
Position error per signal period[1)]	± 5″
Reference marks	One
Hub inside diameter	41 mm
Circular scale outside diameter	70 mm
Mech. permissible speed	≤ 3500 min^{-1}
Moment of inertia	50 x 10^{-6} kgm^2
Permissible axial motion	≤ 0.1 mm
Protection EN 60529	IP 00
Weight (approx.)	71 g

[1)] The position error within one signal period and the accuracy of the graduation result together in the encoder-specific error; for additional error through mounting and the bearing of the measured shaft, see *Measuring accuracy*

ERA 4280C, ERA 4480C, ERA 4880C

Incremental angle encoder for high accuracy
- **Steel scale drum with centering collar**
- **Optional protective cover available for ERA 4480C**
- **Consists of scanning head and scale drum**



ERA 4000



ERA 4000 with protective cover

Scanning head		
Interface		
Cutoff frequency –3 dB		
Electrical connection		
Cable length		
Voltage supply		
Current requirement		
Vibration 55 to 2000 Hz **Shock** 6 ms		
Operating temperature		
Weight (approx.)	Scanning head	

Scale drum		
Measuring standard Expansion factor		
Signal periods/ Position error per signal period[1]	ERA 4200	
	ERA 4400	
	ERA 4800	
Accuracy of graduation		
Reference marks		
Drum inside diameter*		
Drum outside diameter*		
Mechanically permissible speed		
Moment of inertia of rotor		
Permissible axial movement		
Protection* EN 60529		
Without protective cover		
With protective cover[2] and compressed air		
Weight (approx.)	Scale drum	
	Protective cover	

	AK ERA 4280 graduation period 20 µm **AK ERA 4480** graduation period 40 µm **AK ERA 4880** graduation period 80 µm
	⁓ 1 V_{PP}
	≥ 350 kHz
	Cable 1 m, with M23 coupling (12-pin)
	≤ 150 m (with HEIDENHAIN cable)
	5 V DC ± 0.5 V
	< 100 mA (without load)
	≤ 200 m/s^2 (EN 60068-2-6) ≤ 1000 m/s^2 (EN 60068-2-27)
	–10 °C to 80 °C
	20 g; *Scanning head for protective cover:* 35 g (each without cable)

	TTR ERA 4200C graduation period 20 µm **TTR ERA 4400C** graduation period 40 µm **TTR ERA 4800C** graduation period 80 µm								
	Steel drum $\alpha_{therm} \approx 10.5 \cdot 10^{-6}\ K^{-1}$								
	12000/± 1.1″	16384/± 0.8″	20000/± 0.7″	28000/± 0.5″	32768/± 0.4″	40000/± 0.4″	52000/± 0.3″	–	–
	6000/± 2.2″	8192/± 1.6″	10000/± 1.3″	14000/± 1.0″	16384/± 0.8″	20000/± 0.7″	26000/± 0.5″	38000/± 0.4″	44000/± 0.3″
	3000/± 4.4″	4096/± 3.2″	5000/± 2.6″	7000/± 1.9″	8192/± 1.6″	10000/± 1.3″	13000/± 1.0″	–	–
	± 5″	± 3.7″	± 3″	± 2.5″				± 2″	
	Distance-coded, one upon request								
	40 mm	70 mm	80 mm	120 mm	150 mm	180 mm	270 mm	425 mm	512 mm
	76.75 mm	104.63 mm	127.64 mm	178.55 mm	208.89 mm	254.93 mm	331.31 mm	484.07 mm	560.46 mm
	10000 min^{-1}	8500 min^{-1}	6250 min^{-1}	4500 min^{-1}	4250 min^{-1}	3250 min^{-1}	2500 min^{-1}	1800 min^{-1}	1500 min^{-1}
	$0.27 \cdot 10^{-3}$ kgm^2	$0.81 \cdot 10^{-3}$ kgm^2	$1.9 \cdot 10^{-3}$ kgm^2	$7.1 \cdot 10^{-3}$ kgm^2	$12 \cdot 10^{-3}$ kgm^2	$28 \cdot 10^{-3}$ kgm^2	$59 \cdot 10^{-3}$ kgm^2	$195 \cdot 10^{-3}$ kgm^2	$258 \cdot 10^{-3}$ kgm^2
	≤ ± 0.5 mm (scale drum relative to scanning head)								
	IP 00								
	IP 40	IP 40	IP 40	IP 40	IP 40	IP 40	IP 40	–	
	0.28 kg	0.41 kg	0.68 kg	1.2 kg	1.5 kg	2.3 kg	2.6 kg	3.8 kg	3.6 kg
	0.07 kg	0.1 kg	0.12 kg	0.17 kg	0.28 kg	0.26 kg	0.35 kg	–	

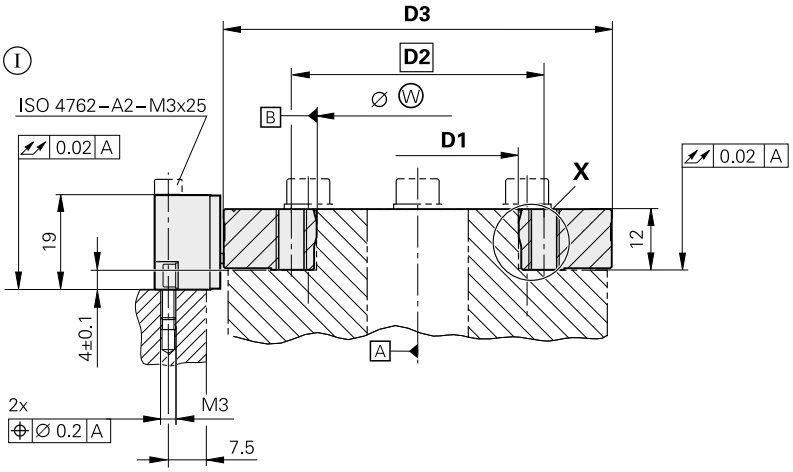
***** Please select when ordering

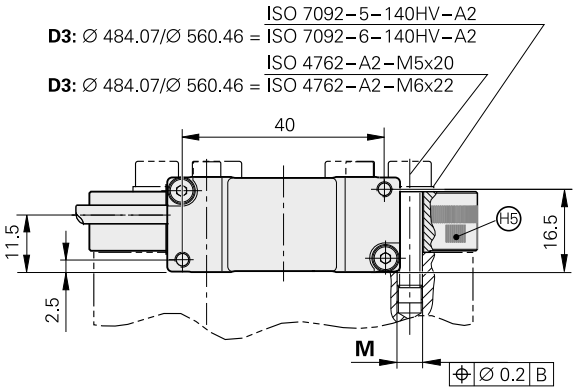
[1] The position error within one signal period and the accuracy of the graduation result together in the encoder-specific error; for additional error through mounting and the bearing of the measured shaft, see *Measuring accuracy*

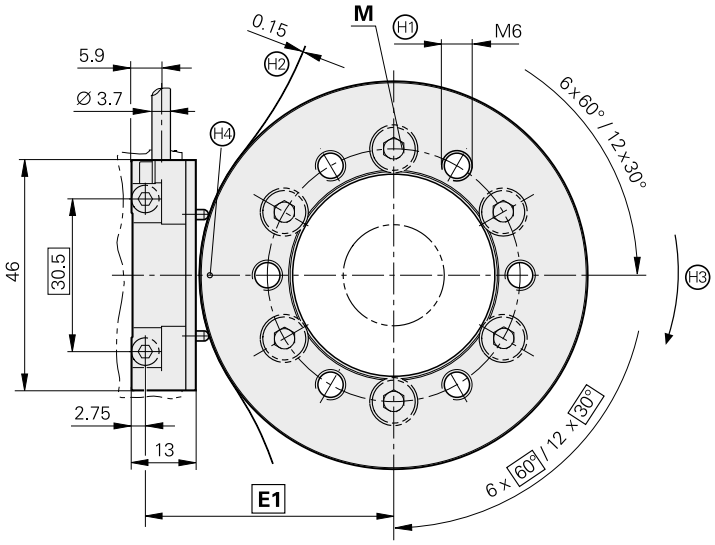
[2] Only with ERA 4480; the protective cover must be ordered separately

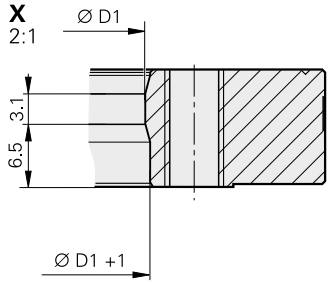
ERA 4280C, ERA 4480C, ERA 4880C

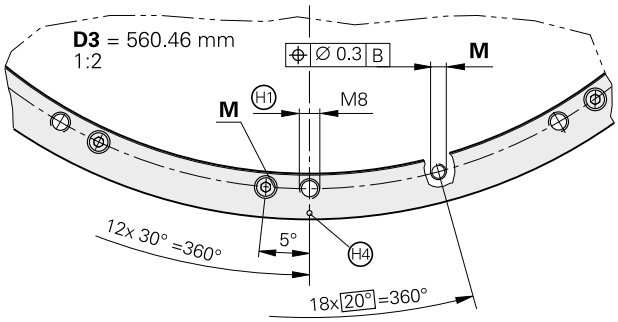
Without protective cover



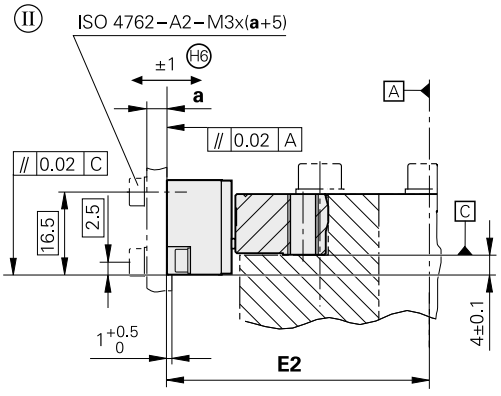


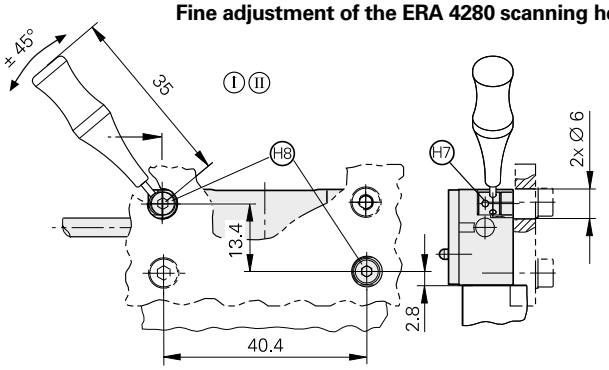


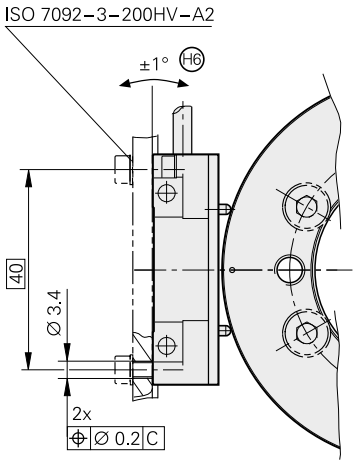




Fine adjustment of the ERA 4280 scanning head







For CAD data go to *cad.heidenhain.de*

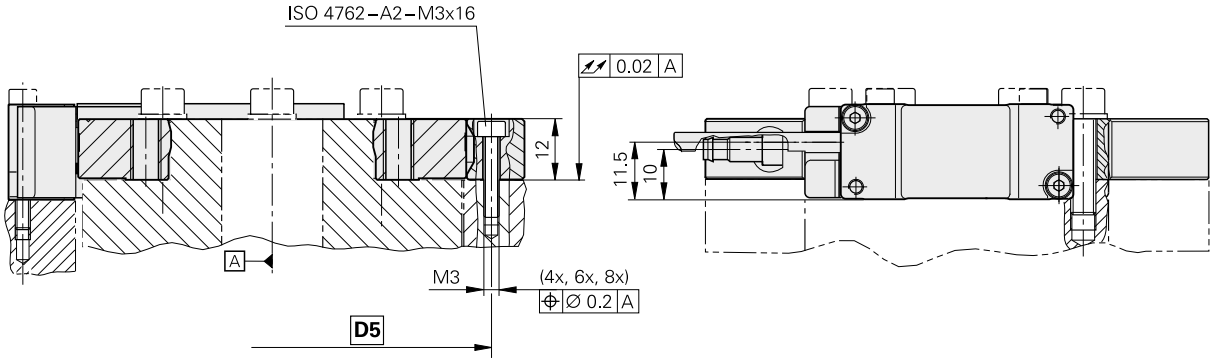
mm

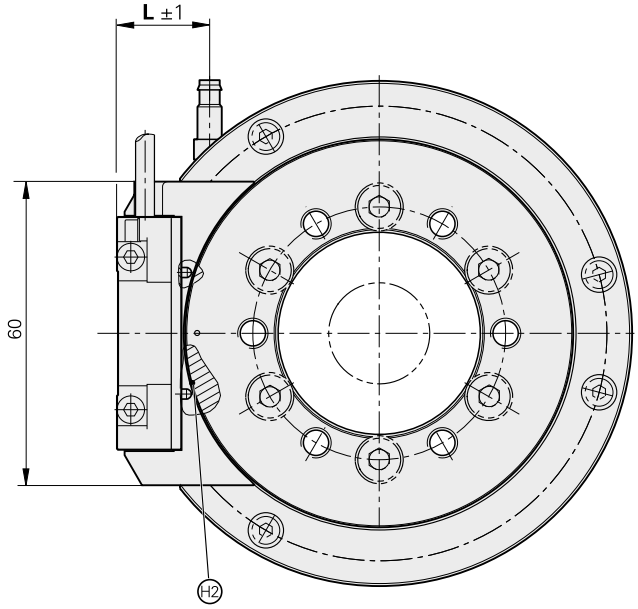
Tolerancing ISO 8015
ISO 2768 - m H
< 6 mm: ±0.2 mm

D1	Ⓦ	*)	D2	D3	E1	E2	M
Ø 40 –0.001/–0.005	Ø 40 +0.004	0.001	Ø 50	Ø 76.75	49.34	52.08	6x M5
Ø 70 –0.001/–0.005	Ø 70 +0.005	0.001	Ø 85	Ø 104.63	63.28	66.02	6x M5
Ø 80 –0.001/–0.005	Ø 80 +0.006	0.0015	Ø 95	Ø 127.64	74.78	77.52	6x M5
Ø 120 –0.001/–0.008	Ø 120 +0.008	0.002	Ø 140	Ø 178.55	100.24	102.98	6x M5
Ø 150 –0.001/–0.008	Ø 150 +0.008	0.002	Ø 165	Ø 208.89	115.41	118.15	6x M5
Ø 180 –0.001/–0.008	Ø 180 +0.010	0.003	Ø 200	Ø 254.93	138.43	141.17	6x M5
Ø 270 0/–0.01	Ø 270 +0.012	0.003	Ø 290	Ø 331.31	176.62	179.36	12x M5
Ø 425 0/–0.01	Ø 425 +0.015	0.006	Ø 445	Ø 484.07	253.00	255.74	12x M6
Ø 512 0/–0.015	Ø 512 +0.016	0.007	Ø 528	Ø 560.46	291.19	293.93	18x M6

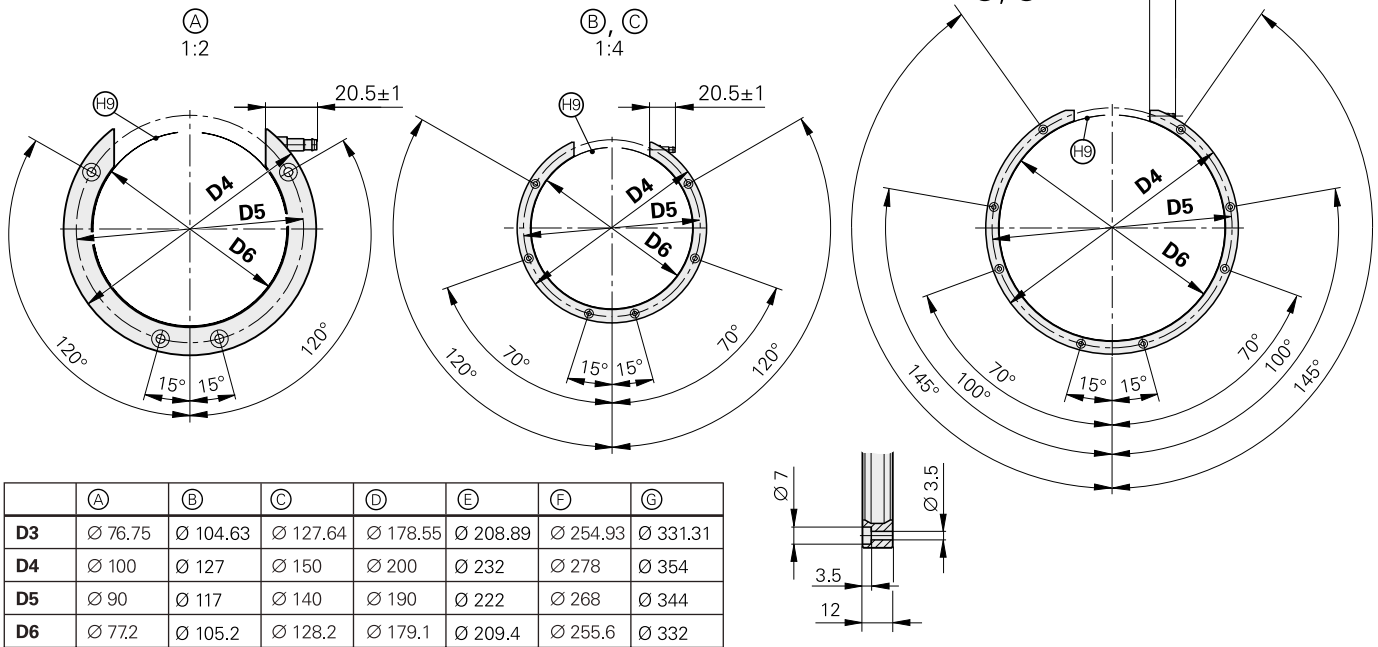
***)** Roundness of mating diameter for shaft

ERA 4480C
With protective cover





Ⓘ, Ⓘ = Mounting options
M = Mounting screws
Ⓐ = Bearing
Ⓦ = Mating shaft
H1 = Back-off thread
H2 = Mounting clearance (spacer foil)
H3 = Positive direction for output signals as per the interface description
H4 = Marker for reference mark, position tolerance with respect to reference mark: ±1.0 mm
H5 = Reference mark
H6 = Ensure adjustability of mounting surface for scanning head
H7 = Cam bushing
H8 = Holes required for fine adjustment
H9 = Mounting clearance 0.15 mm (protective cover)

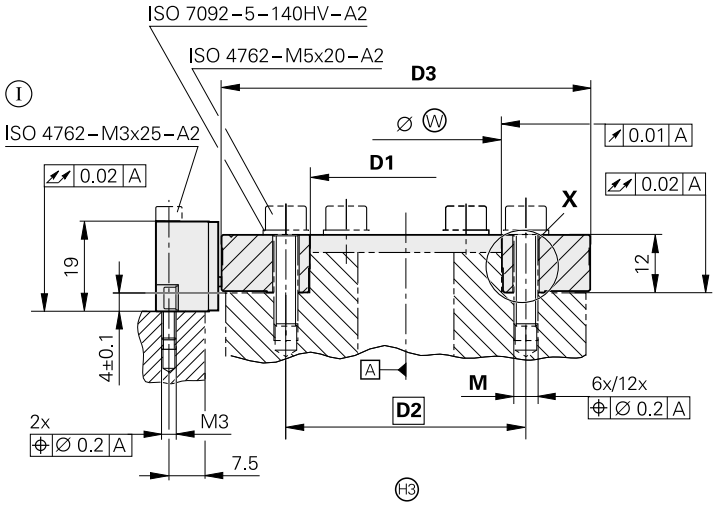


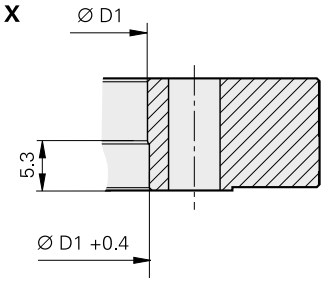
	Ⓐ	Ⓑ	Ⓒ	Ⓓ	Ⓔ	Ⓕ	Ⓖ
D3	Ø 76.75	Ø 104.63	Ø 127.64	Ø 178.55	Ø 208.89	Ø 254.93	Ø 331.31
D4	Ø 100	Ø 127	Ø 150	Ø 200	Ø 232	Ø 278	Ø 354
D5	Ø 90	Ø 117	Ø 140	Ø 190	Ø 222	Ø 268	Ø 344
D6	Ø 77.2	Ø 105.2	Ø 128.2	Ø 179.1	Ø 209.4	Ø 255.6	Ø 332
L	18.6	16.5	15.5	14.5	13.2	12.7	12.1

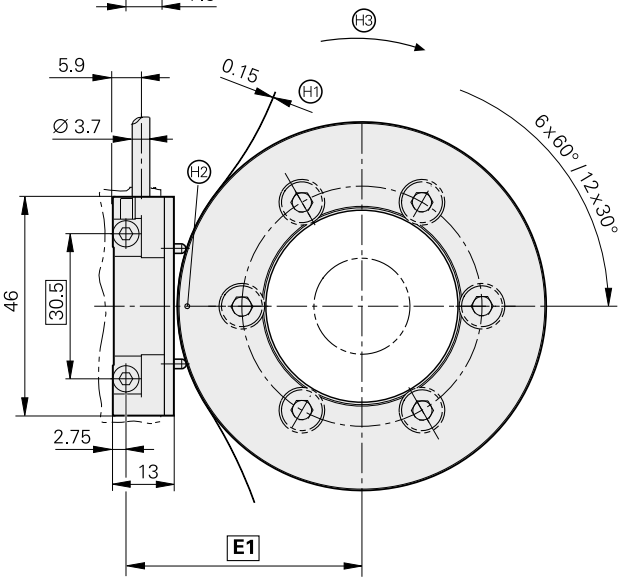
For CAD data go to *cad.heidenhain.de*

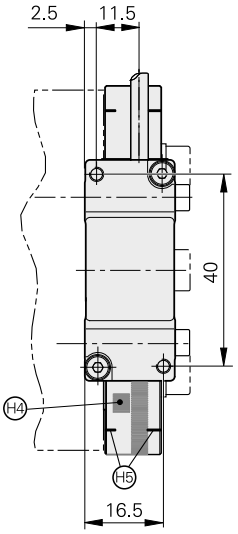
ERA 4282 C

Incremental angle encoder for high accuracy
- **Steel scale drum for increased accuracy requirements**
- **Consists of scanning head and scale drum**





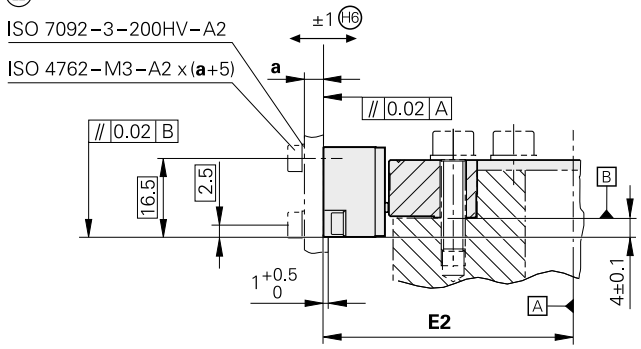




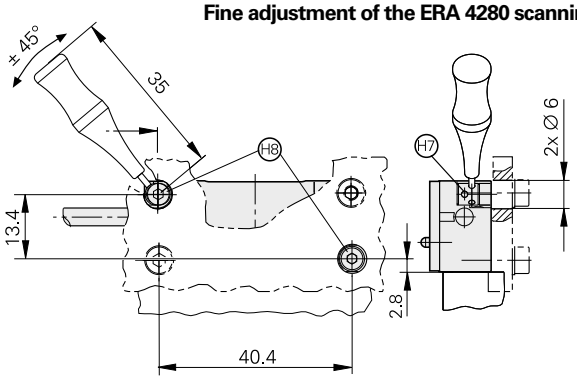
mm
Tolerancing ISO 8015
ISO 2768 - m H
< 6 mm: ±0.2 mm

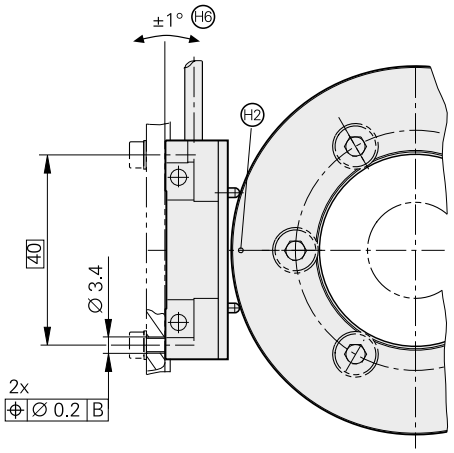
Ⓘ, Ⓘ = Mounting options
Ⓐ = Bearing
Ⓦ = Mating shaft
H1 = Mounting clearance (spacer foil)
H2 = Marker for reference mark
H3 = Positive direction for output signals as per the interface description
H4 = Reference mark
H5 = Marks for drum centering (3 x 120°)
H6 = Ensure adjustability of mounting surface for scanning head
H7 = Cam bushing
H8 = Mounting holes for fine adjustment (only for ERA 4280 scanning head)

Ⓘ



Fine adjustment of the ERA 4280 scanning head





For CAD data go to *cad.heidenhain.de*

D1	Ⓦ	D2	D3	E1	E2	M
Ø 40 +0.07/+0.05	Ø ≤ 40	Ø 50	Ø 76.75	49.34	52.08	M5 6x
Ø 70 +0.07/+0.05	Ø ≤ 70	Ø 85	Ø 104.63	63.28	66.02	M5 6x
Ø 80 +0.07/+0.05	Ø ≤ 80	Ø 95	Ø 127.64	74.78	77.52	M5 6x
Ø 120 +0.07/+0.05	Ø ≤ 120	Ø 140	Ø 178.55	100.24	102.98	M5 6x
Ø 150 +0.07/+0.05	Ø ≤ 150	Ø 165	Ø 208.89	115.41	118.15	M5 6x
Ø 180 +0.07/+0.05	Ø ≤ 180	Ø 200	Ø 254.93	138.43	141.17	M5 6x
Ø 185 +0.07/+0.05	Ø ≤ 185	Ø 197	Ø 208.89	115.41	118.15	M3 12x
Ø 210 +0.07/+0.05	Ø ≤ 210	Ø 230	Ø 254.93	138.43	141.17	M3 12x
Ø 270 +0.07/+0.05	Ø ≤ 270	Ø 290	Ø 331.31	176.62	179.36	M5 12x

Scanning head	AK ERA 4280
Interface	∿ 1 V_{PP}
Cutoff frequency –3 dB	≥ 350 kHz
Electrical connection	Cable 1 m, with M23 coupling (12-pin)
Cable length	≤ 150 m (with HEIDENHAIN cable)
Voltage supply	5 V DC ± 0.5 V
Current requirement	< 100 mA (without load)
Vibration 55 to 2000 Hz **Shock** 6 ms	≤ 100 m/s^2 (EN 60068-2-6) ≤ 500 m/s^2 (EN 60068-2-27)
Operating temperature	–10 °C to 80 °C
Weight (approx.)	20 g (without cable)

Scale drum	TTR ERA 4202C								
Measuring standard Grating period Expansion factor	Steel drum 20 µm $\alpha_{therm} \approx 10.5 \cdot 10^{-6}\ K^{-1}$								
Signal periods	12000	16384	20000	28000	32768	40000	32768	40000	52000
Accuracy of graduation	± 4″	± 3″	± 2.5″	± 2″	± 1.9″	± 1.8″	± 1.9″	± 1.8″	± 1.7″
Position error per signal period[1]	± 1.1″	± 0.8″	± 0.7″	± 0.5″	± 0.4″	± 0.4″	± 0.4″	± 0.4″	± 0.3″
Reference marks	Distance-coded								
Drum inside diameter*	40 mm	70 mm	80 mm	120 mm	150 mm	180 mm	185 mm	210 mm	270 mm
Drum outside diameter*	76.75 mm	104.63 mm	127.64 mm	178.55 mm	208.89 mm	254.93 mm	208.89 mm	254.93 mm	331.31 mm
Mech. permissible speed	10000 min^{-1}	8500 min^{-1}	6250 min^{-1}	4500 min^{-1}	4250 min^{-1}	3250 min^{-1}	3250 min^{-1}	3250 min^{-1}	2500 min^{-1}
Moment of inertia of rotor	$0.28 \cdot 10^{-3}$ kgm^2	$0.83 \cdot 10^{-3}$ kgm^2	$2.0 \cdot 10^{-3}$ kgm^2	$7.1 \cdot 10^{-3}$ kgm^2	$12 \cdot 10^{-3}$ kgm^2	$28 \cdot 10^{-3}$ kgm^2	$6.5 \cdot 10^{-3}$ kgm^2	$20 \cdot 10^{-3}$ kgm^2	$59 \cdot 10^{-3}$ kgm^2
Perm. axial movement	≤ ± 0.5 mm (scale drum relative to scanning head)								
Protection EN 60529	IP 00								
Weight (approx.)	0.30 kg	0.42 kg	0.70 kg	1.2 kg	1.5 kg	2.3 kg	0.66 kg	1.5 kg	2.6 kg

***** Please select when ordering

[1] The position error within one signal period and the accuracy of the graduation result together in the encoder-specific error; for additional error through mounting and the bearing of the measured shaft, see *Measuring accuracy*

ERA 7000 series

Incremental angle encoder for high accuracy
- **Steel scale tape for internal mounting**
- **Full-circle and segment versions, also for very large diameters**
- **Consists of scanning head and scale tape**



ERA 7480

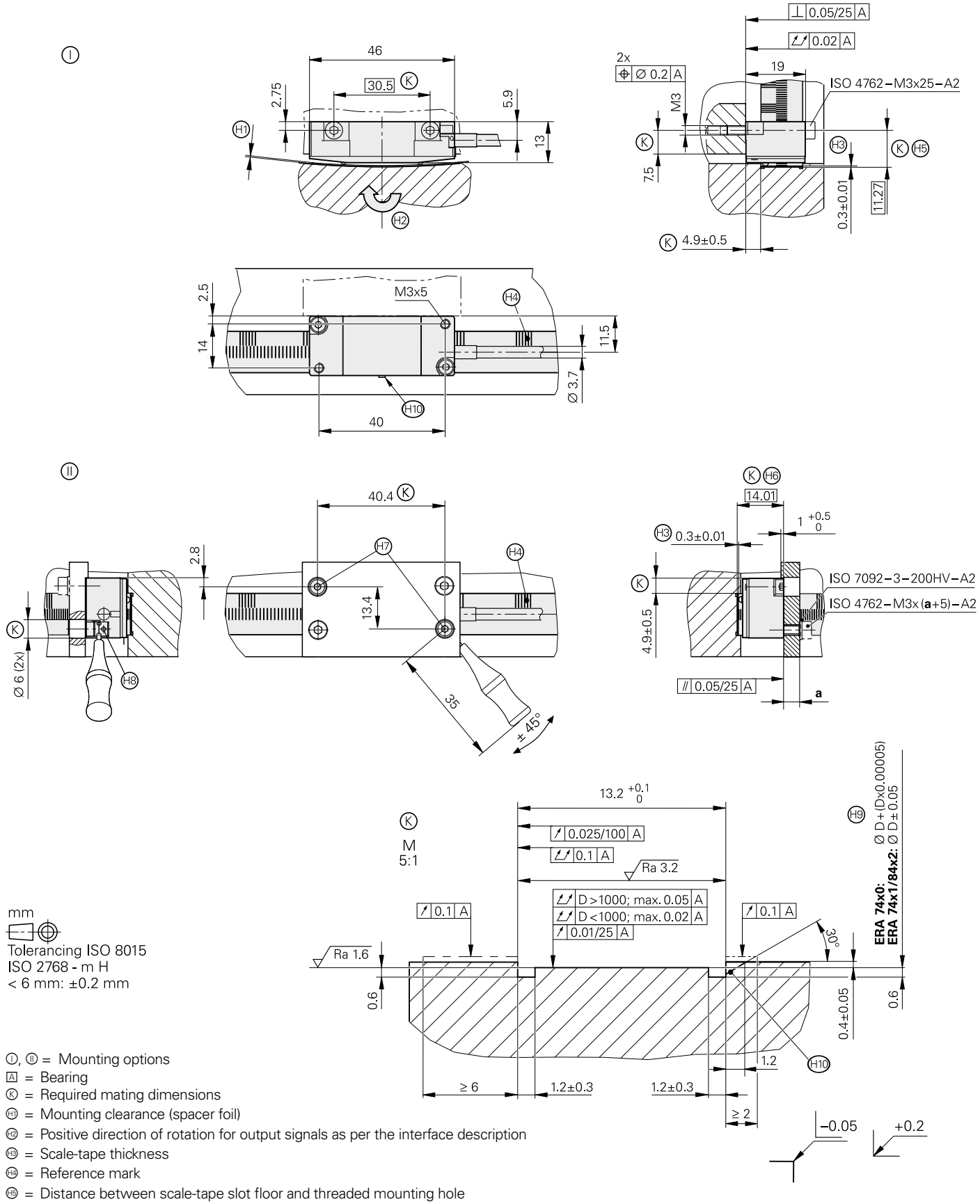


ERA 7481

Scanning head	**AK ERA 7480**
Interface	⁓ 1 V_{PP}
Cutoff frequency –3 dB	≥ 350 kHz
Electrical connection	Cable 1 m, with M23 coupling (12-pin)
Cable length	≤ 150 m (with HEIDENHAIN cable)
Voltage supply	5 V DC ± 0.25 V
Current requirement	< 100 mA (without load)
Vibration 55 to 2000 Hz **Shock** 6 ms	≤ 200 m/s^2 (EN 60068-2-6) ≤ 1000 m/s^2 (EN 60068-2-27)
Operating temperature	–10 °C to 80 °C
Weight (approx.)	20 g (without cable)

Scale tape		**MSB ERA 7400C** full-circle version **MSB ERA 7401C** segment version		
Measuring standard Grating period Expansion factor		Steel scale-tape with METALLUR graduation 40 µm $\alpha_{therm} \approx 10.5 \cdot 10^{-6}\ K^{-1}$		
Signal periods[1]		36000	45000	90000
Accuracy of the graduation[2]		± 3.9″	± 3.2″	± 1.6″
Position error per signal period[2]		± 0.4″	± 0.3″	± 0.1″
Accuracy of the scale tape		± 3 µm/m of tape length		
Reference marks		Distance-coded		
Scale-slot diameter*	Full circle	458.62 mm	573.20 mm	1146.10 mm
	Segment	≥ 400 mm		
Mech. permissible speed		≤ 250 min^{-1}	≤ 250 min^{-1}	≤ 220 min^{-1}
Perm. axial movement		≤ 0.5 mm (scale tape relative to scanning head)		
Permissible expansion coefficient of shaft		$\alpha_{therm} \approx 9 \cdot 10^{-6}\ K^{-1}$ to $12 \cdot 10^{-6}\ K^{-1}$		
Protection EN 60529		IP 00		
Weight (approx.)		30 g/m		

***** Please select when ordering
[1] Applies to full-circle version; for segment versions depends on mating diameter and tape length
[2] The accuracy of the graduation and the position error within one signal period result together in the encoder-specific error; for additional error through mounting and the bearing of the measured shaft, see *Measuring accuracy*
Other diameters and higher speeds available on request

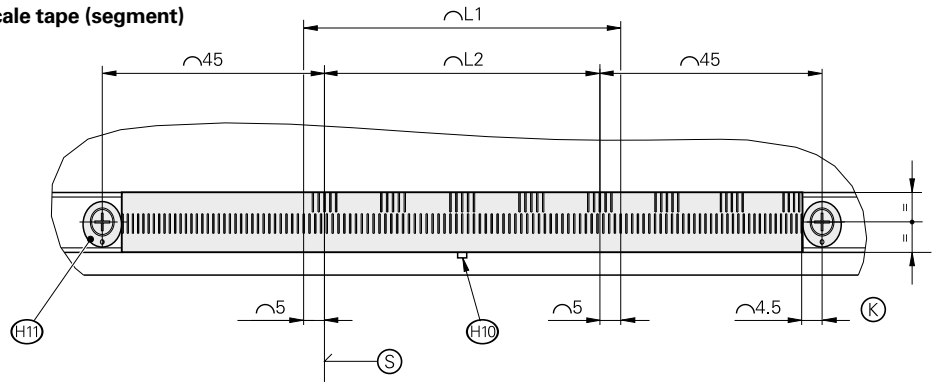


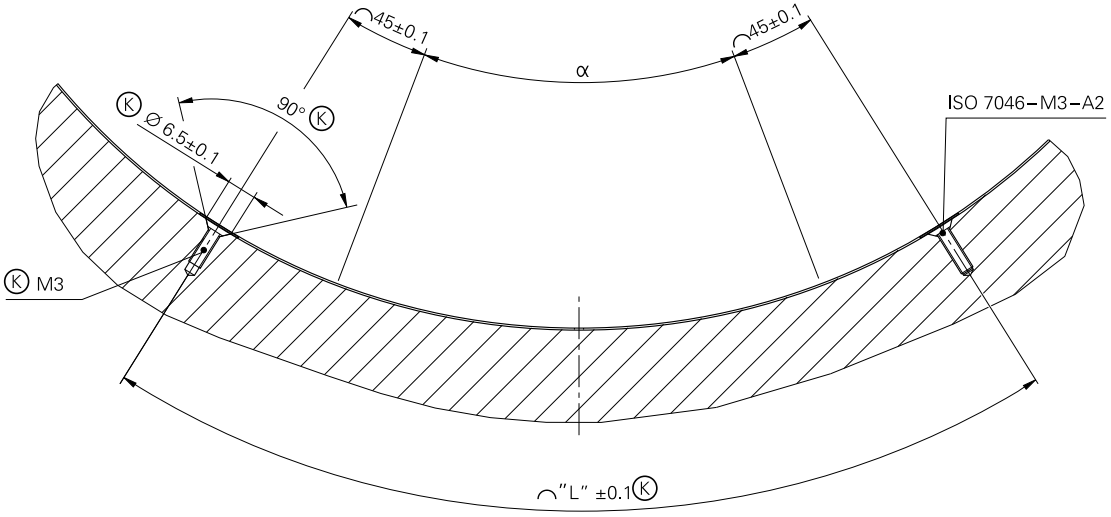
mm

Tolerancing ISO 8015
ISO 2768 - m H
< 6 mm: ±0.2 mm

Ⓘ, Ⓘ = Mounting options
Ⓐ = Bearing
Ⓚ = Required mating dimensions
Ⓗ1 = Mounting clearance (spacer foil)
Ⓗ2 = Positive direction of rotation for output signals as per the interface description
Ⓗ3 = Scale-tape thickness
Ⓗ4 = Reference mark
Ⓗ5 = Distance between scale-tape slot floor and threaded mounting hole
Ⓗ6 = Distance between scale-tape slot floor and scanning head's rear mounting surface
Ⓗ7 = Holes required for fine adjustment
Ⓗ8 = Cam bushing (Moiré setting)
Ⓗ9 = Scale-tape slot-floor Ø D
Ⓗ10 = Notch for removing the scale tape (b = 2 mm)

ERA 74x1 scale tape (segment)





$$D = \frac{n \times 0.04 \times 0.9999}{\pi} + 0.3$$

$$\alpha = \frac{n \times 0.04 \times 0.9999}{\pi} \times 360°$$

$$L2 = n \times 0.04 \times 0.9999$$

Ⓚ = Required mating dimensions
Ⓢ = Beginning of measurement
H10 = Notch for removing the scale tape (b = 2 mm)
H11 = Cam disk for tensioning the scale tape
⌒ = Length of the arc in the stress-free zone, pay attention to the scale-tape thickness
⌒L = Position of the threaded mounting holes
⌒L1 = Traverse path
⌒L2 = Measuring range in the arc

n = Line count
D = Mating diameter
α = Measuring range in degrees (segment angle)
π = 3.14159...

ERA 8000 series

Incremental angle encoder for high accuracy
- **Steel scale tape for external mounting**
- **Full-circle and segment versions, also for very large diameters**
- **Consists of scanning head and scale tape**



ERA 8480 full-circle version



ERA 8481 segment version,
scale tape secured with tensioning elements

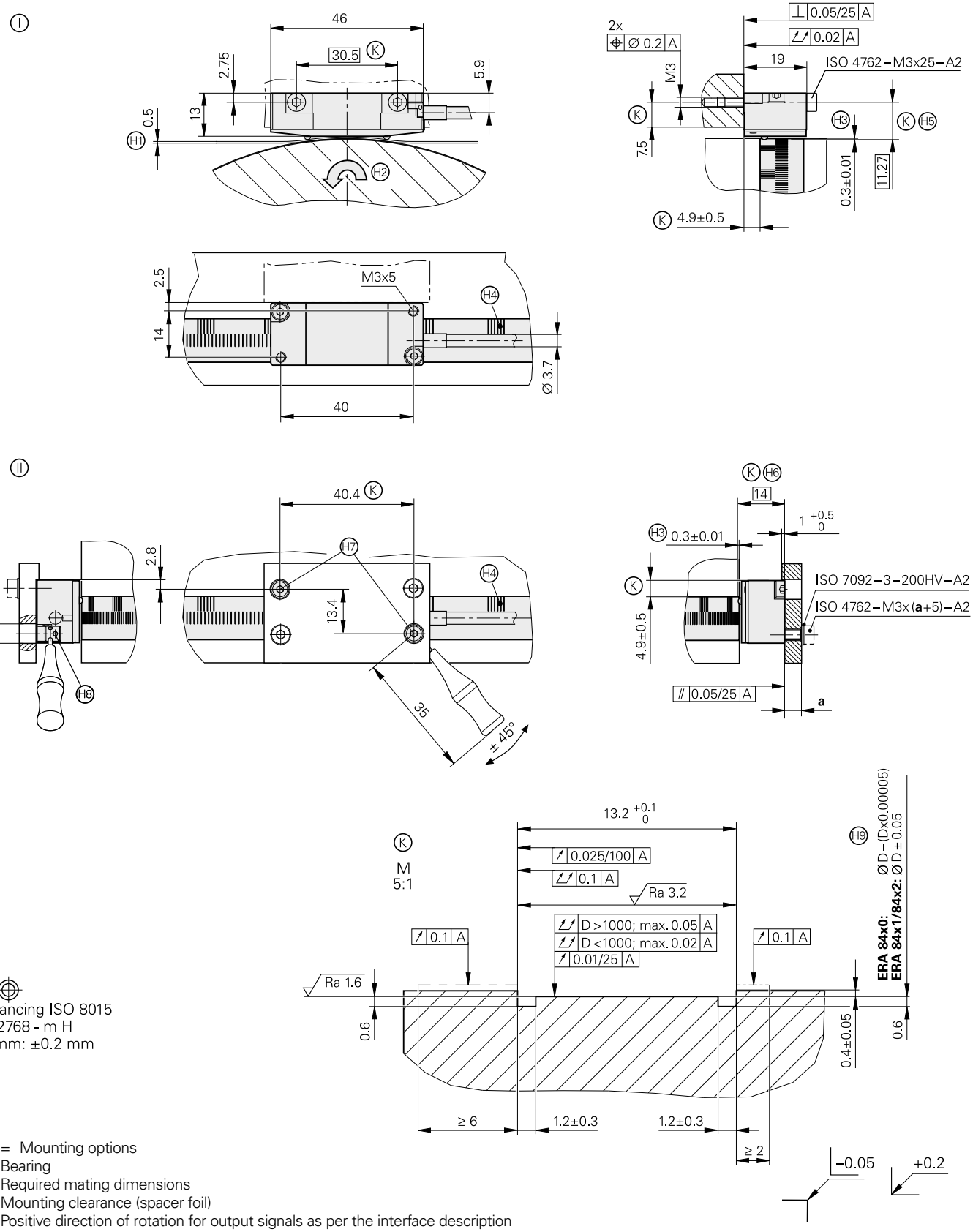


ERA 8482 segment version,
scale tape without tensioning elements

Scanning head	**AK ERA 8480**
Interface	⁓ 1 V_{PP}
Cutoff frequency –3 dB	≥ 350 kHz
Electrical connection	Cable 1 m, with M23 coupling (12-pin)
Cable length	≤ 150 m (with HEIDENHAIN cable)
Voltage supply	5 V DC ± 0.25 V
Current requirement	< 100 mA (without load)
Vibration 55 to 2000 Hz **Shock** 6 ms	≤ 200 m/s^2 (EN 60068-2-6) ≤ 1000 m/s^2 (EN 60068-2-27)
Operating temperature	–10 °C to 80 °C
Weight (approx.)	20 g (without cable)

Scale tape		**MSB ERA 8400C** full-circle version **MSB ERA 8401C** segment version with tensioning elements **MSB ERA 8402C** segment version without tensioning elements		
Measuring standard Grating period Expansion factor		Steel scale-tape with METALLUR graduation 40 µm $\alpha_{therm} \approx 10.5 \cdot 10^{-6}\ K^{-1}$		
Signal periods[1]		36000	45000	90000
Accuracy of the graduation[2]		± 4.7″	± 3.9″	± 1.9″
Position error per signal period[2]		± 0.4″	± 0.3″	± 0.1″
Accuracy of the scale tape		± 3 µm/m of tape length		
Reference marks		Distance-coded		
Scale-slot diameter*	Full circle	458.11 mm	572.72 mm	1145.73 mm
	Segment	≥ 400 mm		
Mech. permissible speed		≤ 50 min^{-1}	≤ 50 min^{-1}	≤ 45 min^{-1}
Perm. axial movement		≤ 0.5 mm (scale tape relative to scanning head)		
Permissible expansion coefficient of shaft		$\alpha_{therm} \approx 9 \cdot 10^{-6}\ K^{-1}$ to $12 \cdot 10^{-6}\ K^{-1}$		
Protection EN 60529		IP 00		
Weight (approx.)		30 g/m		

***** Please select when ordering
[1] Applies to full-circle version; for segment versions depends on mating diameter and tape length
[2] The accuracy of the graduation and the position error within one signal period result together in the encoder-specific error; for additional error through mounting and the bearing of the measured shaft, see *Measuring accuracy*
Other diameters and higher speeds available on request

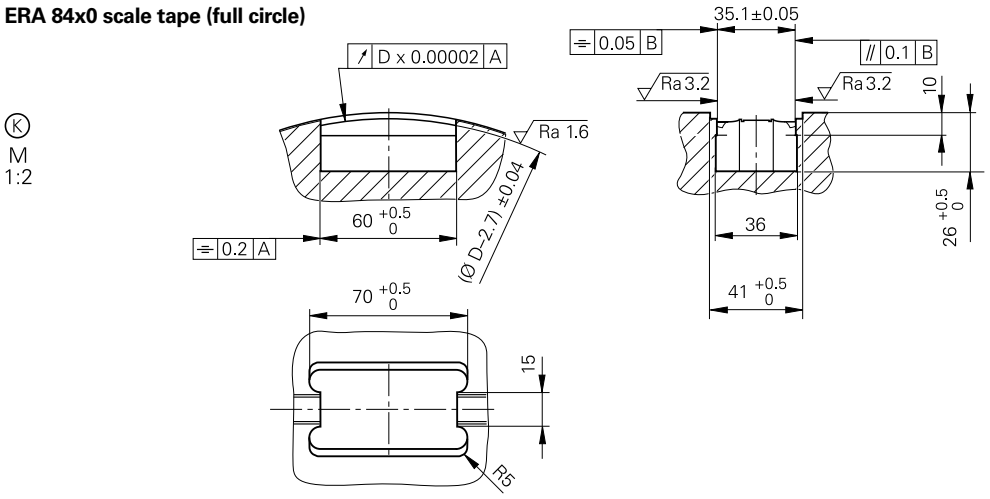


mm

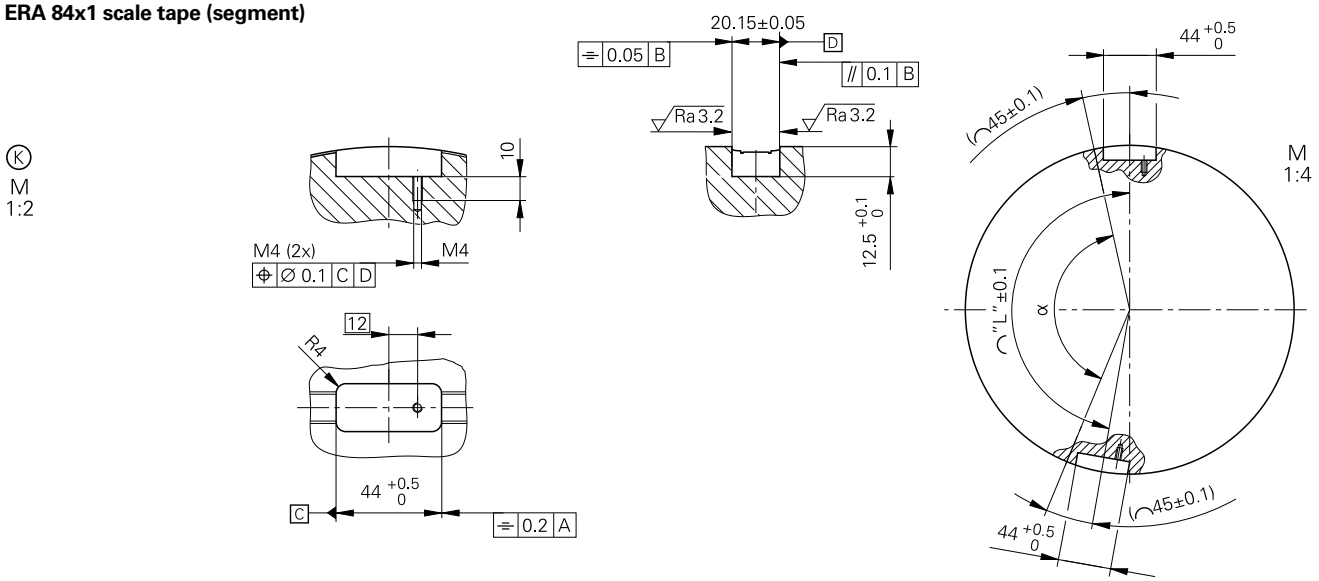
Tolerancing ISO 8015
ISO 2768 - m H
< 6 mm: ±0.2 mm

Ⅰ, Ⅱ = Mounting options
Ⓐ = Bearing
Ⓚ = Required mating dimensions
Ⓗ1 = Mounting clearance (spacer foil)
Ⓗ2 = Positive direction of rotation for output signals as per the interface description
Ⓗ3 = Scale-tape thickness
Ⓗ4 = Reference mark
Ⓗ5 = Distance between scale-tape slot floor and threaded mounting hole
Ⓗ6 = Distance between scale-tape slot floor and scanning head's rear mounting surface
Ⓗ7 = Holes required for fine adjustment
Ⓗ8 = Cam bushing (Moiré setting)
Ⓗ9 = Scale-tape slot-floor Ø D

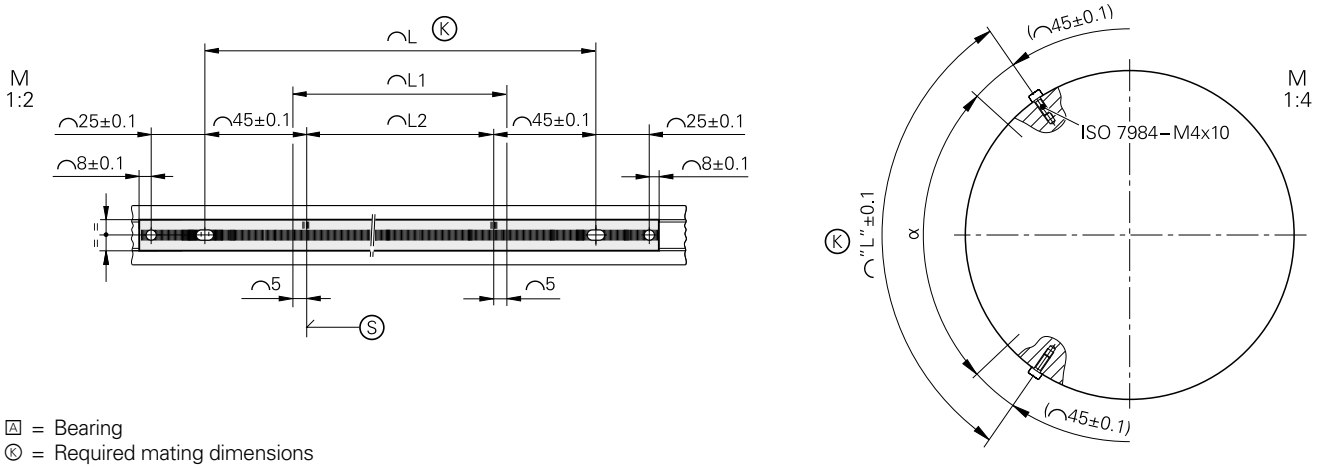
ERA 84x0 scale tape (full circle)



ERA 84x1 scale tape (segment)



ERA 84x2 scale tape (segment)



Ⓐ = Bearing
Ⓚ = Required mating dimensions
Ⓢ = Beginning of measurement
⌒ = Length of the arc in the stress-free zone, pay attention to the scale-tape thickness
⌒L = Position of the two end-piece openings or threaded mounting holes
⌒L1 = Traverse path
⌒L2 = Measuring range in the arc

n = Line count
D = Mating diameter
α = Measuring range in degrees (segment angle)
π = 3.14159...

$$D = \frac{n \times 0.04 \times 1.0001}{\pi} - 0.3$$

$$\alpha = \frac{n \times 0.04 \times 1.0001}{(D + 0.3) \times \pi} \times 360°$$

$$L2 = n \times 0.04 \times 1.0001$$

Interfaces
Incremental signals ∿ 1 V_{PP}

HEIDENHAIN encoders with ∿ 1 V_{PP} interface provide voltage signals that can be highly interpolated.

The sinusoidal **incremental signals** A and B are phase-shifted by 90° elec. and have amplitudes of typically 1 V_{PP}. The illustrated sequence of output signals—with B lagging A—applies for the direction of motion shown in the dimension drawing.

The **reference mark signal** R has a usable component G of approx. 0.5 V. Next to the reference mark, the output signal can be reduced by up to 1.7 V to a quiescent value H. This must not cause the subsequent electronics to overdrive. Even at the lowered signal level, signal peaks with the amplitude G can also appear.

The data on **signal amplitude** apply when the supply voltage given in the specifications is connected to the encoder. They refer to a differential measurement at the 120 ohm terminating resistor between the associated outputs. The signal amplitude decreases with increasing frequency. The **cutoff frequency** indicates the scanning frequency at which a certain percentage of the original signal amplitude is maintained:
- -3 dB ≙ 70 % of the signal amplitude
- -6 dB ≙ 50 % of the signal amplitude

The data in the signal description apply to motions at up to 20% of the —3 dB cutoff frequency.

Interpolation/resolution/measuring step
The output signals of the 1 V_{PP} interface are usually interpolated in the subsequent electronics in order to attain sufficiently high resolutions. For **velocity control,** interpolation factors are commonly over 1000 in order to receive usable information even at low rotational or linear velocities.

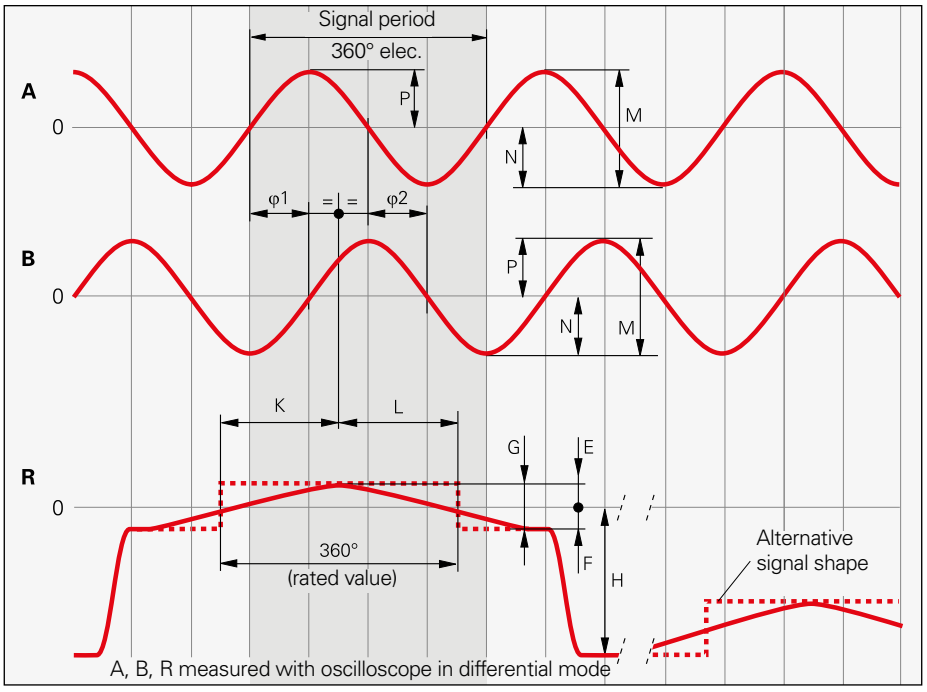
Measuring steps for **position measurement** are recommended in the specifications. For special applications, other resolutions are also possible.

Short-circuit stability
A temporary short circuit of one signal output to 0 V or U_P (except encoders with U_{Pmin} = 3.6 V) does not cause encoder failure, but it is not a permissible operating condition.

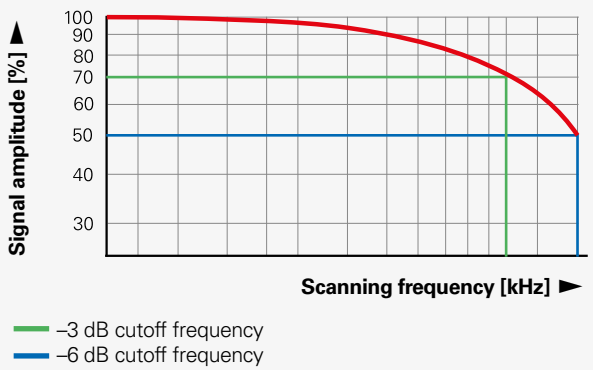
Short circuit at	20 °C	125 °C
One output	< 3 min	< 1 min
All outputs	< 20 s	< 5 s

Interface	Sinusoidal voltage signals ∿ **1 V_{PP}**	
Incremental signals	**Two nearly sinusoidal signals A and B**	
	Signal amplitude M:	0.6 to 1.2 V_{PP}; typically 1 V_{PP}
	Asymmetry |P – N|/2M:	≤ 0.065
	Amplitude ratio M_A/M_B:	0.8 to 1.25
	Phase angle |φ1 + φ2|/2:	90° ± 10° elec.
Reference mark signal	**One or several signal peaks R**	
	Usable component G:	≥ 0.2 V
	Quiescent value H:	≤ 1.7 V
	Switching threshold E, F:	0.04 to 0.68 V
	Zero crossovers K, L:	180° ± 90° elec.
Connecting cable	Shielded HEIDENHAIN cable For example PUR [4(2 x 0.14 mm²) + (4 x 0.5 mm²)]	
Cable length	Max. 150 m at 90 pF/m distributed capacitance	
Propagation time	6 ns/m	

These values can be used for dimensioning of the subsequent electronics. Any limited tolerances in the encoders are listed in the specifications. For encoders without integral bearing, reduced tolerances are recommended for initial operation (see the mounting instructions).



Cutoff frequency
Typical signal amplitude curve with respect to the scanning frequency (depends on encoder)



Input circuitry of subsequent electronics

Dimensioning
Operational amplifier MC 34074
Z_0 = 120 Ω
R_1 = 10 kΩ and C_1 = 100 pF
R_2 = 34.8 kΩ and C_2 = 10 pF
U_B = ±15 V
U_1 approx. U_0

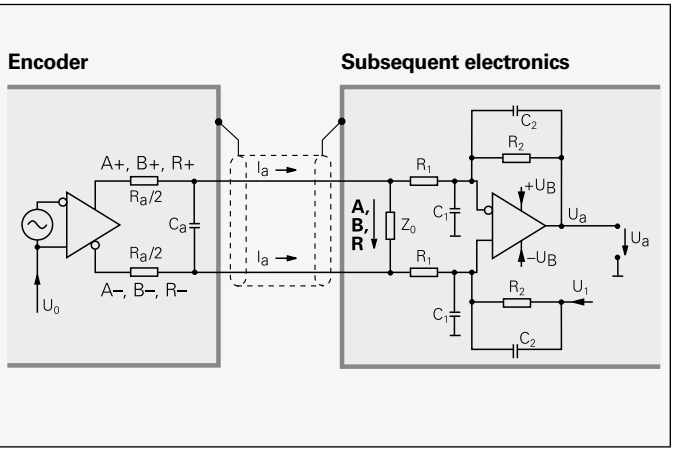
–3 dB cutoff frequency of circuitry
Approx. 450 kHz
Approx. 50 kHz with C_1 = 1000 pF
and C_2 = 82 pF
The circuit variant for 50 kHz does reduce the bandwidth of the circuit, but in doing so it improves its noise immunity.
Encoders with **higher signal frequencies** (e.g. LIP 281) require special input circuitry (see the *Exposed Linear Encoders* brochure).

Circuit output signals
U_a = 3.48 V_{PP} typically
Gain 3.48

Monitoring of the incremental signals
The following sensitivity levels are recommended for monitoring the signal amplitude M:
Lower threshold: 0.30 V_{PP}
Upper threshold: 1.35 V_{PP}

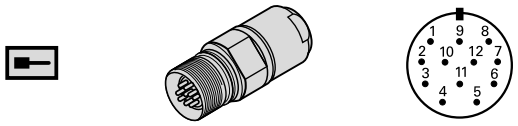
Incremental signals
Reference mark signal

R_a < 100 Ω,
typically 24 Ω
C_a < 50 pF
ΣI_a < 1 mA
U_0 = 2.5 V ± 0.5 V
(relative to 0 V of the voltage supply)

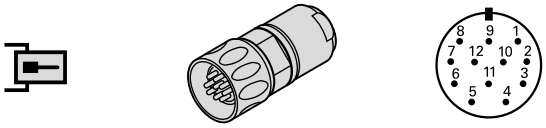


Pin layout

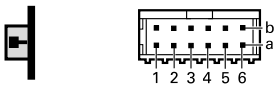
12-pin coupling, M23



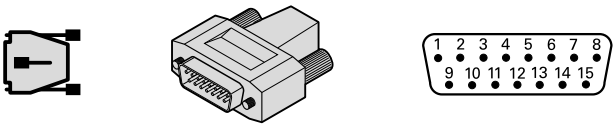
12-pin connector, M23



12-pin PCB connector
on ERP 880



15-pin D-sub connector



	Voltage supply				Incremental signals						Other signals		
	12	**2**	**10**	**11**	**5**	**6**	**8**	**1**	**3**	**4**	**9**	**7**	**/**
	2a	**2b**	**1a**	**1b**	**6b**	**6a**	**5b**	**5a**	**4b**	**4a**	**3b**	**3a**	**/**
	4	**12**	**2**	**10**	**1**	**9**	**3**	**11**	**14**	**7**	**5/6/8**	**13**	**15**
	U_P	**Sensor** U_P	**0 V**	**Sensor** 0 V	**A+**	**A–**	**B+**	**B–**	**R+**[1)]	**R–**[1)]	**Vacant**	**Vacant**	**Vacant**
	Brown/ Green	Blue	White/ Green	White	Brown	Green	Gray	Pink	Red	Black	/	Violet	Yellow

Cable shield connected to housing; **U_P** = Power supply voltage
Sensor: The sensor line is connected in the encoder (*ERO 6x80:* in the connector) with the corresponding power line.
Vacant pins or wires must not be used!

[1)] **ERP 4080/ERP 8080:** Vacant

Interfaces
Incremental signals ⊓⊔TTL

HEIDENHAIN encoders with ⊓⊔TTL interface incorporate electronics that digitize sinusoidal scanning signals with or without interpolation.

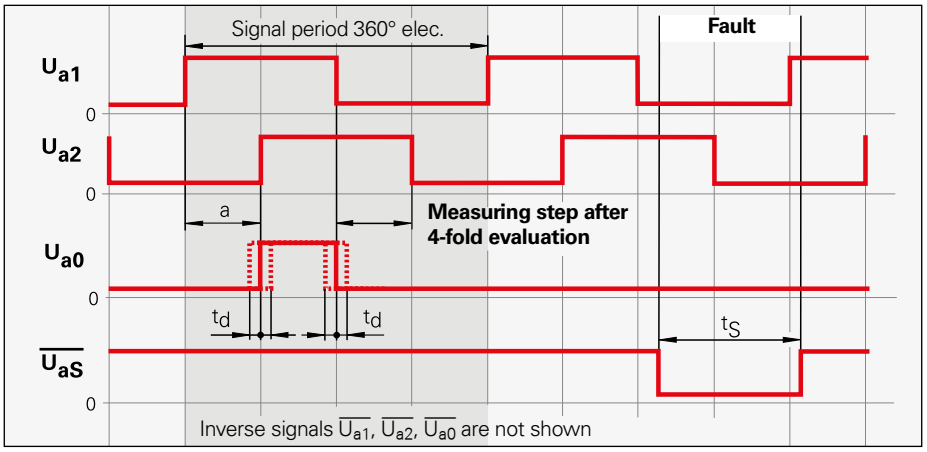
The **incremental signals** are transmitted as the square-wave pulse trains U_{a1} and U_{a2}, phase-shifted by 90° elec. The **reference mark signal** consists of one or more reference pulses U_{a0}, which are gated with the incremental signals. In addition, the integrated electronics produce their **inverted signals** $\overline{U_{a1}}$, $\overline{U_{a2}}$ and $\overline{U_{a0}}$ for noise-proof transmission. The illustrated sequence of output signals—with U_{a2} lagging U_{a1}—applies to the direction of motion shown in the dimension drawing.

The **fault-detection signal** $\overline{U_{aS}}$ indicates fault conditions such as breakage of the power line or failure of the light source. It can be used for such purposes as machine shut-off during automated production.

The distance between two successive edges of the incremental signals U_{a1} and U_{a2} through 1-fold, 2-fold or 4-fold evaluation is one **measuring step.**

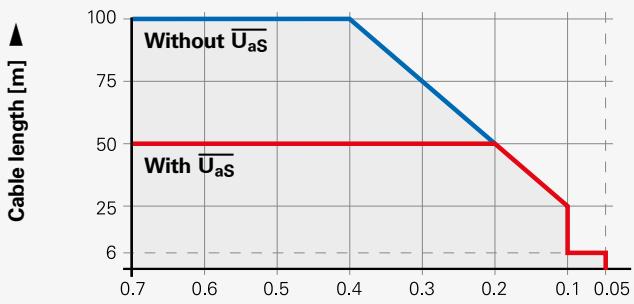
The subsequent electronics must be designed to detect each edge of the square-wave pulse. The minimum **edge separation a** listed in the *Specifications* applies for the specified input circuitry with a cable length of 1 m, and refers to measurement at the output of the differential line receiver. Cable-dependent differences in the propagation times additionally reduce the edge separation by 0.2 ns per meter of cable. To prevent counting errors, design the subsequent electronics so that they can process as little as 90 % of the resulting edge separation.
The max. permissible **shaft speed** or **traversing velocity** must never be exceeded.

Interface	Square-wave signals ⊓⊔ **TTL**
Incremental signals	**Two TTL square-wave signals U_{a1}, U_{a2}** and their inverted signals $\overline{U_{a1}}$,$\overline{U_{a2}}$
Reference mark signal Pulse width Delay time	**One or more TTL square-wave pulses U_{a0}** and their inverted pulses $\overline{U_{a0}}$ 90° elec. (other widths available on request) $\|t_d\| \leq 50$ ns
Fault-detection signal Pulse width	**One TTL square-wave pulse $\overline{U_{aS}}$** Improper function: LOW (upon request: U_{a1}/U_{a2} high impedance) Proper function: HIGH $t_S \geq 20$ ms
Signal amplitude	Differential line driver as per EIA standard RS-422 $U_H \geq 2.5$ V at $-I_H = 20$ mA *ERN 1x23:* 10 mA $U_L \leq 0.5$ V at $I_L = 20$ mA *ERN 1x23:* 10 mA
Permissible load	$Z_0 \geq 100\ \Omega$ Between associated outputs $\|I_L\| \leq 20$ mA Max. load per output (*ERN 1x23:* 10 mA) $C_{load} \leq 1000$ pF With respect to 0 V Outputs protected against short circuit to 0 V
Switching times (10% to 90%)	$t_+ / t_- \leq 30$ ns (typically 10 ns) with 1 m cable and recommended input circuitry
Connecting cable Cable length Propagation time	Shielded HEIDENHAIN cable For example PUR [4(2 × 0.14 mm²) + (4 × 0.5 mm²)] Max. 100 m ($\overline{U_{aS}}$ max. 50 m) at distributed capacitance 90 pF/m 6 ns/m



The permissible **cable length** for transmission of the TTL square-wave signals to the subsequent electronics depends on the edge separation a. It is at most 100 m, or 50 m for the fault detection signal. This requires, however, that the voltage supply (see *Specifications*) be ensured at the encoder. The sensor lines can be used to measure the voltage at the encoder and, if required, correct it with an automatic control system (remote sense voltage supply).

Permissible cable length with respect to the edge separation

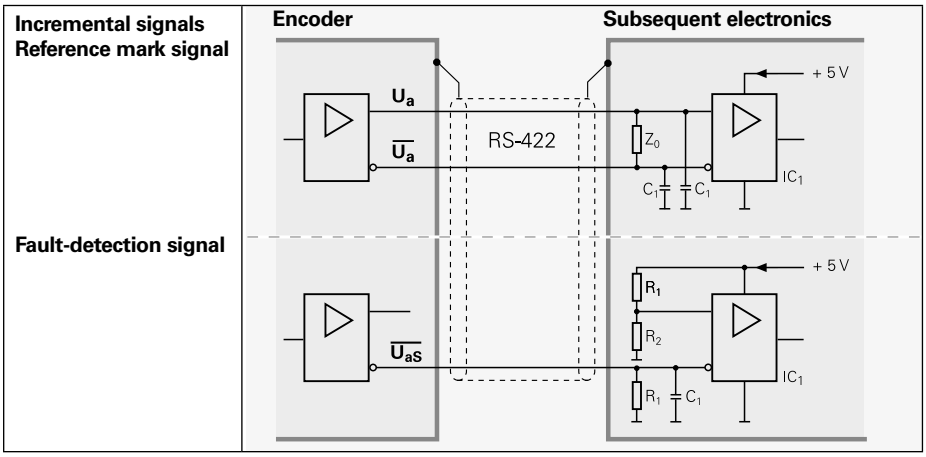


Input circuitry of subsequent electronics

Dimensioning

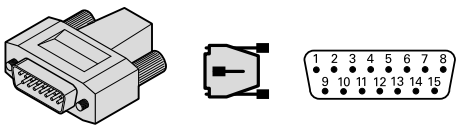
IC_1 = Recommended differential line receiver
DS 26 C 32 AT
Only for a > 0.1 µs:
AM 26 LS 32
MC 3486
SN 75 ALS 193

R_1 = 4.7 kΩ
R_2 = 1.8 kΩ
Z_0 = 120 Ω
C_1 = 220 pF (serves to improve noise immunity)

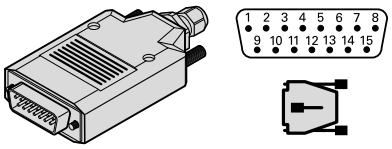


Pin layout

15-pin D-sub connector



15-pin D-sub connector with integrated interface electronics



	Voltage supply				Incremental signals						Other signals		
	4	**12**	**2**	**10**	**1**	**9**	**3**	**11**	**14**	**7**	**13**	**5/6/8**	**15**
	U_P	**Sensor** U_P	**0 V**	**Sensor** 0 V	**U_{a1}**	**$\overline{U_{a1}}$**	**U_{a2}**	**$\overline{U_{a2}}$**	**U_{a0}**	**$\overline{U_{a0}}$**	**$\overline{U_{aS}}$**	**Vacant**	**Vacant**[1]
	Brown/ Green	Blue	White/ Green	White	Brown	Green	Gray	Pink	Red	Black	Violet	/	Yellow

Cable shield connected to housing; **U_P** = Power supply voltage
Sensor: The sensor line is connected in the encoder (*ERO 6x70:* in the connector) with the corresponding power line.
Vacant pins or wires must not be used!

[1] **ERO 6x70:** Switchover TTL/11 μA_{PP} for PWT, otherwise vacant

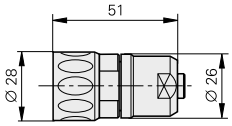
Cables and connecting elements
General information

Connector (insulated): A connecting element with a coupling ring. Available with male or female contacts.

Symbols



M23

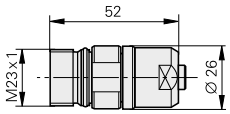


Coupling (insulated): Connecting element with external thread; available with male or female contacts.

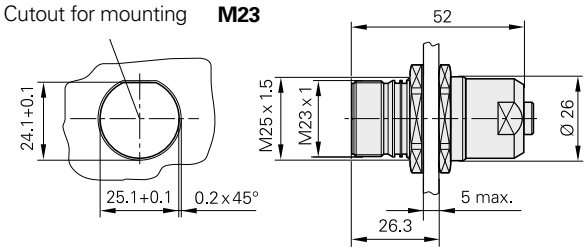
Symbols



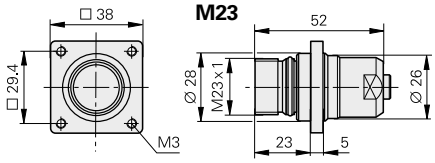
M23



Mounted coupling with central fastening



Mounted coupling with flange

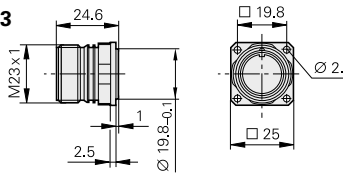


Flange socket: Permanently mounted on the encoder or a housing, with external thread (like a coupling), available with male or female contacts.

Symbols



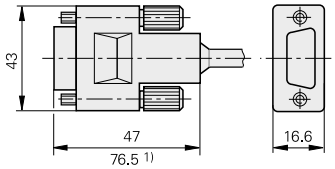
M23



D-sub connector: For HEIDENHAIN controls, counters and IK absolute value cards.

Symbols





1) With integrated interpolation electronics

The pins on connectors are **numbered** in the direction opposite to those on couplings or flange sockets, regardless of whether the connecting elements have

male or



female contacts.



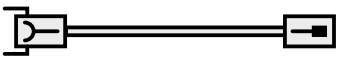
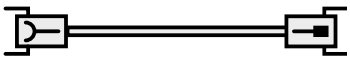
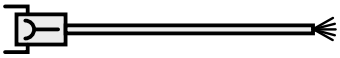
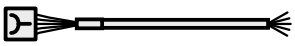
When engaged, the connections are **protected** to IP 67 (D-sub connector: IP 50; EN 60529). When not engaged, there is no protection.

Accessories for flange sockets and M23 mounted couplings

Bell seal
ID 266526-01

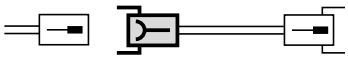
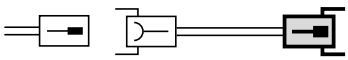
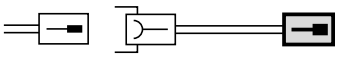
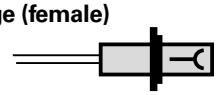
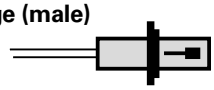
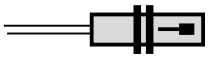
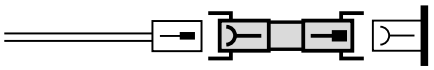
Threaded metal dust cap
ID 219926-01

Connecting cables

		12-pin M23	
PUR connecting cable [6(2 x 0.19 mm²)]; A_P = 0.19 mm²			
PUR connecting cable [4(2 × 0.14 mm²) + (4 × 0.5 mm²)]; A_P = 0.5 mm²		Ø 8 mm	Ø 6 mm[1]
Complete with connector (female) and coupling (male)		298401-xx	–
Complete with connectors (female and male)		298399-xx	–
Complete with connector (female) and D-sub connector (female) for IK 220/ND 780		310199-xx	–
Complete with connector (female) and D-sub connector (male) for IK 115/IK 215/ND 280/ND 287/EIB 741		310196-xx	–
With **one** connector (female)		309777-xx	–
Complete with D-sub connector (female) and M23 connector (male)		331693-xx	355215-xx
With **one** D-sub connector (female)		332433-xx	355209-xx
Complete with D-sub connectors (female and male)		335074-xx	355186-xx
Complete with D-sub connectors (female and female) for IK 220/ND 780		335077-xx	349687-xx
Cable without connectors		244957-01	291639-01
Output cable for ERP 880	PUR [4(2 x 0.05) + (4 x 0.14)] mm²; A_P = 0.14 mm²	Ø 4.5 mm	
With **one** 12-pin PCB connector	 Length 1 m	372164-01	

[1] Cable length for Ø 6 mm max. 9 m
A_P: Cross section of power supply lines

Connecting elements

			12-pin M23
Mating element on connecting cable to connecting element on encoder	**Connector (female)** 	For cable with Ø 8 mm	291697-05
Connector for connection to subsequent electronics	**Connector (male)** 	For cable with Ø 8 mm Ø 6 mm	291697-08 291697-07
Coupling on encoder cable or connecting cable	**Coupling (male)** 	For cable with Ø 3.7 mm Ø 4.5 mm Ø 6 mm Ø 8 mm	291698-14 291698-14 291698-03 291698-04
Flange socket for mounting on subsequent electronics	**Flange socket (female)** 		315892-08
Mounted couplings	**With flange (female)** 	Ø 6 mm Ø 8 mm	291698-17 291698-07
	With flange (male) 	Ø 6 mm Ø 8 mm	291698-08 291698-31
	With central fastening (male) 	Ø 6 mm to 10 mm	291698-33 741045-01
Adapter ∿ 1 V_{PP}/11 μA_{PP} For converting the 1 V_{PP} signals to 11 μA_{PP}; 12-pin M23 connector (female) and 9-pin M23 connector (male)			364914-01

General electrical information

Voltage supply

Connect HEIDENHAIN encoders only to subsequent electronics whose supply voltage is generated from PELV systems (DIN EN 50 178).

If HEIDENHAIN encoders are to be operated in accordance with DIN EN 61 010-1, power must be supplied from a secondary circuit with current or power limitation as per DIN EN 61 010-1:2011-07, section 9.4 or DIN EN 60 950-1:2011-01, section 2.5 or a Class 2 secondary circuit as specified in UL1310.

The encoders require a **stabilized DC voltage U_P** as voltage supply. The required current consumption and power consumption are listed in the respective *Specifications*. The permissible ripple content of the DC voltage is:

- High frequency interference U_{PP} < 250 mV with dU/dt > 5 V/µs
- Low frequency fundamental ripple U_{PP} < 100 mV

However, the limits of the supply voltage must not be violated by the ripple content.

The values apply as measured at the encoder, i.e., without cable influences. The voltage can be monitored and adjusted with the encoder's **sensor lines**, if available. If an adjustable power supply is not available, the voltage drop can be reduced by switching the sensor lines parallel to the corresponding supply wires.

The voltage U_P actually applied to the encoder is to be considered when **calculating the encoder's current and power consumption.** This voltage consists of the supply voltage U_E provided by the subsequent electronics minus the **voltage drop ΔU** in the supply wires.

For **encoders with an expanded supply voltage range**, the calculation of the voltage drop ΔU in the supply wires must consider the nonlinear current consumption (see next page).

For **encoders without expanded supply voltage range** (typical supply voltage 5 V) the voltage drop ΔU in the supply wires is calculated as follows:

$$\Delta U = 2 \cdot \frac{1.05 \cdot L_C}{56 \cdot A_P} \cdot I_M \cdot 10^{-3}$$

Where:

ΔU	Line drop in V
L_C	Cable length in m
A_P	Cross section of supply wires in mm^2 (see cable)
I_M	Current consumption in mA
2	Outgoing and incoming lines
1.05	Length factor due to twisted wires
56	Electrical conductivity of copper

If the value for the voltage drop is known, the parameters of voltage at the encoder, current consumption, as well as power consumption of the encoder and the power provided by the subsequent electronics can be calculated for the encoder and subsequent electronics.

Switch-on/off behavior of the encoders
After the switch-on time t_{SOT}, valid output signals are available. During the time t_{SOT}, the output signals reach the maximum voltage values given in the table. The switch-on time t_{SOT} depends on the interface.

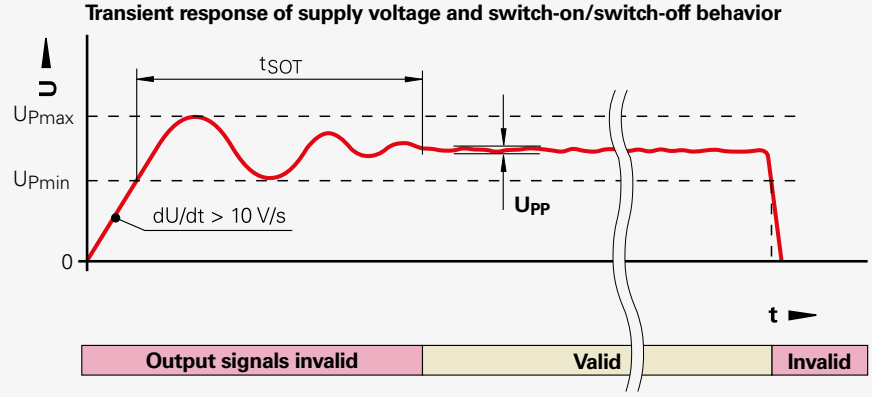
Interface	Switch-on time t_{SOT}	Maximum voltage
1 V_{PP}	1.3 s	5.5 V
11 µA_{PP}		
TTL		
HTL		U_{Pmax}
EnDat		5.5 V
PROFIBUS-DP	2 s	5.5 V
PROFINET	10 s	U_{Pmax}

If the power supply is switched off, or when the supply voltage falls below U_{Pmin}, the output signals are also invalid.

In addition, the interface-specific switch-on/off characteristics must be considered. If interface electronics are inserted between the encoder and the subsequent electronics, the switch-on/off characteristics of the interface electronics must also be considered.

During restart, the voltage must remain below 0.2 V for the time t_{SOT} before power on. Other proprietary interfaces supported by HEIDENHAIN are not considered.

Transient response of supply voltage and switch-on/switch-off behavior

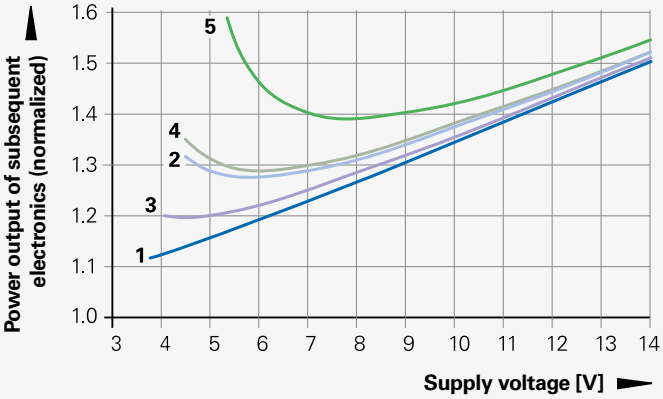


Encoders with expanded supply voltage range

For encoders with expanded supply voltage range, the current consumption has a nonlinear relationship with the supply voltage. On the other hand, the power consumption follows an approximately linear curve (see *Current and power consumption* diagram).
The maximum power consumption at minimum and maximum supply voltage is listed in the **Specifications**. The maximum power consumption accounts for:

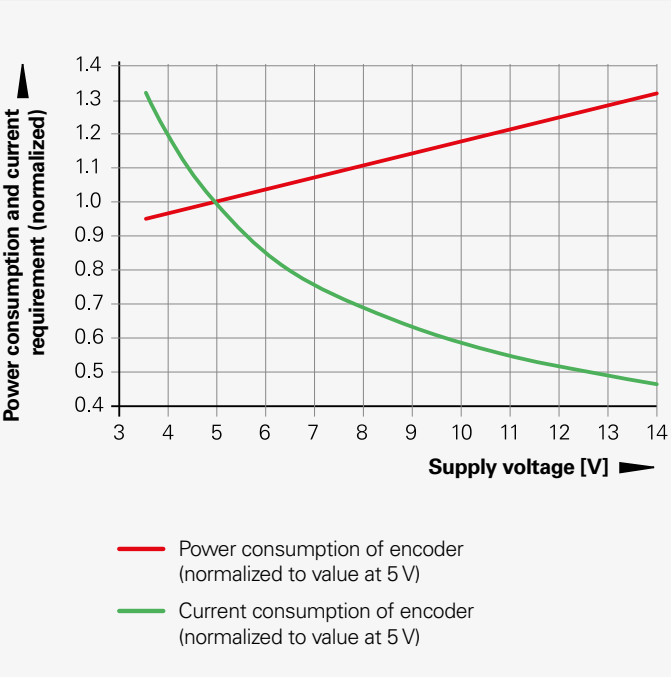
- Recommended receiver circuit
- Cable length 1 m
- Aging and influences of temperature
- Proper use of the encoder with respect to clock frequency and cycle time

For comparative and inspection purposes, the typical current or power consumption is additionally listed in typical ambient and operating conditions without load (only voltage supply connected) for the typical supply voltage or rated voltage. This information only has informative character; it is subject to change without notice. The maximum power consumption is to be used for dimensioning the voltage supply.



	Encoder cable/adapter cable	Connecting cable	Total
1	3 m	/	3 m
2	20 m	/	20 m
3	3 m	17 m	20 m
4	3 m	47 m	50 m
5	3 m	97 m	100 m

Influence of cable length on the power output of the subsequent electronics (example representation)



Current and power consumption with respect to the supply voltage (example representation)

The **actual power consumption** of the encoder and the required power output of the subsequent electronics are calculated, while taking the voltage drop on the supply wires into consideration, in four steps:

Step 1: **Resistance of the supply wires**
The resistance values of the supply wires (adapter cable and encoder cable) can be calculated with the following formula:

$$R_L = 2 \cdot \frac{1.05 \cdot L_C}{56 \cdot A_P}$$

Step 2: **Coefficients for calculation of the voltage drop**

$$b = -R_L \cdot \frac{P_{Mmax} - P_{Mmin}}{U_{Pmax} - U_{Pmin}} - U_E$$

$$c = P_{Mmin} \cdot R_L + \frac{P_{Mmax} - P_{Mmin}}{U_{Pmax} - U_{Pmin}} \cdot R_L \cdot (U_E - U_{Pmin})$$

Step 3: **Voltage drop based on the coefficients b and c**

$$\Delta U = -0.5 \cdot (b + \sqrt{b^2 - 4 \cdot c})$$

Step 4: **Parameters for subsequent electronics and the encoder**
Voltage at encoder:
$U_P = U_E - \Delta U$

Current requirement of encoder:
$I_M = \frac{\Delta U}{R_L}$

Power consumption of encoder:
$P_M = U_P \cdot I_M$

Power output of subsequent electronics:
$P_E = U_E \cdot I_M$

Where:

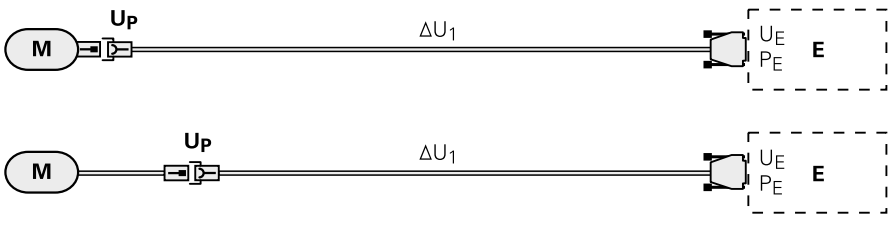
R_L	Cable resistance (for both directions) in ohms
L_C	Cable length in m
A_P	Cross section of supply wires in mm^2 (see cable)
2	Outgoing and incoming lines
1.05	Length factor due to twisted wires
56	Electrical conductivity of copper
P_{Mmin}, P_{Mmax}	Maximum power consumption at minimum or maximum power supply, respectively, in W
U_{Pmin}, U_{Pmax}	Minimum or maximum supply voltage of the encoder in V
U_E	Supply voltage at the subsequent electronics in V
ΔU	Voltage drop in the cable in V
U_P	Voltage at encoder in V
I_M	Current requirement of encoder in mA
P_M	Power consumption of encoder in W
P_E	Power output of subsequent electronics in W

If an encoder operates at a subsequent electronics unit via **interface electronics,** the power consumption of the encoder and of the interface electronics must be added to calculate the resulting power consumption.

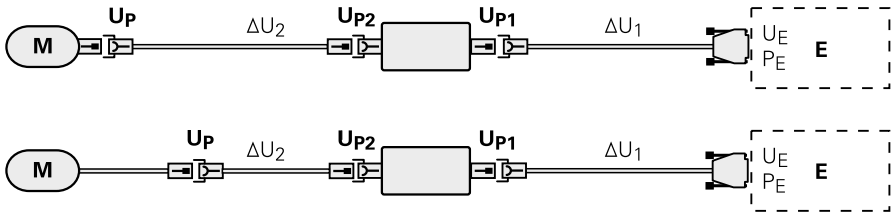
Depending on the interface electronics, a compensation factor for the efficiency of the interface electronics' switching power supply (see Product Information) may have to be considered.

Encoders with **DRIVE-CLiQ interface** are designed for a rated voltage of 24 V DC. The subsequent electronics manufacturer specifies 20.4 V to 28.8 V DC as the tolerance of the power supply. HEIDENHAIN encoders with DRIVE-CLiQ interface permit a greater voltage range (see Specifications). Operation is briefly allowed up to 36.0 V DC. Higher power consumption is to be expected in the range of 28.8 V to 36.0 V DC.

Measuring device M to subsequent electronics E:
$\mathbf{U_P} = U_E - \Delta U_1$



Interface electronics between measuring device M and subsequent electronics E:
$\mathbf{U_P} = U_{P2} - \Delta U_2$
$\mathbf{U_{P1}} = U_E - \Delta U_1$



Electrically permissible speed/ traversing velocity

The maximum permissible shaft speed or traversing velocity of an encoder is derived from

- the **mechanically** permissible shaft speed or traversing velocity and
- the **electrically** permissible shaft speed or traversing velocity.

For incremental encoders with **sinusoidal output signals,** the electrically permissible shaft speed or traversing velocity is limited by the –3dB/ –6dB cutoff frequency or the permissible input frequency of the subsequent electronics.

For incremental encoders with **square-wave signals,** the electrically permissible shaft speed or traversing velocity is limited by

– the maximum permissible scanning/ output frequency f_{max} of the encoder and
– the minimum permissible edge separation a for the subsequent electronics.

For angle or rotary encoders

$$n_{max} = \frac{f_{max}}{z} \cdot 60 \cdot 10^3$$

For linear encoders

$$v_{max} = f_{max} \cdot SP \cdot 60 \cdot 10^{-3}$$

Where:

n_{max}	Electrically permissible speed in min^{-1}
v_{max}	Electrically permissible traversing velocity in m/min
f_{max}	Max. scanning/output frequency of encoder or input frequency of subsequent electronics in kHz
z	Signal periods of the angle or rotary encoder per 360°
SP	Signal period of the linear encoder in µm

Cables

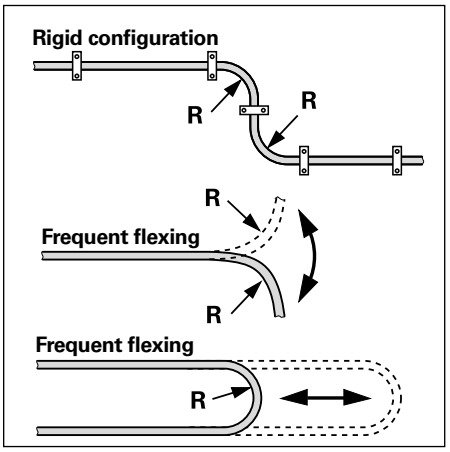
Versions
The cables of almost all HEIDENHAIN encoders and adapter and connecting cables are sheathed in **polyurethane (PUR).** In addition, **special elastomer (EPG), special thermoplastic elastomer (TPE)** and **polyvinyl chloride (PVC)** are used. These cables are identified in the catalog as PUR, EPG, TPE or PVC.

Durability
PUR cables are resistant to oil and hydrolysis in accordance with DIN EN 60811-2-1 and resistant to microbes in accordance with DIN EN 50363-10-2. They are free of PVC and silicone and comply with UL safety directives. The **UL certification** AWM STYLE 20963 80 °C 30 V E63216 is documented on the cable.

EPG cables are suitable for high temperatures and are resistant to oil in accordance with DIN EN 60811-2-1, hydrolysis in accordance with DIN EN 50363-10-2, and are free of PVC, silicone and halogens. In comparison with PUR cables, they are only somewhat resistant to media, frequent flexing and continuous torsion.

PVC cables are oil-resistant. The UL certification is documented on the cable with AWM E64638 STYLE20789 105C VW-1SC NIKKO.

TPE wires with braided sleeving have low oil resistance.



Temperature range

	Rigid configuration	Frequent flexing
PUR	–40 °C to 80 °C	–10 °C to 80 °C
EPG	–40 °C to 120 °C	–
TPE	–40 °C to 120 °C	–
PVC	–20 °C to 90 °C	–10 °C to 90 °C

With limited hydrolytic and media exposure, PUR cables can be used up to 100°C. If needed, please ask for assistance from HEIDENHAIN.

Lengths
The cable lengths listed in the Specifications apply only for HEIDENHAIN cables and the recommended input circuitry of subsequent electronics.

Cable	Material	Bend radius R	
		Rigid configuration	Frequent flexing
Ø 3.7 mm	**PUR**	≥ 8 mm	≥ 40 mm
Ø 4.3 mm		≥ 10 mm	≥ 50 mm
Ø 4.5 mm			
Ø 4.5 mm	**EPG**	≥ 18 mm	–
Ø 5.1 mm	**PUR**	≥ 10 mm	≥ 50 mm
Ø 5.5 mm	**PVC**	Upon request	Upon request
Ø 6 mm	**PUR**	≥ 20 mm	≥ 75 mm
Ø 6.8 mm			
Ø 8 mm		≥ 40 mm	≥ 100 mm
Ø 10 mm[1)]		≥ 35 mm	≥ 75 mm
Ø 14 mm[1)]		≥ 100 mm	≥ 100 mm
TPE wires with braided sleeving	**TPE**	≥ 10 mm	–

[1)] Metal armor

Electrical safety and electromagnetic compatibility

Electrical safety
The encoder housings are isolated against internal circuits. Rated surge voltage: 500 V as per DIN EN 60664-1.

Electromagnetic compatibility (EMC)
When properly installed, and when HEIDENHAIN cables are used, HEIDENHAIN encoders fulfill the requirements for electromagnetic compatibility according to **EMC directive 2004/108/EC** with respect to the generic standards for:

- **Immunity DIN EN 61000-6-2:**

Specifically the following basic standards:

– ESD	DIN EN 61000-4-2
– Electromagnetic fields	DIN EN 61000-4-3
– Burst	DIN EN 61000-4-4
– Surge	DIN EN 61000-4-5
– Conducted disturbances	DIN EN 61000-4-6
– Power frequency magnetic fields	DIN EN 61000-4-8
– Voltage dips, short interruptions	DIN EN 61000-4-11

- **Emission** **DIN EN 61000-6-4:**

Specifically the following product (family) standard:

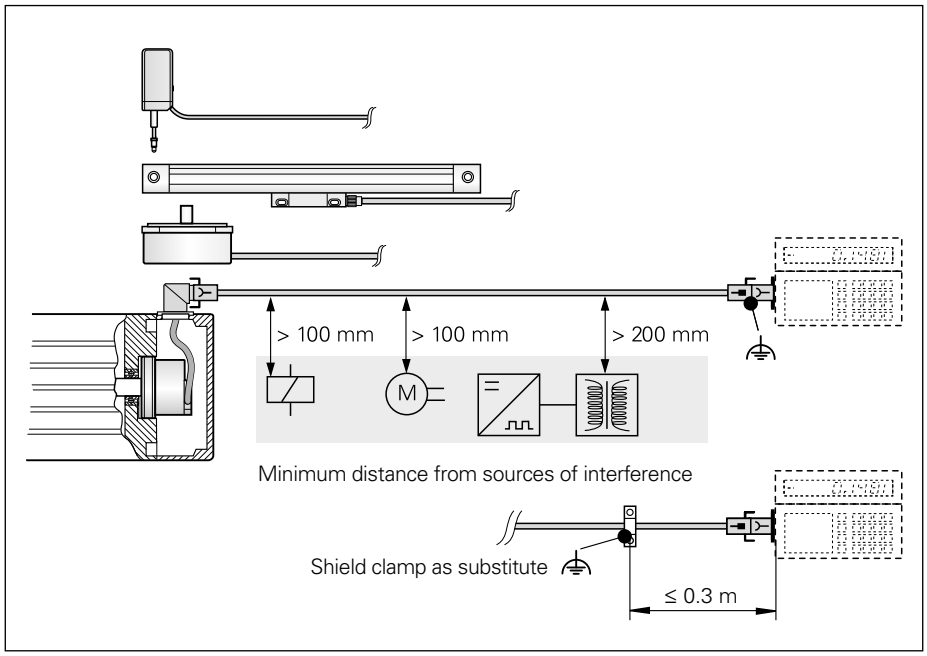
– For information technology equipment	DIN EN 55022

Sources of electrical interference
Electrical interference is caused mainly through capacitive or inductive transfer. Inductive transfer can be introduced into the system over signal lines and input or output terminals.
Typical sources for electrical interference include:

- Strong magnetic fields from transformers, brakes and electric motors
- Relays, contactors and solenoid valves
- High-frequency equipment, pulse devices, and stray magnetic fields from switch-mode power supplies
- AC power lines and supply wires to the above devices

Measures
The following measures must be complied with for disturbance-free operation. If other actions are taken, specific measures regarding electrical safety and EMC are required.

- Use only original HEIDENHAIN cables. Consider the voltage drop in the supply wires.
- Use connecting elements (such as connectors or terminal boxes) with metal housings. Only the signals and voltage supply of the connected encoder may be routed through these elements (exception: hybrid motor cables from HEIDENHAIN).
- Connect the housings of the encoder, connecting elements and subsequent electronics through the shield of the cable. Ensure that the shield has complete contact over the entire surface (360°). For encoders with more than one electrical connection, refer to the documentation for the respective product.
- Cables with inner and outer shielding are to be kept spatially apart. Connect the inner shield to 0 V of the subsequent electronics. Do not connect the inner shield with the outer shield, neither in the encoder nor in the cable.
- Connect the (outer) shield to functional earth as per the mounting instructions.
- Prevent contact of the shield (e.g. connector housing) with other metal surfaces. Pay attention to this when installing cables.
- Do not install signal cables in the direct vicinity of interference sources (inductive consumers such as contactors, motors, frequency inverters, solenoids, etc.).
  - Sufficient decoupling from interference-signal-conducting cables can usually be achieved by an air clearance of 100 mm or, when cables are in metal ducts, by a grounded partition.
  - A minimum spacing of 200 mm to inductors in switch-mode power supplies is required.
- If compensating currents are to be expected within the overall system, a separate equipotential bonding conductor must be provided. The shield does not have the function of an equipotential bonding conductor.
- Only provide power from PELV systems (see DIN EN 50178 for an explanation of the term) to position encoders, and provide high-frequency grounding with low impedance (see DIN EN 60204-1 Chapter EMC).
- For encoders with 11 μA_{PP} interface: Use only HEIDENHAIN cable ID 244955-01 as extension cable. Overall length: max. 30 m.



Minimum distance from sources of interference

Evaluation electronics

IK 220
Universal PC counter card
The IK 220 is an expansion board for PCs for recording the measured values of two incremental or absolute HEIDENHAIN encoders. The subdivision and counting electronics subdivide the sinusoidal input signals 4096-fold. A driver software package is included.



For more information, see the *IK 220* Product Information sheet.

	IK 220			
Encoder inputs Switchable	∿ 1 V_{PP}	∿ 11 μA_{PP}	EnDat 2.1	SSI
Connection	Two D-sub connections (15-pin, male)			
Input frequency	≤ 500 kHz	≤ 33 kHz	–	
Signal subdivision	4096-fold		–	
Internal memory	8192 position values per input			
Interface	PCI bus (plug and play)			
Driver software and demo program	**For Windows 2000/XP/Vista/7** in VISUAL C++, VISUAL BASIC and BORLAND DELPHI			

IBV / APE series
Interpolation and digitizing electronics
Interpolation and digitizing electronics interpolate and digitize the sinusoidal output signals (∿ 1 V_{PP}) from HEIDENHAIN encoders up to 400-fold, and convert them to TTL square-wave pulse trains.



IBV 101

For more information, see the *IBV 100, IBV 600* and *APE 371* Product Information documents, as well as the *Interface Electronics* Product Overview.

	IBV 101	**IBV 102**	**IBV 660 B**	**APE 371**
Design	Housing			Connector
Protection	IP 65			IP 40
Encoder input	∿ 1 V_{PP}			
Connection	*IBV:* M23 flange socket (12-pin, female) *APE:* D-sub connector (15-pin, female) or M23 connector (12-pin, female)			
Interpolation Switchable	5-fold 10-fold	20-fold 25-fold 50-fold 100-fold	25-fold 50-fold 100-fold 200-fold 400-fold	5-fold 10-fold 20-fold 25-fold 50-fold 100-fold
Output	• Two ⊓⊔ TTL square-wave pulse trains U_{a1} and U_{a2} and their inverted signals $\overline{U_{a1}}$ and $\overline{U_{a2}}$ • Reference pulse U_{a0} and $\overline{U_{a0}}$ • Fault detection signal $\overline{U_{aS}}$ • Limit and homing signals H, L (for APE 371)			
Voltage supply	5 V DC ± 0.25 V %			

EIB series
External interface box
The external interface box subdivides the sinusoidal output signals from HEIDENHAIN encoders and converts them into absolute position values with the aid of the integrated counting function. When the reference mark is crossed, the position value is defined with respect to a fixed reference point.



EIB 392

For more information, see the *EIB 192* and *EIB 392* Product Information sheets.

	EIB 192	EIB 392
Design	Housing	Connector
Protection	IP 65	IP 40
Encoder input	∿ 1 V_{PP}	
Connection	M23 connector (12-pin, female)	• D-sub (15-pin, female) • M23 connector (12-pin, female)
Signal subdivision	≤ 16384-fold	
Interface (output)	***EIB 192/EIB 392:*** EnDat 2.2 ***EIB 192 F/EIB 392 F:*** Fanuc Serial Interface ***EIB 192 M/EIB 392 M:*** Mitsubishi high speed interface	
Voltage supply	5 V DC ± 0.25V	

EIB 741
External interface box
The EIB 741 is ideal for applications requiring high resolution, fast measured-value acquisition, mobile data acquisition or data storage.
Up to four incremental or absolute HEIDENHAIN encoders can be connected to the EIB 741. The data is output over a standard Ethernet interface.



For more information, see the *EIB 741* Product Information sheet.

	EIB 741		
Encoder inputs Switchable	∿ 1 V_{PP}	EnDat 2.1	EnDat 2.2
Connection	Four D-sub connections (15-pin, female)		
Input frequency	≤ 500 kHz	–	
Signal subdivision	4096-fold	–	
Internal memory	Typically 250000 position values per input		
Interface	Ethernet as per IEEE 802.3 (≤ 1 gigabit)		
Driver software and demo program	**For Windows, Linux, LabView** Program examples		

EIB 1500 series
External interface box
The EIB 1500 is an interpolation and digitizing unit for digital calculation of the positions of two scanning heads on an incremental rotational HEIDENHAIN encoder. When the two scanning heads are mounted appropriately (180° ± 5°), errors due to eccentricity of the mating shaft and centering errors can be minimized.



	EIB 1512	EIB 1592 F	EIB 1592 M
Encoder inputs	2 x ∿ 1 V_{PP}		
Connection	M23 connector (12-pin, female)		
Signal subdivision	≤ 16384-fold (depending on encoder)		
Interface (output)	EnDat 2.2	Fanuc Serial Interface	Mitsubishi high speed interface
Connection	M12 flange socket (8-pin, male)		
Voltage supply	3.6 to 14 V DC		

HEIDENHAIN testing equipment

The **PWM 9** is a universal measuring device for checking and adjusting HEIDENHAIN incremental encoders. Expansion modules are available for checking the various types of encoder signals. The values can be read on an LCD monitor. Soft keys provide ease of operation.



	PWM 9
Encoder inputs	Expansion modules (interface boards) for 11 μA_{PP}; 1 V_{PP}; TTL; HTL; EnDat*/SSI*/commutation signals *No display of position values or parameters
Functions	• **Measures** signal amplitudes, current consumption, operating voltage, scanning frequency • **Graphically displays** incremental signals (amplitudes, phase angle and on-off ratio) and the reference-mark signal (width and position) • **Displays symbols** for the reference mark, fault-detection signal, counting direction • **Universal counter,** interpolation selectable from single to 1024-fold • **Adjustment support** for exposed linear encoders
Outputs	• Inputs are connected through to the subsequent electronics • BNC sockets for connection to an oscilloscope
Power supply	10 V to 30 V DC, max. 15 W
Dimensions	150 mm × 205 mm × 96 mm

The **PWT** is a simple adjusting aid for HEIDENHAIN incremental encoders. In a small LCD window the signals are shown as bar charts with reference to their tolerance limits.



	PWT 10	PWT 17	PWT 18
Encoder input	∿ 11 μA_{PP}	⊓⊔ TTL	∿ 1 V_{PP}
Functions	Measurement of signal amplitude Wave-form tolerance Amplitude and position of the reference mark signal		
Power supply	Via power supply unit (included)		
Dimensions	114 mm x 64 mm x 29 mm		

The **APE 381** interface electronics unit is necessary in order to connect PWM/PWT units to encoders with signal-error compensation. The APE 381 deactivates the signal-error compensation integrated in the scanning head, permitting evaluation of the uncompensated 1 V_{PP} output signals of the encoder.



	APE 381
Encoder input	∿ 1 V_{PP} (signals are connected through)
Design	Cable with D-sub connector
Function	Switch-off of the signal-error compensation integrated in the scanning head
Power supply	Via subsequent electronics

PWM 20
Together with the ATS adjusting and testing software, the PWM 20 phase angle measuring unit serves for diagnosis and adjustment of HEIDENHAIN encoders.



	PWM 20
Encoder input	• EnDat 2.1 or EnDat 2.2 (absolute value with/without incremental signals) • DRIVE-CLiQ • Fanuc Serial Interface • Mitsubishi high speed interface • Yaskawa • SSI • 1 V_{PP}/TTL/11 μA_{PP}
Interface	USB 2.0
Power supply	100 V to 240 V AC or 24 V DC
Dimensions	258 mm x 154 mm x 55 mm

	ATS
Languages	Choice between English and German
Functions	• Position display • Connection dialog • Diagnosis • Mounting wizard for EBI/ECI/EQI, LIP 200, LIC 4000 and others • Additional functions (if supported by the encoder) • Memory contents
System requirements and recommendations	PC (dual-core processor, > 2 GHz) RAM > 2 GB Windows operating systems XP, Vista, 7 (32-bit/64-bit), 8 200 MB free space on hard disk

DRIVE-CLiQ is a registered trademark of Siemens Aktiengesellschaft

HEIDENHAIN

DR. JOHANNES HEIDENHAIN GmbH
Dr.-Johannes-Heidenhain-Straße 5
83301 Traunreut, Germany
☏ +49 8669 31-0
FAX +49 8669 5061
E-mail: info@heidenhain.de

www.heidenhain.de

Vollständige und weitere Adressen siehe www.heidenhain.de
For complete and further addresses see www.heidenhain.de

DE **HEIDENHAIN Vertrieb Deutschland**
83301 Traunreut, Deutschland
☏ 08669 31-3132
FAX 08669 32-3132
E-Mail: hd@heidenhain.de

HEIDENHAIN Technisches Büro Nord
12681 Berlin, Deutschland
☏ 030 54705-240

HEIDENHAIN Technisches Büro Mitte
07751 Jena, Deutschland
☏ 03641 4728-250

HEIDENHAIN Technisches Büro West
44379 Dortmund, Deutschland
☏ 0231 618083-0

HEIDENHAIN Technisches Büro Südwest
70771 Leinfelden-Echterdingen, Deutschland
☏ 0711 993395-0

HEIDENHAIN Technisches Büro Südost
83301 Traunreut, Deutschland
☏ 08669 31-1345

AR **NAKASE SRL.**
B1653AOX Villa Ballester, Argentina
www.heidenhain.com.ar

AT **HEIDENHAIN Techn. Büro Österreich**
83301 Traunreut, Germany
www.heidenhain.de

AU **FCR Motion Technology Pty. Ltd**
Laverton North 3026, Australia
E-mail: vicsales@fcrmotion.com

BE **HEIDENHAIN NV/SA**
1760 Roosdaal, Belgium
www.heidenhain.be

BG **ESD Bulgaria Ltd.**
Sofia 1172, Bulgaria
www.esd.bg

BR **DIADUR Indústria e Comércio Ltda.**
04763-070 – São Paulo – SP, Brazil
www.heidenhain.com.br

BY **GERTNER Service GmbH**
220026 Minsk, Belarus
www.heidenhain.by

CA **HEIDENHAIN CORPORATION**
Mississauga, OntarioL5T2N2, Canada
www.heidenhain.com

CH **HEIDENHAIN (SCHWEIZ) AG**
8603 Schwerzenbach, Switzerland
www.heidenhain.ch

CN **DR. JOHANNES HEIDENHAIN (CHINA) Co., Ltd.**
Beijing 101312, China
www.heidenhain.com.cn

CZ **HEIDENHAIN s.r.o.**
102 00 Praha 10, Czech Republic
www.heidenhain.cz

DK **TP TEKNIK A/S**
2670 Greve, Denmark
www.tp-gruppen.dk

ES **FARRESA ELECTRONICA S.A.**
08028 Barcelona, Spain
www.farresa.es

FI **HEIDENHAIN Scandinavia AB**
02770 Espoo, Finland
www.heidenhain.fi

FR **HEIDENHAIN FRANCE sarl**
92310 Sèvres, France
www.heidenhain.fr

GB **HEIDENHAIN (G.B.) Limited**
Burgess Hill RH15 9RD, United Kingdom
www.heidenhain.co.uk

GR **MB Milionis Vassilis**
17341 Athens, Greece
www.heidenhain.gr

HK **HEIDENHAIN LTD**
Kowloon, Hong Kong
E-mail: sales@heidenhain.com.hk

HR Croatia → **SL**

HU **HEIDENHAIN Kereskedelmi Képviselet**
1239 Budapest, Hungary
www.heidenhain.hu

ID **PT Servitama Era Toolsindo**
Jakarta 13930, Indonesia
E-mail: ptset@group.gts.co.id

IL **NEUMO VARGUS MARKETING LTD.**
Tel Aviv 61570, Israel
E-mail: neumo@neumo-vargus.co.il

IN **HEIDENHAIN Optics & Electronics India Private Limited**
Chetpet, Chennai 600 031, India
www.heidenhain.in

IT **HEIDENHAIN ITALIANA S.r.l.**
20128 Milano, Italy
www.heidenhain.it

JP **HEIDENHAIN K.K.**
Tokyo 102-0083, Japan
www.heidenhain.co.jp

KR **HEIDENHAIN Korea LTD.**
Gasan-Dong, Seoul, Korea 153-782
www.heidenhain.co.kr

MX **HEIDENHAIN CORPORATION MEXICO**
20235 Aguascalientes, Ags., Mexico
E-mail: info@heidenhain.com

MY **ISOSERVE SDN. BHD.**
43200 Balakong, Selangor
E-mail: isoserve@po.jaring.my

NL **HEIDENHAIN NEDERLAND B.V.**
6716 BM Ede, Netherlands
www.heidenhain.nl

NO **HEIDENHAIN Scandinavia AB**
7300 Orkanger, Norway
www.heidenhain.no

PH **Machinebanks` Corporation**
Quezon City, Philippines 1113
E-mail: info@machinebanks.com

PL **APS**
02-384 Warszawa, Poland
www.heidenhain.pl

PT **FARRESA ELECTRÓNICA, LDA.**
4470 - 177 Maia, Portugal
www.farresa.pt

RO **HEIDENHAIN Reprezentanţă Romania**
Braşov, 500407, Romania
www.heidenhain.ro

RS Serbia → **BG**

RU **OOO HEIDENHAIN**
125315 Moscow, Russia
www.heidenhain.ru

SE **HEIDENHAIN Scandinavia AB**
12739 Skärholmen, Sweden
www.heidenhain.se

SG **HEIDENHAIN PACIFIC PTE LTD.**
Singapore 408593
www.heidenhain.com.sg

SK **KOPRETINA TN s.r.o.**
91101 Trencin, Slovakia
www.kopretina.sk

SL **NAVO d.o.o.**
2000 Maribor, Slovenia
www.heidenhain.si

TH **HEIDENHAIN (THAILAND) LTD**
Bangkok 10250, Thailand
www.heidenhain.co.th

TR **T&M Mühendislik San. ve Tic. LTD. ŞTİ.**
34728 Ümraniye-Istanbul, Turkey
www.heidenhain.com.tr

TW **HEIDENHAIN Co., Ltd.**
Taichung 40768, Taiwan R.O.C.
www.heidenhain.com.tw

UA **Gertner Service GmbH Büro Kiev**
01133 Kiev, Ukraine
www.heidenhain.ua

US **HEIDENHAIN CORPORATION**
Schaumburg, IL 60173-5337, USA
www.heidenhain.com

VE **Maquinaria Diekmann S.A.**
Caracas, 1040-A, Venezuela
E-mail: purchase@diekmann.com.ve

VN **AMS Co. Ltd**
HCM City, Vietnam
E-mail: davidgoh@amsvn.com

ZA **MAFEMA SALES SERVICES C.C.**
Midrand 1685, South Africa
www.heidenhain.co.za

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