DRIVECOD Rotary actuators & Positioning Units



Smart encoders & actuators

Product range

A comprehensive range of products, designed and manufactured from one hand.



ROTAPULS Incremental rotary encoders



ROTACOD Absolute rotary & Fieldbus encoders



ROTAMAG Rotary Magnetic encoder & Encoder modules



LINEPULS – LINECOD Linear Absolute & Incremental encoders



DRAW-WIRE Draw-wire encoders & potentiometers



POSICONTROL Displays & Signal converters Encoder Interfaces



DRIVECOD Rotary Actuators & Positioning units

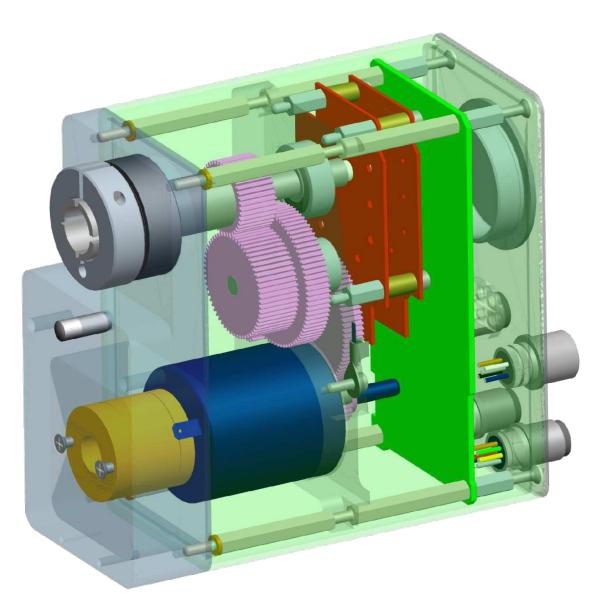


COUPLINGS Flexible & Transmission couplings

Parts of a rotary actuator



Brushless motor Gearbox Brake Absolute encoder Position Controller & Drive



			· · · ·		NEW
	RD1A	RD12A	RD4	RD5	RD53
Dimensions [mm]	59 x 125 x 112	59 x 125 x 128	65 x 153 x 160	48 x 88 x 127	48 x 88 x 127
Torque (nominal) Torque (starting)	5 Nm 12 Nm	5 Nm 12 Nm	15 Nm 30 Nm	5 Nm 12 Nm	5 Nm 12 Nm
Shaft speed [rpm]	60 min 240 max	60 min 240 max	63 min 94 max	60	60
Motor brake	-	*	-	-	*
Interfaces	CanOpen Profibus-DP Modbus RS485 EtherCAT	CanOpen Profibus-DP Modbus RS485 EtherCAT	CanOpen Profibus-DP Modbus RS485	CanOpen Profibus-DP Modbus RS485	CanOpen Profibus-DP Modbus RS485
Absolute Encoder	1024 x 1024	1024 x 1024	1024 x 1024	1024 x 256	1024 x 256

RD1A, RD12A series





Torque	5 Nm @ 60rpm (starting 12Nm) 2,5Nm@120rpm (starting 6Nm) 1,2Nm@240rpm (starting 3Nm)
BLDC	High performance brushless motor
Brake	integrated (RD12A)
Ø14mm	Hollow shaft
M12	Connectors, Bus IN/OUT, PWR
LED	Diagnostics for Bus & Power supply
Jog +/-	Buttons for easy calibration
1024x1024	absolute encoder
RS232	service interface (excl. Modbus)













CANOpen

Torque	15 Nm@63rpm (starting 30Nm) 10 Nm@94rpm (starting 24Nm)
BLDC	High performance brushless motor
Gearbox	in oil-bath
	(continuous operation possible)
Ø14mm	Hollow shaft
M12	Connectors
LEDs	Diagnostics for Bus & Power supply
1024x1024	absolute encoder
3+3	configurable I/O's
PROFI	







Torque	5 Nm@60rpm (12Nm peak)
BLDC	High performance brushless motor
Brake	integrated (on RD53 series)
Ø14mm	Hollow shaft
M12	Connectors, Bus IN/OUT, PWR
1024x256	absolute encoder
LED	Diagnostics for Bus & Power supply









Torque	0,426 Nm @ 3000rpm
BLDC	High performance brushless motor
NEMA23	size flange
Ø8mm	Solid shaft
M12	Connectors, Bus IN/OUT, PWR
12x16bit	absolute encoder
LED	Diagnostics for Bus & Power supply



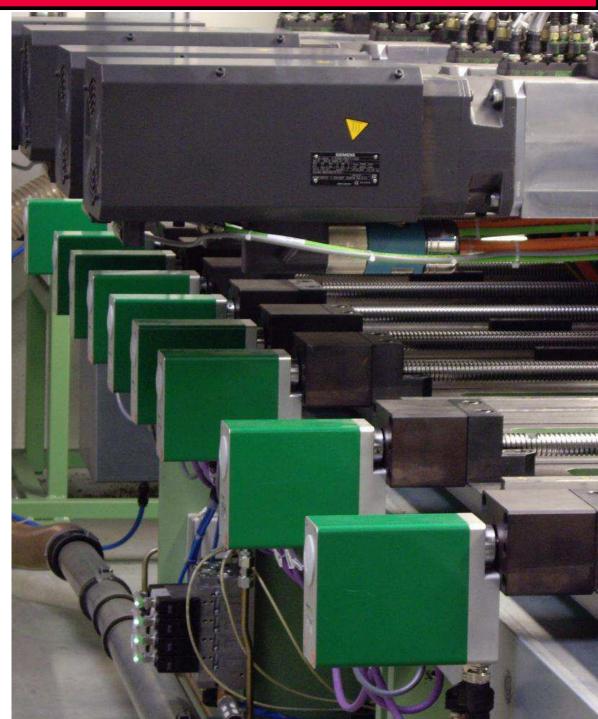




Advantages

Fasteraxis setupMultipleadjustmentsPrecisepositioningRepeatablepositioningCentralized-> Increased

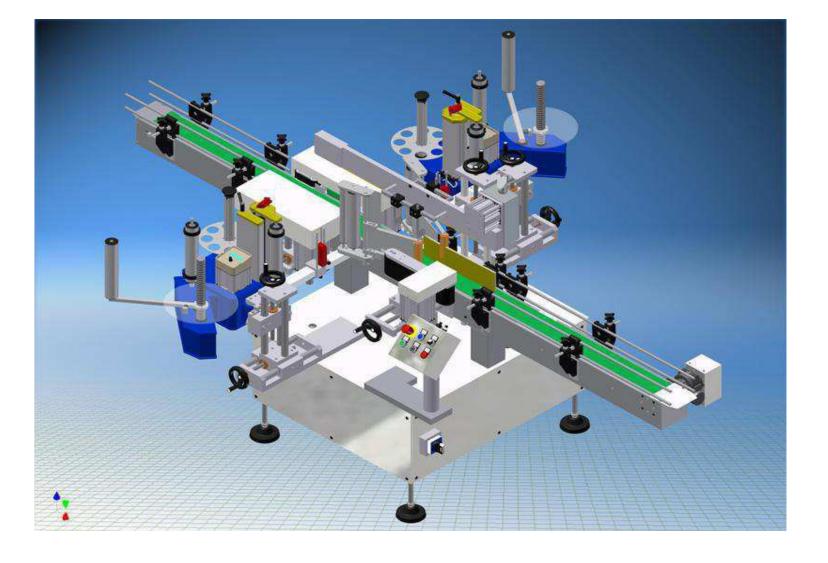
Flexibility



Labeling & Bottling machines

Axis setting for:

- Bottle height
- Label size
- Feeder/Conveyor



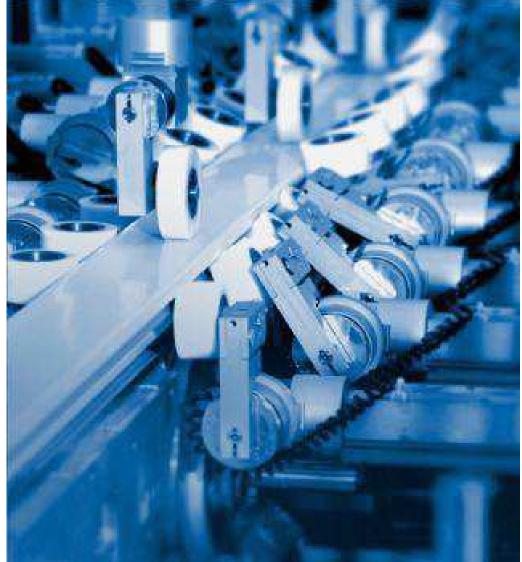


Pastry laminating thickness control



Woodworking machinery

- Material stops
- Height settings
- Edge bending axis
- Suction cup positioning
- Drilling head positioning
- Set-axes on frame working machines



Printing & Paper machinery

- Automatic format adjustment
- Distance/Size settings
- Throughput adjustment on flexo & spooling machines, printing presses



LDT10 HMI touch panel









- LCD display with resistive touch screen panel (7-inch 16:9 format)
- Configure & control up to 8 RDxx rotary actuators
- NEMA4 and IP65 protection ratings

LDT10 pages & levels



HOME





RD4 RD5

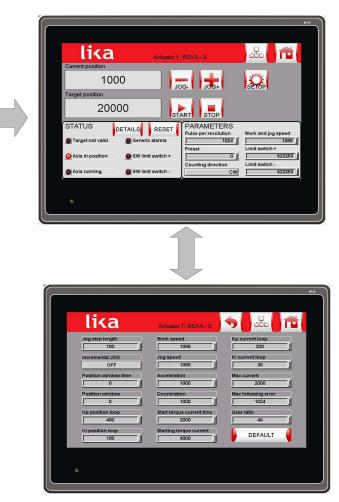
RD4 RD5

RD4

n.c. RD1 RD4 RD5

RD4 RD5

NODE



3 levels of users:

- User can only activate recipes
- Manager has complete recipes management
- Administrator can manage network and actuators parameters

Actuator 2: RD5 - Y

Actuator 3

Actuator 5

Actuator 6:

Actuator 7

Actuator 8

LDT10 Home page



	lika				, Q		
	t program		-	Actual position		55 arget	
1	PROG 1	activate		1	י. זו גער		
2	PROG 2	recipe	RD1A - X	0	│ ⋜╿	10000	
3	PROG 3		RD5 - Y	0	 ~ 	20000	
4		STOP					
5		SIUP					
6	7 8 7 2017 2019						
7							
	-0-						
8							
9							
10							1
Φ							

- To create and activate recipes (set of target positions for each axis)
- Possible to transfer current positions (manually defined) into recipe targets

LDT10 Network pages





Network control

Allow to enter in Node control, Network setup and different user levels

Network setup

Allows Administrator to name and associate an actuator to each axis (address)

lik	а					
Actuator 1:	RD1A - X	n.c.	RD1	RD4	RD5	
Actuator 2:	RD5 - Y	 	RD1	RD4	RD5	
Actuator 3:		n.c.	RD1	RD4	RD5	
Actuator 4:		n.c.	RD1	RD4	RD5	
Actuator 5:		n.c.	RD1	RD4	RD5	
Actuator 6:		n.c.	RD1	RD4	RD5	
Actuator 7:		n.c.	RD1	RD4	RD5	
Actuator 8:		n.c.	RD1	RD4	RD5	
		n.c.: not cor	nnected			
6						

LDT10 Node pages



				EE
lika	Actuator 1:	RD1A - X	品合	
Current position				
1000	JC	DG- JOG+	SETUP	
Target position				
20000	ST/	ART		
STATUS	RESET	PARAMETERS Pulse per revolution	Work and jog speed	
Target not valid	c alarms	1024	1066]	
		Preset	Limit switch +	
Axis in position	it switch +	0	523263	
	14	Counting direction	Limit switch -	
Axis running SW lim	it switch -	CW	523263	

Node control

allows to check position, manual jog, define target, check alarms, set up main parameters, reset, enter in node setup

Node setup

Allows Administrator to set up all actuator parameters

Lika Actuator 1: RD1A - X Jog step length Work speed 100 1066 100 Jog speed Incremental JOG Jog speed OFF 1066 OFF 1066 0 1000 Position window time Acceleration 0 1000 Position window Deceleration 0 1000 Very position loop Start torque current time 400 200 Ki position loop Start torque current 100 Max 0 Very position loop Start torque current 100 DEFAULT			
100 1066 200 Incremental JOG Jog speed Ki current loop OFF 1066 30 Position window time Acceleration Max current 0 1000 2000 Position window Deceleration Max following error 0 1000 1024 Kp position loop Start torque current time Gear ratio 400 2000 48 Ki position loop Starting torque current DEEAULT	lika	Actuator 1: RD1A - X	
OFF 1066 30 Position window time Acceleration Max current 0 1000 2000 Position window Deceleration Max following error 0 1000 1024 Kp position loop Start torque current time Gear ratio 400 2000 48 Ki position loop Starting torque current DECEAULT			
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0 1000 1024 Kp position loop Start torque current time Gear ratio 400 2000 48 Ki position loop Starting torque current DEFAULT			
400 2000 48 Ki position loop Starting torque current DEFAULT			
			DEFAULT
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