



## Mounting Instructions

**smartServo BL 4000-D**  
**smartServo BL 4000-M**

***Important!***  
***Read thoroughly before use!***  
***Retain for future reference!***

## Original Mounting Instructions

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## ➤ Contact

Metronix Meßgeräte und Elektronik GmbH  
Kocherstraße 3  
38120 Braunschweig  
Germany  
Telephone: +49 (0)531 8668 0  
Fax: +49 (0)531 8668 555  
E-mail: [vertrieb@metronix.de](mailto:vertrieb@metronix.de)  
<https://www.metronix.de>

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# 1 About this Mounting Instructions

The purpose of these Mounting Instructions is to ensure the safe installation and proper wiring of the servo drives of the smartServo BL 4000-D or BL 4000-M series. The safe use of the servo drive and of the Metronix ServoCommander® parameterisation program is described in the Product manual smartServo BL 4000-D and BL 4000-M.

The safety instructions and warnings in this Mounting Instructions must always be followed.

## 1.1 Explanations and notation

### 1.1.1 Structure of the warning notes

Warning notes have the following structure:

- Signal word
- Type of hazard
- Measures to prevent the hazard

#### > Signal words

##### **⚠ DANGER**

Indicates an imminent hazard.

If the situation is not avoided, extremely serious and possibly fatal injuries will result.

##### **⚠ WARNING**

Indicates a potentially hazardous situation.

If the situation is not avoided, extremely serious and possibly fatal injuries may result.

##### **⚠ CAUTION**

Indicates a potentially hazardous situation.

If the situation is not avoided, slight or minor injuries may result.

##### **NOTICE**

Warns against damage to property.

#### > Warning signs as per ISO 7010

| Warning sign                                                                        | Explanation                             |
|-------------------------------------------------------------------------------------|-----------------------------------------|
|  | Warning against fatal electric voltage. |
|  | Warning against hot surfaces.           |

## 1.1.2 Structure of notes

The notes in this Mounting Instructions have the following structure:

- Signal word "NOTE"
- Introductory phrase
- Explanations and special tips

## 1.2 Additional documents

Further information can be found in the following manuals:

- Product manual smartServo BL 4000-D and BL 4000-M: Describes the safe installation and proper wiring of the servocontrollers smartServo BL 4000-D or BL 4000-M, as well as safe working with the servocontroller and the parameterisation program Metronix ServoCommander®.
- EtherCAT and CANopen manual BL 4000: This manual describes the commissioning procedure for the servo drives ARS 2000 FS or BL 4000 with a CANopen or EtherCAT control system.
- PROFIBUS/PROFINET manual ARS 2000 FS / smartServo BL 4000: This manual describes the commissioning procedure for the servo drives ARS 2000 FS or BL 4000 with a PROFINET control system.

You can find all of these documents on our homepage for download. Certificates and declarations of conformity for the products described in this manual can also be found at our homepage: <https://www.metronix.de>

## 1.3 Order numbers

| Order number   | Description   |
|----------------|---------------|
| 9200-4840-2000 | BL 4840-M     |
| 9200-4840-3000 | BL 4840-D     |
| 9200-4840-2015 | BL 4840-M CAN |
| 9200-4840-3015 | BL 4840-D CAN |

| Order number   | Description   |
|----------------|---------------|
| 9200-4104-2000 | BL 4104-M     |
| 9200-4104-3000 | BL 4104-D     |
| 9200-4104-2015 | BL 4104-M CAN |
| 9200-4104-3015 | BL 4104-D CAN |

## 1.4 Applicable standards

| Standard           | Description                                                                                                                              |
|--------------------|------------------------------------------------------------------------------------------------------------------------------------------|
| EN 13849-1:2015    | Safety of machinery - Safety-related parts of control systems - Part 1: General principles for design                                    |
| EN 50581           | Technical documentation for the assessment of electrical and electronic products with respect to the restriction of hazardous substances |
| EN 60204-1         | Safety of machinery - Electrical equipment of machines - Part 1: General requirements                                                    |
| EN 61800-3         | Adjustable speed electrical power drive systems - Part 3: EMC requirements and specific test methods                                     |
| EN 61800-5-1       | Adjustable speed electrical power drive systems - Part 5-1: Safety requirements - Electrical, thermal and energy                         |
| EN 61800-5-2       | Adjustable speed electrical power drive systems - Part 5-2: Safety requirements - Functional                                             |
| EN 62061           | Safety of machinery - Functional safety of safety-related electrical, electronic and programmable electronic control systems             |
| EN ISO 12100       | Safety of machinery - General principles for design - Risk assessment and risk reduction                                                 |
| IEC 61508 Teil 1-7 | Functional safety of electrical/electronic/programmable electronic safety-related systems                                                |
| IEC 82079-1        | Preparation of instructions for use - Structuring, content and presentation - Part 1: General principles and detailed requirements       |
| UL 61800-5-1       | Standard for Adjustable Speed Electrical Power Drive Systems - Part 5-1: Safety Requirements - Electrical, Thermal and Energy            |
| CSA C22.2 No. 274  | Adjustable speed drives                                                                                                                  |

## 2 For your own safety

Servo drives of the BL 4000-M / BL 4000-D series can only be used safely, if you read and comply with this document.

### 2.1 General information

The servo drive has a safe design. However, certain hazards exist in the context of certain activities. These hazards can be avoided by following the correct procedures. The correct procedures for avoiding these hazards are described in this document.

In addition to the instructions described in this document, there may be additional health and safety instructions as well as general safety instructions that you must comply with. Keep informed about all of these aspects.

Professional project planning is a prerequisite for the correct and trouble-free operation of the servo drive.

The following requirements must be fulfilled to ensure the trouble-free and safe operation of the servo drive.

- Proper and correct transport
- Proper storage
- Proper installation
- Proper project planning taking in consideration all of the potential risks, necessary protective and emergency measures and the installation
- Careful operation and proper maintenance.

Only trained and qualified personnel in accordance with section 2.3 *Target group* on page 10 are authorised to work with or on the electrical systems.

The following instructions must be read and understood prior to the initial operation of the system in order to prevent injuries and/or damage to property. The following safety instructions must be complied with at all times:

- Do not attempt to install or start the servo drive without having read all of the safety instructions in this document concerning the electrical drives and controllers. These safety instructions and all other user notes must be read prior to performing any work with the servo drive.
- If the servo drive is sold, rented out or otherwise distributed to third parties, these safety instructions must be included.
- The user must not open the servo drive for safety and warranty reasons.

## 2.2 Intended use

The electronic drive control unit (servo drive) is intended for operation in combination with electric motors in an industrial environment. The handling of the servo drive requires qualified personnel that have been trained in terms of general and, in particular, electrical safety. The intended use also includes compliance with the information and instructions in this manual.

Any use going beyond or deviating from the intended use will be considered as misuse.

### **▲ WARNING Hazards caused by misuse**

Misuse of the servo drive will lead to dangerous situations.

- Use the servo drive only under the specified ambient condition.
- Do not use the servo drive outdoors or in explosive atmospheres.
- Use suitable and qualified specialist personnel for any type of work on the servo drive.
- Always comply with the voltage ranges that are specified in section 6 *Technical data* on page 63.
- Follow all of the instructions in this manual concerning the safe use of the servo drive.

## 2.3 Target group

Over its entire service life, work on the servo drive, with the exception of its operation, may only be performed by specialist personnel and/or instructed persons who have been trained for the required tasks. The servo drive is to be operated by the user.

### **› Trained and qualified personnel**

Qualified personnel in the sense of this document are persons who are sufficiently familiar with the project, set-up, installation, commissioning and operation of the servo drive as well as with all of the warnings and precautions and who are sufficiently qualified in their field of expertise:

- They have been trained, instructed and authorised to perform the switching and earthing (grounding) of the devices/systems in line with the applicable safety standards and to label them accordingly as per the job requirements.
- The service and maintenance personnel have undergone special training in the context of ESD protection measures.
- They have been trained and instructed in line with the applicable safety standards in terms of the maintenance and use of adequate safety equipment.
- They have completed first aid training.

## 2.4 General safety instructions

### **DANGER** **Danger to life due to electric shock!**

Non-compliance with the safety instructions will lead to a potentially fatal electric shock. The general set-up and safety rules and regulations concerning the work on power installations (e.g. DIN, VDE, EN, IEC or any other national or international rules and regulations) must be complied with.

- Safety-critical applications of the servo drive are not allowed unless specifically approved by the manufacturer.
- For information about the EMC-compliant installation, see section 5.1 *Notes concerning the safe and EMC-compliant installation* on page 26. The manufacturer of the machine or system is responsible for ensuring compliance with the limits that are specified by the applicable national rules and regulations.
- The ambient conditions that are specified in the product manual must be strictly observed.
- The technical data as well as the connection and installation conditions of the servo drive are stated in this document and must be complied with at all times.
- Refer to *General technical data* on page 63 for the protection rating and pollution degree of the servo drive. Ensure that the environment corresponds to this protection rating and pollution degree rating.
- Use only original accessories and original spare parts that have been approved by the manufacturer.
- The servo drives must be connected to the mains power supply in accordance with the country-specific regulations (EN standards, VDE rules) so that they can be disconnected from the mains power supply by way of suitable disconnectors (e.g. main switches, contactors, circuit breakers).
- Use gold contacts or contacts with a high contact pressure for switching the control contacts.
- Preventive interference suppression measures should be taken for the switchgear. This can be done, for example, by connecting RC circuits or diodes to the contactors and relays.

## 2.5 Personal protective equipment

Always use personal protective equipment during the transport, installation, start-up, cleaning, maintenance and removal of the servo drive, for example:

- **Protective gloves**  
To prevent superficial hand injuries.
- **ESD safety shoes**  
To prevent foot injuries caused by falling parts.  
To prevent electrostatic charging.
- **Protective work clothes**  
To prevent superficial injuries and soiling.
- **Protective goggles**  
To prevent eye injuries caused by dust or shards/splinters.
- **Light respiratory protection**  
To prevent the inhalation of harmful substances.

## 2.6 Safety notes for installation and maintenance

### **DANGER** **Dangerous electrical voltage!**

Prior to performing any maintenance tasks, you need to ensure that the power supply and the external power supply of the servo drive have been disconnected and secured against reconnection and that the DC bus has discharged.

During operation and also for a very long time after the servo drive has been switched off, the corresponding connections and an external braking resistor carry dangerous DC bus voltages. Contact with these voltages may result in serious or even fatal injuries.

Make sure that the DC bus has discharged by measuring at the DC bus terminals ZK+ and ZK- or wait for the maximum discharge time. This is for the BL 4100-M / BL 4100-D **30 minutes**. For the BL 4800-M / BL 4800-D no waiting time is required. In the event of a device defect, connections other than those specified here may also carry a life-threatening voltage. Under these circumstances, the discharge time must be waited for in any case.

### **WARNING** **Risk of burns due to hot surfaces**

The servo drive and, in particular, the (external or internal) braking resistor may become hot during operation. Always wait a sufficient amount of time prior to touching these parts.

Always use suitable personal protective equipment to avoid severe burns.

### **CAUTION** **Risk of injury for unqualified personnel!**

Only personnel who are trained and qualified for working on or with electrical devices are authorised to install, maintain and repair the servo drive.

**> To prevent accidents, injuries and damage to property:**

Perform a risk assessment and follow all of the statutory and local safety instructions and accident prevention regulations when installing or maintaining the system.

Ensure that the AC or DC power supplies are switched off and locked prior to performing any work in the area of the machine. The deactivation of the output stages or servo drive enable signals is not a suitable means of locking. In the case of a malfunction, the drive may accidentally be put into action. This does not apply to drives with the special "Safe Torque Off" feature in accordance with EN 61800-5-2.

Electronic devices are never completely fail-safe. It is the user's responsibility to ensure that the system is brought to a safe state if the electrical device fails.

Disconnect the electric equipment from the power supply via the main switch and secure it against reconnection. Wait until the DC bus has discharged in the following cases:

- maintenance and repairs
- cleaning
- long downtimes

The standard motor holding brake that is included in the scope of supply or any other external motor holding brake that is actuated by the servo drive is not suitable for the protection of the operators if used alone!

Be particularly careful during the installation process. During the installation and also later on during the operation of the drive, ensure that no drilling chips, metal dust or installation parts (screws, nuts, cable sections) can fall into the servo drive.

Use suitable personal protective equipment during the installation.

Vertical axes must be additionally secured against falling down or lowering after the motor has been switched off, for example by way of the following:

- mechanical locking of the vertical axis,
- external braking, catching or clamping devices, or
- sufficient weight counterbalance of the axis.

Perform the start-up process with idling motors. This is to avoid mechanical damage, e.g. due to an incorrect direction of rotation.

## 2.7 Protection against contact with electrical parts

### **⚠ DANGER** ⚠ **Dangerous electrical voltage!**

In certain device constellations, the rapid discharge of the DC bus voltage of the servo drive may be rendered ineffective. In these cases, the servo drives may still carry dangerous voltage levels for a very long time after they have been switched off (residual capacitor charge).

Make sure that the DC bus has discharged by measuring at the DC bus terminals ZK+ and ZK- or wait for the maximum discharge time. This is for the BL 4100-M / BL 4100-D **30 minutes**. For the BL 4800-M / BL 4800-D no waiting time is required. In the event of a device defect, connections other than those specified here may also carry a life-threatening voltage. Under these circumstances, the discharge time must be waited for in any case.

### ➤ **To prevent accidents, injuries and damage to property:**

Follow the national accident prevention regulations (for Germany, this is DGUV regulation 3 (formerly BGV A3)).

Do not touch the electrical connections of the components when they are switched on.

Prior to accessing electrical parts carrying voltages above 50 V, disconnect the device from the mains power supply or voltage source. Secure it against reconnection.

Install the respective covers and guards against accidental contact prior to switching the device/system on. Rack-mounted devices must be protected against accidental contact by way of an enclosure, e.g. a switch cabinet.

Prior to start-up and even for brief measurements or tests, connect the protective earth conductor (ground conductor) of all of the electrical devices in accordance with the circuit diagram (see section 5 *Electrical installation* on page 26) in a fixed manner (hardwiring) to the supply network or to the earthing system on site.

Comply with the minimum copper cross-section for the protective earth conductor (ground conductor) over its entire length (see EN 61800-5-1). Otherwise, the housing may carry high voltages which can cause electric shock.

With mains-powered servo drives (BL 4100-M / BL 4100-D), the leakage current is greater than 3.5 mA due to the integrated mains filters. Therefore, two separate protective earth connection points must be hard-wired for these units.

The magnitude of the DC bus voltage must be taken into consideration during the installation process in order to ensure proper insulation and protection. Ensure proper earthing (grounding), conductor rating and protection against short circuits.

## 2.8 Protection against electric shock by way of protective extra-low voltage (PELV)

### **⚠ DANGER** ⚠ **Dangerous electrical voltage!**

There is a risk of high electrical voltage due to incorrect electrical connections.

Always follow the safety instructions stated hereinbelow.

All of the connections and terminals with voltages up to 50 V of the servo drive have protective extra-low voltage. They are protected against contact in accordance with IEC 61800-5-1 and EN 61800-5-1.

Only devices, electrical components and wires or cables with protective extra-low voltage (PELV) may be connected to connectors and terminals with voltages from 0 to 50 V.

When connecting voltages and circuits, ensure that they are securely isolated from any dangerous voltages. This isolation can be realised by way of isolation transformers, safe optocouplers or battery operation without mains power.

## 2.9 Protection against dangerous movements

### **⚠ WARNING** **Risk of injury due to dangerous movements**

Always follow the safety instructions stated hereinbelow.

Dangerous movements can be caused by the faulty actuation of the connected motors. Causes may be as follows:

- improper or faulty wiring or cabling
- errors during the operation of the components
- errors of the sensors and transducers
- defective or non-EMC-compliant components
- software errors in the superordinate control system.

These errors can occur directly after the activation of the device or after some time during the operation.

The monitoring systems in the drive components exclude any malfunction in the connected drives to the greatest possible extent. However, in view of the protection of the operators, particularly in terms of the risk of injuries and damage to property, relying solely on this measure is not recommended. Until the built-in monitoring systems become effective, faulty drive movements should always be anticipated. The extent of these faulty drive movements depends on the type of control and on the operating state.

For the reasons mentioned above, protection must be ensured by monitoring or by superordinate measures. This must be implemented by the system manufacturer based on the specific system situation and on a hazard and fault analysis. This also includes the safety rules and regulations that apply to the system. Random movements of the machine or other malfunctions may be caused by deactivating, bypassing or failing to activate the safety devices.

## 2.10 Protection against contact with hot parts

### **⚠ WARNING** Risk of burns due to hot surfaces

The servo drive and, in particular, the (external or internal) braking resistor may become hot during operation. Always wait a sufficient amount of time prior to touching these parts. Always use suitable personal protective equipment to avoid severe burns.

## 2.11 Protection during the handling and installation of the devices

### **⚠ CAUTION** Risk of injury caused by crushing, shearing, cutting or impacts

Improper handling and installation of certain parts will cause injuries. Always follow the safety instructions stated hereinbelow.

- When installing the servo drive, ensure that it can be installed, operated and removed without any danger.
- Appropriate installation clearances must also be defined.
- Comply with the intended use of the servo drive.
- When transporting the servo drive, pay particular attention to the edges and corners of housings and other components. Use suitable personal protective equipment.
- If you install the components of the system on a wall or on the floor, dust may be created by drilling. Use suitable personal protective equipment.
- Use only suitable installation and transport equipment.
- Prevent trapping and crushing by suitable protective measures.
- Use only suitable tools. If specified, use special tools.
- Use lifting equipment and tools in a proper manner.
- Do not step under suspended loads.
- Liquid spills on the floor must be removed immediately.

## 3 Product description

The servo drives of the smartServo BL 4000-M / BL 4000-D series are smart AC servo drives for controlling three-phase synchronous motors, torque motors and linear motors. The servo drives can be used in a universal manner, since they can be combined with a wide range of encoder systems and motors. Due to their extensive parameterisation options, they can be adapted to a variety of different applications. The decentralised servo drives of the BL 4000-M / BL 4000-D device family are available in 4 different variants: BL 4000-M are designed for mounting on the motor, BL 4000-D for decentralised mounting near the motor outside a control cabinet. For both device families, devices with 230 V power supply as well as with 48 V power supply are available. Depending on the fieldbus variant, the connection to a superordinate control system can be realised via the integrated CANopen or EtherCAT/PROFINET interface.

Parameter sets that have been created for the ARS 2000 FS series can be used for the BL 4000-C, BL 4000-M / BL 4000-D series and vice versa.

### 3.1 Type designation

Type key using the example of a BL 4840-D.



Figure 1: Nomenclature

| Pos. | Description                                                                                               |
|------|-----------------------------------------------------------------------------------------------------------|
| 1    | Type designation: Basic Line                                                                              |
| 2    | 4th servo drive product family                                                                            |
| 3    | Mains power connection: 1 = single-phase / 3 = three-phase                                                |
| 4    | Nominal current in [A <sub>eff</sub> ]                                                                    |
| 5    | Cabinet (control cabinet device)<br>Decentral (separate from the motor)<br>Mounted (mounted on the motor) |
| 6    | Fieldbus variant CAN = CANopen / not stated = PROFINET / EtherCAT                                         |

Based on this, the following type designations are used:

| Designation | Description                                                                                 |
|-------------|---------------------------------------------------------------------------------------------|
| BL 4000-D   | Any decentralised (separate from the motor) device, regardless if with 48 V or 230 V supply |
| BL 4000-M   | Any device mounted on the motor, regardless if with 48 V or 230 V supply                    |
| BL 4100-D   | Any decentralised device (separate from the motor) with 230 V supply                        |
| BL 4800-D   | Any decentralised device (separate from the motor) with 48 V supply                         |
| BL 4100-M   | Any motor-mounted device supplied with 230 V                                                |
| BL 4800-M   | Any motor-mounted device supplied with 48 V                                                 |

| Designation | Description                                                                                           |
|-------------|-------------------------------------------------------------------------------------------------------|
| BL 4840-D   | A servo drive supplied with 48 V DC, separated from the motor, with 40 A <sub>eff</sub> rated current |
| BL 4104-M   | A motor-mounted servo drive supplied with 230 V and 4 A <sub>eff</sub> rated current                  |

All listed examples can also be marked with the addition CAN. In this case, the information refers to the units with the CANopen fieldbus variant.

## 3.2 Device view BL 4000-M

### > Front view

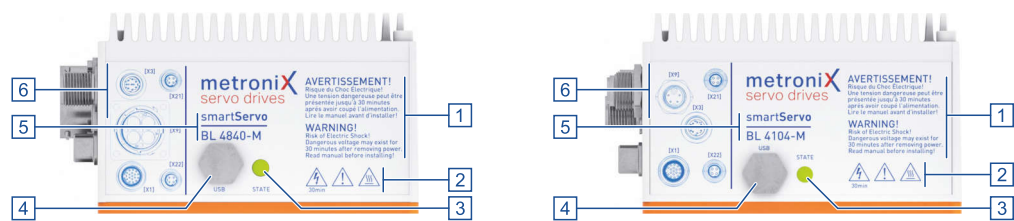


Figure 2: Front view of a BL 4800-M (left) and BL 4100-M (right)

|   |                                                        |   |                                    |
|---|--------------------------------------------------------|---|------------------------------------|
| 1 | Warnings                                               | 4 | [X19] USB interface with cover cap |
| 2 | Safety Symbols as per ISO 7000                         | 5 | Product name                       |
| 3 | Status indicator LED (READY, ERROR, ENABLE, BLUETOOTH) | 6 | Connector descriptions             |

### > View on connector side

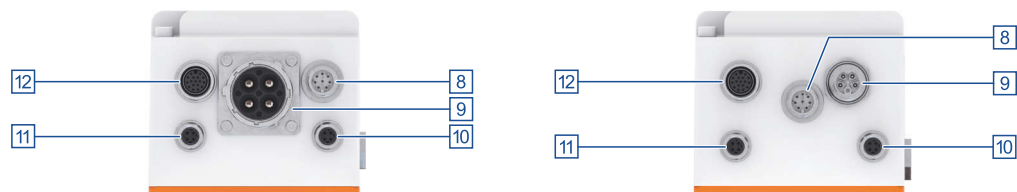


Figure 3: View on connector side of a BL 4800-M (left) and a BL 4100-M (right)

|    |                                    |    |                                    |
|----|------------------------------------|----|------------------------------------|
| 8  | [X3] 24 V supply and STO           | 11 | [X22] Real-time Ethernet interface |
| 9  | [X9] Power supply                  | 12 | [X1] I/O communication             |
| 10 | [X21] Real-time Ethernet interface |    |                                    |

## 3.3 Device view BL 4000-D

### › Front view

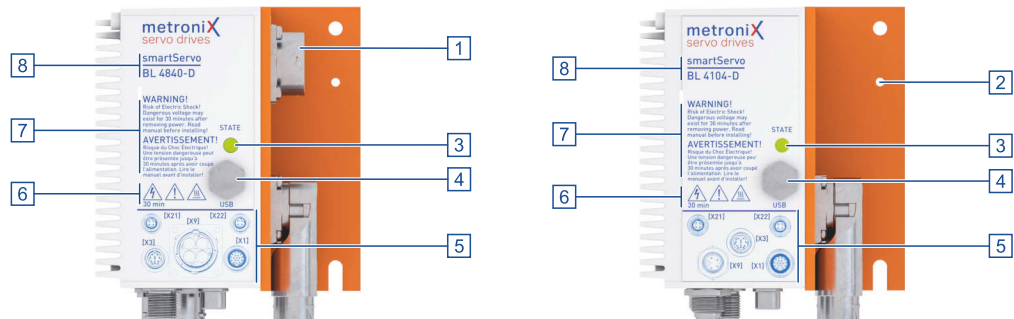


Figure 4: Front view of a BL 4800-D (left) and BL 4100-D (right)

|   |                                                        |   |                                |
|---|--------------------------------------------------------|---|--------------------------------|
| 1 | [X6A] Motor connection                                 | 5 | Connector descriptions         |
| 2 | Earthing screw                                         | 6 | Safety Symbols as per ISO 7000 |
| 3 | Status indicator LED (READY, ERROR, ENABLE, BLUETOOTH) | 7 | Warnings                       |
| 4 | [X19] USB interface with cover cap                     | 8 | Product name                   |

### › Bottom view

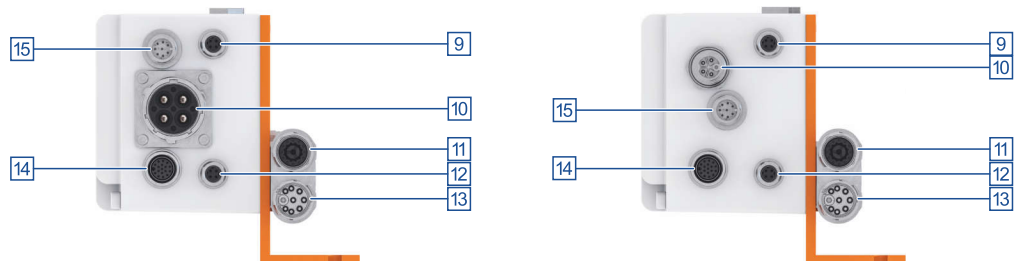


Figure 5: Bottom view of a BL 4800-D (left) and BL 4100-D (right)

|    |                                    |    |                          |
|----|------------------------------------|----|--------------------------|
| 9  | [X21] Real-time Ethernet interface | 13 | [X6] Motor connection    |
| 10 | [X9] Power supply                  | 14 | [X1] I/O communication   |
| 11 | [X2] Resolver/Multi-encoder        | 15 | [X3] 24 V supply and STO |
| 12 | [X22] Real-time Ethernet interface |    |                          |

> Side view

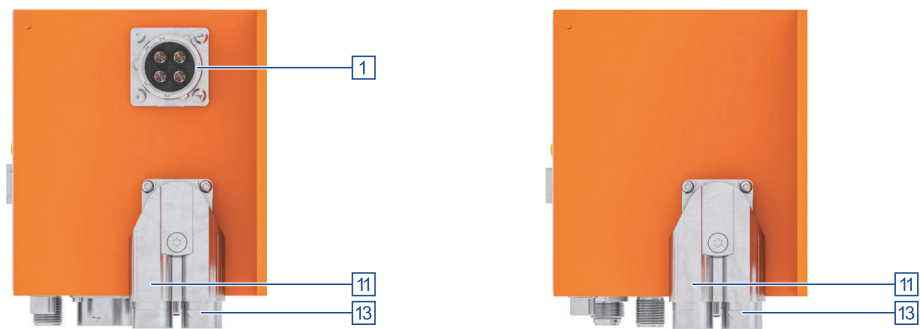


Figure 6: Side view of a BL 4800-D (left) and BL 4100-D (right)

|    |                                   |    |                                  |
|----|-----------------------------------|----|----------------------------------|
| 1  | [X6A] BL 4800-D: Motor connection | 13 | [X6] BL 4100-D: Motor connection |
| 11 | [X2] Resolver/Multi-encoder       |    |                                  |

## 3.4 Features

All of the servo drives of this series have the following features:

### › Integrated fieldbus interfaces

- Fieldbus variant CAN: CANopen interface
- Fieldbus variant EtherCAT/PROFINET:
  - EtherCAT interface (CoE)
  - PROFINET interface (Metronix standard telegrams, based on PROFIdrive)

### › Integrated universal shaft encoder evaluation for the following encoder types:

- Resolvers
- Analogue and digital incremental encoders with and without commutation signals
- High-resolution Stegmann incremental encoders with HIPERFACE®
- High-resolution Sick incremental encoders with HIPERFACE DSL® (single-cable variant)
- High-resolution Heidenhain incremental encoders with EnDat 2.2 (ENDAT22)
- Master frequency input/output and pulse direction interface

### › Suitable motors

- Permanent-magnet synchronous machines with sinusoidal EMF
- Torque motors
- Linear motors
  - Air-core and iron-core linear motors with a low motor inductance (0,1 ... 4 mH)
  - Automatic determination of the motor parameters

### › User-friendly parameterisation with the Metronix ServoCommander® software

- Adjustment of all of the parameters via a PC and online representation of operating parameters and diagnostic messages
- User-guided initial start-up, loading and saving of parameter sets as well as offline parameterisation are possible
- Oscilloscope function for optimising the drive and for analysing the PLC I/O coupling
- Supported languages: German, English
- Automatic motor identification and procedures for the automatic determination of the commutation position in the case of encoders without a commutation track
- Automatic adjustment of the control circuits for current, speed and position control

### › Integrated functional safety

- "Safe Torque Off (STO)" safety function integrated in the device
- SS1 functionality possible

### › Homing and positioning

- Integrated positioning control with a wide range of functions as per "CAN in Automation (CiA) DSP402" plus numerous additional application-specific functions.
- Jerk-free or time-optimal positioning, relative or absolute with regard to a reference point. Point-to-point positioning with and without smooth position transitions.
- High-speed sample inputs for triggering the storage of position marks
- Numerous homing methods
- Rotor and position triggers

### › Brake control and automatic brake

- Direct control of a motor holding brake with high current without using an external relay
- Adjustable brake delay times
- "Automatic brake" for deactivating the power section during longer breaks to save energy

### › Electrical characteristics BL 4100-M / BL 4100-D

- Wide-range supply input (AC)
- "Soft switch-on" features for the soft precharging and quick charging of the DC bus
- DC bus coupling between devices with the same mains power supply for buffering the brake energy
- Improved monitoring and analysis of the mains power supply by a direct measurement of the mains voltage

### › Electrical characteristics BL 4800-M / BL 4800-D

- Wide-range supply input (DC)
- Due to the robust design, no DC link precharging is required when connecting the battery
- DC bus coupling between devices with the same mains power supply for buffering the brake energy

### › Applications

- Speed- and angle-synchronous operation with an electronic gear unit via the incremental encoder input or fieldbus. Extensive modes of operation for synchronisation, e.g. "flying saw"
- Jog mode, teach-in mode, motion programs, torque-limited set control and much more

### › Special control features

- High control quality due to high-quality sensors, far superior to conventional market standards, and above-average processor resources
- Short cycle times, bandwidth in the current control circuit approx. 2 kHz (with  $t_i = 32 \mu s$ ), in the speed control circuit approx. 500 Hz (with  $t_n = 64 \mu s$ )
- Parameterisable band-stop filters for suppressing the natural frequency of the controlled system
- Load torque compensation for vertical axes
- Synchronisable internal clock system for the synchronisation with external clock sources for CANopen and EtherCAT fieldbus systems by way of an internal PLL

### › Certification and qualification

- Integration of numerous filters (e.g. filters for the 24 V supply, the inputs and outputs, etc.) within the device, so that only with the BL 4100-M / BL 4100-D an external mains filter has to be used to comply with the current CE and EN standards
- Enclosed on all sides, EMC-optimised housing for mounting on or near the motor
- Protection class IP54, depending on the mounting and the sealing up to IP67 can be achieved
- UL Recognized

# 4 Mounting

## ➤ Mounting BL 4000-D

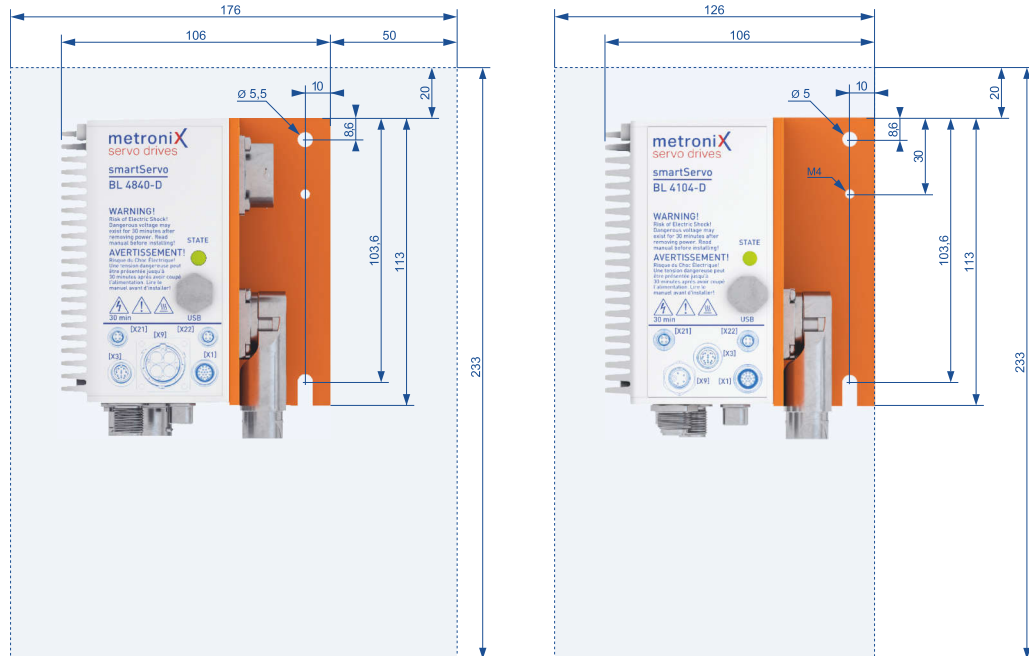


Figure 7: Dimensions and installation clearance for BL 4800-D (left) and BL 4100-D (right)

The following requirements must be fulfilled for the installation of the servo drive:

- Follow the general set-up and safety rules and regulations concerning the installation.
- Follow the safety instructions in section 2.6 *Safety notes for installation and maintenance* on page 12.
- Use only suitable tools. If specified, use special tools.
- Always use suitable personal protective equipment, see section 2.5 *Personal protective equipment* on page 12 section 2.5 *Personal protective equipment* on page 12.
- The servo drives of device family BL 4000-D are intended for decentralised mounting near the motor outside a control cabinet.
- Preferred installation position: Vertical with the circular connectors [X1], [X3], etc. facing downwards. Generally, other mounting positions are also possible.
- The servo drives of device family BL 4000-D have mounting holes at the top and bottom of the mounting bracket. The servo drive is fastened with these holes using two M5 screws. Recommended tightening torque for an M5 screw of property class 5.6: 2.8 Nm.
- Excessive heating may cause premature ageing and/or damage to the device. For sufficient heat dissipation, the minimum distances from other components shown in the illustration above must therefore be observed. If these distances cannot be complied with in special installation situations, please contact the Technical Support.

- As the Intercontec connector [X6]/[X2] can be turned, the motor/encoder cable can also be connected from the front or from above.

### › Mounting BL 4000-M

Servo drives of device family BL 4000-M are usually already mounted on the motor and do not have to be mounted separately. However, when mounting the motor/servo drive combination, always observe the following requirements and notes:

- Follow the general set-up and safety rules and regulations concerning the installation.
- Follow the safety instructions in section 2.6 *Safety notes for installation and maintenance* on page 12.
- Use only suitable tools. If specified, use special tools.
- Always use suitable personal protective equipment, see section 2.5 *Personal protective equipment* on page 12.
- The motor/servo drive combination can be mounted in any position. However, it must be ensured that the heat loss can be properly dissipated. Excessive heating can lead to premature ageing and/or damage to the device. Please contact the Technical Support if you have any questions about the installation situation.

## 5 Electrical installation

This chapter provides all of the relevant information for the electrical installation of a servo drive of the BL 4000-M / BL 4000-D series with an integrated "Safe Torque Off (STO)" safety function.

### 5.1 Notes concerning the safe and EMC-compliant installation

#### 5.1.1 Explanations and terminology

Electromagnetic compatibility (EMC) or electromagnetic interference (EMI) includes the following requirements:

- Sufficient **immunity** of an electrical installation or an electrical device against external electrical, magnetic or electromagnetic interferences via cables or the environment.
- Sufficiently small **unwanted emission** of electrical, magnetic or electromagnetic interference from an electrical installation or an electrical device to other devices in the vicinity via cables or the environment.

#### 5.1.2 General information about electromagnetic compatibility

The interference emission and interference immunity of a servo drive always depend on the overall drive concept consisting of the following components:

- Power supply
- Servo drive
- Motor
- Electromechanical system
- Configuration and type of wiring
- Superordinate control system

In order to increase interference immunity and to decrease interference emissions, the servo drive has numerous integrated filters so that BL 4800-M / BL 4800-D servo drives can be operated in most applications completely without additional shielding and filtering devices, and with BL 4100-M / BL 4100-D servo drives only an external mains filter needs to be used.

### 5.1.3 BL 4100-M / BL 4100-D: Proper wiring

The following must be observed for servo drives of type BL 4100-M / BL 4100-D to ensure a safe and EMC-compliant design of the drive system:

**⚠ DANGER ⚠ Dangerous electrical voltage!**

For safety reasons, all of the PE earth (ground) conductors must be connected prior to the initial operation of the system. The shields must be connected on both sides.

The EN 61800-5-1 regulations concerning protective earthing (grounding) must be complied with during the installation.

Motor and servo drive must be screwed firmly and with good conductivity to the machine or the control cabinet, which in turn must be well earthed. Moving system parts on which motors or servo controllers are installed must also be earthed with low impedance (e.g. by using copper tape).

- In order to keep the leakage currents and losses in the motor connecting cable as small as possible, the servo drive should be located as close to the motor as possible.
- The motor cable and angle encoder cable must be shielded.
- Connect the shield of the motor cable to the back panel of the control cabinet by way of suitable shield terminals. The unshielded cable end should not be longer than 80 mm.
- The mains-end PE connector must be connected to the PE connection point of the supply connector [X9].
- The earthing (grounding) screw of the mounting plate must also be connected to the mains-side PE connector via a separate earth lead:  
BL 4100-D: See section 3.3 *Device view BL 4000-D* on page 19.
- The cross-section of each earth lead must not be smaller than the cross-section of the supply leads (L/N or L1-L3).
- The inner PE conductor of the motor cable must be connected to the PE connection point of the motor connector [X6].
- The signal lines must be as far away from the power cables as possible. They should not be laid in parallel. If intersections cannot be avoided, they should be installed at right angles if possible.
- Unshielded signal and control lines should not be used. If their use is inevitable, they should at least be twisted.
- All connectors must be correctly locked or screwed with the tightening torque specified by the manufacturer. For circular connectors we recommend the use of suitable special tools (e.g. TSD 02 SAC/TSD 04 SAC with matching plug attachments).

In general, the following applies:

- Connect the inner shields to the associated pins of the connectors.
- Connect the overall shield on the motor side to the connector or motor housing over a large contact area.

## 5.1.4 ESD protection

**NOTICE** Damage to property due to ESD (electrostatic discharge)

At unassigned plug connectors, damage can occur to the device or to other system parts as a result of ESD (electrostatic discharge). To prevent this type of damage, comply with the following:

- Ensure proper earthing of all of the system components and wire the servo drive completely prior to switching on the voltage supply.
- The person commissioning the system as well as the service and maintenance personnel must have undergone ESD training and wear corresponding footwear.
- When handling the system, e.g. the USB connector, it is useful to touch the control cabinet housing (should be at PE potential) with your hand prior to touching one of the connectors of the servo drive.

## 5.2 Additional requirements for the UL approval

### › Mains power supply protection

Integral solid state short circuit protection does not provide branch circuit protection. Branch circuit protection must be provided in accordance with the Manufacturer Instructions, National Electrical Code and any additional local codes.

- BL 4000-M / BL 4000-D:  
For Use On A Circuit Capable Of Delivering Not More Than 5000rms Symmetrical Amperes, 240V maximum and When Protected by Circuit Breaker S201UP K16 manufactured by ABB, rated 277V/16A.
- BL 4800-M / BL 4800-D:  
For use in Protective Class III circuits in which dc supply source meets following criteria:
  - DC source shall provide galvanic separation from mains voltage
  - DC source voltage shall not exceed 48Vdc and be capable of delivering not more than 1000Adc of prospective current and
  - When products are protected by fuses or circuit breakers:  
Fuse: BF1 142.5631.5702, Littelfuse  
Circuit breaker: Listed S201UDC K20, ABB

### › Wiring requirements and environmental conditions

- For use in Pollution Degree 2 Environment only.
- BL 4000-M: Suitability of the controller when installed onto other motor series [than those tested] shall be determined in end-use by subjecting the combination to temperature rise test.

### › Motor overload protection

For effective motor protection, the motor parameters and the I<sup>2</sup>t-Integral must be parameterised appropriately (see section *Configuration of the motor data* in the Product manual smartServo BL 4000-D and BL 4000-M).

## 5.3 Connector BL 4100-M / BL 4100-D: Power supply [X9]

Servo drives of the BL 4100-M / BL 4100-D series must be connected to the power supply in accordance with the following illustration:

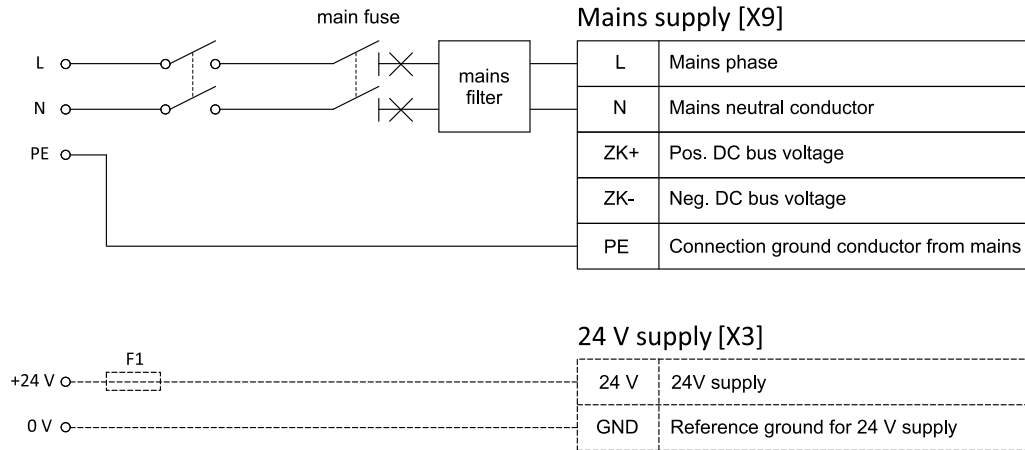


Figure 8: Connecting a BL 4100-M / BL 4100-D to the supply voltage

### **NOTICE** Risk of damage to the servo drive

The servo drive will be damaged in the following cases:

- reverse connection of the 24 V operating voltage connections,
- excessive operating voltage, or
- accidental interchanging of the operating voltage and motor connectors.

A 24 V supply and a single-phase mains power supply are required to operate a BL 4100-M / BL 4100-D. Mains voltage is supplied via [X9], whereas the 24 V supply is provided via [X3] (See section 5.5 *Connector: 24 V supply and STO [X3]* on page 35).

A single-phase automatic circuit breaker and a mains filter must be installed in the mains power supply line (see *Cable type and configuration [X9]* on page 31). In addition, you can protect the servo drive with an AC/DC-sensitive residual-current device (RCD) with 300 mA minimum.

Direct DC coupling of the DC buses of several devices with equal DC bus voltage is possible by way of the terminals ZK+ and ZK- (see section *DC bus coupling* in the product manual BL 4000-M / BL 4000-D).

The servo drive has an internal brake chopper and an internal braking resistor. For greater braking power, an external braking module or capacitor storage can be connected in parallel to the DC link. In such cases, please contact the Technical Support.

The servo drive must be connected to earth (ground) with its PE connector (Be sure to see section 5.1.3 *BL 4100-M / BL 4100-D: Proper wiring* on page 27).

First, wire the servo drive completely. Then, switch on the 24 V supply and the mains power supply.

### › Configuration on the device [X9]

Phoenix Contact SACC-CI-M12MSK-4PE-L180 THR T (M12, 5-pin K-coded)

### › Mating connector [X9]

3m Power cable, shielded: SAC-5P- 3,0-PUR/M12FSK PE SH - 1414789

Single plug: SACC-M12FSK-4PECT-CL SH

#### **INFORMATION** Self-assembly connectors

The connectors for self-assembly have a larger outer radius than pre-assembled connectors. For space reasons, a self-assembly connector can therefore only be used for [X9] or [X3]. The other plug must be pre-assembled.

### › Pin assignment [X9]

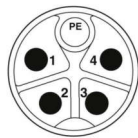


Figure 9: Connector "Power supply [X9]", pin side view

| Pin | Name | Specification                                                                   |
|-----|------|---------------------------------------------------------------------------------|
| 1   | L    | Phase conductor/mains phase                                                     |
| 2   | N    | Neutral conductor                                                               |
| 3   | ZK+  | Pos. DC bus voltage                                                             |
| 4   | ZK-  | Neg. DC bus voltage                                                             |
| PE  | PE   | Connection of the protective earth (ground) conductor of the mains power supply |

### › Cable type and configuration [X9]

We recommend using the pre-assembled cables from Phoenix Contact listed above. If other cables are used, the minimum cross-sections listed in the following table must be observed in any case. The power supply cable must be shielded up to the mains filter. A single-phase circuit breaker with the listed characteristics ("Circuit breaker") must be used in the mains supply line.

| Specification (L, N, PE)                    | Circuit Breaker |
|---------------------------------------------|-----------------|
| 5 x 1,0 mm <sup>2</sup> , shielded (AWG 18) | K 16            |

#### **⚠ DANGER** ⚠ Dangerous electrical voltage!

When using pre-assembled cables, always connect all available wires. For example, life-threatening DC link voltage is present on the wires at connection 3/4.

➤ **Mains filter**

To comply with the EMC standard, an external mains filter is required between the circuit breaker and the controller:

Mains filter Würth 810912010 or comparable.

In larger systems with many controllers of the same family, the use of a suitable common mains filter may make more sense. In this case, contact the technical support.

## 5.4 Connector BL 4800-M / BL 4800-D: Power supply [X9]

Servo drives of the BL 4800-M / BL 4800-D series must be connected to the power supply in accordance with the following illustration:

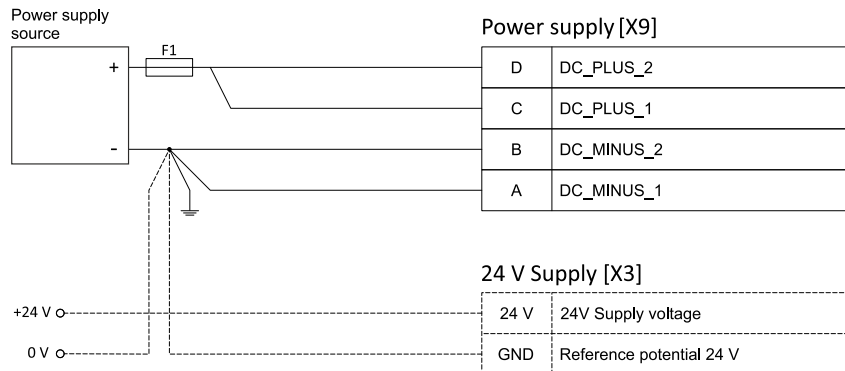


Figure 10: Connecting a BL 4800-M / BL 4800-D to the supply voltage

### **NOTICE** Risk of damage to the servo drive

The servo drive will be damaged in the following cases:

- reverse connection of the 24 V operating voltage connections,
- excessive operating voltage, or
- accidental interchanging of the operating voltage and motor connectors.

### **NOTICE** Risk of destruction due to a connection with reverse polarity

If the polarity of the 24 V supply at [X3] is reversed, the servo drive and the PC will be destroyed. It is essential that you follow the correct connection instructions.

A 24 V supply and a 48 V power supply are required to operate a BL 4800-M / BL 4800-D. The 48 V is supplied via [X9], whereas the 24 V supply is provided via [X3]. (See section 5.5 Connector : 24 V supply and STO [X3] on page 35). A melting fuse or an automatic circuit breaker must be used in the 48 V power supply (see *Cable type and configuration [X9]* on page 34). The GND potentials of the 24 V and the 48 V supply must be connected to each other at a common point to reduce potential shifts. This common point must be earthed.

It is possible to couple the DC links of several devices of the BL 4800-M / BL 4800-D device family by connecting them to a common voltage source. Even in this case, all GND lines should be connected at a common point.

### **NOTICE** BL 4800-M / BL 4800-D: Danger of destroying the power supply unit

During braking, a high voltage can be present at [X9], which can destroy the power supply unit. To prevent this, the switch-off threshold in case of overvoltage must be suitably parameterised (see section *Power supply via main power unit* in the Product manual smartServo BL 4000-D and BL 4000-M).

First, wire the servo drive completely. Then, switch on the 24 V supply and the mains power supply.

### › Configuration on the device [X9]

Amphenol RT00164PNH03

Inserts: male, SC000518S

### › Mating connector [X9]

Amphenol RT06164SNH Gasket

Amphenol RT0L-16CG-S1 Backshell straight

Amphenol RT0B-16CG-S1 Backshell angled

Inserts: female, SC000519S

### › Pin assignment [X9]

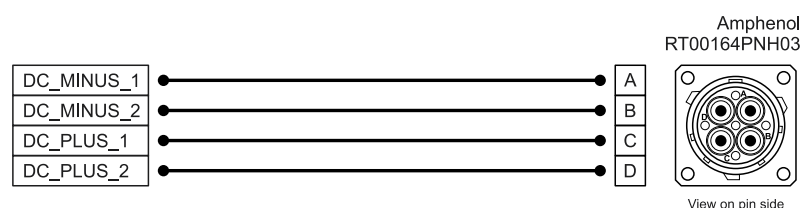


Figure 11: Connector "Power supply [X9]", pin side view

| Pin | Name       | Specification                         |
|-----|------------|---------------------------------------|
| A   | DC_MINUS_1 | Reference potential 48 V power supply |
| B   | DC_MINUS_2 | Reference potential 48 V power supply |
| C   | DC_PLUS_1  | 48 V power supply                     |
| D   | DC_PLUS_2  | 48 V power supply                     |

### › Cable type and configuration [X9]

The cable names that are stated refer to cables made by Letronic and Kaltenbach. They have proved to be reliable and are successfully used in many applications. However, it is also possible to use comparable cables from other manufacturers. A melting fuse or an automatic circuit breaker must be used in the supply line to protect the cable and the device.

For fixed installation: ÖLFLEX SERVO 719 CY 4G4

For flexible use: ÖLFLEX SERVO FD 796CP 4G4

Single stranded wires:

Letronic UL 3289 4 mm<sup>2</sup> rt. 56x0,30 or

Kaltenbach RADOX® – Stranded wire UL 3289/CSA CL 1503 AWG8

| Specification           | Fuse/Circuit breaker                                                                               |
|-------------------------|----------------------------------------------------------------------------------------------------|
| 4 x 4,0 mm <sup>2</sup> | Littelfuse BF1 142.5631.5402 or similar<br>or<br>Circuit breaker<br>20A, K-Type, 60 VDC, SCCR 14kA |

## 5.5 Connector : 24 V supply and STO [X3]

### **NOTICE** Risk of damage to the servo drive

The servo drive will be damaged in the following cases:

- reverse connection of the 24 V operating voltage connections,
- excessive operating voltage, or
- accidental interchanging of the operating voltage and motor connectors.

### **NOTICE** Risk of destruction due to a connection with reverse polarity

If the polarity of the 24 V supply at [X3] is reversed, the servo drive and the PC will be destroyed. It is essential that you follow the correct connection instructions.

### **⚠ DANGER** ⚠ Dangerous electrical voltage!

Use only PELV circuits for the STO wiring and the 24V supply!

Make sure that no jumpers or the like can be inserted parallel to the safety wiring. For example, use the maximum wire cross-section of 1.5 mm<sup>2</sup> or suitable wire end sleeves with insulating collars for the connection to the associated connector.

### › Configuration on the device [X3]

Phoenix Contact SACC-CIP-M12MS-8P SMD SH T - 1411959 (M12, 8-pin, A-coded)

### › Mating connector

Phoenix Contact:

1,5 m Cable (PVC): SAC-8P- 1,5-PUR/M12FS SH - 1522862

2,0 m Cable (PUR): SAC-8P- 2,0-542/ FS SH SCO BK - 1406083

Single plug: SACC-FS-8QO-0,5 SH SCO - 1414611

### **INFORMATION** Self-assembly connectors

The connectors for self-assembly have a larger outer radius than pre-assembled connectors. For space reasons, a self-assembly connector can therefore only be used for [X9] or [X3]. The other plug must be pre-assembled.

### › Pin assignment [X3]

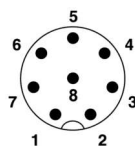


Figure 12: Connector 24 V supply and STO [X3], view on pin side

| Pin | Name | Specification                        |
|-----|------|--------------------------------------|
| 1   | STOA | Control input A for the STO function |
| 2   | GNDA | Reference potential for STOA         |
| 3   | STOB | Control input B for the STO function |
| 4   | GNDB | Reference potential for STOB         |
| 5   | DIN6 | Digital input 6 (limit switch 0)     |
| 6   | DIN7 | Digital input 7 (limit switch 1)     |
| 7   | 24 V | 24 V supply                          |
| 8   | GND  | Reference potential for 24 V supply  |

For wiring the 24 V supply, be sure to also observe the instructions in section 5.3  
*Connector BL 4100-M / BL 4100-D: Power supply [X9]* on page 30 or in section 5.4  
*Connector BL 4800-M / BL 4800-D: Power supply [X9]* on page 33.

To ensure the STO ("Safe Torque Off") function, the control inputs STOA and STOB must be connected in a dual-channel manner with parallel wiring. See section *Safe torque off (STO)* in the Product manual smartServo BL 4000-D and BL 4000-M. This type of connection can be part of an emergency stop circuit or safety door setup, for example.

### › Cable type and configuration [X3]

| Characteristic                                                                                   | Value                                        |
|--------------------------------------------------------------------------------------------------|----------------------------------------------|
| Max. cable length, unshielded                                                                    | 30 m                                         |
| Max. cable length, shielded                                                                      | > 30 m                                       |
| Cable cross-section (flexible conductors, wire end sleeve with insulating collar), one conductor | 0.25 mm <sup>2</sup> ... 0.5 mm <sup>2</sup> |

### › Minimum wiring for commissioning [X3]

#### **⚠ DANGER** Danger to life due to bypassed safety functions

Safety functions must never be bypassed.

For the commissioning of the system without any safety systems, STOA and STOB can be connected to the 24 V supply and GNDA and GNDB can be connected to GND in a fixed manner.

Perform the minimum wiring of the inputs STOA/STOB and GNDA/GNDB for the commissioning process in such a way that it must be removed when the final safety wiring is performed.

## 5.6 Connector BL 4100-M: motor [X6], [X6B]

On BL 4100-M type devices, the motor is connected via a PCB connector ([X6], see the following figure, label A), before the servo drive is mounted on the motor. The motor is connected to the terminals U,V,W. A possibly existing motor holding brake can be connected via a PCB terminal with push-in technology [X6B] (Label B). An analogue motor temperature sensor is connected via the encoder interface at [X2] (Label C). This is described in section 5.11 *Connector BL 4000-M: resolvers and encoder [X2]* on page 53.

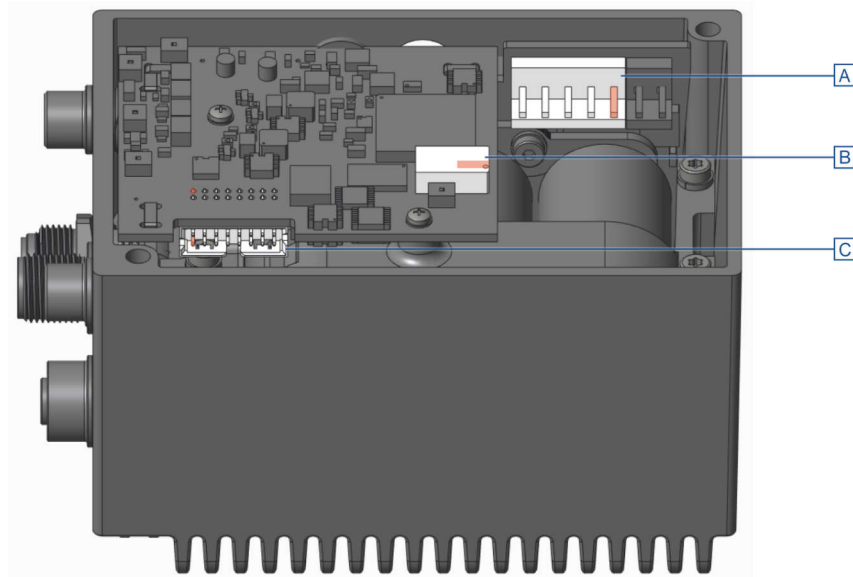


Figure 13: Connector arrangement: motor [X6], holding brake [X6B] and angle encoder [X2]

### › Configuration on the device [X6], [X6B]

X6: B5P-VH-B LF (Manufacturer: JST)

X6B: Push-in PCB terminal 2060-452/998-404 (Manufacturer: Wago)

### › Mating connector [X6]

X6: VHR-5N with 4 Contacts SVH-41T-P1.1 (Manufacturer: JST)

## > Pin assignment

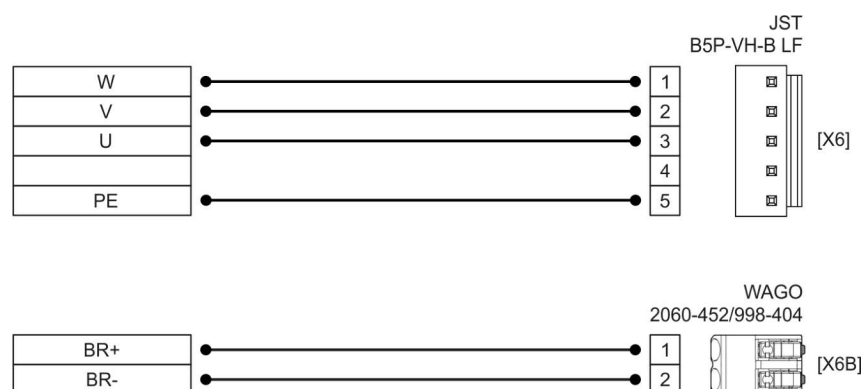


Figure 14: Pin assignment: motor connector (motor with holding brake) [X6], [X6B]

| Pin X6 | Name | Specification                           |
|--------|------|-----------------------------------------|
| 1      | W    | Motor phase W                           |
| 2      | V    | Motor phase V                           |
| 3      | U    | Motor phase U                           |
| 4      |      |                                         |
| 5      | PE   | Protective earth conductor of the motor |

| Pin X6B | Name | Specification   |
|---------|------|-----------------|
| 1       | BR+  | Holding brake + |
| 2       | BR-  | Holding brake - |

### **▲ WARNING** Risk of injury

The brake output of the servo drive (BR+, BR-) must not be used as the sole stop element in safety-oriented applications.

## > Cable type and configuration [X6]

The cable names that are stated refer to cables made by Lapp and Helukabel. However, it is also possible to use comparable cables from other manufacturers, for example Lütze.

U, V, W and PE: LAPP KABEL MULTI-STANDARD SC 1 (UL), 0,75 mm<sup>2</sup>, 300V, 105 °C

BR+, BR-: HELUTHERM 145 (UL), AWG 24, 0,2 mm<sup>2</sup>, 300V, 120 °C,

### **INFORMATION** Comply with the required minimum cross-section

Always observe the minimum cross-sections for the lines U, V, W and PE.

### › Connection notes [X6]

Assemble the connector [X6] according to the manufacturer's specifications. To maintain the necessary safety distance, pin 4 must not be equipped with a crimp contact.

An existing holding brake in the motor is connected to the terminals BR+ and BR- of [X6B]. The cables must be fitted with suitable wire ferrules on the plug side.

When connecting the holding brake, be sure to observe the maximum output current provided by the servo drive.

## 5.7 Connector BL 4100-D: motor [X6]

On BL 4100-D type devices, the motor is connected via a Intercontec connector. The motor is connected to the terminals U,V,W. An analogue motor temperature sensor can be connected to the terminals MT+ and MT- if it is routed together with the motor phases in one cable. Alternatively, it can be connected via the encoder cable to [X2] (section 5.10 *Connector BL 4000-D: resolvers and encoder [X2]* on page 48). A holding brake of the motor can be connected to terminals BR+ and BR-. If a motor with a HIPERFACE DSL<sup>®</sup> encoder is used, this encoder is also connected via [X6].

### › Configuration on the device [X6]

Intercontec 615/915 ytec Double-Receptacles angled rotatable  
EEDA107NN0000002000 with Inserts 60.251.11 and 60.252.11

### › Mating connector [X6]

Intercontec 615/915 ytec Double-Receptacles angled rotatable  
ESTA201MR01320500000 with Inserts 61.231.11 and 61.232.11

### › Pin assignment: motor with a motor temperature sensor

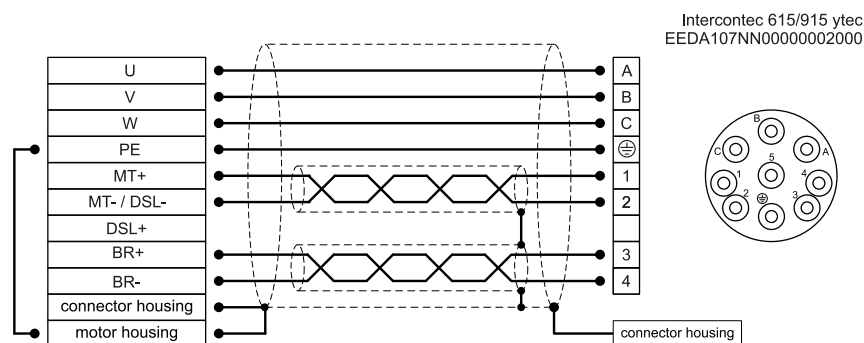


Figure 15: Pin assignment „motor with a motor temperature sensor [X6]“

| Pin | Name      | Specification                           |
|-----|-----------|-----------------------------------------|
| A   | U         | Motor phase U                           |
| B   | V         | Motor phase V                           |
| C   | W         | Motor phase W                           |
| PE  | PE        | Protective earth conductor of the motor |
| 1   | MT+       | Motor temperature sensor +              |
| 2   | MT-/ DSL- | Motor temperature sensor -              |
| 3   | BR+       | Holding brake +                         |
| 4   | BR-       | Holding brake -                         |
| 5   | DSL+      |                                         |

### ➤ Pin assignment: motor connector (HIPERFACE DSL®)

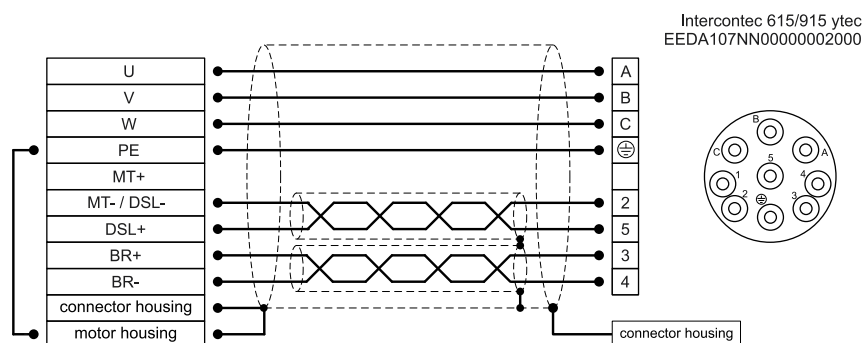


Figure 16: Pin assignment: „motor connector (HIPERFACE DSL®) [X6]“

| Pin | Name     | Specification                           |
|-----|----------|-----------------------------------------|
| A   | U        | Motor phase U                           |
| B   | V        | Motor phase V                           |
| C   | W        | Motor phase W                           |
| PE  | PE       | Protective earth conductor of the motor |
| 1   | MT+      |                                         |
| 2   | MT-/DSL- | HIPERFACE DSL -                         |
| 3   | BR+      | Holding brake +                         |
| 4   | BR-      | Holding brake -                         |
| 5   | DSL+     | HIPERFACE DSL +                         |

### ➤ Cable type and configuration [X6]

The cable names that are stated refer to cables made by Lapp. However, it is also possible to use comparable cables from other manufacturers, for example Lütze or Helukabel.

For fixed installation: LAPP KABEL ÖLFLEX SERVO 719 CY

For highly flexible use (drag chains): LAPP KABEL ÖLFLEX SERVO FD 796 CP

| Device type | Cable type               | Specification (U, V, W, PE)      |
|-------------|--------------------------|----------------------------------|
| BL 4104-D   | 4 G 1,0 + 2 x (2 x 0,75) | 4 x 1,0 mm <sup>2</sup> (AWG 18) |

#### **INFORMATION** Comply with the required minimum cross-section

Always observe the minimum cross-sections for the lines U, V, W and PE according to the above table. Comply also with the maximum permissible cable capacity as per section 6.5 *BL 4100-M / BL 4100-D: Motor connector [X6]* on page 72.

**> Connection notes [X6]**

Connect the inner and outer cable shield to the connector housing according to the connector manufacturer's specifications.

An existing holding brake in the motor is connected to the terminals BR+ and BR-. When connecting the holding brake, be sure to observe the maximum output current provided by the servo drive.

**⚠ DANGER ⚠ Dangerous electrical voltage!**

The signals for the temperature sensor "MT-" and "MT+" at the motor connector [X6] must be connected to protective extra-low voltage (PELV) on the motor side and they must be insulated against the motor phases.

**⚠ WARNING Risk of injury**

The brake output of the servo drive (BR+, BR-) must not be used as the sole stop element in safety-oriented applications.

**NOTICE Risk of destruction due to the mix-up of connectors**

The servo drive may be irreparably damaged if the connectors for the motor [X6] and supply [X9] are mixed up.

## 5.8 Connector BL 4800-M: motor [X6]

On BL 4800-M type devices, the motor is connected via threaded terminals on the power unit PCB ([X6], see the following Figure, Label C), before the servo drive is mounted on the motor. A possibly existing motor holding brake can be connected via a PCB terminal with push-in technology [X6B] (Label A). An analogue motor temperature sensor is connected via the encoder interface at [X2] (Label B). This is described in section 5.11 *Connector BL 4000-M: resolvers and encoder [X2]* on page 53.

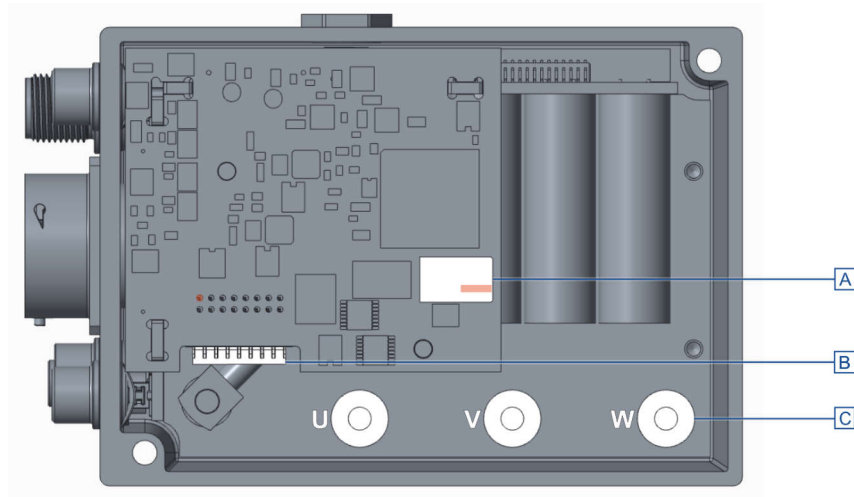


Figure 17: Threaded terminals motor [X6], holding brake plug [X6B] and angle encoder plug [X2]

### › Configuration on the device [X6]

Threaded terminals M4

### › Mating connector [X6]

Cable lug standard, e.g. Weitkowitz 13015, M4, 4mm<sup>2</sup>  
 Angled cable lug 90°, e.g. Weitkowitz 13115, M4, 4mm<sup>2</sup>  
 Screw hexagon socket  
 M4x10mm Tension washer (DIN 6796)

### › Pin assignment: motor with holding brake

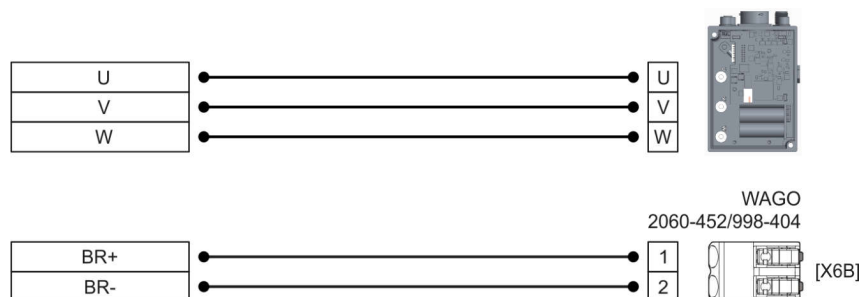


Figure 18: Pin assignment „motor with holding brake [X6], [X6B]“

| Pin X6  | Name | Specification   |
|---------|------|-----------------|
| U       | U    | Motor phase U   |
| V       | V    | Motor phase V   |
| W       | W    | Motor phase W   |
| Pin X6B | Name | Specification   |
| 1       | BR+  | Holding brake + |
| 2       | BR-  | Holding brake - |

**⚠ WARNING Risk of injury**

The brake output of the servo drive (BR+, BR-) must not be used as the sole stop element in safety-oriented applications.

➤ **Cable type and configuration [X6]**

The cable names that are stated refer to cables made by Letronic and Helukabel. However, it is also possible to use comparable cables from other manufacturers, for example Lütze.

U, V, W und PE: Letronic UL 3289, 4 mm<sup>2</sup>, 56 x 0,30 vz., 600V, 150°C

BR+, BR-: HELUTHERM 145 (UL), AWG 24, 0,2 mm<sup>2</sup>, 300V, 120 °C

**INFORMATION Comply with the required minimum cross-section**

Always observe the minimum cross-sections for the lines U, V and W.

➤ **Connection notes [X6]**

Connect the motor phases U, V, W to the threaded terminals with standard or angled cable lugs. For optimum conductivity, the cable lug must rest directly on the screw terminal and be screwed tight with an M4x10 screw with a tightening torque of 2 Nm. A suitable clamping washer must be used to secure against vibration.

Since there is very little space available in the enclosure, it is essential to ensure

- that the cable lugs cannot touch the housing or the adjacent cable lug under any circumstances. In addition, the cable lug must be insulated with heat shrink tubing.
- that the specified bending radii of the cable used are observed.

## 5.9 Connector BL 4800-D: motor [X6], [X6A]

On BL 4800-D type devices, the motor is connected via an Amphenol connector [X6A]. The motor is connected to the terminals U, V, W. An analogue motor temperature sensor can be connected to the terminals MT+ and MT- if it is routed together with the motor phases in one cable. Alternatively, it can be connected via the encoder cable to [X2] (section 5.10 *Connector BL 4000-D: resolvers and encoder [X2]* on page 48). A holding brake of the motor can be connected to terminals BR+ and BR-. If a motor with a HIPERFACE DSL<sup>®</sup> encoder is used, this encoder is also connected via [X6].

### › Configuration on the device [X6], [X6A]

X6: Intercontec 615/915 ytec Double-Receptacles angled rotatable  
EEDA107NN0000002000 with Inserts 60.252.11

X6A: Amphenol RT00164SNH03

X6A: Inserts: female, SC000519S

### › Mating connector [X6], [X6A]

X6: Intercontec 615/915 ytec Stecker  
ESTA201MR01320500000 with 4x Inserts 61.232.11

X6A: Amphenol RT06164PNH Gasket

X6A: Amphenol RT0L-16CG-S1 Backshell straight

X6A: Amphenol RT0B-16CG-S1 Backshell angled

X6A: Inserts: male, SC000518S

### › Pin assignment: motor with a motor temperature sensor

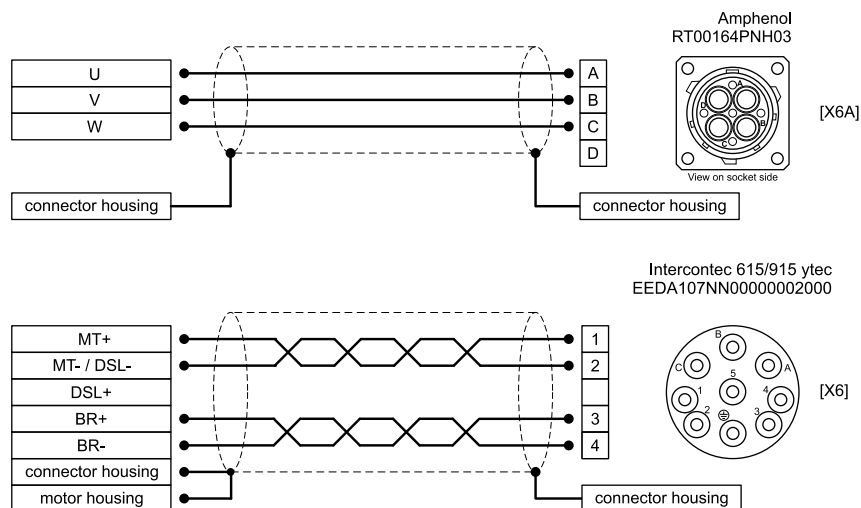


Figure 19: Pin assignment „motor with a motor temperature sensor [X6], [X6A]“

| Pin X6A | Name | Specification |
|---------|------|---------------|
| 1       | U    | Motor phase U |
| 2       | V    | Motor phase V |
| 3       | W    | Motor phase W |

| Pin X6 | Name      | Specification              |
|--------|-----------|----------------------------|
| 1      | MT+       | Motor temperature sensor + |
| 2      | MT-/ DSL- | Motor temperature sensor - |
| 3      | BR+       | Holding brake +            |
| 4      | BR-       | Holding brake -            |
| 5      | DSL+      |                            |

### > Pin assignment: motor connector (HIPERFACE DSL®)

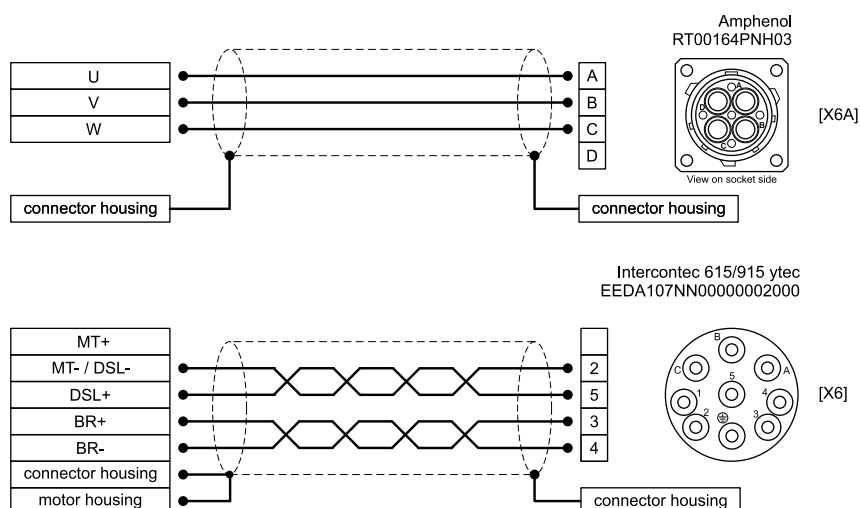


Figure 20: Pin assignment: „motor connector (HIPERFACE DSL®) [X6], [X6A]“

| Pin X6A | Name | Specification |
|---------|------|---------------|
| 1       | U    | Motor phase U |
| 2       | V    | Motor phase V |
| 3       | W    | Motor phase W |

| Pin X6 | Name      | Specification   |
|--------|-----------|-----------------|
| 1      | MT+       |                 |
| 2      | MT-/ DSL- | HIPERFACE DSL - |
| 3      | BR+       | Holding brake + |
| 4      | BR-       | Holding brake - |
| 5      | DSL+      | HIPERFACE DSL + |

### > Cable type and configuration [X6] und [X6A]

The cable names that are stated refer to cables made by Lapp. However, it is also possible to use comparable cables from other manufacturers, for example Lütze or Helukabel.

X6: LAPP UNITRONIC LiYCY (TP) 2x2x0,75

X6A: ÖLFLEX CLASSIC 135 CH 3G4

| Connector | Cable type                        |
|-----------|-----------------------------------|
| X6        | (2 x (2 x 0,75 mm <sup>2</sup> )) |
| X6A       | (3 x 4 mm <sup>2</sup> )          |

**INFORMATION** Comply with the required minimum cross-section

Always observe the minimum cross-sections for the lines U, V and W.

**> Connection notes [X6]**

Connect the outer cable shield to the connector housing according to the connector manufacturer's specifications.

An existing holding brake in the motor must be connected to the terminals BR+ and BR-. Please note the maximum output current that is provided by the servo drive.

**⚠ WARNING Risk of injury**

The brake output of the servo drive (BR+, BR-) must not be used as the sole stop element in safety-oriented applications.

**NOTICE Risk of destruction due to the mix-up of connectors**

The servo drive may be irreparably damaged if the connectors for the motor [X6] and supply [X9] are mixed up.

## 5.10 Connector BL 4000-D: resolvers and encoder [X2]

Different types of encoders can be connected to the 15-pin Intercontec connector (see also section 6.7 *Resolver and encoder connector [X2]* on page 77):

- Resolvers
- Analogue Hall generators with tracks that are offset by 90° (sine/cosine)
- Analogue incremental encoders (1 V<sub>ss</sub>)
- Incremental encoders with a serial interface (RS485 level, e.g. EnDat, HIPERFACE®, BISS)
- Digital incremental encoders (RS422, HALL sensors)

It is also possible to evaluate an optional error signal (AS/NAS). With some incremental encoders, it is possible to detect and signal soiling or other faults/malfunctions of the measuring system via an output (AS or NAS). The error signal can be evaluated by digital as well as analogue incremental encoders. In the case of analogue incremental encoders, the evaluation is only possible if no commutation track (Z1) is parameterised and connected. The evaluation of the error signal can be inverted.

With all encoders except resolvers and analogue Hall encoders, the supply voltage of the angle encoder can be set. This must be set correctly before connecting the encoder.

### **NOTICE** Damage to property caused by an incorrect power supply

If an incorrect power supply is used, the encoder may be destroyed. Ensure that the correct voltage is activated prior to connecting the encoder to [X2]. To do so, start the Metronix ServoCommander® parameterisation software and select the [Parameters/Device parameters/Angle encoder settings](#).

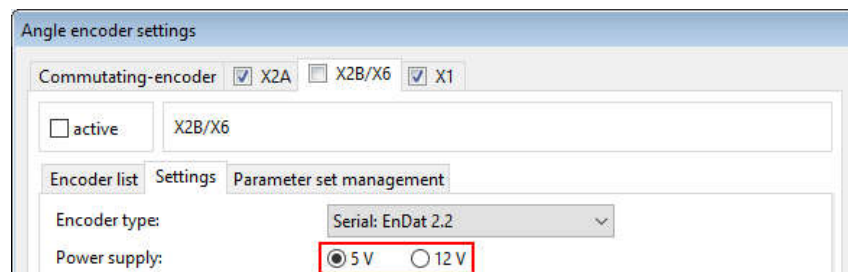


Figure 21: Angle encoder settings: Parameterisation of supply voltage

### › Configuration on the device [X2]

Intercontec Double-Receptacles angled rotatable EEDA107NN00000002000,  
15 pin female inserts

### › Mating connector [X2]

ESTA204MR03330003000, 7x Pin 61.232.11, 1x Pin 61.231.11 (Contact A)

### › Pin assignment: resolvers

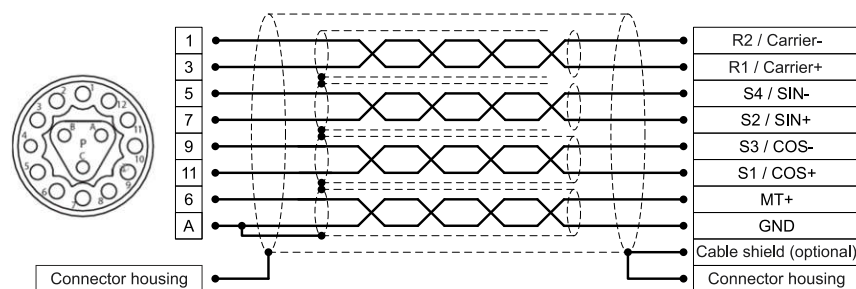


Figure 22: Pin assignment „resolvers [X2]“

| Pin | Name    | Specification                                                      |
|-----|---------|--------------------------------------------------------------------|
| 1   | R2      | Carrier signal for the resolver                                    |
| 3   | R1      |                                                                    |
| 5   | S4/SIN- | SINE track signal, differential<br>Analogue Hall sensor (SINE)     |
| 7   | S2/SIN+ |                                                                    |
| 9   | S3/COS- | COSINE track signal, differential<br>Analogue Hall sensor (COSINE) |
| 11  | S1/COS+ |                                                                    |
| 6   | MT+     | Motor temperature sensor, normally closed contact, PTC, NTC, KTY   |
| A   | GND     | Temperature sensor reference potential                             |

### > Pin assignment: analogue incremental encoders

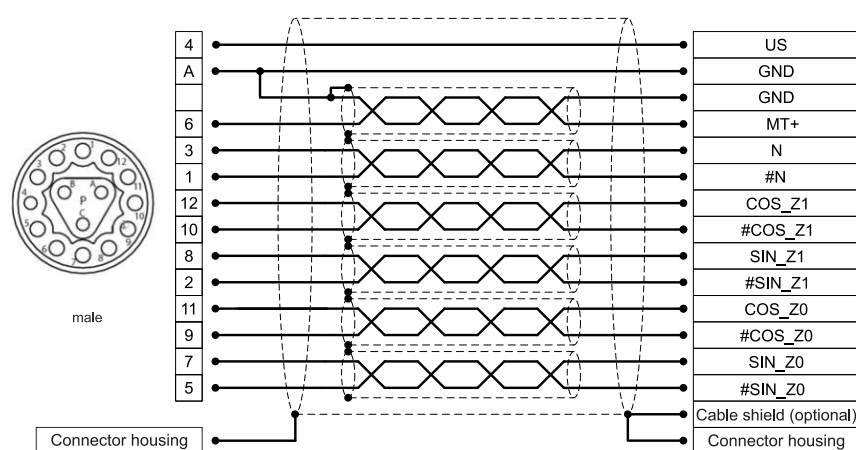


Figure 23: Pin assignment: „analogue incremental encoders [X2]“

| Pin | Name                    | Specification                                                                       |
|-----|-------------------------|-------------------------------------------------------------------------------------|
| 4   | US                      | Operating voltage for incremental encoders                                          |
| A   | GND                     | Associated reference potential                                                      |
| 6   | MT+                     | Motor temperature sensor, normally closed contact, PTC, NTC, KTY                    |
| 3   | N                       | Index pulse track signal (differential) of the high-resolution incremental encoder  |
| 1   | #N                      |                                                                                     |
| 12  | COS_Z1 / D+             | COSINE commutation signal (differential) of the high-resolution incremental encoder |
| 10  | #COS_Z1 / D-            |                                                                                     |
| 8   | SIN_Z1 / C+             | SINE commutation signal (differential) of the high-resolution incremental encoder   |
| 2   | #SIN_Z1 / C- / AS / NAS |                                                                                     |
| 11  | COS_Z0 / B+             | COSINE track signal (differential) of the high-resolution incremental encoder       |
| 9   | #COS_Z0 / B-            |                                                                                     |
| 7   | SIN_Z0 / A+             | SINE track signal (differential) of the high-resolution incremental encoder         |
| 5   | #SIN_Z0 / A-            |                                                                                     |

### > Pin assignment: incremental encoder with a serial interface

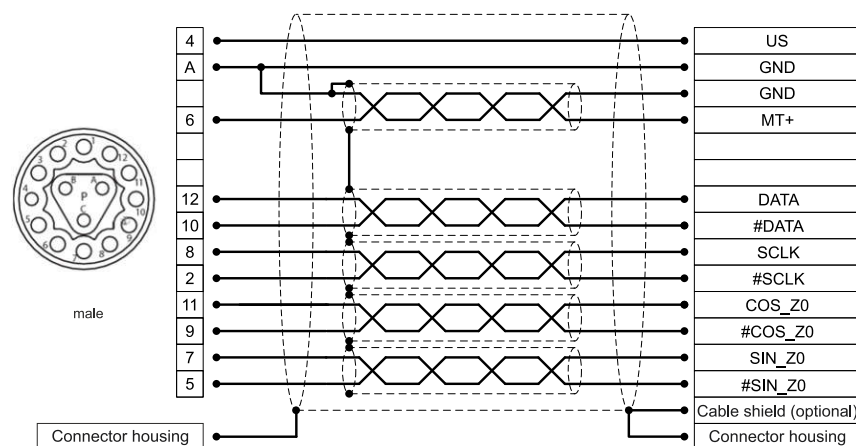


Figure 24: Pin assignment: „incremental encoder with a serial interface [X2]“

| Pin | Name         | Specification                                                                 |
|-----|--------------|-------------------------------------------------------------------------------|
| 4   | US           | Operating voltage                                                             |
| A   | GND          | Associated reference potential                                                |
| 6   | MT+          | Motor temperature sensor, normally closed contact, PTC, NTC, KTY              |
| 12  | DATA / SL+   | Bidirectional RS485 data line (differential) (EnDat/HIPERFACE®, BiSS)         |
| 10  | #DATA / SL-  |                                                                               |
| 8   | SCLK / MA+   | Clock pulse output RS485 (differential) (EnDat, BiSS)                         |
| 2   | #SCLK / MA-  |                                                                               |
| 11  | COS_Z0 / B+  | COSINE track signal (differential) of the high-resolution incremental encoder |
| 9   | #COS_Z0 / B- |                                                                               |
| 7   | SIN_Z0 / A+  | SINE track signal (differential) of the high-resolution incremental encoder   |
| 5   | #SIN_Z0 / A- |                                                                               |

### > Pin assignment: digital incremental encoder (RS422)

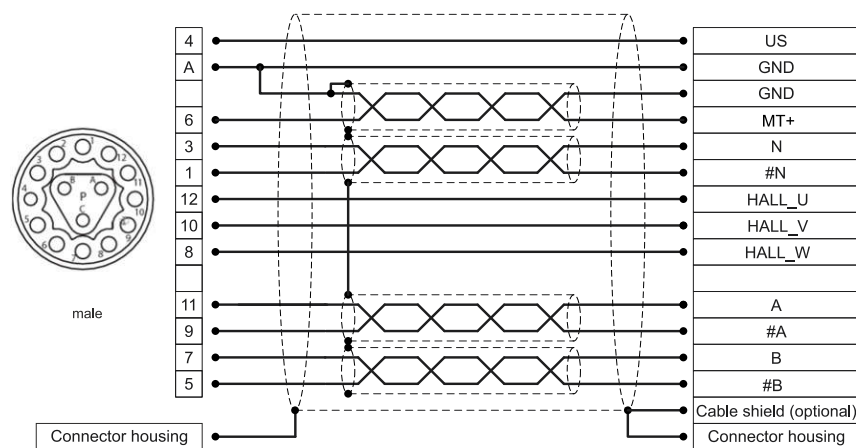


Figure 25: Pin assignment: „digital incremental encoder (RS422) [X2]“

| Pin | Name                     | Specification                                                          |
|-----|--------------------------|------------------------------------------------------------------------|
| 4   | US                       | Operating voltage for incremental encoders                             |
| A   | GND                      | Associated reference potential                                         |
| 6   | MT+                      | Motor temperature sensor, normally closed contact, PTC, NTC, KTY       |
| 3   | N / $U_{a0}$             | Index pulse RS422 (differential) of the digital incremental encoder    |
| 1   | #N / $\overline{U}_{a0}$ |                                                                        |
| 12  | HALL_U                   | Phase U of the Hall sensor for commutation                             |
| 10  | HALL_V                   | Phase V of the Hall sensor for commutation                             |
| 8   | HALL_W                   | Phase W of the Hall sensor for commutation                             |
| 11  | A / $U_{a1}$             | A track signal RS422 (differential) of the digital incremental encoder |
| 9   | #A / $\overline{U}_{a1}$ |                                                                        |
| 7   | B / $U_{a2}$             | B track signal RS422 (differential) of the digital incremental encoder |
| 5   | #B / $\overline{U}_{a2}$ |                                                                        |

### > Cable type and configuration [X2]

The cable names that are stated refer to cables made by Lapp. However, it is also possible to use comparable cables from other manufacturers, for example Lütze or Helukabel.

#### Resolvers / analogue Hall generators:

LAPP ÖLFLEX SERVO 728 CY; 3 x (2 x 0,14) + 2 x (0,5);

LAPP ÖLFLEX SERVO FD 798 CP; 3 x (2 x 0,14) + 2 x (0,5);

use 2 x (0,5) for the resolver carrier.

#### Other encoder types:

We recommend using the encoder connection cables that are approved by the respective manufacturer (Heidenhain, Sick-Stegmann, etc.) for their product. For the angle encoder supply US and GND we recommend a minimum cross-section of 0.25 mm<sup>2</sup>.

## 5.11 Connector BL 4000-M: resolvers and encoder [X2]

On BL 4100-M type devices, the angle encoder is connected via a PCB connector [X2], see the following Figure (C), before the servo drive is mounted on the motor.

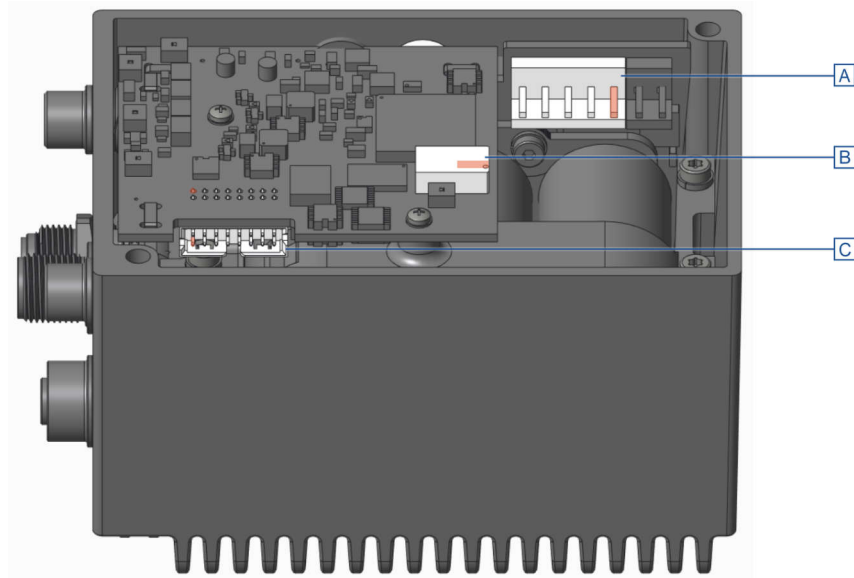


Figure 26: Connector arrangement: motor [X6], holding brake [X6B] and angle encoder [X2]

Different types of encoders can be connected to the Molex connector (see also section 6.7 *Resolver and encoder connector [X2]* on page 77):

- Resolvers
- Analogue Hall generators with tracks that are offset by 90° (sine/cosine)
- Analogue incremental encoders (1 V<sub>SS</sub>)
- Incremental encoders with a serial interface (RS485 level, e.g. EnDat, HIPERFACE®, BISS)
- Digital incremental encoders (RS422, HALL sensors)

It is also possible to evaluate an optional error signal (AS/NAS). With some incremental encoders, it is possible to detect and signal soiling or other faults/malfunctions of the measuring system via an output (AS or NAS). The error signal can be evaluated by digital as well as analogue incremental encoders. In the case of analogue incremental encoders, the evaluation is only possible if no commutation track (Z1) is parameterised and connected. The evaluation of the error signal can be inverted.

### › Configuration on the device [X2]

Molex No. 0878331619

### › Mating connector [X2]

Molex No. 51110-1651 with up to 16 contacts No. 50394-8051

With all encoders except resolvers and analogue Hall encoders, the supply voltage of the angle encoder can be set. This must be set correctly before connecting the encoder.

**NOTICE** Damage to property caused by an incorrect power supply

If an incorrect power supply is used, the encoder may be destroyed. Ensure that the correct voltage is activated prior to connecting the encoder to [X2]. To do so, start the Metronix ServoCommander® parameterisation software and select the **Parameters/Device parameters/Angle encoder settings**.

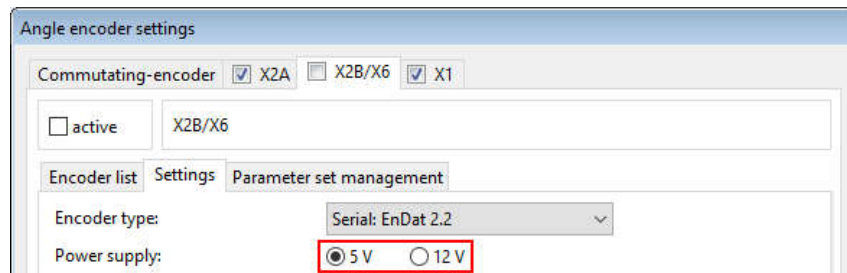


Figure 27: Angle encoder settings: Parameterisation of supply voltage

➤ **Pin assignment: resolvers**

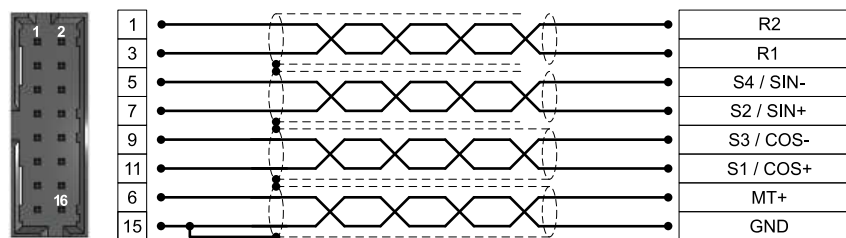


Figure 28: Pin assignment „resolvers [X2]“

| Pin | Name    | Specification                                                      |
|-----|---------|--------------------------------------------------------------------|
| 1   | R2      | Carrier signal for the resolver                                    |
| 3   | R1      |                                                                    |
| 5   | S4/SIN- | SINE track signal, differential<br>Analogue Hall sensor (SINE)     |
| 7   | S2/SIN+ |                                                                    |
| 9   | S3/COS- | COSINE track signal, differential<br>Analogue Hall sensor (COSINE) |
| 11  | S1/COS+ |                                                                    |
| 6   | MT+     | Motor temperature sensor, normally closed contact, PTC, NTC, KTY   |
| 15  | GND     | Temperature sensor reference potential                             |

### > Pin assignment: analogue incremental encoders

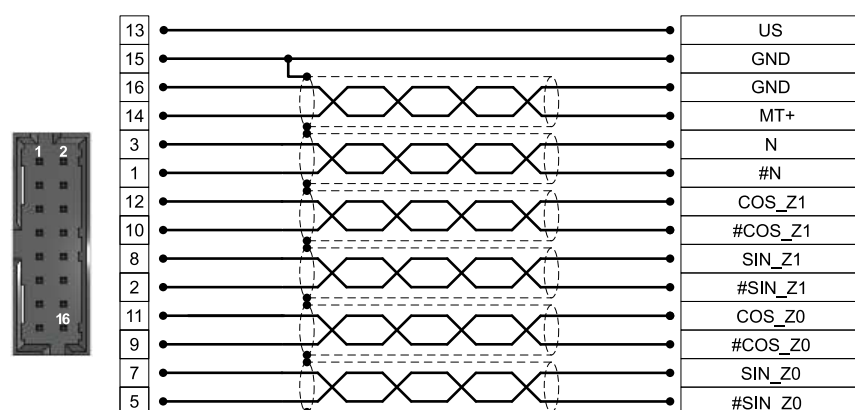


Figure 29: Pin assignment: „analogue incremental encoders [X2]“

| Pin | Name                    | Specification                                                                       |
|-----|-------------------------|-------------------------------------------------------------------------------------|
| 13  | US                      | Operating voltage for incremental encoders                                          |
| 15  | GND                     | Associated reference potential                                                      |
| 14  | MT+                     | Motor temperature sensor, normally closed contact, PTC, NTC, KTY                    |
| 3   | N                       | Index pulse track signal (differential) of the high-resolution incremental encoder  |
| 1   | #N                      |                                                                                     |
| 12  | COS_Z1 / D+             | COSINE commutation signal (differential) of the high-resolution incremental encoder |
| 10  | #COS_Z1 / D-            |                                                                                     |
| 8   | SIN_Z1 / C+             | SINE commutation signal (differential) of the high-resolution incremental encoder   |
| 2   | #SIN_Z1 / C- / AS / NAS |                                                                                     |
| 11  | COS_Z0 / B+             | COSINE track signal (differential) of the high-resolution incremental encoder       |
| 9   | #COS_Z0 / B-            |                                                                                     |
| 7   | SIN_Z0 / A+             | SINE track signal (differential) of the high-resolution incremental encoder         |
| 5   | #SIN_Z0 / A-            |                                                                                     |

### ➤ Pin assignment: incremental encoder with a serial interface

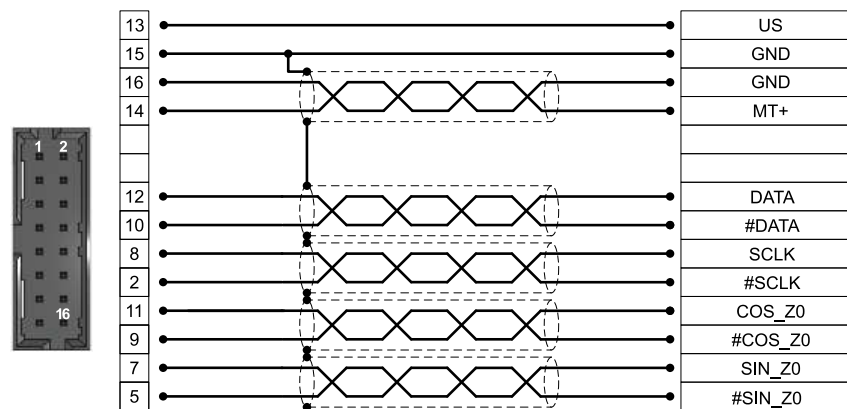


Figure 30: Pin assignment: „incremental encoder with a serial interface [X2]“

| Pin | Name         | Specification                                                                      |
|-----|--------------|------------------------------------------------------------------------------------|
| 13  | US           | Operating voltage                                                                  |
| 15  | GND          | Associated reference potential                                                     |
| 14  | MT+          | Motor temperature sensor, normally closed contact, PTC, NTC, KTY                   |
| 12  | DATA / SL+   | Bidirectional RS485 data line (differential) (EnDat/HIPERFACE <sup>®</sup> , BiSS) |
| 10  | #DATA / SL-  |                                                                                    |
| 8   | SCLK / MA+   | Clock pulse output RS485 (differential) (EnDat, BiSS)                              |
| 2   | #SCLK / MA-  |                                                                                    |
| 11  | COS_Z0 / B+  | COSINE track signal (differential) of the high-resolution incremental encoder      |
| 9   | #COS_Z0 / B- |                                                                                    |
| 7   | SIN_Z0 / A+  | SINE track signal (differential) of the high-resolution incremental encoder        |
| 5   | #SIN_Z0 / A- |                                                                                    |

### ➤ Pin assignment: digital incremental encoder (RS422)

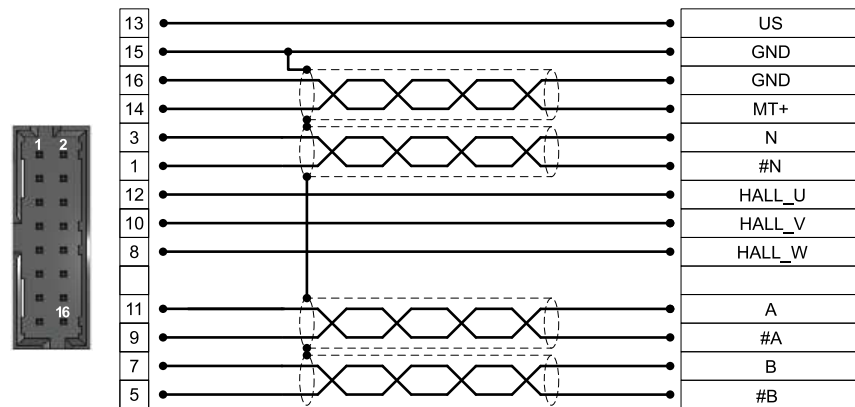


Figure 31: Pin assignment: „digital incremental encoder (RS422) [X2]“

| Pin | Name                     | Specification                                                          |
|-----|--------------------------|------------------------------------------------------------------------|
| 13  | US                       | Operating voltage for incremental encoders                             |
| 15  | GND                      | Associated reference potential                                         |
| 14  | MT+                      | Motor temperature sensor, normally closed contact, PTC, NTC, KTY       |
| 3   | N / $U_{a0}$             | Index pulse RS422 (differential) of the digital incremental encoder    |
| 1   | #N / $\overline{U}_{a0}$ |                                                                        |
| 12  | HALL_U                   | Phase U of the Hall sensor for commutation                             |
| 10  | HALL_V                   | Phase V of the Hall sensor for commutation                             |
| 8   | HALL_W                   | Phase W of the Hall sensor for commutation                             |
| 11  | A / $U_{a1}$             | A track signal RS422 (differential) of the digital incremental encoder |
| 9   | #A / $\overline{U}_{a1}$ |                                                                        |
| 7   | B / $U_{a2}$             | B track signal RS422 (differential) of the digital incremental encoder |
| 5   | #B / $\overline{U}_{a2}$ |                                                                        |

### ➤ Cable type and configuration [X2]

As only short cables are used for the motor installation variant, shielded and twisted cables can usually be omitted. However, the cables must not exceed a maximum length of 80 mm. For the encoder supply US and GND we recommend a minimum cross-section of 0.25 mm<sup>2</sup>, for all other cables a cross-section of 0.14 mm<sup>2</sup>.

## 5.12 Connector: USB [X19]

The BL 4000-M / BL 4000-D servo drive has a Type Mini-B USB connector.

The correct operation requires a short USB cable (< 3 m) and the correct installation and earthing of the servo drive. If excessive malfunctions/faults lead to communication problems (frozen communication), the USB connector can be briefly disconnected to restart the communication. In any case, we recommend using certified and double-shielded cables with shielded plugs of the following type :

Type AB type (USB 2.0 connecting cable, type A connector to type Mini-B connector)  
AWG24-2C

### **INFORMATION** Non-EMC-compliant wiring of the servo drive and motor

In case of non-EMC-compliant wiring of the servo drive and motor, compensating electric current may flow via the connected computer and the USB interface. This may lead to communication problems. To avoid this, we recommend using an electrically isolated USB adapter "Delock USB Isolator" (type 62588 by Delock) or a comparable adapter.

### **INFORMATION** Use USB only during commissioning

The USB interface should only be used during commissioning and not as a process interface in an application. In an industrial environment, the electrically much more robust Ethernet interface should be preferred instead.

### › Configuration on the device [X19]

USB connector (female), type Mini-B

### › Mating connector [X19]

USB connector (male), type Mini-B

### › Pin assignment USB [X19]

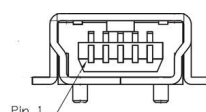


Figure 32: Pin assignment of the USB connector

| Pin | Name | Specification |
|-----|------|---------------|
| 1   |      |               |
| 2   | D-   | Data -        |
| 3   | D+   | Data +        |
| 4   |      |               |
| 5   | GND  | GND           |

## 5.13 Connector: Fieldbus [X21], [X22]

The integration into a fieldbus network, is done via two M8 connectors according to IEC 61076-114 (4-pin, socket, D-coded). Depending on the existing fieldbus variant (see section 3.1 *Type designation* on page 17), the connector is either used for the connection of a real-time Ethernet fieldbus (EtherCAT/PROFINET) or a CAN fieldbus (CANopen). Both fieldbus variants must never be used simultaneously in the same network, as they are electrically incompatible! With fieldbus variant PROFINET/EtherCAT, the connection [X22] *RTE1* is also used for communication with the Metronix ServoCommander® as long as neither EtherCAT nor PROFINET are active. The CAN fieldbus variant does not have an Ethernet interface!

Details on the fieldbus connection can be found in the respective fieldbus manuals.

### › Configuration on the device [X21], [X22]

Flush-type connector, Ethernet/PROFINET

Phoenix Contact, SACC-CIP-M8FSD-4P SMD SH R32 - 1068454

### › Mating connector [X21], [X22]

Assembled network cable Phoenix Contact:

M8 plug to M8 plug: NBC-M8MSD/ 1,0-93C/M8MSD - 1423707

M8 plug to RJ45: NBC-M8MSD/ 1,0-93C/R4AC - 1423711

M8 plug to free cable end: NBC-M8MSD/ 1,0-93C - 1423703

### › Pin assignment [X21], [X22]

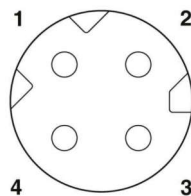


Figure 33: Pin assignment of the fieldbus connector

Pin assignment **EtherCAT/PROFINET**:

| Pin | Name | Description           | Colour |
|-----|------|-----------------------|--------|
| 1   | TD+  | Transmission signal + | Yellow |
| 2   | RD+  | Reception signal +    | White  |
| 3   | TD-  | Transmission signal - | Orange |
| 4   | RD-  | Reception signal -    | Blue   |

Pin assignment **CANopen**:

| Pin | Name    | Description              | Colour |
|-----|---------|--------------------------|--------|
| 1   | CAN-H   | Differential Signal High | Yellow |
| 2   | CAN-GND | Reference potential      | Orange |
| 3   | CAN-L   | Differential Signal Low  | White  |
| 4   | CAN-GND | Reference potential      | Blue   |

### ➤ Cable type and configuration (CAN variant) [X21], [X22]

We recommend using the pre-assembled cables listed above or comparable products from other manufacturers.

For trouble-free operation of the CAN bus communication, the following instructions must be observed

- Ideally, the individual nodes of the networks are always connected in a linear manner so that the CAN cable is looped through from servo drive to servo drive.
- A terminating resistor of 120  $\Omega$ , 5%, must be present on both ends of the CAN bus cable
- We advise against the use of intermediate plugs for cabling the CAN bus. However, if this is necessary, use metal connector housings for connecting the cable shield.

In order to keep interferences as low as possible ensure that

- the motor cables are not installed parallel to signal lines
- the motor cables comply with the specification
- the motor cables are properly shielded and earthed (grounded)

## 5.14 Connector: I/O interface [X1]

The analogue input (AIN) and the analogue output (AOUT) are rated for voltages in the range  $\pm 10$  V. Both the analogue inputs and the analogue output must be connected to the controller via twisted and shielded cables.

If the control system has a single-ended output, the output is connected to AIN and the reference potential of the control system is connected to GND. Use a twisted pair of wires for AIN/GND.

If the controller has a differential output, the differential signals should - if possible - be led to the controller in a twisted pair of wires and the reference potential in another pair of wires. Directly in connector [X1], the negative differential signal is then connected to GND and the positive differential signal to AIN. This reduces potential shifts and equalising currents via [X1]. For the best possible interference suppression on the analogue signal lines, the wires of the analogue signals must also be shielded separately.

The connections related to 24 V can be unshielded. For long lines ( $l > 2$  m) to the controller, shielded lines should be used, with the shields connected to PE at both ends.

The servo drive provides a 5 V auxiliary voltage to supply external encoders connected to the master frequency input. The differential signals of the master frequency interface (A/#A and B/#B) should each be routed in a twisted pair of wires.

If a 24V auxiliary supply is needed, one of the digital outputs can be permanently configured to *On*. This can be used, for example, to supply an external switch or an operating unit.

The digital outputs are designed as so-called "high-side switches". This means that only the 24 V is switched through to the output in the active state. In the passive state, the output is high-impedance and the level is defined only by the flyback diode and a high-impedance internal resistor.

### › Configuration on the device [X1]

M12 Flush-type connector Phoenix Contact, SACC-CI-M12FS-17P SMD T - 1411917

### › Mating connector [X1]

Single connector:

Connector, Universal, 17-position, Plug straight M12 SPEEDCON, Coding: A, Piercecon® fast connection, knurl material: Zinc die-cast, nickel-plated, external cable diameter 5.4 mm ... 8.2 mm:

Phoenix Contact, SACC-MS-17PCON SCO - 1559602

Assembled cable:

Sensor/actuator cable, 17-position, PUR/PVC, black RAL 9005, shielded, Plug straight M12 SPEEDCON, coding: A, on free cable end, cable length: 1.5 m:

Phoenix Contact, SAC-17P-MS/ 1,5-35T SH SCO - 1430200

### > Pin assignment [X1]

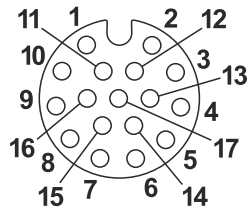


Figure 34: I/O interface [X1]

| Pin | Name     | Specification                                          |
|-----|----------|--------------------------------------------------------|
| 1   | DIN0     | Digital input 0                                        |
| 2   | DIN1     | Digital input 1                                        |
| 3   | DIN2     | Digital input 2                                        |
| 4   | DIN3     | Digital input 3                                        |
| 5   | DIN4     | Digital input 4                                        |
| 6   | DIN5     | Digital input 5 (servo drive enable signal)            |
| 7   | DIN8     | Digital Input (flying saw, sampling)                   |
| 8   | DOUT0    | Freely programmable digital output 0                   |
| 9   | DOUT1    | Freely programmable digital output 1                   |
| 10  | AOUT     | Analogue output                                        |
| 11  | A / CLK  | Incremental encoder signal A/stepper motor signal CLK  |
| 12  | #A / CLK | Incremental encoder signal #A/stepper motor signal CLK |
| 13  | B / DIR  | Incremental encoder signal B/stepper motor signal DIR  |
| 14  | #B / DIR | Incremental encoder signal #B/stepper motor signal DIR |
| 15  | +5 V     | Encoder supply (see pin 11 to 14)                      |
| 16  | AIN      | Analogue input, input voltage 30 V max.                |
| 17  | GND      | Reference potential for Analogue input                 |

### > Cable type and configuration [X1]

The specified cable type refers to a ready-assembled cable from Phoenix Contact. It is possible to use comparable cables from other manufacturers.

Phoenix Contact, SAC-17P-MS/ 1,5-35T SH SCO - 1430200

## 6 Technical data

This chapter provides all of the relevant technical data of the BL 4000-M / BL 4000-D servo drives with an integrated "Safe Torque Off (STO)" safety function.

### 6.1 General technical data

#### > Qualification

| Characteristic                            | Value                                                                                                                                                                                                                                      |
|-------------------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| Low Voltage Directive                     | 2014/30/EU by applying the harmonised standard EN 61800-5-1<br>See section 9.1 <i>CE conformity (EMC, RoHS, Low Voltage Directive)</i> on page 89                                                                                          |
| EMC                                       | 2014/35/EU by applying the harmonised standard EN 61800-3<br>See section 9.1 <i>CE conformity (EMC, RoHS, Low Voltage Directive)</i> on page 89 and section 5.1 <i>Notes concerning the safe and EMC-compliant installation</i> on page 26 |
| Machinery Directive/<br>Functional Safety | 2006/42/EC<br>See section 9.2 <i>CE conformity (Machinery Directive)</i> on page 91                                                                                                                                                        |
| UL                                        | Recognised according to UL 61800-5-1, C22.2 No. 274-13<br>See section 9.3 <i>cURus certification</i> on page 93 and section 5.2 <i>Additional requirements for the UL approval</i> on page 29                                              |

#### > Ambient conditions

| Characteristic                                  | Value                                                                                                           |
|-------------------------------------------------|-----------------------------------------------------------------------------------------------------------------|
| Storage temperature                             | -25°C to +70°C                                                                                                  |
| Ambient temperature                             | 0 °C to +30 °C (BL 4104-D : 0 °C to +40 °C)<br>up to +50°C with a power reduction of 2.5%/K                     |
| Permissible installation altitude               | Max. installation altitude 2,000 m above MSL;<br>with a power reduction of 1% per 100 m as of 1,000 m above MSL |
| Atmospheric humidity                            | Relative humidity up to 90%, non-condensing                                                                     |
| Type of enclosure                               | IP54, depending on mounting type up to IP67                                                                     |
| Protection class                                | I                                                                                                               |
| Pollution degree rating                         | 2                                                                                                               |
| Operational environment according to EN 61800-3 | Without additional measures:<br>First and second environment (C2/C3)                                            |

**INFORMATION Compliance with the pollution degree rating**

The integrated safety technology requires compliance with pollution degree rating 2 and thus a protected enclosure (IP54). This must always be ensured through appropriate measures.

**⚠ WARNING Use in residential environment**

In a residential environment, servo drives of the BL 4000-M / BL 4000-D device family can cause high-frequency interference, which makes interference suppression measures necessary.

**› Maximum housing temperature**

Depending on the installation, the servo drive is additionally heated by the motor, for example. The following housing temperatures must not be exceeded under any circumstances:

| Characteristic              | BL 4840-M | BL 4840-D | BL 4104-M | BL 4104-D |
|-----------------------------|-----------|-----------|-----------|-----------|
| Maximum housing temperature | 82 °C     | 81 °C     | 85 °C     | 93 °C     |

**› Dimensions and weight<sup>\*)</sup>**

| Characteristic                                  | BL 4000-M          | BL 4000-D            |
|-------------------------------------------------|--------------------|----------------------|
| Dimensions including the mounting plate (H*W*D) | 125 mm*80 mm*65 mm | 127 mm*106 mm*104 mm |
| Housing dimensions (H*W*D)                      | 125 mm*80 mm*65 mm | 125 mm*80 mm*65 mm   |
| Weight                                          | approx. 0.7 kg     | approx. 1.0 kg       |

<sup>\*)</sup> Device dimensions without the mating connector.

## 6.2 BL 4100-M / BL 4100-D: Power supply [X9]

### › Power data

| Characteristic                                                     | Value                                         |
|--------------------------------------------------------------------|-----------------------------------------------|
| Supply voltage                                                     | 1 x 75...230 VAC [ $\pm 10\%$ ], 50 ... 60 Hz |
| Supply network type                                                | TN, TT                                        |
| Maximum mains current in continuous operation (S1) * <sup>1)</sup> | 6 A <sub>eff</sub>                            |
| DC bus voltage                                                     | 325 VDC (with U <sub>mains</sub> = 230 VAC)   |

\*<sup>1)</sup> with a supply voltage of 230 V and power factor 0.6

#### **INFORMATION** Supply with low voltage

If low-voltage operation is necessary, we recommend using a series transformer or isolating transformer for decreasing the voltage.

#### **NOTICE** DC supply

The BL 4100-M / BL 4100-D servo drives cannot be supplied with DC voltage via the DC link terminals nor via L1/N (DC supply).

### › Internal braking resistor

| Characteristic   | Value       |
|------------------|-------------|
| Braking resistor | 47 $\Omega$ |
| Peak power       | 4 kW        |
| Continuous power | 13 W        |

## 6.3 BL 4800-M / BL 4800-D: Power supply [X9]

### > Power data

| Characteristic                                     | Value                             |
|----------------------------------------------------|-----------------------------------|
| Supply voltage                                     | 24 ... 48 VDC [ $\pm 10\%$ ]      |
| Maximum mains current in continuous operation (S1) | 40 A <sub>eff</sub>               |
| DC bus voltage                                     | corresponds to the supply voltage |

#### **INFORMATION** Supplying with power supply unit

The power supply unit used must

- be able to charge the capacitive load of the DC link capacitors with current limitation when switched on.
- be able to tolerate the high voltage at [X9] occurring during braking without raising an error.

Additional external buffer capacitors can be used to buffer the braking energy.

#### **NOTICE** BL 4800-M / BL 4800-D: Danger of destroying the power supply unit

During braking, a high voltage can be present at [X9], which can destroy the power supply unit. To prevent this, the switch-off threshold in case of overvoltage must be suitably parameterised (see section *Power supply via main power unit* in the Product manual smartServo BL 4000-D and BL 4000-M).

#### **NOTICE** High charging current when battery is connected

When connecting a battery, a high compensating current ( $> 1000\text{ A}$ ) flows until the internal capacitors of the servo drive are charged. We therefore recommend initially connecting the battery via a  $1\text{ k}\Omega$  resistor for precharging.

### > Internal braking resistor

| Characteristic   | Value         |
|------------------|---------------|
| Braking resistor | $3.9\ \Omega$ |
| Peak power       | 1.6 kW        |
| Continuous power | 5 W           |

## 6.4 24 V supply and STO [X3]

### > 24 V supply

| Characteristic | Value                                        |
|----------------|----------------------------------------------|
| 24 V supply    | 24 VDC [ $\pm 20\%$ ] (0.2 A) <sup>*1)</sup> |

<sup>\*1)</sup> plus the current consumption of the I/O's and a possibly existing holding brake.

### > Characteristic values

| Characteristic                                   | Value                                                            |
|--------------------------------------------------|------------------------------------------------------------------|
| Safety level                                     | Category 4 and performance level e or SIL3/SIL CL3.              |
| PFH (probability of dangerous failure per hour)  | $3 \times 10^{-11}$                                              |
| PFD (probability of dangerous failure on demand) | $5 \times 10^{-6}$                                               |
| DCavg (average diagnostic coverage)              | High                                                             |
| MTTFd (mean time to dangerous failure)           | Limited to 100 years (cat. 3)<br>Limited to 2,500 years (cat. 4) |

See also section 9.2 *CE conformity (Machinery Directive)* on page 91.

#### **INFORMATION** Proof-testing of the STO function

Comply with the following test intervals in order to reach the specified values:

- For SIL 2, PL d/category 3: 1x per year
- For SIL 3, PL e/category 3: every 3 months
- For SIL 3, PL e/category 4: daily

## 6.4.1 Electrical data of the STO function

### > Control inputs STOA/STOB [X3]

| Characteristic                     | Value                                       |
|------------------------------------|---------------------------------------------|
| Nominal voltage                    | 24 V (referred to GNDA/GNDB)                |
| Voltage range                      | 19.2 V... 28.8 V                            |
| Permissible ripple                 | 2 % (referred to a nominal voltage of 24 V) |
| Nominal current                    | 12 mA typ., 30 mA max.                      |
| Switch-on input voltage threshold  | $\geq 16$ V                                 |
| Switch-off input voltage threshold | $< 5$ V                                     |

For the technical data of the digital inputs DIN6 and DIN7, see the section 6.10 *I/O Interface [X1]* on page 81.

### › Response time until power output stage inactive and maximum OSSD test pulse duration

The typical response time and the maximum test pulse duration depend on the input voltage at STOA/STOB:

| Characteristic                  | Value  |      |        |
|---------------------------------|--------|------|--------|
| Input voltage (STOA/STOB)       | 19.2 V | 24 V | 28.8 V |
| Typical response time           | 2 ms   | 3 ms | 4 ms   |
| Max. test pulse duration (OSSD) | 0.5 ms | 1 ms | 1.5 ms |

The maximum response time  $t_{\text{STOAB/OFF}}$  is described in section 6.4.2.1 *Time response of the STO activation during operation with a restart* on page 68.

## 6.4.2 Time response

### **INFORMATION** Equal inputs in terms of their functionality

The inputs STOA and STOB are absolutely equal in terms of their functionality, which is why the switching sequence of STOA/STOB is interchangeable in all of the diagrams.

### 6.4.2.1 Time response of the STO activation during operation with a restart

The illustration shows the time response starting with the disconnection of the control voltage at STOA/B and the sequence that is necessary for restarting the device.

- The actuation of the holding brake is realised via the basic device and not in a safety-oriented manner.
- The illustration shows the coasting of the motor regardless of the activation/deactivation of the brake
- The setpoint will not be enabled until the holding brake delay  $T_F$  has elapsed.
- An error will be issued as the STO inputs are deactivated while the output stage is active. It is not included in the drawing.

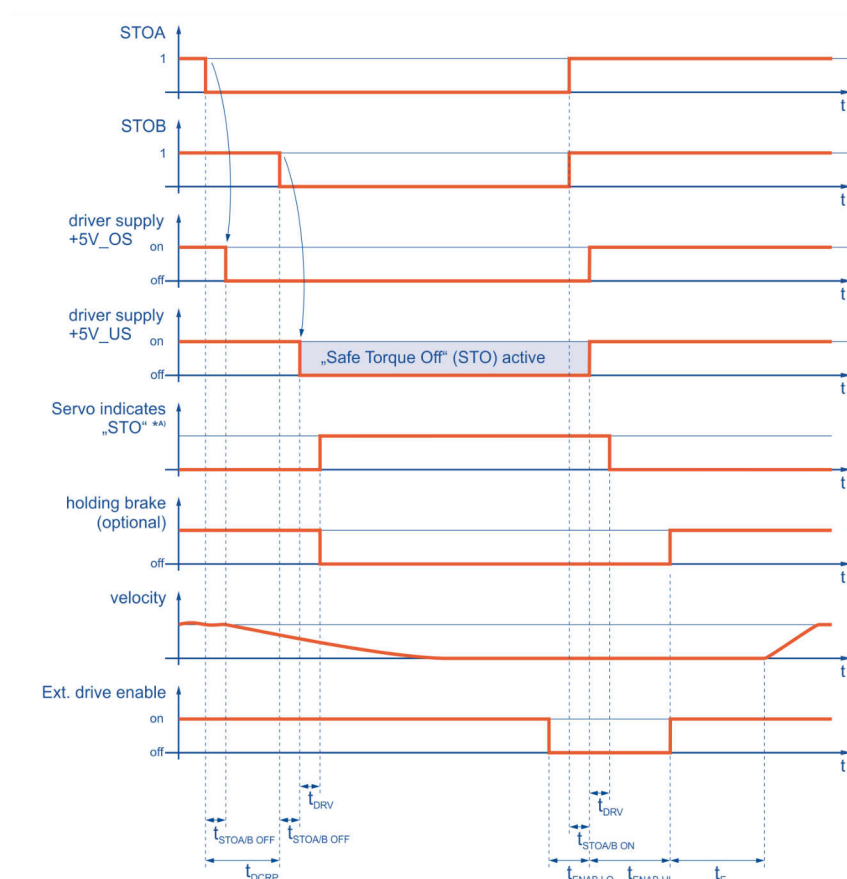


Figure 35: Time response of the activation of the STO safety function with a restart

\*A) see section 0.1 *Operating mode and error indication* on page 1

| Time              | Description                                                                                                                                                        | Value                        |
|-------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------|------------------------------|
| $t_{DCRP}$        | Maximum permissible discrepancy time without the servo drive issuing an error                                                                                      | 100 ms                       |
| $t_{STOA/B\ OFF}$ | STOA/B – switching time from high to low (See also section <i>Response time until power output stage inactive and maximum OSSD test pulse duration</i> on page 68) | Maximum response time 5 ms   |
| $t_{STOA/B\ ON}$  | STOA/B switching time from low to high                                                                                                                             | 0.6 ms typ., 1 ms max.       |
| $t_{DRV}$         | Delay of the internal sequence control of the servo drive                                                                                                          | 10 ms max.                   |
| $t_{ENAB\ LO}$    | Time that the servo drive enable signal (DIN5 or bus enable signal) must be low before STOA/B will be activated                                                    | 0                            |
| $t_{ENAB\ HI}$    | Time that the servo drive enable signal (DIN5 or bus enable signal) must be low after STOA/B has been reactivated and the status of the STO circuit has changed    | > 20 ms                      |
| $t_F$             | Brake control and automatic brake                                                                                                                                  | Parameterisable <sup>1</sup> |

<sup>1</sup> see section *Brake control and automatic brake* in the Product manual smartServo BL 4000-D and BL 4000-M

### 6.4.2.2 Time response of the SS1 activation during operation with a restart

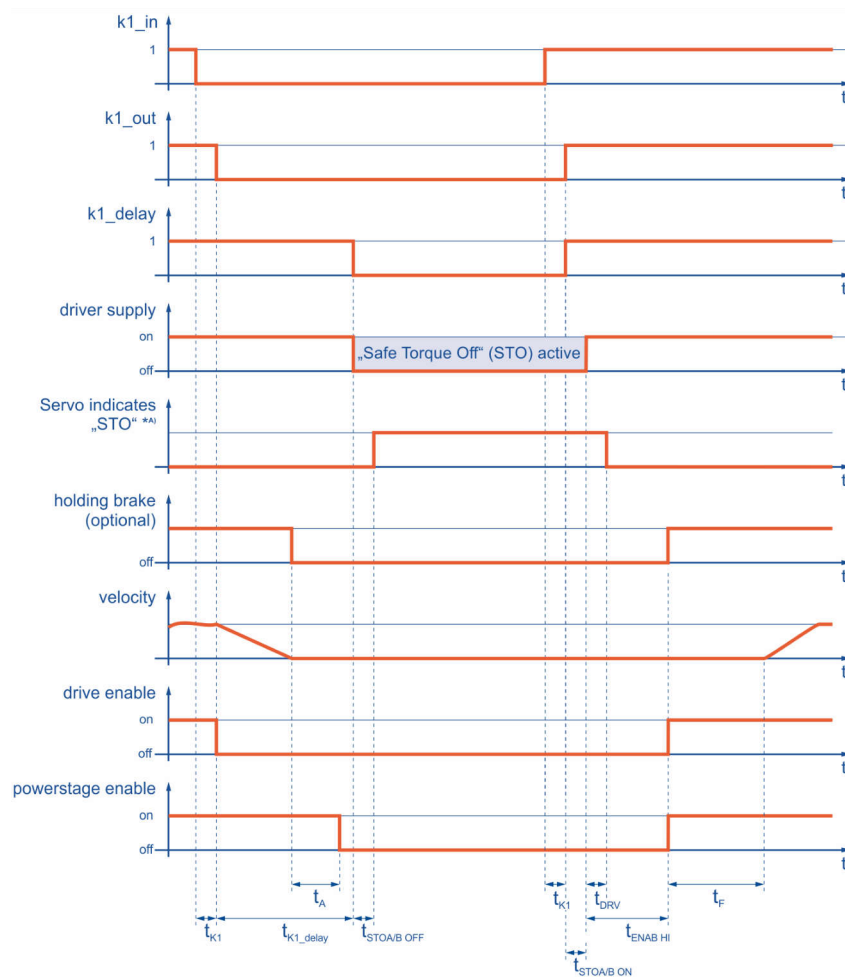


Figure 36: Time response during the activation of the SS1 safety function (external switching) with a restart

\*A) see section 0.1 *Operating mode and error indication* on page 1

| Time            | Description                                                                                                                                                         | Value                                  |
|-----------------|---------------------------------------------------------------------------------------------------------------------------------------------------------------------|----------------------------------------|
| $t_{K1}$        | Delay between the switching of S1 and the closing of the undelayed contact K1                                                                                       | See the data sheet of the safety relay |
| $t_{K1\_delay}$ | Delay between S1 and the opening of the off-delayed contacts K1                                                                                                     | Can be adjusted on the safety relay    |
| $t_{STOA/BOFF}$ | STOA/B – switching time from high to low<br>See also section <i>Response time until power output stage inactive and maximum OSSD test pulse duration</i> on page 68 | Maximum response time<br>5 ms          |
| $t_{STOA/BON}$  | STOA/B – switching time from high to low                                                                                                                            | 0.6 ms typ., 1 ms max.                 |
| $t_{DRV}$       | Delay of the internal sequence control of the servo drive                                                                                                           | 10 ms max.                             |
| $t_{ENABHI}$    | Time that DIN5 must be low after STOA/B has been reactivated and the status of the STO circuit has changed                                                          | > 20 ms                                |
| $t_A$           | Switch-off delay of the holding brake                                                                                                                               | Parameterisable <sup>1</sup>           |
| $t_F$           | Switch-on delay of the holding brake                                                                                                                                | Parameterisable <sup>1</sup>           |

<sup>1</sup> see section *Brake control and automatic brake* in the Product manual smartServo BL 4000-D and BL 4000-M

## 6.5 BL 4100-M / BL 4100-D: Motor connector [X6]

### › Performance data

Supply voltage 230 VAC [ $\pm 10\%$ ], 50 Hz,  $f_{PWM} = 5\text{ kHz}$ ,  $f_{el} > 2\text{ Hz}$ ,  
 $T_{Ambient} = 30^\circ\text{C}$

| Characteristic                      | BL 4104-D           | BL 4104-M           |
|-------------------------------------|---------------------|---------------------|
| Nominal output power                | 800 W               | 700 W               |
| Maximum output power for 2 s        | 2400 W              | 2400 W              |
| Nominal output current              | 4 A <sub>eff</sub>  | 3 A <sub>eff</sub>  |
| Max. output current for 2 s         | 12 A <sub>eff</sub> | 12 A <sub>eff</sub> |
| Power loss/efficiency <sup>*)</sup> | 4 % / 96 %          |                     |

<sup>\*)</sup> As a guide value for the cooling measures.

### › Current derating

The BL 4100-M / BL 4100-D series servo drives have a current derating during nominal operation. The rated current and the duration of the maximum permissible peak current of the servo drive depend on several factors. These factors are:

- Output current level: The higher the output current is, the shorter the permissible time will be.
- Clock frequency of the power output stage: The higher the clock frequency is, the shorter the permissible time will be.

The current derating begins as of a PWM frequency of 10 kHz ( $f_{PWM}$ ) and is linear between the reference values that are stated in the following table:

| PWM frequency $f_{PWM}$ <sup>*)</sup> | BL 4104-M / BL 4104-D |                  |
|---------------------------------------|-----------------------|------------------|
|                                       | I <sub>nominal</sub>  | I <sub>max</sub> |
| 10 kHz                                | 4 A                   | 12 A             |
| 16 kHz                                | 3 A                   | 9 A              |

<sup>\*)</sup> The PWM frequency is the reciprocal of half of the current controller cycle time  $t_i$ . The variable cycle times enable particularly high dynamics combined with reduced power data.

### › Motor cable requirements

| Characteristic | Value                                                                                                             |
|----------------|-------------------------------------------------------------------------------------------------------------------|
| Cable length   | $l \leq 3\text{ m}$<br>See section 5.1 <i>Notes concerning the safe and EMC-compliant installation</i> on page 26 |
| Cable capacity | $C' \leq 160\text{ pF/m}$<br>of one phase against shield or between two lines                                     |

## ➤ Motor temperature monitoring system

### **⚠ DANGER** ⚠ Dangerous electrical voltage!

The signals for the temperature sensor "MT-" and "MT+" at the motor connector [X6] must be connected to protective extra-low voltage (PELV) on the motor side and they must be insulated against the motor phases.

### **NOTICE** Electronic overload protection of the motor

The servo drive has an electronic cut-out for overload protection combined with thermal memory retention. For an effective protection, the nominal motor current, maximum motor current and overload time ( $I^2t$  time) must be parameterised as described in the product manual.

| Characteristic       | Value                                                         |
|----------------------|---------------------------------------------------------------|
| Sensor type          | Analogue                                                      |
| Sensor type          | Silicon temperature sensor PTC/NTC, e.g. KTY84-130 or similar |
| Characteristic curve | Linear/non-linear, parameterisable (10 nodes)                 |
| Measuring range      | from 300 $\Omega$ to 20 k $\Omega$ (+-10 %)                   |
| Output voltage       | + 3.3 V                                                       |
| Output current       | 1.7 mA max. (via 2 k $\Omega$ measuring resistor)             |
| Internal resistance  | approx. 2 k $\Omega$                                          |

## ➤ Output for the holding brake in the motor

| Characteristic                                                       | Value                                                                       |
|----------------------------------------------------------------------|-----------------------------------------------------------------------------|
| Nominal voltage                                                      | 24 V                                                                        |
| Nominal current                                                      | 700 mA (total of all digital outputs and of the holding brake: 900 mA max.) |
| Voltage drop referred to the 24 V input with a load current of 0.7 A | approx. 1.5 V                                                               |
| Overload protection                                                  | Yes, current limitation to 2 A max                                          |
| Overvoltage protection                                               | up to 60 V                                                                  |
| Internal flyback diode                                               | Yes                                                                         |

**> HIPERFACE DSL<sup>®</sup> connector [X6]**

| Characteristic                                             | Value                                                                                    |
|------------------------------------------------------------|------------------------------------------------------------------------------------------|
| HPF_DSL-, HPF_DSL+                                         | In accordance with the HIPERFACE DSL <sup>®</sup> specification RS485                    |
| Baud rate                                                  | 9.37 MHz                                                                                 |
| Frame rate                                                 | 12.1 to 27 $\mu$ s                                                                       |
| Supply voltage                                             | 10 V (250 mA)                                                                            |
| Supported transfer modes                                   | Transfer of short and long messages with storage of the set of parameters in the encoder |
| Characteristic impedance of the cable and line termination | 110 $\Omega$                                                                             |

## 6.6 BL 4800-M / BL 4800-D: Motor connector [X6]

### > Performance data

With supply voltage 48 VDC [ $\pm 10\%$ ],  $f_{\text{PWM}} = 5 \text{ kHz}$ ,  $f_{\text{el}} > 3 \text{ Hz}$ ,  
 $T_{\text{Ambient}} = 30^\circ\text{C}$

| Characteristic                      | BL 4840-M            | BL 4840-D           |
|-------------------------------------|----------------------|---------------------|
| Nominal output power                | 1.0 kW               | 1.1 kW              |
| Maximum output power for 2 s        | 3.6 kW               |                     |
| Nominal output current              | 40 A <sub>eff</sub>  | 42 A <sub>eff</sub> |
| Max. output current for 2 s         | 120 A <sub>eff</sub> |                     |
| Power loss/efficiency <sup>*)</sup> | 3 % / 97 %           |                     |

<sup>\*)</sup> As a guide value for the cooling measures.

### > Current derating

The BL 4800-M / BL 4800-D series servo drives have a current derating during nominal operation. The rated current and the duration of the maximum permissible peak current of the servo drive depend on several factors. These factors are:

- Output current level: The higher the output current is, the shorter the permissible time will be.
- Clock frequency of the power output stage: The higher the clock frequency is, the shorter the permissible time will be.

The current derating begins as of a PWM frequency of 10 kHz ( $f_{\text{PWM}}$ ) and is linear between the reference values that are stated in the following table:

| PWM frequency $f_{\text{PWM}}$ <sup>*)</sup> | BL 4840-M / BL 4840-D |                  |
|----------------------------------------------|-----------------------|------------------|
|                                              | I <sub>nominal</sub>  | I <sub>max</sub> |
| 10 kHz                                       | 40 A                  | 120 A            |
| 16 kHz                                       | 30 A                  | 90 A             |

<sup>\*)</sup> The PWM frequency is the reciprocal of half of the current controller cycle time  $t_i$ . The variable cycle times enable particularly high dynamics combined with reduced power data.

### > Motor cable requirements

| Characteristic | Value                                                                                                                |
|----------------|----------------------------------------------------------------------------------------------------------------------|
| Cable length   | $l \leq 3 \text{ m}$<br>siehe section 5.1 <i>Notes concerning the safe and EMC-compliant installation</i> on page 26 |
| Cable capacity | $C' \leq 160 \text{ pF/m}$<br>of one phase against shield or between two lines                                       |

**NOTICE Electronic overload protection of the motor**

The servo drive has an electronic cut-out for overload protection combined with thermal memory retention. For an effective protection, the nominal motor current, maximum motor current and overload time ( $I^2t$  time) must be parameterised as described in the product manual.

| Characteristic       | Value                                                         |
|----------------------|---------------------------------------------------------------|
| Sensor type          | Analogue                                                      |
| Sensor type          | Silicon temperature sensor PTC/NTC, e.g. KTY84-130 or similar |
| Characteristic curve | Linear/non-linear, parameterisable (10 nodes)                 |
| Measuring range      | from 300 $\Omega$ to 20 k $\Omega$ (+-10 %)                   |
| Output voltage       | + 3.3 V                                                       |
| Output current       | 1.7 mA max. (via 2 k $\Omega$ measuring resistor)             |
| Internal resistance  | approx. 2 k $\Omega$                                          |

**› Output for the holding brake in the motor**

| Characteristic                                                     | Value                                                                       |
|--------------------------------------------------------------------|-----------------------------------------------------------------------------|
| Nominal voltage                                                    | 24 V                                                                        |
| Nominal current                                                    | 700 mA (total of all digital outputs and of the holding brake: max. 900 mA) |
| Voltage drop referred to the 24 V input with a load current of 2 A | approx. 0.5 V                                                               |
| Overload protection                                                | Yes, current limitation to 2 A max.                                         |
| Overvoltage protection                                             | up to 60 V                                                                  |
| Internal flyback diode                                             | Yes                                                                         |

**› HIPERFACE DSL<sup>®</sup> connector [X6]**

| Characteristic                                             | Value                                                                                    |
|------------------------------------------------------------|------------------------------------------------------------------------------------------|
| HPF_DSL-, HPF_DSL+                                         | In accordance with the HIPERFACE DSL <sup>®</sup> specification RS485                    |
| Baud rate                                                  | 9.37 MHz                                                                                 |
| Frame rate                                                 | 12.1 to 27 $\mu$ s                                                                       |
| Supply voltage                                             | 10 V (250 mA)                                                                            |
| Supported transfer modes                                   | Transfer of short and long messages with storage of the set of parameters in the encoder |
| Characteristic impedance of the cable and line termination | 110 $\Omega$                                                                             |

## 6.7 Resolver and encoder connector [X2]

The correct parameterisation of the multi-encoder interface is described in section „Encoder“ tab in the Product manual smartServo BL 4000-D and BL 4000-M.

### **INFORMATION** Possibly not all encoders of a manufacturer are supported

It is possible that not all encoders of a manufacturer are fully supported. In individual cases it is therefore always recommended to test the encoder in advance in the intended application.

### › Resolver

| Characteristic                     | Value                                      |
|------------------------------------|--------------------------------------------|
| Transformation ratio               | 1:2 to 1:4                                 |
| Carrier frequency                  | 5-10 kHz                                   |
| Excitation voltage                 | 5-6 V <sub>eff</sub> , short-circuit-proof |
| Excitation impedance (at 10 kHz)   | 4 Ω                                        |
| Stator impedance                   | > 30 Ω                                     |
| Measuring range (for Hall sensors) | 6 V <sub>ss</sub>                          |
| Resolution                         | 14 bits                                    |
| Signal detection delay             | < 200 µs                                   |
| Speed resolution                   | approx. 5 rpm                              |
| Actual speed value filter          | 400 µs                                     |
| Absolute angle detection accuracy  | < 0.022°                                   |
| Max. speed                         | 16,000 rpm                                 |

### › Power supply output

The power supply for the encoders can be changed.

### **NOTICE** Risk of destruction due to excessive voltage

If the voltage is too high, the angle encoder may be destroyed. Ensure that you have selected the correct supply voltage prior to connecting the encoder to the [X2] connector.

| Characteristic         | Low voltage | High voltage |
|------------------------|-------------|--------------|
| Output voltage         | 5.4 V       | 10.4 V       |
| Output current         | 250 mA      | 200 mA       |
| Short-circuit strength | Yes         | Yes          |

### › Digital incremental encoders

Digital incremental encoders with RS422-compatible A/B/N signals with a line count of up to 16,384 lines can be connected (e.g. ERN 420). In addition, Hall generator signals with a TTL level for determining the commutation position can also be connected.

| Characteristic                          | Value                                                                           |
|-----------------------------------------|---------------------------------------------------------------------------------|
| Parameterisable number of encoder lines | 1 to $2^{18}$ lines/revolution                                                  |
| Track signals A, B (Z0 track)           | In accordance with RS422<br>Input 0.4 V with a common-mode level of -0.3 to 5 V |
| Track signal N (index pulse)            | In accordance with RS422<br>Input 0.4 V with a common-mode level of -0.3 to 5 V |
| Hall generator input                    | TTL level (<0.5 V = Low, > 2 V = Hi)<br>2 k $\Omega$ pull-up                    |
| Error input (AS/NAS)                    | TTL level (<0.5 V = Low, > 2 V = Hi)<br>2 k $\Omega$ pull-up                    |
| Track signal input impedance            | Differential input ca. 400 $\Omega$                                             |
| Limit frequency                         | 10 MHz                                                                          |

### › Analogue incremental encoders with commutation signals

Analogue incremental encoders with RS422-compatible 1 V<sub>SS</sub> signals (e.g. ERN 1387) can be connected.

| Characteristic                                                           | Value                                                        |
|--------------------------------------------------------------------------|--------------------------------------------------------------|
| Parameterisable number of encoder lines                                  | 1 to $2^{18}$ lines/revolution                               |
| High position resolution of the AB track (Z0) and commutation track (Z1) | 12 bits/period                                               |
| Track signals A, B (Z0 track)                                            | 1.2 V <sub>SS</sub> differential                             |
| Track signal N (index pulse) switching threshold                         | 0.1 V <sub>SS</sub> differential                             |
| Commutation track (Z1 track)                                             | 1.2 V <sub>SS</sub> differential                             |
| Error input (AS/NAS)                                                     | TTL level (<0.5 V = Low, > 2 V = Hi)<br>2 k $\Omega$ pull-up |
| Z0 Track signal input impedance                                          | Differential input 400 $\Omega$                              |
| Z1 Track signal input impedance                                          | Differential input 100 $\Omega$                              |
| Z0 track limit frequency                                                 | $f_{\text{limit}} > 300 \text{ kHz}$                         |
| Z1 track limit frequency                                                 | $f_{\text{limit}}$ approx. 10 kHz (commutation track)        |

### > HIPERFACE® encoders

Shaft encoders with HIPERFACE® made by Sick-Stegmann are supported in the single-turn and multi-turn variants. The following encoder models can be connected:

- Single-turn SinCos encoders: SCS 60/70, SKS 36, SRS 50/60/64, SEK 34/37/52
- Multi-turn SinCos encoders: SCM 60/70, SKM 36, SRM 50/60/64, SEL 34/37/52
- Single-turn SinCos encoders for hollow shaft drives: SCS-Kit 101, SHS 170, SCK 25/35/40/45/50/53
- Multi-turn SinCos encoders for hollow shaft drives: SCM-Kit 101, SCL 25/35/40/45/50/53

In addition, the following Sick-Stegmann encoder systems can be connected and evaluated:

- Absolute, non-contact length measuring systems L230 and TTK70 (HIPERFACE®)
- Digital incremental encoder CDD 50

| Characteristic                          | Value                                                                           |
|-----------------------------------------|---------------------------------------------------------------------------------|
| Parameterisable number of encoder lines | Depending on the encoder                                                        |
| Track signals A, B (Z0 track)           | As per RS485<br>Input: 0.4 V, output: 0.8 V to 2 V                              |
| Hall generator input                    | TTL level (<0.5 V = Low, > 2 V = Hi)<br>2 kΩ pull-up                            |
| Error input (AS/NAS)                    | TTL level (<0.5 V = Low, > 2 V = Hi)<br>2 kΩ pull-up                            |
| Track signal input impedance            | Differential input 120 Ω                                                        |
| Limit frequency                         | Up to 10 MHz, depending on the encoder system                                   |
| Supported operating modes               | Storage of the parameter set in the encoder in the case of Endat and HIPERFACE® |

Angle encoders made by Sick with the HIPERFACE DSL® interface (e.g. EKM36) are also supported. They must be connected to X6 on the BL 4000-D. See section 6.6 *BL 4800-M / BL 4800-D: Motor connector [X6]* on page 75 or section 6.5 *BL 4100-M / BL 4100-D: Motor connector [X6]* on page 72.

### › EnDat encoders

Incremental and absolute encoders by Heidenhain with the ordering code ENDAT22 can be evaluated. The following encoder models can be connected:

- Analogue incremental encoders: ROD 400, ERO 1200/1300/1400, ERN 100/400/1100/1300
- Single-turn encoders (ENDAT22): ROC 425, ECI 119/1118/1319, ECN 125/425/1023
- Multi-turn encoders (ENDAT22): ROQ 437/1035, EQI 1131/1331, EQN 437/1035/1135/1337
- Absolute length measuring systems (ENDAT22): LC 115/415
- Battery-buffered encoders (ENDAT22): EBI 135/1135/4010
- Angle encoder modules (ENDAT22): MRP 2010/5010/8010

### › BiSS encoders<sup>®</sup>

Type C BiSS encoders are supported. The evaluation of the internal type plate, however, is not supported. The storage of data in the encoder is not possible.

Encoders made by Hengstler, Kübler and Balluff are supported.

## 6.8 USB [X19]

| Communication interface | Value                                  |
|-------------------------|----------------------------------------|
| Function                | USB 2.0, USB-B, slave-client           |
| Connector type          | USB-B                                  |
| Current consumption     | None (self-powered)                    |
| Protocol                | Manufacturer-specific (generic device) |

## 6.9 Fieldbus [X21], [X22]

Depending on the fieldbus variant (see section 3.1 *Type designation* on page 17), the servo drives of the device family BL 4000-M / BL 4000-D support the following fieldbuses and application protocols:

| Fieldbus | Profile                                                   | Fieldbus variant    |
|----------|-----------------------------------------------------------|---------------------|
| CAN      | CiA DS 402 CANopen V 2.0                                  | CAN                 |
| PROFINET | Manufacturer-specific protocol (based on PROFIdrive V3.1) | PROFINET / EtherCAT |
| EtherCAT | CoE (Can over EtherCAT)                                   | PROFINET / EtherCAT |

The support of these fieldbus types is integrated in the servo drive. Additional modules are not required. The parameterisation is performed with the aid of the Metronix ServoCommander<sup>®</sup>. For further information about the fieldbus connection, see the fieldbus-specific product manuals (section 1.2 *Additional documents* on page 7).

Suitable GSDML (PROFINET) and XML (EtherCAT) files for the integration of the fieldbus slave into the environment of an external control system can be found at (<https://www.metronix.de>).

**INFORMATION** Compatibility with servo drives of the ARS 2000 series

The behaviour on the bus and the object directory is largely compatible with the behaviour of the ARS 2000 series. There are certain differences, e.g. in terms of the device IDs (CANopen product\_code ID 1018\_02).

## 6.10 I/O Interface [X1]

Servo drives of the BL 4000-M / BL 4000-D series have 2 digital outputs (DOUT), 9 digital inputs (DIN), 1 analogue input (AIN) and 1 analogue output (AOUT).

### > Digital outputs

| Characteristic  | Value                                                                           |
|-----------------|---------------------------------------------------------------------------------|
| Nominal voltage | 24 V                                                                            |
| Output current  | Approx. 100 mA per output, but 900 mA max. in total, including the brake output |

### > Digital inputs

| Characteristic      | Value                                                   |
|---------------------|---------------------------------------------------------|
| Nominal voltage     | 24 V as per DIN EN 61131-2 (< 10 V low, >15..30 V high) |
| Current consumption | 3.2 mA max.                                             |

The mode of operation of the digital inputs can be configured to a large extent. The default setting is stated in brackets.

| Characteristic | Value                                      | Filter time         | Max. jitter                              |
|----------------|--------------------------------------------|---------------------|------------------------------------------|
| DIN0...DIN3    | Freely configurable (position selector)    | $4 \times t_x^{*)}$ | $1 \times t_x$                           |
| DIN4           | Freely configurable (positioning start)    | $4 \times t_x$      | $1 \times t_x$ ,<br>(15 ns for sampling) |
| DIN5           | Controller enable signal                   | $4 \times t_x$      | $1 \times t_x$                           |
| DIN6, DIN7     | Limit switch 0, 1                          | $4 \times t_x$      | $1 \times t_x$                           |
| DIN8           | Freely configurable (sampling, flying saw) | $4 \times t_x$      | $1 \times t_x$ ,<br>(15 ns for sampling) |

<sup>\*)</sup>  $t_x$  corresponds to the configurable position controller cycle time

### ➤ Analogue input AIN

| Characteristic | Value                                  |
|----------------|----------------------------------------|
| Input range    | $\pm 10\text{ V}$                      |
| Resolution     | 12 Bit                                 |
| Filter time    | configurable: $2 \times t_i$ to 200 ms |

\*)  $t_i$  corresponds to the configurable current controller cycle time

### ➤ Analogue output AOUT

| Characteristic | Value                                  |
|----------------|----------------------------------------|
| Output voltage | $\pm 10\text{ V}$                      |
| Offset         | $\pm 0.4\text{ V}$                     |
| Resolution     | 10 Bit                                 |
| Filter time    | $1 \times t_i + 85\text{ }\mu\text{s}$ |

\*)  $t_i$  corresponds to the configurable current controller cycle time

### ➤ Master frequency input [X1]

This input cannot only be used for the connection of the master frequency output of another BL 4000-C , BL 4000-M / BL 4000-D. It can also be used for the connection of encoders as per the RS422 industry standard or of encoders with "single-ended" TTL output or "open-collector" outputs. If TTL encoders are used, it must be taken into consideration that the hysteresis is negligible. In addition, the requirements concerning the signal shield must be fulfilled.

As an alternative, the A and B track signals of the device are interpreted as pulse direction signals by the device so that the servo drive can also be controlled by stepper motor control boards.

Ensure the correct configuration of the interface. This is important since the master frequency input can also be used as the master frequency output.

| Characteristic             | Value                                                    |
|----------------------------|----------------------------------------------------------|
| Parameterisable line count | 1 to $2^{28}$ lines/revolution                           |
| Track signals A, B         | As per the RS 422 specification                          |
| Maximum input frequency    | 10 MHz                                                   |
| Filtering                  | Quadruple oversampling                                   |
| Supply output              | 5 V, 200 mA, short-circuit-proof – not overvoltage-proof |

### › Master frequency output [X1]

The connector [X1] also accommodates the master frequency output (encoder emulation). To use this function, [X1] must be configured as the master frequency output.

| Characteristic     | Value                                       |
|--------------------|---------------------------------------------|
| Number of lines    | Programmable 1 to $2^{16}$ lines/revolution |
| Track signals A, B | As per the RS422 specification              |
| Limit frequency    | $f_{\text{limit}} > 10 \text{ MHz}$         |

The signals are generated based on the angle of rotation of the encoder with a freely programmable line count.

Please also note that the track signals will not be automatically output with a constant frequency. They may also be generated as so-called "pulse packets" depending on the covered rotational angle of the source. This means that the interface for any downstream circuits must be suitable for incremental encoders. As a result, the measurement of gate times or the analysis of the time between two lines for determining a speed value is possible only to a limited extent.

## 6.10.1 Time response of the digital inputs

The digital inputs are digitally filtered to improve the interference suppression. The following illustration shows the filter time mechanism. In addition, the special reaction to the "Positioning start" function is also shown. Although the signal is evaluated during the position controller cycle  $t_x$  the start of a movement will be performed within the interpolation cycle time matrix  $t_p$ .

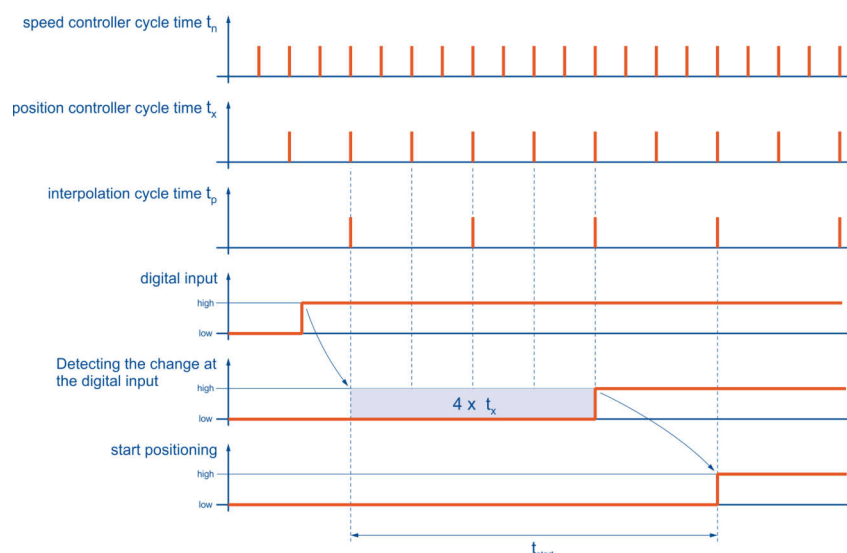


Figure 37: Filter time mechanism in the case of digital inputs

| Parameter                                                                  | Max.                  |
|----------------------------------------------------------------------------|-----------------------|
| Maximum delay until the start of a position set becomes active $t_{start}$ | $5 \cdot t_x + t_p$   |
| Current rise time (with current feedforward control)                       | $t_n + t_i + t_{pwm}$ |

$t_i$  = Current controller cycle time (typically 50  $\mu s$ )

$t_x$  = position controller cycle time (typically 200  $\mu s$  with a current controller cycle time  $t_i$  of 50  $\mu s$ )

$t_n$  = speed controller cycle time (typically 100  $\mu s$  with a current controller cycle time  $t_i$  of 50  $\mu s$ )

$t_{pwm}$  = half the cycle time of the PWM (corresponds to  $t_i$ )

## 6.10.2 Time response of the digital outputs

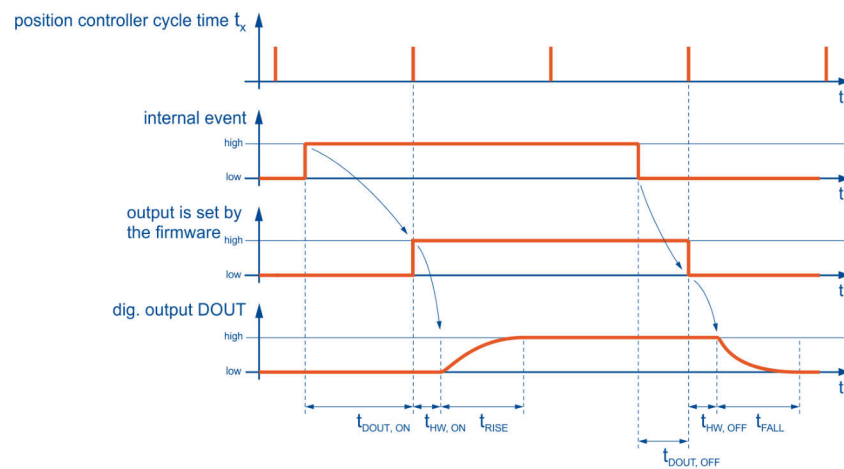


Figure 38: Filter time mechanism in the case of digital outputs

| Parameter                                                 | Value                                        |
|-----------------------------------------------------------|----------------------------------------------|
| Delay caused by the firmware $t_{DOUT\_ON}/t_{DOUT\_OFF}$ | $t_x$                                        |
| DOUT $t_{HW, ON}$                                         | typically 100 $\mu$ s                        |
| DOUT $t_{HW, OFF}$                                        | typically 300 $\mu$ s                        |
| $t_{RISE}$                                                | typically 100 ms with 2 A and inductive load |
| $t_{FALL}$                                                | typically 100 ms with 2 A and inductive load |

$t_x$  = position controller cycle time (typically 200  $\mu$ s with a current controller cycle time  $t_i$  of 50  $\mu$ s)

### 6.10.3 Time response during power ON

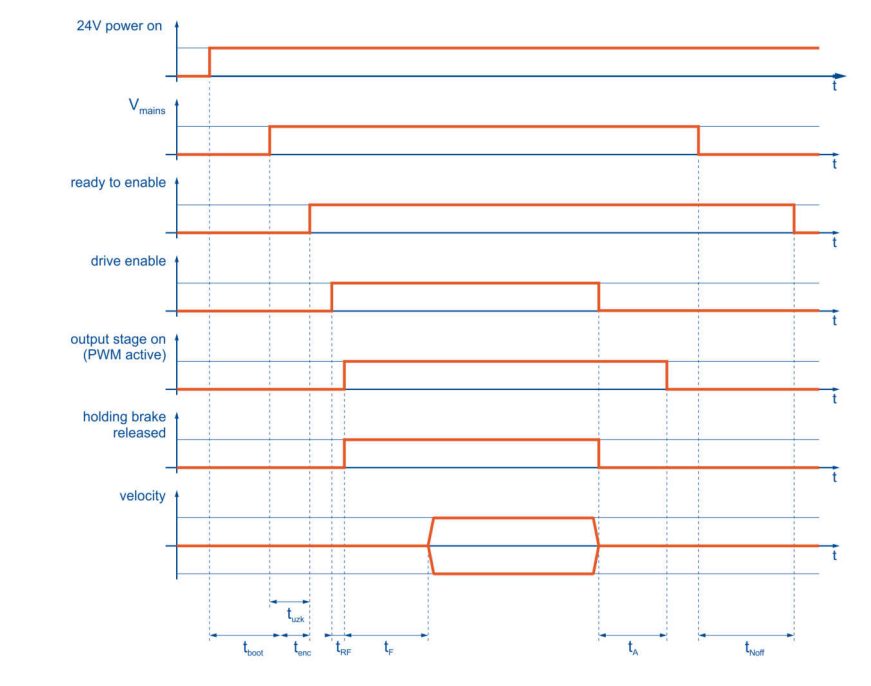


Figure 39: Time diagram of the servo drive

| Parameter                                               | Min.                | Typ.  | Max.                    |
|---------------------------------------------------------|---------------------|-------|-------------------------|
| Start of the firmware after power ON $t_{boot}$         |                     |       | 4 s                     |
| Encoder start time $t_{enc}$                            | 0.7 s<br>(resolver) |       | 2 s<br>(HIPERFACE DSL®) |
| DC bus charging time $t_{UZK}$                          |                     | 1 s   |                         |
| Output stage active after servo drive enabling $t_{RF}$ |                     | 6 ms  |                         |
| Movement start delay $t_F$ (parameterisable)            | 0                   |       | 32 s                    |
| Stop delay $t_A$ (parameterisable)                      | 0                   |       | 32 s                    |
| Detection of mains power OFF $t_{Noff}$                 |                     | 0.6 s |                         |

# 7 Storage/transport

The following requirements must be fulfilled for the storage and transport of the servo drive:

## > Storage

- Store the servo drive in line with the specified storage temperatures. Use only its original packaging.
- After approximately six months of storage, the oxide layer of the capacitors may become damaged. This is why the servo drive must be supplied with power for approximately 1 hour every six months (24 V and 230 V) in order to preserve the oxide layer.

## > Transport

### **⚠ CAUTION** Risk of injury due to improper transport

Follow these instructions to ensure the safe transport of the servo drive and to avoid injuries.

- Use only qualified personnel for the transport of the servo drive.
- Transport the servo drive only in its original packaging.
- Use only suitable transport equipment.
- Use suitable personal protective equipment.
- If you notice that the packaging is damaged, notify the carrier without delay. Then, inspect the servo drive for any signs of external or internal damage.

## > Transport damage

### **⚠ DANGER** ⚠ Dangerous electrical voltage!

Transport damage to the servo drive may compromise the insulation between the low-voltage part and the high-voltage part. This results in an extremely dangerous electrical voltage. Do not use the servo drive in this case. The servo drive needs to be checked by the sales partner or manufacturer.

In case of external damage (dents, deformed mounting flange, etc.) it must be presumed that some of the components have come loose and the breakdown strength concerning the high-voltage part may no longer be existent.

## 8 Maintenance, cleaning, repair and disposal

The following requirements must be fulfilled for the maintenance, cleaning, repair and disposal of the servo drive:

### > Maintenance

Servo drives of the BL 4000-M / BL 4000-D device series are maintenance-free.

### > Cleaning

#### **NOTICE** Damage to the servo drive due to improper cleaning

To remove surface soiling, e.g. residues of adhesive labels, the servo drive can be cleaned carefully on the outside with suitable tools. It must be absolutely ensured that liquids of any kind cannot penetrate the servo drive. Seals may be destroyed which, in turn, would lead to short circuits.

Use the servo drive in a clean environment. Soiling due to dust, oil, oil vapour, grease, fibres or similar inside the device will compromise the insulation with regard to the high-voltage part. Stop using the device immediately if this is the case.

### > Repair

Opening the device is not permissible and will render the warranty null and void. Only the manufacturer is authorised to perform repairs. Please contact your sales partner.

### > Disposal, removal, decommissioning, replacement

#### **⚠ DANGER** ⚠ Dangerous electrical voltage!

Following the instructions stated hereinbelow to ensure the safe decommissioning of the servo drive.

- Switch the power supply completely off.
- Disconnect the mains power connectors.
- Lock the system so that it cannot be reactivated.
- Make sure that the DC bus has discharged by measuring at the DC bus terminals ZK+ and ZK- or wait for the maximum discharge time. This is for the BL 4100-M / BL 4100-D **30 minutes**. For the BL 4800-M / BL 4800-D no waiting time is required. In the event of a device defect, connections other than those specified here may also carry a life-threatening voltage. Under these circumstances, the discharge time must be waited for in any case.
- Contact a sales partner in terms of a return or replacement of the device.

## 9 Appendix

### 9.1 CE conformity (EMC, RoHS, Low Voltage Directive)

#### > BL 4100-M / BL 4100-D



A company of Apex Tool Group, LLC.

# 06/2022

#### EU Konformitätserklärung

#### EU Declaration of Conformity

**Metronix Meßgeräte und Elektronik GmbH, Kocherstrasse 3, 38120 Braunschweig GERMANY**

erklärt hiermit in alleiniger Verantwortung, dass die  
Servoregler

hereby declares under sole responsibility that the  
Servo drives

**smartServo BL 4104-D, smartServo BL 4104-D CAN**  
**smartServo BL 4104-M, smartServo BL 4104-M CAN**

konform sind mit den Vorschriften der folgenden  
Richtlinien und Normen:

comply with the following directives and standards:

#### Niederspannungsrichtlinie 2014/35/EU

Angewandte harmonisierte Normen:  
**EN 61800-5-1:2007 + A1: 2017**

#### Low Voltage Directive 2014/35/EU

Applied harmonized standards:  
**EN 61800-5-1:2007 + A1:2017**

#### EMV-Richtlinie 2014/30/EU

Angewandte harmonisierte Normen:  
**EN 61800-3:2004 + A1:2012**  
**EN IEC 61800-3:2018**

#### EMC Directive 2014/30/EU

Applied harmonized standards:  
**EN 61800-3:2004 + A1:2012**  
**EN IEC 61800-3:2018**

#### RoHS Richtlinie 2011/65/EU\*

\*inklusive aller aktuell gültigen Erweiterungen  
Angewandte harmonisierte Normen:  
**EN IEC 63000:2018**

#### RoHS Directive 2011/65/EU\*

\*including all currently valid amendments  
Applied harmonized standards:  
**EN IEC 63000:2018**

#### Weitere angewandte nicht harmonisierte Normen oder sonstige Spezifikationen:

**Keine**

#### More applied non-harmonized standards or specifications:

**None**

#### Besondere Bedingungen:

Die aufgeführten Geräte sind im Sinne der EMV-  
Richtlinie keine eigenständig betreibbaren  
Produkte. Die Einhaltung der Richtlinie setzt den  
korrekten Einbau der Produkte, die Beachtung der  
spezifischen Installationshinweise und der  
Produktdokumentation voraus. Dies wurde an  
bestimmten Anlagenkonfigurationen  
nachgewiesen.

#### Specific Requirements:

According to the EMC Directive, the listed devices  
are not independently operable products.  
Compliance of the directive requires the correct  
installation of the product, the observance of the  
specific installation notes and product  
documentation. This was tested in specific system  
configurations.

Diese Erklärung bescheinigt die Übereinstimmung  
mit den genannten Richtlinien, beinhaltet jedoch  
keine Zusicherung von Eigenschaften.

This declaration certifies compliance with the stated  
Directive but implies no warranty of properties.

Die Sicherheits- und Installationshinweise der  
Produktdokumentation sind zu beachten.

The safety and installation instructions of the product  
documentation are to be considered

Ort / Place  
Datum / Date

Braunschweig  
3.3.2022

Director Sales and  
Commercial

General Manager

Unterschrift /  
Signature:

  
Olaf Donner

  
Walter Wehmeyer

FM 7.3.3-4 Vers. 2.1

## ➤ BL 4800-M / BL 4800-D



A company of Apex Tool Group, LLC.

# 05/2022

### EU Konformitätserklärung

### EU Declaration of Conformity

**Metronix Meßgeräte und Elektronik GmbH, Kocherstrasse 3, 38120 Braunschweig GERMANY**

erklärt hiermit in alleiniger Verantwortung, dass die  
Servoregler

hereby declares under sole responsibility that the  
Servo drives

**smartServo BL 4840-D, smartServo BL 4840-D CAN**  
**smartServo BL 4840-M, smartServo BL 4840-M CAN**

konform sind mit den Vorschriften der folgenden  
Richtlinien und Normen:

comply with the following directives and standards:

#### EMV-Richtlinie 2014/30/EU

Angewandte harmonisierte Normen:  
**EN 61800-3:2004 + A1:2012**  
**EN IEC 61800-3:2018**

#### EMC Directive 2014/30/EU

Applied harmonized standards:  
**EN 61800-3:2004 + A1:2012**  
**EN IEC 61800-3:2018**

#### RoHS Richtlinie 2011/65/EU\*

\*inklusive aller aktuell gültigen Erweiterungen  
Angewandte harmonisierte Normen:  
**EN IEC 63000:2018**

#### RoHS Directive 2011/65/EU\*

\*including all currently valid amendments  
Applied harmonized standards:  
**EN IEC 63000:2018**

#### Weitere angewandte nicht harmonisierte Normen oder sonstige Spezifikationen:

**Keine**

#### More applied non-harmonized standards or specifications:

**None**

#### Besondere Bedingungen:

Die aufgeführten Geräte sind im Sinne der EMV-  
Richtlinie keine eigenständig betreibbaren  
Produkte. Die Einhaltung der Richtlinie setzt den  
korrekten Einbau der Produkte, die Beachtung der  
spezifischen Installationshinweise und der  
Produktdokumentation voraus. Dies wurde an  
bestimmten Anlagenkonfigurationen  
nachgewiesen.

#### Specific Requirements:

According to the EMC Directive, the listed devices  
are not independently operable products.  
Compliance of the directive requires the correct  
installation of the product, the observance of the  
specific installation notes and product  
documentation. This was tested in specific system  
configurations.

Diese Erklärung bescheinigt die Übereinstimmung  
mit den genannten Richtlinien, beinhaltet jedoch  
keine Zusicherung von Eigenschaften.

This declaration certifies compliance with the stated  
Directive but implies no warranty of properties.

Die Sicherheits- und Installationshinweise der  
Produktdokumentation sind zu beachten.

The safety and installation instructions of the product  
documentation are to be considered

Ort / Place  
Datum / Date

Braunschweig  
3.3.2022

Director Sales and  
Commercial

General Manager

Unterschrift /  
Signature:

  
Olaf Donner

  
Walter Wehmer

FM 7.3.3-4 Vers. 2.1

## 9.2 CE conformity (Machinery Directive)

### ➤ BL 4000-M / BL 4000-D



A company of Apex Tool Group, LLC.

#4/2022

#### EG Konformitätserklärung

#### EC Declaration of Conformity

**Metronix Meßgeräte und Elektronik GmbH, Kocherstrasse 3, 38120 Braunschweig GERMANY**

erklärt hiermit in alleiniger Verantwortung, dass das Sicherheitsmodul

hereby declares under sole responsibility that the safety module

##### Sicherheitsfunktion STO

innerhalb der Servoregler

smartServo BL 4104-M  
smartServo BL 4840-M  
smartServo BL 4104-D  
smartServo BL 4840-D  
smartServo BL 4104-M CAN  
smartServo BL 4840-M CAN  
smartServo BL 4104-D CAN  
smartServo BL 4840-D CAN

##### Safety function STO

within the servo drives

smartServo BL 4104-M  
smartServo BL 4840-M  
smartServo BL 4104-D  
smartServo BL 4840-D  
smartServo BL 4104-M CAN  
smartServo BL 4840-M CAN  
smartServo BL 4104-D CAN  
smartServo BL 4840-D CAN

konform ist mit den Vorschriften der folgenden Richtlinien und Normen:

complies with the following directives and standards:

##### Maschinenrichtlinie 2006/42/EG

Angewandte harmonisierte Normen:

EN 61800-5-2:2017  
max. SIL 3  
(Sicherheitsfunktionen siehe Betriebsanleitung)  
EN 62061:2005+AC:2010+A1:2013+A2:2015  
max. SIL CL 3  
(Sicherheitsfunktionen siehe Betriebsanleitung)  
EN ISO 13849-1:2015  
max. Kategorie 4  
PL e  
(Sicherheitsfunktionen siehe Betriebsanleitung)  
IEC 61508 Teil 1-7:2010  
max. SIL 3  
(Sicherheitsfunktionen siehe Betriebsanleitung)

##### Machinery Directive 2006/42/EC

Applied harmonized standards:

EN 61800-5-2:2017  
max. SIL 3  
(safety functions see manual)  
EN 62061:2005+AC:2010+A1:2013+A2:2015  
max. SIL CL 3  
(safety functions see manual)  
EN ISO 13849-1:2015  
max. Category 4  
PL e  
(safety functions see manual)  
IEC 61508 Parts 1-7:2010  
max. SIL 3  
(safety functions see manual)

##### Konformitätsbewertung

Das bezeichnete Produkt verfügt über die integrierten Sicherheitsfunktionen STO. Es wird bestätigt, dass der Prüfgegenstand mit den Anforderungen nach Anhang I der Richtlinie 2006/42/EG über Maschinen übereinstimmt.

##### Benannte Stelle

TÜV Rheinland Industrie Service GmbH  
Certification Body for Machinery, NB 0035  
Alboinstrasse 56  
12103 Berlin / Germany

Zertifikat:  
01/205/5701.00/19

Gültigkeit  
31.01.2024

##### Conformity Assessment

The designated product offers the integrated safety functions STO. It is confirmed, that the product under test complies with the requirements for machines defined in Annex I of the EC Directive 2006/42/EC.

##### notified body

TÜV Rheinland Industrie Service GmbH  
Certification Body for Machinery, NB 0035  
Alboinstrasse 56  
12103 Berlin / Germany

Certificate:  
01/205/5701.00/19

Date of expiry  
2024-01-31



A company of Apex Tool Group, LLC.

#4/2022

**Weitere angewandte nicht harmonisierte Normen oder sonstige Spezifikationen:**  
keine

**More applied non-harmonized standards or specifications:**  
None

**Besondere Bedingungen:**

Diese Erklärung bescheinigt die Übereinstimmung mit den genannten Richtlinien, beinhaltet jedoch keine Zusicherung von Eigenschaften.

Die Sicherheits- und Installationshinweise der Produktdokumentation sind zu beachten.

Die Produkte sind bestimmt zum Einbau in Maschinen. Die Inbetriebnahme ist solange untersagt bis festgestellt wurde, dass die Maschine, in welche diese Produkte eingebaut werden sollen, den Bestimmungen der o.g. EG Richtlinie entsprechen.

**Specific Requirements:**

This declaration certifies compliance with the stated Directive, but implies no warranty of properties.

The safety and installation instructions of the product documentation are to be considered

These products are intended for installation in machines. Operation is prohibited until it has been determined that the machines in which these products are to be installed, conforms to the above mentioned EC Directive.

Ort / Place ..... Braunschweig .....

Datum / Date ..... 3.3.2022 .....

**Director Sales and  
Commercial**

**General Manager**

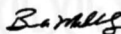
Unterschrift /  
Signature:

  
.....  
Olaf Donner

  
.....  
Walter Wehmeyer

## 9.3 cURus certification

### ➤ BL 4000-M / BL 4000-D

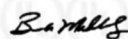
| CERTIFICATE OF COMPLIANCE                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 |                                                                                                                                                                                                                                                                                                                                                  |
|---------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|--------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------------|
| <b>Certificate Number</b>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                 | UL-US-2128204-0                                                                                                                                                                                                                                                                                                                                  |
| <b>Report Reference</b>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                   | E219816-20210527                                                                                                                                                                                                                                                                                                                                 |
| <b>Date</b>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                               | 7-Jun-2021                                                                                                                                                                                                                                                                                                                                       |
| <b>Issued to:</b>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                         | Metronix Messgeraete und Elektronik GmbH<br>Kocherstr. 3 Braunschweig<br>Germany 38120                                                                                                                                                                                                                                                           |
| <b>This is to certify that representative samples of</b>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                  | NMMS2 - Power Conversion Equipment - Component<br>See Addendum Page for Product Designation(s).                                                                                                                                                                                                                                                  |
|                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                           | Have been investigated by UL in accordance with the component requirements in the Standard(s) indicated on this Certificate. UL Recognized components are incomplete in certain constructional features or restricted in performance capabilities and are intended for installation in complete equipment submitted for investigation to UL LLC. |
| <b>Standard(s) for Safety:</b>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                            | UL 61800-5-1, 1st Ed., Issue Date: 2012-06-08, Revision Date: 2018-06-20                                                                                                                                                                                                                                                                         |
| <b>Additional Information:</b>                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                                            | See the UL Online Certifications Directory at <a href="https://iq.ulprospector.com">https://iq.ulprospector.com</a> for additional information                                                                                                                                                                                                   |
| <p>This <i>Certificate of Compliance</i> does not provide authorization to apply the UL Recognized Component Mark. Only the UL Follow-Up Services Procedure provides authorization to apply the UL Mark.</p> <p>Only those products bearing the UL Recognized Component Mark should be considered as being UL Certified and covered under UL's Follow-Up Services.</p> <p>Look for the UL Recognized Component Mark on the product.</p>                                                                                                                                                                                                                                                                                                                                   |                                                                                                                                                                                                                                                                                                                                                  |
| <div style="display: flex; justify-content: space-between; align-items: flex-end;"> <div style="text-align: left;"> <br/> <small>Bruce Mahrenholz, Director North American Certification Program<br/>UL LLC</small> </div> <div style="text-align: right;">  </div> </div> <p><small>Any information and documentation involving UL Mark services are provided on behalf of UL LLC (UL) or any authorized licensee of UL. For questions, please contact a local UL Customer Service Representative at <a href="http://ul.com/aboutul/locations/">http://ul.com/aboutul/locations/</a></small></p> |                                                                                                                                                                                                                                                                                                                                                  |

# CERTIFICATE OF COMPLIANCE

**Certificate Number** UL-US-2128204-0  
**Report Reference** E219816-20210527  
**Date** 7-Jun-2021

This is to certify that representative samples of the product as specified on this certificate were tested according to the current UL requirements

| Model                 | Category Description       |
|-----------------------|----------------------------|
| smartServo, BL 4104-D | Power Conversion Equipment |
| smartServo, BL 4104-M | Power Conversion Equipment |
| smartServo, BL 4840-D | Power Conversion Equipment |
| smartServo, BL 4840-M | Power Conversion Equipment |



Bruce Mahrenholz, Director North American Certification Program

UL LLC

Any information and documentation involving UL Mark services are provided on behalf of UL LLC (UL) or any authorized licensee of UL. For questions, please contact a local UL Customer Service Representative at <http://ul.com/aboutul/locations/>



## CERTIFICATE OF COMPLIANCE

Certificate Number UL-CA-2123280-0  
Report Reference E219816-20210527  
Date 7-Jun-2021

Issued to: Metronix Messgeraete und Elektronik GmbH  
Kocherstr. 3 Braunschweig  
Germany 38120

**This is to certify that  
representative samples of**

NMMS8 - Power Conversion Equipment Certified for  
Canada - Component

See Addendum Page for Product Designation(s).

Have been investigated by UL in accordance with the  
component requirements in the Standard(s) indicated on  
this Certificate. UL Recognized components are incomplete  
in certain constructional features or restricted in  
performance capabilities and are intended for installation in  
complete equipment submitted for investigation to UL LLC.

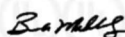
Standard(s) for Safety: CSA C22.2 NO. 274, 2nd Ed., Issue Date: 2017-04-01,  
Revision Date: 2017-04-01

Additional Information: See the UL Online Certifications Directory at  
<https://iq.ulprospector.com> for additional information

This *Certificate of Compliance* does not provide authorization to apply the UL Recognized Component Mark.  
Only the UL Follow-Up Services Procedure provides authorization to apply the UL Mark.

Only those products bearing the UL Recognized Component Mark should be considered as being UL Certified  
and covered under UL's Follow-Up Services.

Look for the UL Recognized Component Mark on the product.



Bruce Mahrenholz, Director North American Certification Program

UL LLC

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contact a local UL Customer Service Representative at <http://ul.com/about/locations/>

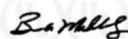


## CERTIFICATE OF COMPLIANCE

**Certificate Number** UL-CA-2123280-0  
**Report Reference** E219816-20210527  
**Date** 7-Jun-2021

This is to certify that representative samples of the product as specified on this certificate were tested according to the current UL requirements

| Model                 | Category Description       |
|-----------------------|----------------------------|
| smartServo, BL 4104-D | Power Conversion Equipment |
| smartServo, BL 4104-M | Power Conversion Equipment |
| smartServo, BL 4840-D | Power Conversion Equipment |
| smartServo, BL 4840-M | Power Conversion Equipment |



Bruce Mahrenholz, Director North American Certification Program

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