Datasheet

ORLIN Controller

The new ORLIN Technologies controller can be operated as a fully programmable stand-alone servo controller with its powerful scripting language (based on Python), or as a slave drive to a master PLC or motion controller over a choice of several industry standard fieldbuses.

Forthcoming versions will be available to drive brushed DC, BLDC servo motors, moving coil actuators (single and multi-phase) and stepper motors. Fieldbuses will include EtherCAT, Profibus, Profinet, CANopen and Modbus, along with RS232

Technical Data (EtherCAT version)

Power	
Electronic supply voltage Ue	9..30 V
Electronic current consumption @ Ue=24V (Bus not connected)	typ. 50 mA
Power supply voltage Up	9..60 V
Max. output current	15 A
Continuous output current	5 A
Output voltage	90% Up
PWM frequency	25, 32*, 50 kHz
Min. load inductance	200 uH

Incremental encoder	
Type	incremental
Signals	A, A/, B, B/, I, I/
Max. frequency (per channel)	100 kHz
Input voltage	5 V
Signal type	Line driver, differential
Max. frequency (per channel)	100 kHz

Hall sensors	
Signals	H1, H2, H3
Max. frequency (per channel)	10kHz
Input voltage	5 V
Signal type	open collector, single ended
Max. frequency (per channel)	10 kHz

Digital inputs	
Number	3 (Din0..2)
Low voltage	-10..5 V
High voltage	6..30 V
Note:	Din2 shared with Dout0

Digital outputs	
Number	1 (Dout 0)
Continuous output current	1.5 A
Load	resistive, inductive
Output voltage	Electronic supply voltage Ue
Signal type	positive switching
Note:	Dout0 shared with Din2

Analog inputs	
Number	1 (Ain0)
Signal type	0..10 V, 12 Bit, single ended

CAN bus	
Protocol	DS301
Device profile	DS402
Max. baudrate	1 Mbit/s
CAN specification	2.0B
Galvanically isolated	no

EtherCAT	
Type	EtherCAT Slave
Physical layer	100 Base-Tx EtherCAT
Bus controller	ET1100
Max. baudrate	100 Mbit/s
Number of ports	2xRJ45 (In,Out)
Protocol	CoE (CANopen over EtherCAT)