

CONTROLLERS		UNIT	EA-P2M-400-05/10A	EA-P2M-400-10/20A	EA-P2M-400-15/40A
Number of axes		-	2	2	2
Current range	Continuous current (per axis)	Arms	5	10 (PWM at 10 kHz)	15 (PWM at 10 kHz)
	Max. overload current (per axis)	Arms	10	20	40
Power input	DC voltage	VDC	48 - 400	48 - 400	48 - 400
	Max. current	Arms	30	30	30
PWM frequency		kHz	10, 20	10, 20	10, 20
Weight		kg	3.3	3.3	4

POWER SUPPLY		UNIT	EA-S0M-400-40/80A
Power input	AC voltage (single or 3-phases)	VAC	71 - 280 (50 / 60Hz)
	Max. AC current	A	10
	Max. inrush current	Apeak	15 at 280 VAC
	Max. continuous power	kW	2.8 (with 1-phase AC input) or 4.8 (with 3-phase AC input)
Auxiliary input	DC voltage	VDC	24 (0 +10%)
	Max. current	A	10
Power output	DC voltage	VDC	100 - 400
	Max. continuous current	Arms	10 (limited by max. AC input current)
	Max. pulse current	A	80
Auxiliary output	DC voltage	VDC	24 ± 10%
	Max. continuous current	A	10

CONTROL FEATURES		UNIT	
General	Motion profile and command management sampling time	µs	500
	Current loop sampling time	µs	50
	Position loop sampling time	µs	50
	Basic motion profiles	-	Trapezoidal, S-curve, Sine, Look-up table, ...
	CANopen motion profiles	-	Cyclic Synchronous Position (CSP), Profile Position (PP), Homing
	Power safety relay	-	Relay disabling the output power bridge
	Communication interface	Protocol	-
EtherCAT cycle time		µs	500 (up to 4000)
USB 2.0 (for setting only)		-	Full speed (12 Mbps)
Position encoder interface	Analog 1 Vpp	-	Max. 500 kHz input frequency
	Digital (TTL)	-	Max. 10 MHz input frequency
	EnDat 2.1 and 2.2	-	RS485
User's inputs / outputs	Digital inputs / outputs	-	5 / 2 (per axis)
	Fast digital inputs / outputs	-	4 / 4 (common to both axes)
	Analog inputs / outputs	-	0 / 0
Software / programmability	ComET commissioning software	-	For setting / monitoring (for software compatibility, refer to the ComET manual)
	ESI configuration files	-	Available within ComET install
	Firmware update	-	USB

ADVANCED FEATURES	
Identification tools	Powerfull indentification tool for fine tuning and machine performance evaluation.
Stage protection	Safety algorithm to handle very fast and controlled axis stop.
Cogging and friction compensation	Learning algorithm to compensate disturbances like friction and cogging.
Dual encoder feedback	Optimized management of dual encoder feedback on a single axis.
Trajectory filters	Advanced trajectory shapes to avoid axis vibrations and reduce settling times.
EtherCAT touch probe function	Fast position capture based on user defined triggers.

