



Product description

Characteristics

- Supplies low resolution signals to an external control unit
- Embedded in the rotor bearing
- Cannot be combined with the electromagnetic brake option

Application

- For applications which require the continuous control of the speed, direction, and position of the Motorized Pulley belt or load



Technical data

Rated voltage	From 5 to 24 VDC
Max.operated current	From 8 to 10 mA
Max.output current	20 mA
High level voltage	> 3.5 V
Low level voltage	<0.1 V

INC resolution

The INC resolution (number of increments per pulley revolution) depends on encoder type and can be calculated as follows:

$$INC = Z \times i$$

i Gear ratio of the Motorized Pulley (except for model 80LS). Gear ratio of 80LS equals one because encoder is mounted on end housing and not on motor rotor.

Z Number of encoder increments per rotor revolution

Product range

Motorized Pulley	Bearing type	Increments per rotor revolution
from 80LS to 138LS	6202	32
165LS	6205	48

Note: The Motorized Pulley 80LS with encoder has 2 cables-one exiting through each shaft at either end.



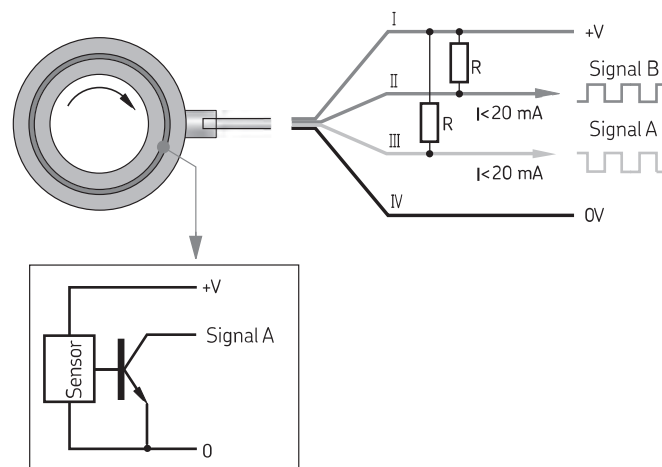
Encoders: SKF Bearing

Control interface

The encoder has open collector NPN transistor outputs. When connected to the input of a control interface the required load resistances (R) have to be used. The load resistances are stated in the table below. When using different interfaces or when you have any doubts, please contact Rulmeca or a local electronic specialist.

Rulmeca recommends the use of an Opto-coupler for the following reasons:

- To protect the encoder
- To enable connection to other levels such as PNP
- To get the maximum potential between high and low signal



Voltage +VDC	Load Resistances R (ohms) Ω
5	270
9	470
12	680
24	1500