

# Absolute Encoder Configuration

Endat2.2

BissC



## Application Note



[www.agito-akribis.com](http://www.agito-akribis.com)

Member of Akribis Systems group



## Revision History

Version	Description	Date
1.0	Initial Release	6 December 2021

## Contact Information

Manufacturer	Agito Akribis Systems Ltd., Member of Akribis Systems Group
Address	6 Yad-Harutsim St., P.O.Box 7172, Kfar-Saba 4464103
Telephone	+972-9-8909797
Website	www.agito-akribis.com

## Copyright Notice

©2022 Agito Akribis Systems Ltd.

All rights reserved. This work may not be edited in any form or by any means without written permission of Agito Akribis Systems Ltd.

## Products Rights

AGDx, AGCx, AGMx, AGAx, AGIx, and AGLx are products designed by Agito Akribis Systems Ltd. in Israel. Sales of the products are licensed to Akribis Systems Pte Ltd. under intercompany license agreement.

Agito Akribis Systems Ltd. has full rights to distribute above products worldwide.

## Disclaimer

This product documentation was accurate and reliable at the time of its release.

Agito Akribis Systems Ltd. reserves the right to change the specifications of the product described in this manual without notice at any time.

## Trademarks

Agito PCSuite is a trademark of Agito Akribis Systems Ltd..

## Warranty

This product is warranted to be free of defects in material and workmanship and conforms to the specifications listed in this manual, for a period of 12 months from the shipment date from factory.

## Contents

1	Introduction	4
1.1	Scope	4
2	Configuration	5
2.1	PCSuite Configuration	5

# 1 Introduction

---

## 1.1 Scope

---



This document seeks to explain how to configure absolute encoders using Agito PCSuite. In particular, it explains a method of trial and error to obtain the encoder's resolution (number of bits). The wiring details will not be discussed in this document, please refer to the hardware manual for this information.

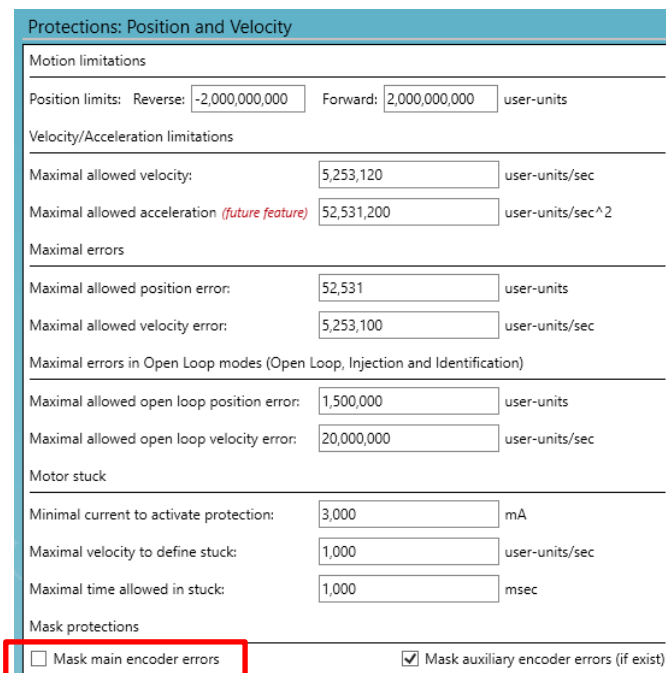
## 2 Configuration

### 2.1 PCSuite Configuration

Firstly, ensure that the controller is not masking the main encoder error. This will allow for encoder faults to be detected. In the case of absolute encoders, encoder fault will be reported if the encoder is disconnected, if the encoder read head is not detecting the scale or if the CRC checksum does not match the position data.





To do so, launch PCSuite and connect the controller. Navigate to  tab and then  page. Ensure that the  Mask main encoder errors checkbox is not checked.



Protections: Position and Velocity	
Motion limitations	
Position limits: Reverse:	-2,000,000,000 user-units
Forward:	2,000,000,000 user-units
Velocity/Acceleration limitations	
Maximal allowed velocity:	5,253,120 user-units/sec
Maximal allowed acceleration (future feature)	52,531,200 user-units/sec^2
Maximal errors	
Maximal allowed position error:	52,531 user-units
Maximal allowed velocity error:	5,253,100 user-units/sec
Maximal errors in Open Loop modes (Open Loop, Injection and Identification)	
Maximal allowed open loop position error:	1,500,000 user-units
Maximal allowed open loop velocity error:	20,000,000 user-units/sec
Motor stuck	
Minimal current to activate protection:	3,000 mA
Maximal velocity to define stuck:	1,000 user-units/sec
Maximal time allowed in stuck:	1,000 msec
Mask protections	
<input type="checkbox"/> Mask main encoder errors	<input checked="" type="checkbox"/> Mask auxiliary encoder errors (if exist)

Figure 1. Screen capture of Protections: Position and Velocity Menu page.



Next, configure the protocol and set the number of bits. Navigate to  tab  page. Set **EncType** for the protocol you are using (3 -Endat2.2, 6 – BissC). Set **EncAbsBits** according to the resolution of the encoder. In the future, this information can be read by the controller. But for now, it has to be input manually. To know the number of bits, check the encoder datasheet or with the manufacturer. Alternatively, this value can be obtained via trial and error which will be explained below.

To obtain the number of bits through brute force, simply iterate through the values of **EncAbsBits** while observing the second bit of **HWProtectBits**. If the bit is on, and assuming there are no faults with the wiring, it means that **EncAbsBits** is set wrongly and therefore the CRC checksum is not adding up.

An easy way to check for this would be to open a status window and change the bits at the side. In PCSuite, use **Alt + Shift + S** to open the status window. Click on the **HW Protect. (1)** tab and observe if the **Main enc. err.** indicator is lighted up. Start by setting the highest value possible and slowly decrease the value down to the minimum. At a particular value, the error should go off; this indicates that the value is correct and the CRC checksum adds up.

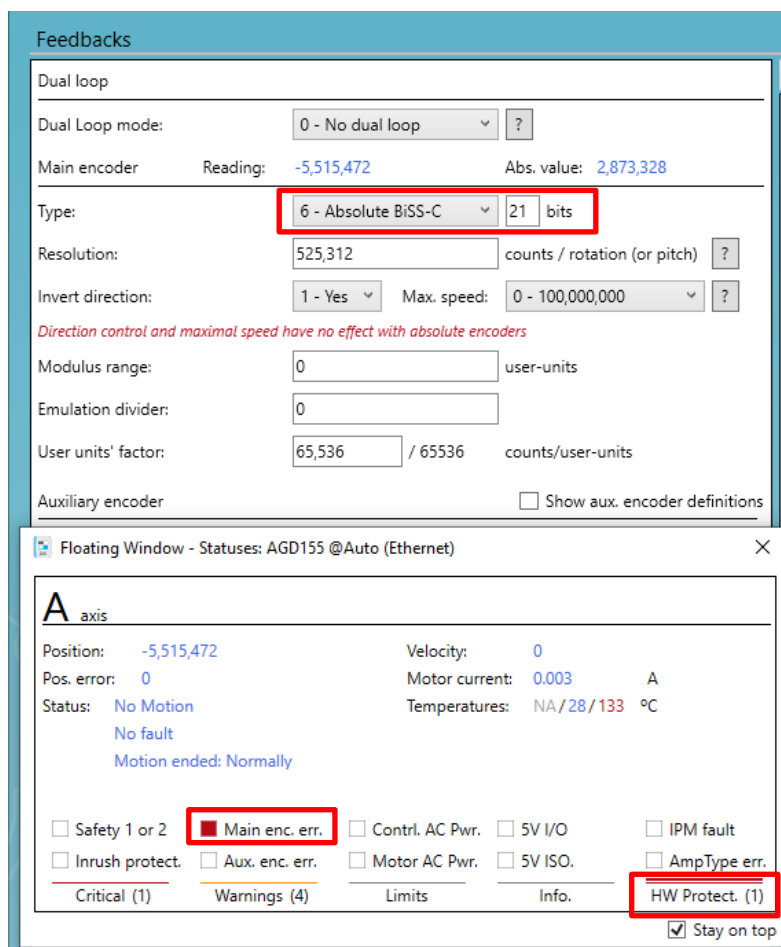


Figure 2. Screen capture of Feedbacks Menu page with Floating Status window.



**Note – Corner case when main encoder error does not trigger**

There are corners cases when the CRC might not report an error at certain positions, in the case where the bits are set 6 less than supposed number of bits. E.g. if the bits are supposed to be 22 and in the software it is set to 16, the CRC might pass at certain positions.

## *PCSuite Configuration*



Lastly, configure the remain parameters **EncRes**, **EncDir** and **EncFilt** as you would with an incremental encoder and the setup is done.

