NR25
Networked Resolver
**Important User Information**

The products and application data described in this manual are useful in a wide variety of different applications. Therefore, the user and others responsible for applying these products described herein are responsible for determining the acceptability for each application. While efforts have been made to provide accurate information within this manual, AMCI assumes no responsibility for the application or the completeness of the information contained herein.

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**We Want Your Feedback**

Manuals at AMCI are constantly evolving entities. Your questions and comments on this manual are both welcomed and necessary if this manual is to be improved. Please direct all comments to: Technical Documentation, AMCI, 20 Gear Drive, Terryville CT 06786, or fax us at (860) 584-1973. You can also e-mail your questions and comments to techsupport@amci.com
TABLE OF CONTENTS

GENERAL INFORMATION
Important User Information ..................... 2
Standard Warranty ............................... 2
Returns Policy .................................... 2
24 Hour Technical Support Number .......... 2
We Want Your Feedback ....................... 2

Table of Contents
About this Manual
Audience ........................................... 7
Applicable Units ................................. 7
Navigating this Manual ......................... 7
Manual Conventions ............................ 8
Trademarks and Other Legal Stuff .......... 8
Revision Record .................................. 8
Revision History ................................. 8
Where to Go From Here ....................... 9

Chapter 1: Introduction to the NR25
Overview .......................................... 11
Electrical Specifications ....................... 12
Mechanical Specifications ..................... 12
Environmental Specifications ................ 12
Parallel Output Option ......................... 13
Part Number Description ....................... 13
Available Data ................................... 13
Programmable Parameters .................... 14
  Direction Counting Toggle .................. 14
  Scaling Function Control .................... 14
  Counts per Turn ................................ 14
  Preset Value ................................... 14
  Velocity Format ............................... 15
  Device Type ................................... 15
Calculating Position and Velocity Data .... 15
Total Measurement Range
  Parameter (Rev. 2.3+) ....................... 16
  Storage of Internal Position Offset .... 16
  Roll Over on Fractional Travel .......... 17
  Quasi-Absolute Multi-turn ............... 18
Effects of Reversing Count Direction ..... 18

Chapter 2: Installation
2.5” Servo Mount Outline Drawing ........ 19
  Aluminum Body, End Connect ............ 19
  Aluminum Body, Side Connect .......... 19
  Stainless Steel Body,
    End Connect ............................... 20
  Stainless Steel Body,
    Side Connect ............................. 20
  Alternate Shafts ............................. 21
  Shaft Loading ................................ 21
58 mm Servo Mount Outline Drawing ..... 22
  Aluminum Body, End Connect ............ 22
  Aluminum Body, Side Connect .......... 22
  Stainless Steel Body,
    End Connect ................................ 23
  Stainless Steel Body,
    Side Connect ............................. 23
  Shaft Details ................................ 24
  Shaft Loading ................................ 24
Flange Mount Outline Drawings ............ 25
  Aluminum Body, End Connect ............ 25
  Aluminum Body, Side Connect .......... 25
  Stainless Steel Body,
    End Connect ................................ 26
  Stainless Steel Body,
    Side Connect ............................. 26
  Alternate Shafts ............................. 27
  Shaft Loading ................................ 27
  5/8" Shaft, Aluminum Body,
    End Connect ............................... 28
  5/8" Shaft, Aluminum Body,
    Side Connect ................................ 29
  5/8" Shaft, Stainless Steel Body,
    End Connect ............................... 30
  5/8" Shaft, Stainless Steel Body,
    Side Connect ................................ 31
  Shaft Loading ................................ 31
Hub Shaft Mount Outline Drawings ......... 32
  Aluminum Body, End Connect ............ 32
  Aluminum Body, Side Connect .......... 33
  Stainless Steel Body,
    End Connect ............................... 34
  Stainless Steel Body,
    Side Connect ................................ 35
  Available Shaft Diameters ................ 35
  Shaft Loading ................................ 35
TABLE OF CONTENTS

Chapter 2: Installation
End View .................................................. 36
Status LED’s ............................................. 36
  Network Status LED ................................. 36
  Module Status LED ................................. 36
  Link/Activity LED .................................... 36
Connector Pinout ...................................... 37
  TIA/EIA-568 Color Codes ..................... 37
Compatible Connectors and Cordsets ...... 37
  Power Connector and Cordset ............. 38
  Ethernet Connector and Cordset .... 38
Power over Ethernet (PoE) ....................... 38

Chapter 3: NR25 Configuration
Factory Default ........................................ 40
Assumptions ........................................... 40
Firewalls ............................................... 40
Download the AMCI Net Configurator Software ........ 40
Configure Your Network Interface Card (NIC) .......... 40
Attach the NR25 ..................................... 42
Using the AMCI Net Configurator ................. 43
  Start the Software .......................... 43
  Scanning for your NR25 Encoder ........ 44
  Manually Connecting to your NR25 .... 45
The Meaning of the Product Name ............. 45
Changing the IP Address ..................... 46
Setting Communications Protocol ............ 47
Cycle Power to the NR25 ................ 47
Testing the New Address ............... 47
NR25 Tab ...................................... 47
Using the Ping Command .................... 48

Chapter 4: RSLogix 5000 EtherNet/IP Configuration (cont’d)
Configuring the NR25 ....................... 52
  The NR25 Must be Configured .......... 52
  Assembly Instance = 102 .......... 52
  Assembly Instance = 103
    (revision 2.3+ only) ..................... 53
  Module Fault Code 16#0110 .......... 54
Reading Data from the NR25 ............... 54
  Buffering Read Data ..................... 54
  Assembly Instance = 1 ............... 55
  Assembly Instance = 3 ............... 55
  Assembly Instance = 104 .......... 55
  Assembly Instance = 105 .......... 56
Writing Data to the NR25 .................... 56
  Presetting the Position Value .... 56
  Storing Configuration Data and the Internal Position Offset .......... 57

Chapter 5: RSLogix 5000 EtherNet/IP Configuration
Explicit Messaging ............................... 59
RSLogix 5000 Configuration ..................... 59
  Configuring a Built-in Ethernet Port .......... 59
Read Data Format ............................... 60
  Assembly Instance = 1 ................ 60
  Assembly Instance = 3 ................ 60
  Assembly Instance = 104
    (revision 2.3+ only) ..................... 61
  Assembly Instance = 105
    (revision 2.3+ only) ..................... 61
Write Data Format ............................... 61
  Assembly Instance = 102 ............ 62
  Assembly Instance = 103
    (revision 2.3+ only) ..................... 63
Presetting the Position Value ............ 64
Saving Configuration Data and Position Offset .......... 64
Determining Needed Registers ............ 65
# TABLE OF CONTENTS

## Chapter 5: RSLogix 500 EtherNet/IP Configuration (cont’d)
- Configuring a Message Instruction .......... 66
- Read Message Instructions ............... 67
- Write Configuration
  - Message Instructions .................... 68
- Apply Preset Message
  - Instruction .................................. 70
- Save Configuration and Offset
  - Message Instruction ...................... 71
- Setting the MultiHop Address ...... 72
- Troubleshooting Message Instructions ... 72
- Configuration Error Response ....... 72

## Chapter 6: Modbus TCP Configuration
- NR25 Memory Layout .......................... 73
- Supported Modbus Functions .................. 73
- Supported Modbus Exceptions ............... 74
- Multi-Word Format ............................. 74
- Output Data Format ............................ 74
  - Command Word ............................. 75
  - Configuration Word .......................... 76
- Input Data Format ............................. 76

## Appendix A: IP Address Setup with Bootp
- Initial Configuration .......................... 77
- Start Your Bootp Server .................... 77
- Set the Default Gateway Address .......... 77
- Changing the IP Address .................... 78
  - Enabling Bootp Protocol .................. 78
  - Setting the IP Address .................... 79
  - Disabling the Bootp Protocol .......... 79
- Testing the New IP Address ............... 80
- Continue with Chapter 3 .................... 80

## Appendix B: CIP Position Sensor Object
- Common Industrial Protocol ................. 81
- Supported Services ........................... 81
- Supported Class Attributes ................. 81
- Supported Instance Attributes ............. 82
- Supported Alarms ............................ 83

## Appendix C: Parallel Output Option
- Outline Drawings ............................. 85
  - 2.5" Servo Mount .......................... 85
  - 58 mm Servo Mount ....................... 86
  - Flange Mount .............................. 86
  - 5/8" Shaft, Flange Mount ................. 87
  - Hub Shaft Mount ......................... 88
- Connector Pin Out ........................... 89
- Specifications ............................... 90
Notes
ABOUT THIS MANUAL

Read this chapter to learn how to navigate through this manual and familiarize yourself with the conventions used in it. The last section of this chapter highlights the manual’s remaining chapters and their target audience.

Audience

This manual explains the installation and operation of AMCI’s NR25 Networked Resolver encoders. It is written for the engineer responsible for incorporating the NR25 into a design as well as the engineer or technician responsible for its actual installation. If there are any unanswered questions after reading this manual, call the factory. An applications engineer will be available to assist you.

Applicable Units

This manual is applicable to all Ethernet NR25 units with firmware revisions 1.4 through 2.3. Important changes to the units based on firmware revisions are listed below.

Revision 1.4 and below: These units only support the EtherNet/IP protocol and their IP addresses must be set with a Bootp server. Instructions for using the Bootp server from Rockwell Automation can be found in Appendix A, starting on page 77. The AMCI Net Configurator software can be used to set the remaining parameter of the NR25.

Revisions 1.5 and 1.6: These units only support the EtherNet/IP protocol but you have the ability to set the IP address of the NR25 by using the AMCI Net Configurator software.

Revision 1.7, 1.8, and 1.9: NR25 units now support both the EtherNet/IP and Modbus TCP protocols. The factory default is EtherNet/IP. These units can be scanned by the AMCI Net Configurator software to determine the IP address of the NR25 as long as your computer and the NR25 are on the same subnet.

Revision 2.3: NR25 units now have one additional parameter, Total Measuring Range and two additional data values, Time Stamp and Actual Sensor Reading. Revision 2.3 units are backwards compatible with older NR25 Ethernet encoders. They can be used to replace all older NR25 units without changes to your system.

Navigating this Manual

This manual is designed to be used in both printed and on-line forms. Its on-line form is a PDF document, which requires Adobe Acrobat Reader version 7.0+ to open it. If you decide to print out this manual, all chapters contain an even number of pages which allows you to easily print out a single chapter on a duplex (two-sided) printer.

Bookmarks of all the chapter names, section headings, and sub-headings are in the PDF file to help you navigate through it. The bookmarks should have appeared when you opened the file. If they didn’t, press the F5 key on Windows platforms to bring them up. Throughout this manual you will also find blue text that functions as a hyperlink in HTML documents. Clicking on the text will immediately jump you to the referenced section of the manual. If you are reading a printed manual, most links include page numbers.

The PDF file is password protected to prevent changes to the document. You are allowed to select and copy sections for use in other documents and, if you own Adobe Acrobat version 7.0 or later, you are allowed to add notes and annotations.
Manual Conventions

Three icons are used to highlight important information in the manual:

- **NOTES** highlight important concepts, decisions you must make, or the implications of those decisions.
- **CAUTION** tell you when equipment may be damaged if the procedure is not followed properly.
- **WARNING** tell you when people may be hurt or equipment may be damaged if the procedure is not followed properly.

The following table shows the text formatting conventions:

<table>
<thead>
<tr>
<th>Format</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>Normal Font</td>
<td>Font used throughout this manual.</td>
</tr>
<tr>
<td>Emphasis Font</td>
<td>Font used for parameter names and the first time a new term is introduced.</td>
</tr>
<tr>
<td>Cross Reference</td>
<td>When viewing the PDF version of the manual, clicking on the cross reference text jumps you to referenced section or section of the AMCI website if you have Internet access.</td>
</tr>
</tbody>
</table>

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Revision Record

This manual, 940-0D094 is the fifth release of this manual. It was first released on October 1st, 2015. It adds information on the optional, absolute, parallel output connector available on single turn units.

Revision History

940-0D093: 09/26/2013    Corrected a wiring diagram and added several notes and clarifications
940-0D092: 11/06/2012    Added revision 2.3 parameter and data values
940-0D091: 04/19/2011    Added Modbus protocol and stainless steel package outline drawings
940-0D090: 07/12/2010    Initial Release
**ABOUT THIS MANUAL**

**Where to Go From Here**

This manual contains information that is of interest to everyone from engineers to operators. The table below gives a brief description of the content of each chapter to help you find the information you need to assist you in your job.

<table>
<thead>
<tr>
<th>CHP NUM.</th>
<th>Chapter Title</th>
<th>Chapter Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td><em>Introduction to the NR25</em></td>
<td>Intended for anyone new to the NR25 Networked Resolver encoder, this chapter gives a basic overview of the unit, including an explanation of its programmable features. The chapter also explains the NR25 part numbering system.</td>
</tr>
<tr>
<td>2</td>
<td><em>Installation</em></td>
<td>This chapter is intended for the engineer or technician responsible for installing and wiring the NR25 Networked Resolver encoder. Information in this chapter includes mechanical drawings, installation guidelines and connector pinout.</td>
</tr>
<tr>
<td>3</td>
<td><em>NR25 Configuration</em></td>
<td>This chapter is intended for anyone responsible for configuring the NR25 either before or after actual installation. It includes detailed information on using the AMCI Net Configurator utility that is freely available on the AMCI website.</td>
</tr>
<tr>
<td>4</td>
<td><em>RSLogix 5000 EtherNet/IP Configuration</em></td>
<td>This chapter covers how to communicate with the NR25 using the EtherNet/IP protocol and implicit messaging. The RSLogix 5000 software is used as a programming example.</td>
</tr>
<tr>
<td>5</td>
<td><em>RSLogix 500 EtherNet/IP Configuration</em></td>
<td>This chapter covers how to communicate with the NR25 using the EtherNet/IP protocol and explicit messaging. The RSLogix 500 software is used as a programming example.</td>
</tr>
<tr>
<td>6</td>
<td><em>Modbus TCP Configuration</em></td>
<td>This chapter covers how to communicate with the NR25 using the Modbus TCP protocol.</td>
</tr>
<tr>
<td>A</td>
<td><em>IP Address Setup with Bootp</em></td>
<td>Older NR25 units must use a Bootp server to set their IP address. This appendix is a step by step guide to using the Bootp server from Rockwell Automation to change the default IP address of the NR25.</td>
</tr>
<tr>
<td>B</td>
<td><em>CIP Position Sensor Object</em></td>
<td>When using the EtherNet/IP protocol, the NR25 conforms to the Encoder Device Profile as defined by the Common Industrial Protocol (CIP). This chapter explains the Position Sensor Object that is implemented by the NR25 as part of this profile.</td>
</tr>
<tr>
<td>C</td>
<td><em>Parallel Output Option</em></td>
<td>Information and outline drawings for single turn NR25 units that incorporate a 12 bit, absolute, parallel output for redundant applications.</td>
</tr>
</tbody>
</table>
Notes
CHAPTER 1

INTRODUCTION TO THE NR25

Overview

The NR25 is a new line of heavy-duty resolver based encoder products from AMCI. The initial offerings in this line communicate over a standard Ethernet network. A version that communicates over Profibus is also available and is covered in a separate manual.

Two different protocol stacks are built into each NR25 Ethernet product:

- An ODVA compliant EtherNet/IP protocol stack
- A Modbus TCP compliant protocol stack

Having both protocols available allows the NR25 to be used in a vast majority of applications today and allows machine builders to confidently choose a single solution that can be used regardless of the protocol their end customers are using.

Power over Ethernet (PoE) is also a standard feature on all NR25 Ethernet products, allowing you to reduce cabling requirements if you use a network switch that supports PoE. Side connect units have only the Ethernet connector and must use PoE while end connect units have a second connector that can be used for power. This connector allows you to use these NR25 encoders as drop in replacements for other EtherNet/IP encoders.

The NR25 series is composed of absolute single- or multi-turn sensors in an IP67 rated, 2.5 inch diameter package. All NR25 Networked Resolvers offer a maximum single turn position resolution of 16 bits, which is programmable from 1 to 65,536 counts per turn. Two multi-turn units are available in addition to the single turn NR25. One encodes 4,096 turns (12 bit + 16 bit = 28 bit encoder) and the other encodes 16,384 turns (14 bit + 16 bit = 30 bit encoder).

A flange mount unit with end connectors is shown in figure 1.1. The following mounting styles are available:

- Size 25 standard flange mount with 3/8", 1/4", or 10mm shafts
- Size 25 standard servo mount with 3/8", 1/4", or 10mm shafts
- Blind shaft mount for 3/8", 1/2", 10mm, and 12mm shafts, mounting bracket designed for 63mm B.C.
- AMCI face mount with 5/8" shaft for high radial and axial loads

Side and end connect versions of all of these mounting styles are available. Body material is either aluminum with a powder coat finish or 316 stainless steel for use in caustic environments. Outline drawings of all of the packing options are available in the Outline Drawings section of the Installation chapter, starting on page 19.

Every NR25 resolver based encoder is programmable over its Ethernet interface. Initial configuration can be accomplished with the AMCI Net Configurator software while setting the IP address of the unit. Additional configuration can be accomplished once the unit is installed on your machine through simple data reads and writes programmed into your controller. Parameters allow you to set the count direction, the number of counts per turn, the format of the velocity data, and preset the position data to any value within its range. The current version of the firmware also allows you to set the number of counts before returning to zero.

All NR25 resolver based encoders have three status LED’s to help you determine the state of the device. These LED’s are always located on the back cover of the NR25:

- Module Status – Operating status of the NR25 itself
- Network Status – Operating state of the EtherNet/IP or Modbus TCP protocol
- Link/Activity – Physical state of Ethernet connection
**Electrical Specifications**

**Operating Voltage (External Supply)**
12 Vdc to 54 Vdc

**Power Requirements**
2.5 W max.
100 mA @ 24 Vdc typical (DC supply powered)
50 mA @ 48 Vdc typical (PoE powered)

**Ethernet Capability**
10/100 Mbit autosense with auto-switch capability.
Auto-switch eliminates the need of a crossover cable in all applications.

**Power over Ethernet (PoE)**
Compatible with Power over Ethernet standard.
With only data pairs available, the power sourcing equipment (PSE) must be able to output power on these two pairs (Mode A)

**Maximum Cable Length**
100 meters (330 feet), based on Ethernet standard

**Single Turn Resolution**
Programmable from 1 to 65,536 counts per turn (16 bit resolution max.)

**Multi-turn Resolution**
4,096 turns (12 bit) or 16,384 (14 bit)

**Direction of Increasing Counts**
Default of CW increasing when looking at the shaft.
Programmable to CCW increasing over the Ethernet/IP interface.

**Preset Position**
Position can be preset to any value within its range over the Ethernet interface. Internal Position Offset can be stored in non-volatile memory and retrieved on power up.

**Positional Accuracy**
±10 arc-minutes

**Response Time**
1 millisecond

**Velocity Update Time**
100 milliseconds

**Mechanical Specifications**

**Package Style**
2.5 inch housing with flange, servo, or hub shaft mounting

**Mechanical Specifications (cont’d)**

**Connector Location**
Side or End

**Housing**
Powder coated aluminum or 316 stainless steel

**Shaft**
0.250", 0.375", 0.625", or 10 mm
Blind shaft with 0.375", 0.500", 10mm or 12mm hole

**Max. Starting Torque @ 25°C**
2.0 oz-in: 0.250", 0.375", and 10 mm shafts
6.0 oz-in: All blind shafts
6.0 oz-in: 0.625" shaft

**Moment of Inertia (oz-in·sec²)**
6.00 X 10⁻⁴: 0.250", 0.375", and 10 mm shafts
7.00 X 10⁻⁴: All blind shafts
8.50 X 10⁻⁴: 0.625" shaft

**Max. Operating Speed**
6000 RPM max.

**Max. Shaft Loading (0.625” shaft)**
Axial: 50lbs. (222N)
Radial: 100lbs. (445N)
At specified max. loads, minimum bearing life is 2X10⁹ revolutions.

**Max. Shaft Loading (All other shafts)**
Axial: 20lbs. (89N)
Radial: 40lbs. (178N)
At specified max. loads, minimum bearing life is 2X10⁹ revolutions.

**Environmental Specifications**

**Operating Temperature**
−40°F to +185°F (−40°C to +85°C)

**Shock**
50g, 11 millisecond duration

**Vibration**
20g, 5 to 2000Hz

**Enclosure Rating**
IP67

**Approximate Weight**
2.0lbs. (0.91kg) 0.625” shaft - Aluminum Body
3.8lbs. (1.73kg) 0.625” shaft - 316 Steel Body
1.4lbs. (0.65kg) All other shafts - Aluminum Body
2.9lbs. (1.32kg) All other shafts - 316 Steel Body
**Parallel Output Option**

Single turn NR25 units can be ordered with an additional parallel digital position output. Position resolution is fixed at 4,096 counts per turn. This output is used in applications that require redundant position data or when interfacing to a device that requires parallel position data.

All NR25 units that have the additional parallel position outputs appear to be a hybrid of the side and end connect designs. The network connections are on the back of the unit and the parallel outputs are off of the side pedestal. Therefore, this option is only available with aluminum housings. All four mounting options are available.

The parallel output circuitry is completely independent of the network circuitry. A separate power supply connection is required. The power supply must be within the range of 10.8 to 26.4 Vdc. (12 to 24 Vdc ±10%)

Position values increase with CCW rotation of the shaft when looking at the shaft.

Binary and Gray Code encoding options are available.

Outputs are open collector sourcing that turn on for a logic ‘1’. The outputs are directly connected to the power supply that powers the parallel output circuitry. Each output is rated for 15 mA.

Output state is controlled with a Latch Input. Outputs update when this input is high or open circuit, and freeze when this input is pulled low.

Complete specifications for the parallel output can be found in appendix C, *Parallel Output Option*, starting on page 85.

**Part Number Description**

**Available Data**

All NR25 encoders offer position and velocity data that can be scaled with the programmable parameters as described in the following section. The position data can also be preset which allows you to align the position data with your machine position without having to physically rotate the shaft.

NR25 encoders that have firmware revision 2.3 and above can also transmit the following data:

- **Time Stamp**: The time stamp is an unsigned double integer value with an interval of 400 nanoseconds. It will roll over every 1717.9869184 seconds. The time stamp can be used to verify active communications between the NR25 and your host controller.

- **Actual Sensor Reading**: This unsigned double integer value is the raw position data from the NR25. Changing the position scaling parameters will have no effect on this value.
Programmable Parameters

The following parameters are available on all NR25 encoders. Note that most of these parameter names are pulled from the ODVA (EtherNet/IP) specification. They are generic, and sometimes confusing, but they are what is defined in the specification. AMCI has decided to adopt these parameter names for all NR25s to avoid additional translations between protocols with one exception. In the ODVA specification, the parameter that sets the number of counts per turn of the shaft is called the ‘Measurement Units per Span’. This generic name can be applied to both rotary and linear encoders. Being that the NR25 is a rotary encoder, this manual refers to the parameter as Counts per Turn.

Direction Counting Toggle

This parameter allows you to set the direction of shaft rotation needed to produce increasing counts. A value of “0” sets the direction of increasing counts to clockwise when looking at the shaft. A value of “1” sets the direction of increasing counts to counter-clockwise when looking at the shaft. The factory default value is clockwise increasing counts.

Scaling Function Control

The NR25 has a maximum resolution of 65,536 counts per turn and it can be programmed to scale the counts per turn from 1 to 65,536. Scaling is only performed if this parameter is in its “enabled” state. A value of “0” disables the scaling function and a value of “1” enables the scaling function. Note that the Scaling Function Control parameter only affects the scaling of the position data. Once this parameter is enabled, the velocity data will always be scaled by the Counts per Turn parameter until power is cycled to the unit. This is true even if the Scaling Function Control is returned to it disabled state. See Calculating Position and Velocity Data on page 15 for the reasoning behind this behavior.

Counts per Turn

(ODVA: Measuring Units Per Span)

This parameter can range from 1 to 65,536. Note that this parameter is only used to scale the position value when the Scaling Function Control parameter is set to “1”. If the Scaling Function Control parameter is set to “0”, the NR25 will report position data at its full resolution of 65,536 counts per turn. This parameter will always be applied to the velocity data reported by the NR25, regardless of the state of the Scaling Function Control parameter. If you are not using the Counts per Turn parameter, set it to its default value of 65,536.

Preset Value

This parameter allows you to preset the position to any value in its single or multi-turn range without rotating the shaft. The minimum value for this parameter is zero. Its maximum value depends on the NR25 version you have. For single turn NR25’s, the maximum value is 65,535. For 28 bit multi-turn NR25’s, the maximum value is 268,435,455. For 30 bit multi-turn NR25’s, the maximum value is 1,073,741,823. If your NR25 is revision 2.3 or greater, the maximum value of this parameter can be limited by the Total Measurement Range parameter. See the Total Measurement Range Parameter (Rev. 2.3+) section on page 16 for a description of this parameter.
INTRODUCTION TO THE NR25

Programmable Parameters (continued)

Velocity Format
The NR25 reports velocity data as well as position data over the network. This parameter sets the units of measure for the velocity data. This parameter has four fixed values.

- 0x1F04 = pulses/second
- 0x1F05 = pulses/millisecond
- 0x1F07 = pulses/minute
- 0x1F0F = RPM

Once the Scaling Function Control parameter is enabled, the velocity data will always be scaled by the Counts per Turn parameter until power is cycled to the unit. This is true even if the Scaling Function Control is returned to its disabled state. See Calculating Position and Velocity Data below for the reasoning behind this behavior.

Device Type
You can program how the NR25 defines itself to the EtherNet/IP network and is only available when the NR25 is configured to use the EtherNet/IP protocol. This parameter has a double integer (32 bit) data type and two fixed values.

- 0x22 = Encoder Device (factory default value)
- 0x00 = Generic Device

Calculating Position and Velocity Data
The maximum position resolution of an NR25 is 65,536 counts per turn. This value is used unless the Scaling Function Control is set to its Enabled state. If this parameter is set to its enabled state, the number of counts per turn is set to the value specified by the Counts per Turn parameter.

Note that the Scaling Function Control parameter is a true enable/disable control. The Counts per Turn parameter is only used to scale the position data if the Scaling Function Control is in its enabled state. If you change the Scaling Function Control parameter to its disabled state, the NR25 will begin to report position data with a resolution of 65,536 counts per turn as soon as the state change is accepted.

The velocity data calculation is also affected by the Counts per Turn parameter. The velocity data will always be calculated based on the last value of the Counts per Turn parameter. This is true even if the Scaling Function Control is never set to its Enabled state. Therefore, leave the Counts per Turn parameter at its default value of 65,536 if you do not want to scale the velocity data.

For example, if you enable the Scaling Function Control and set the Counts per Turn parameter to 10,000, the position will be calculated at 10,000 counts per turn and the velocity will also be calculated at 10,000 counts per turn. If you then disable the Scaling Function Control, the position will be calculated at 65,536 counts per turn and the velocity will still be calculated at 10,000 counts per turn. Additionally, if you change the Counts per Turn parameter to 5,000 and do not enable the Scaling Function Control parameter, the position will still be calculated at 65,536 counts per turn and the velocity will now be calculated at 5,000 counts per turn. This behavior may be confusing to some users, but may be exactly what other users need. (One example is a packaging machine where you want the position at full resolution, but the velocity data scaled to boxes-per-minute.) If this behavior would not be beneficial to you, then the best way to avoid any issues is to always leave the Scaling Function Control parameter enabled and use the Counts per Turn parameter, even when setting the counts per turn to 65,536.
**Total Measurement Range Parameter (Rev. 2.3+)**

The Total Measurement Range parameter sets the total number of counts before the position value returns to zero. It is always used when determining the position value. Its use is not affected by the state of the Scaling Function Control parameter. If the Total Measurement Range parameter is left at its default value of zero, the roll over position is determined by the Counts per Turn parameter and the number of turns the NR25 can encode. This is the same way NR25 encoders with a revision of 1.9 or less operate. If the Total Measurement Range is non-zero, it places an upper limit on the position value and the Preset Value parameter. Total Measurement Range parameter ranges are as follows:

- **Single Turn NR25**: Range of 0, 2 to 65,536
- **28 bit Multi-turn NR25**: Range of 0, 2 to 268,435,455
- **30 bit Multi-turn NR25**: Range of 0, 2 to 1,073,741,823

There is no fixed relationship between the Total Measurement Range and Counts per Turn parameters, which leads to interesting applications that use the two parameters.

**Storage of Internal Position Offset**

The Total Measurement Range parameter affects how the internal position offset, which is generated when you preset the position value, is stored. When the Total Measurement Range parameter is zero, the position offset is stored in RAM and lost when power is removed from the NR25. You must issue a command to save the position offset to non-volatile memory. This is exactly how NR25 encoders with a revision of 1.9 or below operate. When the Total Measurement Range parameter is non-zero, the internal position offset is automatically stored in non-volatile FRAM memory. You do not need to issue a command to save the internal position offset. If you set the Total Measurement Range parameter as follows, the parameter will have no effect on the position value and the internal position offset will be stored in FRAM.

- **Single Turn NR25**: 65,536 or the value of the Counts per Turn parameter if the Scaling Function Control parameter is set to ‘True’.
- **28 bit Multi-turn NR25**: 268,435,455, or the value of the Counts per Turn parameter multiplied by 4,096 if the Scaling Function Control parameter is set to ‘True’.
- **30 bit Multi-turn NR25**: 1,073,741,823, or the value of the Counts per Turn parameter multiplied by 16,386 if the Scaling Function Control parameter is set to ‘True’.

Using the Total Measurement Range parameter this way only affects how the internal position offset is stored. You must still issue a command to save the programmable parameters to non-volatile memory.
**Total Measurement Range Parameter (continued)**

**Roll Over on Fractional Travel**

When the **Total Measurement Range** is less than the total counts available from the NR25, which is *(Counts per Turn multiplied by the number of turns the NR25 can encode)*, the position will return to zero before the full mechanical travel is completed. Two examples are shown below.

### Figure 1.3 Fractional Turn Examples

#### 28 bit NR25: 4096 Turns

- **Counts per Turn = 1,000 Counts**
- **Total Counts = 4,096,000**
- **Total Measurement Range = 819,200 Counts**

NR25 outputs five cycles of counts from 0 to 819,199 over 4,096 turns.

#### One Rotation of a Single Turn NR25

- **Counts per Turn = 36,000 Counts**
- **Total Measurement Range = 22,500 Counts**

NR25 outputs one cycle of counts from 0 to 22,499 for every 225 degrees of rotation.

The top half of figure 1.3 shows what occurs when the **Total Measurement Range** parameter is used to divide the full range of travel of the NR25 into equal parts. In this case, a twenty-eight bit NR25 has its 4,096 turns evenly divided into five cycles of 819.2 turns.

The bottom half of figure 1.3 shows a single turn NR25 where the **Total Measurement Range** parameter is not used to divide the full range of travel into equal parts. In this case, the position value will roll over to zero after 225 degrees of rotation.

If the value of {Total Counts ÷ Total Measurement Range} is an integer, the NR25 remains an absolute rotary sensor. You can remove power from the NR25, rotate it as far as you want, re-apply power, and the NR25 will give you the correct position value. The top half of figure 1.3 is an example of this setup because the division of the two parameters results in the quotient value of five.

It is also possible for the value of {Total Counts ÷ Total Measurement Range} to be a real number instead of an integer. This case is shown in the bottom half of figure 1.3, where the quotient is 1.6. In these cases, the NR25 becomes what AMCI terms a *quasi-absolute* rotary sensor.

Quasi-absolute means that the NR25 will power up with the correct position value as long as the shaft was rotated less than half of the complete span of the encoder while power was removed. In practical terms:

- **For 30-bit NR25 encoders:** If you remove power from the sensor and rotate the shaft less than 8,192 turns in either direction, when you re-apply power, the position reading will be correct.
- **For 28-bit NR25 encoders:** If you remove power from the sensor and rotate the shaft less than 2,048 turns in either direction, when you re-apply power, the position reading will be correct.
- **For 16-bit NR25 encoders:** If you remove power from the sensor and rotate the shaft less than 180 degrees in either direction, when you re-apply power, the position reading will be correct.

If the shaft rotates further than the limits listed above while power is removed, the position value from the NR25 will be off by at least ±1 turn when power is applied.
**Total Measurement Range Parameter (continued)**

**Quasi-Absolute Multi-turn**

When the *Total Measurement Range* is greater than the total counts available from the NR25, which is (*Counts per Turn* multiplied by the number of turns the NR25 can encode), multiple rotations of the shaft are required before the position value reaches the roll over count. For example, assume a single turn NR25 that has its *Counts per Turn* parameter set to 360 and its *Total Measurement Range* parameter set to 64,800. With this setup, the shaft of the NR25 must rotate 180 turns, \( \frac{64,800}{360} \), before the position returns to zero. In this application, the single turn NR25 acts as a 180 turn encoder with one degree position resolution.

The same trade off between resolution and number of turns encoded can be made with the multi-turn NR25 encoders. For example, if a 30-bit NR25 encoder has its *Counts per Turn* parameter set to 360 and its *Total Measurement Range* parameter set to its maximum of 1,073,741,824, the NR25 will encode 2,982,616.17 turns with one degree resolution.

In all of these applications, the NR25 will act as a quasi-absolute encoder, with the same motion restrictions listed in the *Roll Over on Fractional Travel* section above. Exceeding these limits will result in a position value error when power is re-applied.

**Effects of Reversing Count Direction**

Changing the *Direction Counting Toggle* parameter changes the way the position value is calculated. When you reverse the count direction, the position changes from your current position value to (Maximum number of counts – current position value). For example, assume a 30 bit NR25 with its default of 65,536 counts per turn. If the current position value is 100,000 and you change the Direction Counting Toggle parameter, the current position will change to \( 2^{30} - 100,000 = 1,073,741,824 - 100,000 \) = 1,073,641,824. Most applications do not require you to change the count direction after the machine is setup, so the count direction is typically set before the position value is preset.

Changing the count direction on your machine while maintaining the current position value is a three step process. First, read and store the current position value from the NR25. Second, change the *Direction Counting Toggle* value. Third, write the stored position value back to the NR25 as a preset value.
CHAPTER 2
INSTALLATION

This chapter is intended for the engineer or technician responsible for installing and wiring the NR25 networked resolver encoder. Information in this chapter includes mechanical drawings, installation guidelines and connector pinout.

2.5” Servo Mount Outline Drawing

Aluminum Body, End Connect

( ) = Dimensions in millimeters

![Figure 2.1 Servo Mount, End Connector Outline Drawing](image)

Aluminum Body, Side Connect

( ) = Dimensions in millimeters

![Figure 2.2 Servo Mount, Side Connector Outline Drawing](image)
2.5" Servo Mount Outline Drawings (continued)

Stainless Steel Body, End Connect

( ) = Dimensions in millimeters

Figure 2.3 Servo Mount, End Connector Outline Drawing

Stainless Steel Body, Side Connect

( ) = Dimensions in millimeters

Figure 2.4 Servo Mount, Side Connector Outline Drawing
**Alternate Shafts**

- **10mm Shaft** (Shaft Option 2)
  - 0.3934" (9.993)
  - 0.3931" (9.985)
  - 0.900" (22.86)
  - 0.850" (21.59)

- **1/4" Shaft** (Shaft Option 3)
  - 0.2497" (6.342)
  - 0.2492" (6.330)
  - 0.900" (22.86)
  - 0.850" (21.59)

() = Dimensions in mm

Figure 2.5 2.5" Servo Mount Alternate Shafts

**Shaft Loading**

Limit shaft loading to the following values. These values statistically yield an L10 life of $2 \times 10^9$ revolutions. (Statistically, only 10% of the bearings will have failed after $2 \times 10^9$ revolutions.) Shaft loading has an exponential effect on bearing life. The bearings will statistically last longer if you can limit shaft loading below the given values. Consider using the 5/8" shaft NR25 if your shaft loading is expected to be greater than the values given below. Outline drawings for the 5/8" shaft NR25 can be found starting on page 28.

<table>
<thead>
<tr>
<th>Radial Load</th>
<th>Axial Load</th>
</tr>
</thead>
<tbody>
<tr>
<td>40 lbs. (178 N)</td>
<td>20 lbs. (88 N)</td>
</tr>
</tbody>
</table>

Table 2.1 Servo Mount Shaft Loading
58 mm Servo Mount Outline Drawing

Aluminum Body, End Connect

( ) = Dimensions in millimeters

2.50” (63.5)

<table>
<thead>
<tr>
<th>Diam.</th>
<th>Width</th>
<th>Length</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.969” (50.00)</td>
<td>1.968” (49.97)</td>
<td></td>
</tr>
</tbody>
</table>

M4x0.7 0.315” (8.00) min. depth. Three places, 120º apart on a 1.654” (42) B.C.

0.3934” (9.993)
0.3931” (9.985)

<table>
<thead>
<tr>
<th>Diam.</th>
<th>Width</th>
<th>Length</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.028” (51.50)</td>
<td>2.283” (56.00)</td>
<td></td>
</tr>
</tbody>
</table>

0.807” (20.50)
0.787” (20.00)

<table>
<thead>
<tr>
<th>Diam.</th>
<th>Width</th>
<th>Length</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.020” (0.50) deep x 0.77” (19.5) long flat</td>
<td>0.020” (0.50) deep x 0.77” (19.5) long flat</td>
<td></td>
</tr>
</tbody>
</table>

Additional clearance needed for removal of mating connector.

Figure 2.6 Servo Mount, End Connector Outline Drawing

Aluminum Body, Side Connect

( ) = Dimensions in millimeters

2.78” (70.6) max.

<table>
<thead>
<tr>
<th>Diam.</th>
<th>Width</th>
<th>Length</th>
</tr>
</thead>
<tbody>
<tr>
<td>1.969” (50.00)</td>
<td>1.968” (49.97)</td>
<td></td>
</tr>
</tbody>
</table>

M4x0.7 0.315” (8.00) min. depth. Three places, 120º apart on a 1.654” (42) B.C.

0.3934” (9.993)
0.3931” (9.985)

<table>
<thead>
<tr>
<th>Diam.</th>
<th>Width</th>
<th>Length</th>
</tr>
</thead>
<tbody>
<tr>
<td>2.028” (51.50)</td>
<td>2.283” (56.00)</td>
<td></td>
</tr>
</tbody>
</table>

0.807” (20.50)
0.787” (20.00)

<table>
<thead>
<tr>
<th>Diam.</th>
<th>Width</th>
<th>Length</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.020” (0.50) deep x 0.77” (19.5) long flat</td>
<td>0.020” (0.50) deep x 0.77” (19.5) long flat</td>
<td></td>
</tr>
</tbody>
</table>

Additional clearance needed for removal of mating connector.

Figure 2.7 Servo Mount, Side Connector Outline Drawing
**58 mm Servo Mount Outline Drawings (continued)**

**Stainless Steel Body, End Connect**

( ) = Dimensions in millimeters

![End Connector Outline Drawing](image1)

**Stainless Steel Body, Side Connect**

( ) = Dimensions in millimeters

![Side Connector Outline Drawing](image2)
Shaft Details

6 mm Shaft (Shaft Option 4)  10 mm Shaft (Shaft Option 6)

<table>
<thead>
<tr>
<th>Radial Load</th>
<th>Axial Load</th>
</tr>
</thead>
<tbody>
<tr>
<td>40 lbs. (178 N)</td>
<td>20 lbs. (88 N)</td>
</tr>
</tbody>
</table>

Shaft Loading

Limit shaft loading to the following values. These values statistically yield an L10 life of 2X10^9 revolutions. (Statistically, only 10% of the bearings will have failed after 2X10^9 revolutions.) Shaft loading has an exponential effect on bearing life. The bearings will statistically last longer if you can limit shaft loading below the given values. Consider using the 5/8" shaft NR25 if your shaft loading is expected to be greater than the values given below. Outline drawings for the 5/8" shaft NR25 can be found starting on page 28.
**Flange Mount Outline Drawings**

**Aluminum Body, End Connect**

Figure 2.11  Flange Mount, End Connector Outline Drawing

- Dimensions in millimeters
- Additional clearance needed for removal of mating connector.

**Aluminum Body, Side Connect**

Figure 2.12  Flange Mount, Side Connector Outline Drawing

- Dimensions in millimeters
- Additional clearance needed for removal of mating connector.

NR25 Ethernet Output Flange Mount End Connector

NR25 Ethernet Output Flange Mount Side Connector PoE only

Industry Standard M12 Connector D-Coded, 4 pin Female
**Flange Mount Outline Drawings (continued)**

**Stainless Steel Body, End Connect**

( ) = Dimensions in millimeters

![Flange Mount, End Connector Outline Drawing](image)

**Stainless Steel Body, Side Connect**

( ) = Dimensions in millimeters

![Flange Mount, Side Connector Outline Drawing](image)
**Flange Mount Outline Drawings (continued)**

Alternate Shafts

10mm Shaft  
(Shaft Option 2)

<table>
<thead>
<tr>
<th>0.3934&quot; (9.993)</th>
<th>0.3931&quot; (9.985)</th>
</tr>
</thead>
</table>

| 0.900" (22.86) | 0.850" (21.59) |

1/4" Shaft  
(Shaft Option 3)

<table>
<thead>
<tr>
<th>0.2497&quot; (6.342)</th>
<th>0.2492&quot; (6.330)</th>
</tr>
</thead>
</table>

| 0.900" (22.86) | 0.850" (21.59) |

() = Dimensions in mm  
Figure 2.15 Flange Mount Alternate Shafts

**Shaft Loading**

Limit shaft loading to the following values. These values statistically yield an L10 life of $2 \times 10^9$ revolutions. (Statistically, only 10% of the bearings will have failed after $2 \times 10^9$ revolutions.) Shaft loading has an exponential effect on bearing life. The bearings will statistically last longer if you can limit shaft loading below the given values. Consider using the 5/8" shaft NR25 if your shaft loading is expected to be greater than the values given below. Outline drawings for the 5/8" shaft NR25 can be found starting on page 28.

<table>
<thead>
<tr>
<th>Radial Load</th>
<th>Axial Load</th>
</tr>
</thead>
<tbody>
<tr>
<td>40 lbs. (178 N)</td>
<td>20 lbs. (88 N)</td>
</tr>
</tbody>
</table>

Table 2.3 Flange Mount Shaft Loading
Flange Mount Outline Drawings (continued)

5/8" Shaft, Aluminum Body, End Connect

NOTES:
1) Integral Shaft Seal.
2) 1/4-20 UNC-2B 0.50" (12.7) minimum depth. Six Places.
3) Additional clearance needed for removal of mating connectors.

KEYWAY SPECIFICATIONS

Figure 2.16 5/8" Shaft, Flange Mount, End Connect Outline Drawing
Flange Mount Outline Drawings (continued)

5/8" Shaft, Aluminum Body, Side Connect

NOTES:
1) Integral Shaft Seal.
2) 1/4-20 UNC-2B 0.50" (12.7) minimum depth. Six Places.
3) Additional clearance needed for removal of mating connector.

KEYWAY SPECIFICATIONS

Figure 2.17 5/8" Shaft, Flange Mount, Side Connect Outline Drawing
Flange Mount Outline Drawings (continued)

5/8" Shaft, Stainless Steel Body, End Connect

NOTES:
1) Integral Shaft Seal.
2) 1/4-20 UNC-2B 0.50" (12.7) minimum depth. Six Places.
3) Additional clearance needed for removal of mating connectors.

KEYWAY SPECIFICATIONS

KEYWAY
0.1895" (4.813) X 0.108" (2.74) Deep
0.1885" (4.788) 0.106" (2.69)

KEY
0.188" (4.76) Sq. X 1.00" (25.4)
0.187" (4.75)

Figure 2.18 5/8" Shaft, Flange Mount, End Connect Outline Drawing
**Flange Mount Outline Drawings (continued)**

**5/8" Shaft, Stainless Steel Body, Side Connect**

Limit shaft loading to the following values. These values statistically yield an L10 life of $2 \times 10^9$ revolutions. (Statistically, only 10% of the bearings will have failed after $2 \times 10^9$ revolutions.) Shaft loading has an exponential effect on bearing life. The bearings will statistically last longer if you can limit shaft loading below the given values.

**Shaft Loading**

<table>
<thead>
<tr>
<th>Radial Load</th>
<th>Axial Load</th>
</tr>
</thead>
<tbody>
<tr>
<td>100 lbs. (445 N)</td>
<td>50 lbs. (222 N)</td>
</tr>
</tbody>
</table>

Table 2.4 Flange Mount, 5/8" Shaft Loading
**Hub Shaft Mount Outline Drawings**

Aluminum Body, End Connect

( ) = Dimensions in millimeters

![Diagram of Hub Shaft Mount Outline Drawing](image)

**VIEW A**

- **Customer Side**
- **Shaft Seal**
- **Shaft Length**
  - 0.59" (15) min.
  - 1.10" (27.9) max.

**VIEW A**

- **NR25**
  - Ethernet Output
  - Hub Shaft Mount End Connector

**DIAMETER CHART**

<table>
<thead>
<tr>
<th>Nominal Hole Diameters Available</th>
</tr>
</thead>
<tbody>
<tr>
<td>English</td>
</tr>
<tr>
<td>0.375&quot;</td>
</tr>
<tr>
<td>0.500&quot;</td>
</tr>
</tbody>
</table>

**Figure 2.20 Hub Shaft Mount, End Connect Outline Drawing**
**Hub Shaft Mount Outline Drawings (Continued)**

Aluminum Body, Side Connect

( ) = Dimensions in millimeters

1. **VIEW A**

   - **Shaft Seal**
   - **0.067” (1.70) radius on 2.48” (63.0) B.C.**
   - **2.50” (63.5) Dia.**

2. **Customer Side**

   - **Shaft Length**
   - **0.59” (15) min.**
   - **1.10” (27.9) max.**

3. **VIEW A**

   - **4-40 Thru Tap 3 places, 120° apart**
   - **1.10” (27.9) depth**

4. **DIAMETER CHART**

<table>
<thead>
<tr>
<th>Nominal Hole Diameters Available</th>
</tr>
</thead>
<tbody>
<tr>
<td>English</td>
</tr>
<tr>
<td>0.375”</td>
</tr>
<tr>
<td>0.500”</td>
</tr>
</tbody>
</table>

5. **NR25**

   - **Ethernet Output**
   - **Hub Shaft Mount Side Connector**
   - **PoE only**

6. **Indust Standard M12 Connector**

   - **D-Coded, 4 pin Female**

---

**Figure 2.21** Hub Shaft Mount, Side Connect Outline Drawing
Hub Shaft Mount Outline Drawings (Continued)

Stainless Steel Body, End Connect

( ) = Dimensions in millimeters

Figure 2.22  Hub Shaft Mount, End Connect Outline Drawing
Hub Shaft Mount Outline Drawings (Continued)

Stainless Steel Body, Side Connect

Available Shaft Diameters

The diameter of the drive shaft must be specified when ordering a blind shaft DuraCoder. Available options are given in the table below. Other diameter options may have become available after the release of this manual. Please check our website, www.amci.com, if you do not see the shaft diameter that fits your application.

<table>
<thead>
<tr>
<th>Nominal Hole Diameters</th>
<th>English</th>
<th>Metric</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.375&quot;</td>
<td>10 mm</td>
<td></td>
</tr>
<tr>
<td>0.500&quot;</td>
<td>12 mm</td>
<td></td>
</tr>
</tbody>
</table>

Table 2.5 Available Blind Shaft Diameters

Shaft Loading

The load that the NR25 presents to your input shaft, which is equal to the load presented to the NR25 by your input shaft, is difficult to calculate and depends on the accuracy of the mounting. The flexible metal mounting bracket will be able to absorb most of the radial loading forces, but accurate mounting of the NR25 is important.
End View

The Status LED’s on all NR25’s are located on the end of the unit opposite of the input shaft. Figure 2.24 below shows the layout of a unit with the connectors also located on the end. For side connect units, only the LED’s will be on this surface. Also note that only the Network connector is available on side connect units and these devices must use Power over Ethernet. All end-connect units also include a screw on cap for the power connector so the unit will retain its IP67 rating if you decide to use it as a PoE device.

Status LED’s

As shown in figure 2.24 above, the NR25 has three status LED’s on the rear cover. These LED’s are present on side connector units as well. The tables below list the various states of the LED’s and their meaning.

Network Status LED

<table>
<thead>
<tr>
<th>LED State</th>
<th>EtherNet/IP Definition</th>
<th>Modbus TCP Definition</th>
</tr>
</thead>
<tbody>
<tr>
<td>Off</td>
<td>No Power</td>
<td>No power or no TCP connections</td>
</tr>
<tr>
<td>Alternating Red/Green</td>
<td>Power up Self-Test</td>
<td>Power up Self-Test</td>
</tr>
<tr>
<td>Flashing Green</td>
<td>No Ethernet network connections</td>
<td>Indicates number of concurrent connections with 2 second delay between group. The NR25 supports up to 3 concurrent connections.</td>
</tr>
<tr>
<td>Steady Green</td>
<td>Ethernet network connected</td>
<td>Should not occur. LED should always flash when network is connected.</td>
</tr>
<tr>
<td>Flashing Red</td>
<td>Network Connection Timeout</td>
<td>Not implemented in Modbus TCP</td>
</tr>
<tr>
<td>Steady Red</td>
<td></td>
<td>Duplicate IP address on network.</td>
</tr>
</tbody>
</table>

Table 2.6 Network Status LED States

Module Status LED

<table>
<thead>
<tr>
<th>LED State</th>
<th>Definition</th>
</tr>
</thead>
<tbody>
<tr>
<td>Off</td>
<td>No Power</td>
</tr>
<tr>
<td>Alternating Red/Green</td>
<td>Self-Test (Run on power up.)</td>
</tr>
<tr>
<td>Steady Green</td>
<td>Device Operational</td>
</tr>
<tr>
<td>Blinking Green</td>
<td>Bootp Enabled</td>
</tr>
<tr>
<td>Steady Red</td>
<td>Hardware Fault. (Cycle power. If fault persists, contact AMCI for support.)</td>
</tr>
</tbody>
</table>

Table 2.7 Module Status LED States

Link/Activity LED

This orange LED is on when a Ethernet hardware connection exists to the NR25 and blinks when there is activity on the NR25 Ethernet network segment. Note that this LED shows the state of the hardware network, not the EtherNet/IP or Modbus TCP protocols.
**Connector Pinout**

The diagram below shows the pinout of the NR25 connectors. The Power and Network connectors are both available on units with end connectors. Side connect units only have the Network connector and must be powered using the Power over Ethernet feature of the NR25. All end-connect units also include a screw on cap for the power connector so the unit will retain its IP67 rating if you decide to use it as a PoE device.

![Connector Pinout Diagram](image)

**TIA/EIA-568 Color Codes**

There are two color codes in common use when wiring Ethernet connections with twisted pairs. Either one of these standards is acceptable. The Phoenix Contact cordsets that are suggested by AMCI all follow the 568B standard. Note that accidentally reversing the Tx/Rx pairs will not affect the operation of the NR25. The NR25 has an “auto-sense” port that will automatically adjust for swapped pairs.

<table>
<thead>
<tr>
<th>Signal</th>
<th>568A Color</th>
<th>568B Color</th>
</tr>
</thead>
<tbody>
<tr>
<td>+Transmit (+Tx)</td>
<td>White/Green Tracer</td>
<td>White/Orange tracer</td>
</tr>
<tr>
<td>−Transmit (−Tx)</td>
<td>Solid Green</td>
<td>Solid Orange</td>
</tr>
<tr>
<td>+Receive (+Rx)</td>
<td>White/Orange Tracer</td>
<td>White/Green Tracer</td>
</tr>
<tr>
<td>−Receive (−Rx)</td>
<td>Solid Orange</td>
<td>Solid Green</td>
</tr>
</tbody>
</table>

*Table 2.8 TIA/EIA Color Codes*

**Compatible Connectors and Cordsets**

Many different connectors and cordsets are available on the market, all of which will work with the NR25 provided that the manufacturer follows the connector and ethernet standards. The following connectors and cordsets are available from AMCI for the NR25.

<table>
<thead>
<tr>
<th>AMCI #</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>MS-29</td>
<td>Mating connector for Power connector. Screw terminal connections. 6 to 8 mm dia. cable. 18 AWG max. Straight, IP67 rated when properly installed.</td>
</tr>
<tr>
<td>CNVL-2M</td>
<td>Molded cordset for Power connector. 22 AWG wire, 2 meters in length. Straight connector to flying leads. IP67 rated when properly installed.</td>
</tr>
</tbody>
</table>

*Table 2.9 Compatible Power Connector and Cordset*
**Ethernet Connector and Cordset**

<table>
<thead>
<tr>
<th>AMCI #</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>MS-28</td>
<td>Mating connector for Ethernet port connector. Screw terminal connections. 6 to 8 mm dia. cable. Straight, IP67 rated when properly installed.</td>
</tr>
<tr>
<td>CNER-5M</td>
<td>Molded cordset for Ethernet connector. 5 meters in length. Straight M12 4 pin D-coded to RJ-45 connector. IP67 rated when properly installed.</td>
</tr>
</tbody>
</table>

Table 2.10 Ethernet Connector and Cordset

*NOTE* The cordset includes the NR25 connector, but the other end is un-terminated. This end can be punched down onto a patch panel, or an RJ45 connector can be added if the cordset is plugged directly into a switch.

**Power over Ethernet (PoE)**

All NR25 Ethernet encoders can be powered using only the network connector if the network supports Power of Ethernet.

*NOTE* Because the NR25 connector only has the ±Tx and ±Rx pairs, the network device the NR25 is cabled to, which is called the power source equipment (PSE) in the standard, must be able to output power on these two pairs (Mode A).

All end connect NR25 devices have a second connector for an external supply. The NR25 contains power supply sensing logic that will use the external power supply if power is available on that connector. No operating power will be drawn from the PoE. The NR25 will not be damaged if power is supplied on both connectors. All end-connect units also include a screw on cap for the power connector so the unit will retain its IP67 rating if you decide to use it as a PoE device.

If an end connect NR25 is using PoE, the power connector must be sealed to maintain the unit’s IP67 rating.

*CAUTION* You must use a PoE switch or injector. Do not attempt to connect an external supply to the ethernet data pins.
Notes
CHAPTER 3
NR25 CONFIGURATION

This chapter covers how to configure the NR25 by using the AMCI NR25 Configurator software. This utility is freely available on the AMCI website and it allows you to set the IP address, communications protocol, and most of the other parameters with a simple to use graphic program. If you are only setting the IP address and choose not to use the AMCI utility, you can use a Bootp server as outlined in Appendix A.

Factory Default
The NR25 ships from the factory with a default IP address of 192.168.0.50, a subnet mask of 255.255.255.0. The EtherNet/IP protocol is also the factory default. The NR25 retains its IP address and protocol information when power is removed and a hardware reset button does not exist. The address of the NR25 may be different unless the unit is directly from the factory.

Assumptions
This chapter makes a few assumptions:

1) You understand how IP addressing works and you only need instructions on setting the IP address of the NR25. If you do not yet understand IP addressing, there is plenty of information on the Internet. At the time of this writing, entering the phrase “ip addressing tutorial” into a popular search engine returned 298,000 hits.

2) You have administrative privileges on the computer you are using to configure the NR25. You will only need these privileges if you have to change the IP addressing of the network interface card used when configuring the device or if you have to temporarily disable any firewall on the computer.

3) You are configuring an NR25 encoder that has the factory default address of 192.168.0.50 and a subnet mask of 255.255.255.0. If you have an NR25 that has already been configured with a different address, you must know this address and adjust these instructions accordingly. If you do not know the address of your module, the AMCI Ethernet Configurator software will still be able to connect to the module if they reside on the same subnet mask.

Firewalls
Firewalls are hardware devices or software that prevent unwanted network connections from occurring. Firewall software is present in Windows XP and above and it may prevent your computer for communicating with the NR25. Configuring your firewall to allow communication with the NR25 is beyond the scope of this manual. The easiest thing to do is temporarily disable the firewall from the Control Panel and enable it once you have finished configuring the NR25.

Download the AMCI Net Configurator Software
The AMCI Net Configurator software is available on our website, www.amci.com. It can be found in our Tech Library section under Product Software. Simply download the zip file, extract it, and run the program to install the AMCI Net Configurator software on your computer. The software installs as most products do, giving you the option to change the file locations before installing the software. Once the install is complete, a link to the software is available on the Start Menu.

Configure Your Network Interface Card (NIC)
Ideally, the NIC that you will use when configuring the NR25 is not the NIC that attaches your computer to your corporate network. It is far easier to configure the NR25 with a stand-alone laptop or when your computer has two NIC’s in it, one for the corporate network and one for the NR25.
Configure Your Network Interface Card (NIC)  (continued)

If you only have one NIC, and it is used to attach your computer to your corporate network, you must disconnect your computer from this network before configuring the NR25. DO NOT place a router between your computer and the corporate network so you can try to have access to the network and the NR25 at the same time. The Network Administrator at AMCI can testify to the fact that “Bad Things” can happen when a rogue DHCP server in engineering starts offer network information to computers around it. Save yourself and your IT department some headaches and disconnect yourself from your corporate network if you only have one NIC in the computer that you will used to configure the NR25.

A wireless adapter does count as a network interface and it should be possible to connect to your corporate network with the wireless interface and use a NIC to configure the NR25. It should also be possible to configure the NR25 over a wireless connection by attaching it to a wireless router. However, this configuration has not yet been tested by AMCI.

The easiest way to check the current settings for your NIC is with the ‘ipconfig’ command.

- For Windows XP, click on the [Start] button, and click on [Run...]. A dialog box will open. Enter ‘cmd’ on the text line and press [Enter] on the keyboard.
- For Vista and Windows 7, click on the [Start] button, and type “cmd” in the “Search programs and files” text box. Press [Enter] on the keyboard.
- For Windows 8, bring up the ‘Apps’ search bar and type “cmd” into the text box. Press [Enter] on the keyboard to open the command prompt.

A DOS like terminal will open. Type in ‘ipconfig’, press [Enter] on the keyboard and the computer will return the present Address, Subnet Mask, and Default Gateway for all of your network interfaces. If your present address is 192.168.0.x, where ‘x’ does not equal 50, and your subnet mask is 255.255.255.0, then you are ready to configure your NR25 encoder. Figure 3.1 shows the output of an ipconfig command that shows the “Local Area Connection 2” interface on the 192.168.0 subnet.

![ipconfig Command](Figure 3.1 ipconfig Command)
NR25 CONFIGURATION

Configure Your Network Interface Card (NIC)  (continued)

If your present address in not in the 192.168.0.x range, type in ‘ncpa.cpl’ at the command prompt and hit [Enter] on the keyboard.

➤ In XP, this opens the Network and Dial-up Connections window. Right click on the appropriate interface and select ‘Properties’ from the menu. This will open the Properties windows for the selected interface. Click on the ‘Internet Protocol (TCP/IP)’ component and then click on the [Properties] button.

➤ For Vista and Windows 7, this open the Network Connections window. Double click on the appropriate interface. In the window that opens, select “Internet Protocol Version 4 (TCP/IP v4)” from the list and then click on the [Properties] button.

➤ For Windows 8, this opens the Network Connections window. Double click on the appropriate interface and the Status window for that interface opens. Click on the [Properties] button. In the next window that opens, select “Internet Protocol Version 4 (TCP/IP v4)” from the list and then click on the [Properties] button.

Set the address and subnet mask to appropriate values. (192.168.0.1 and 255.255.255.0 will work for an NR25 that has factory default settings.) The default gateway and DNS server settings can be ignored.

Attach the NR25

The next step in configuring the NR25 is attaching it to your computer. If using an end connect unit with a separate power supply, you can attach the NR25 directly to your computer or use a network switch. The NR25 has an “auto-switch” port which eliminates the need for a crossover cable in direct connect applications. If using a side connect unit, then you must power it with a PoE compatible switch. The diagram below shows how to wire a network cable to an NR25 for use as a programming cable.

![Diagram of a programming cable for NR25](image)

Figure 3.2 Sample Programming Cable

Brown/White and Blue/White Pairs are not shown for clarity. Cut off these two pairs inside the cable jacket before wiring to the connector.

NOTE

Figure 3.2 above shows the proper wiring for a cable that is terminated on the RJ45 connector to the TIA/EIA568B standard. The only difference between the 568A and 568B standards is that the two pairs are swapped. With the “auto-switch” port that is built into the NR25, the system will work correctly, regardless of which standard was used to terminate the RJ45 plug.

If you are not using PoE equipment, refer to the Connector Pinout section on page 37 for information on how to wire the power connector of the NR25.
Using the AMCI Net Configurator

Start the Software

To start the program, simply navigate through your start menu and click on the program’s icon. The program will present a screen similar to figure 3.3 below.
Using the AMCI Ethernet Configurator  (continued)

Scanning for your NR25 Encoder
The first step in configuring your NR25 is to connect to it. The simplest method is to use the [Scan] button:
1) Click on the [Scan] button. An AMCI Net Configurator Scan window will open.
2) In the new window, click on the [Scan] button. The NR25 encoder will appear if the NR25 and your computer are on the same network.
3) Select the IP Address of the unit you wish to connect to and then click on the [Connect] button. The window will close and the main program window will now show that you are connected to the NR25.

![AMCI Net Configurator Scan Window](image)

Figure 3.4 AMCI Net Configurator Scan Window

If a scan for the module does not work, then one of two problems is the usual cause. The first cause only occurs if you have two or more network adapters in your computer. (A wireless adapter counts as an adapter.) If this is the case, then it is likely that the identification request to the NR25 is not going out on the correct network interface. You can try to manually connect to your NR25 as outlined below or you can disable all network adapters except for the one used to communicate with the NR25 and try the scan again. The second cause is that the NR25 is not on the same subnet as the network interface. If this is the case, you can try another subnet that is commonly used at your facility, or use a network protocol analyzing program such as Wireshark to view the address of the NR25.
**NR25 CONFIGURATION**

**Using the AMCI Configurator Software  (continued)**

**Manually Connecting to your NR25**

You have the option to manually connect to your NR25 if you already know the address of the unit. If you have multiple network adapters, you may have to use this method to guarantee that the identification requests use the correct network adapter to reach your module.

To start a manual connection, press the [Manual connect] button. This will result in the window shown in figure 3.5 below.

![Figure 3.5 Manually Connect to an NR25](image)

From here, you can enter the IP address and press the [Connect] button.

**The Meaning of the Product Name**

Once you successfully connect to the NR25, the Product Name will show up under the ‘Device Identity’ section of the main window. The Product Name gives you clues to the configuration of the NR25. As shown in figure 3.6 below, the Product Name is broken down into two parts.

![AMCI–NR25–ENIP](image)

“ENIP” = EtherNet/IP Protocol Enabled
"MDBS" = Modbus TCP Protocol Enabled

Figure 3.6 Product Name Description
Using the AMCI Configurator Software (continued)

Changing the IP Address

Once you have connected to your NR25, you will be presented with a window that has two tabs. The first tab, named “Connect” allows you to configure the Ethernet address and protocol used by the NR25. The “General” tab also shows the Device Identity, which includes the revision of the NR25. The second tab, named “NR25” allows you to set the programmable parameters of the unit. A sample window is shown below.

Before you can change the IP address or communication protocol, you have to click on the check box titled “Allow IP configuration changes. You will need to restart the device.”. When the box is checked, the [Set IP Address], [Set As EtherNet/IP Device], and [Set as Modbus TCP Device] buttons are enabled.

The next step in configuring the Ethernet interface is to set the New IP Address, Subnet Mask, and Default Gateway fields to your desired values.

The Default Gateway setting is not optional! In order to comply with the ODVA specification, it must be set to a valid address on the chosen subnet. Because the Default Gateway is often not used in device level networks, if you do not have a required value for it, AMCI suggests setting the Default Gateway to the IP address of your host controller.

Once these values are set, click on the [Set IP Address] button to write these values to the NR25. You will see a pop up window reminding you that you must cycle power to the module before the changes take effect.
Using the AMCI Configurator Software  (continued)

Setting Communications Protocol
Click on either button to set the communications protocol for your Ethernet Interface. When you click on either, you will see a pop up window reminding you that you must cycle power to the NR25 before the changes take effect.

Cycle Power to the NR25
The NR25 will not use the new IP address and protocol settings until the next time it powers up. You must cycle power to the unit before you can test the new IP address.

Testing the New Address
Once the NR25 finishes its power up sequence, close the “Device Properties” window and press the [Scan] button to re-connect to the unit or re-connect to it manually. Use this step will verify the new address and Network Protocol settings.

If you have changed the network address that the NR25 response to, you may have to adjust the address settings of your network interface card before you can reconnect to the module. If you have to change the address of your NIC, refer back to the Configure Your Network Interface Card (NIC) section of this chapter, starting on page 40 if you need additional information.

NR25 Tab
When you are connected to your device, you will notice a tab at the top of the window named “NR25”. This tabs allow you to configure the encoder and test it before attaching it to your host controller.

NOTE
When using RSLogix 5000 as your programming software, you will have to enter data into the associated configuration tags before the NR25 will communicate with your controller. This data will overwrite any settings you make on this screen.
Using the Ping Command

If you do not have access to the AMCI Net Configurator software in the field, the easiest way to test the address of the NR25 is with the “ping” command. Before you can use the command, you have to be sure the encoder and your computer are still on the same subnet. For example, if the new address of the module is 192.168.0.42 and your computer has an address of 192.168.0.1, with a subnet mask of 255.255.255.0, then the two pieces of equipment are on the same subnet. (In this case, the first three numbers of the IP address must match.) If the new address of the module is 192.168.50.50, then the computer and module are not on the same subnet and you must go back into the Network Configuration panel and change your adapter’s TCP/IP settings. Refer back to the Configure Your Network Interface Card (NIC) section of this chapter, starting on page 40.

Once you are sure your computer and NR25 are on the same subnet, open the DOS terminal if necessary:

- For Windows XP, click on the [Start] button, and click on [Run...]. A dialog box will open. Enter ‘cmd’ on the text line and press [Enter] on the keyboard.
- For Vista and Windows 7, click on the [Start] button, and type “cmd” in the “Search programs and files” text box. Press [Enter] on the keyboard.
- For Windows 8, bring up the ‘Apps’ search bar and type “cmd” into the text box. Press [Enter] on the keyboard to open the command prompt.

Once the terminal is open, type in ‘ping aaa.bbb.ccc.ddd’ where ‘aaa.bbb.ccc.ddd’ in the new IP address of your NR25. The computer will ping the module and the message “Reply from aaa.bbb.ccc.ddd: bytes=32 time<10ms TTL=128” should appear four times.

![Command Prompt](image)

Figure 3.8 IP Address Changed Successfully

If the message “Request timed out.” or “Destination host unreachable” appears, then one of four things has occurred:

- You set the new IP address, but have not yet cycled power to the NR25.
- You did not enter the correct address in the ping command.
- The new IP address of the NR25 was not set correctly.
- The NR25 and the computer are not on the same subnet.
CHAPTER 4

RSLogix 5000 EtherNet/IP Configuration

**Implicit Messaging**

Every PLC that is programmed using RSLogix 5000 software supports implicit messaging. These include the ControlLogix and CompactLogix platforms. Implicit messaging means that the PLC processor will automatically exchange data with the NR25 at the programmed RPI time, thereby simplifying the use of the NR25.

The other form of communication is explicit messaging. In explicit messaging, the PLC processor will only communicate with the NR25 when explicitly told to through instructions that are programmed into your ladder logic. Explicit messages can be used in your RSLogix 5000 programs, and for one-shot events, such as presetting the position, they can make your program simpler to follow. Explicit messaging is explained in the next chapter, *RSLogix 500 EtherNet/IP Configuration*, starting on page 59. (Explicit messaging is the only form of communication supported by platforms programmed with the RSLogix 500 software package.)

**RSLogix 5000 Configuration**

When using the ControlLogix and CompactLogix platforms, you have the option of using the Ethernet port that is built into some processors, or a separate Ethernet Bridge module. If the Ethernet port is built into processor, the only step you have to take before adding the NR25 is to create a new project with the correct processor or modify an existing project. Once this is done, the Ethernet port will automatically appear in the Project Tree. If you are using an Ethernet Bridge module, you will have to add the module to the I/O Configuration tree and configure it before adding the NR25 to your project.

Refer to RA documentation for detailed information on configuring your processor or bridge module.

---

**NOTE**

If you are using an Ethernet Bridge module and have difficulty communicating with the NR25, you may have to upgrade the firmware of the Ethernet Bridge module to its latest version. Also, some bridge modules, such as the 1756-ENBT Series A modules will not work with the NR25.
Adding the NR25 to Your Project

You can add the NR25 to your project once the Ethernet port (Built-in or bridge module) is configured.

1) As shown in figure 4.1 on the right, the Ethernet port will be listed under the I/O Configuration tree. Right click on the port and then click on “New Module...” in the pop-up menu.

2) In the resulting window, scroll down the list until you find the entry that has a description of “Generic Ethernet Module”. (Module Type is ETHERNET-MODULE in figure.) Click on the module name to select and then click the [OK] button. A Module Properties window will open.

3) Set the following parameters in the Module Properties window. All parameters not listed here are optional. Figure 4.2 shows a completed screen.

- **Name**: A descriptive name for the NR25.
- **Comm Format**: Data - INT *(MUST be changed from the default Data - DINT.)*
- **IP Address**: Must be the address you set for the NR25. Refer to Chapter 3, *NR25 Configuration* starting on page 40 for information on setting the IP Address of the NR25.

- **Input**: You have four choices:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
<th>Available with:</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>2</td>
<td>Position Value</td>
<td>All firmware revisions</td>
</tr>
<tr>
<td>3</td>
<td>4</td>
<td>Position Value and Velocity Data</td>
<td>All firmware revisions</td>
</tr>
<tr>
<td>104</td>
<td>4</td>
<td>Position Value and Time Stamp</td>
<td>Revision 2.3 and above</td>
</tr>
<tr>
<td>105</td>
<td>4</td>
<td>Position Value and Actual Sensor Reading</td>
<td>Revision 2.3 and above</td>
</tr>
</tbody>
</table>

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
<th>Available with:</th>
</tr>
</thead>
<tbody>
<tr>
<td>101</td>
<td>3</td>
<td>Command and Preset Value</td>
<td>All firmware revisions</td>
</tr>
</tbody>
</table>

Table 4.1 Input Assembly Instances

- **Output**: You have one choice:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
<th>Available with:</th>
</tr>
</thead>
<tbody>
<tr>
<td>101</td>
<td>3</td>
<td>Command and Preset Value</td>
<td>All firmware revisions</td>
</tr>
</tbody>
</table>

Table 4.2 Output Assembly Instance
RSLogix 5000 Configuration (continued)
Adding the NR25 to Your Project (continued)

> **Configuration:** You have two choices:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
<th>Available with:</th>
</tr>
</thead>
<tbody>
<tr>
<td>102</td>
<td>8</td>
<td>Direction Counting Toggle, Scaling Function Control, Measuring Units per Span, Velocity Format</td>
<td>All firmware revisions</td>
</tr>
<tr>
<td>103</td>
<td>12</td>
<td>Direction Counting Toggle, Scaling Function Control, Measuring Units per Span, Total Measurement Range, Velocity Format</td>
<td>Revision 2.3 and above</td>
</tr>
</tbody>
</table>

Table 4.3 Configuration Assembly Instances

> **NOTE**
The NR25 must have valid data in the Configuration Registers before it will communicate with the network. This is true even if you have saved a valid configuration to the NR25 when using the AMCI Net Configurator software. You must put valid data into the Configuration Assembly Instance before the NR25 will send data through the Input Assembly Instance. See **Configuring the NR25** on page 52.

4) Click on [OK] to close the window.

5) Double click on the name you gave the NR25 in the I/O Configuration tree. A “Module Properties” window will open. Click on the “Connections” tab and set the RPI time that is required for your system. The minimum RPI time for an NR25 is two milliseconds. The number of nodes on the network has an effect on the minimum RPI time. You may have to increase this RPI time if your network is heavily loaded. When done, click on [OK] to complete the setup.

**Communication Errors**

> **Error Code 16#0315 Connection Request Error: Invalid Segment Type.** You have programmed an invalid assembly instance in the connection parameters.

> **No communications, but no error code.** Most commonly caused when the Comm Format not set to “Data - INT” or when the number of inputs words is incorrect.
**Configuring the NR25**

The NR25 Must be Configured

NOTE: The NR25 must have valid data in the Configuration Registers before it will communicate with the network. This is true even if you have saved a valid configuration to the NR25 when using the AMCI Net Configurator software. This requirement includes setting values for the Counts per Turn and Velocity Format parameters, even if they are not used in your application. The suggested value for the Counts per Turn parameter is 65,536 (0x0100) and Velocity Format is 0x1F04 (7,940). Missing or incorrect data in the configuration registers is the most common cause of technical support calls to AMCI for the NR25 product family.

Assembly Instance = 102

The NR25 is configured through the eight bytes in the Configuration Assembly Instance assigned to it when you added the encoder to your project. These bytes are accessed through the data tags assigned to the NR25. Table 4.4 below shows the layout of the parameters programmed through the configuration bytes.

<table>
<thead>
<tr>
<th>Byte #</th>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Direction Counting Toggle</td>
<td>“0” = Clockwise increasing counts looking at shaft. “1” = Counter-Clockwise increasing counts looking at shaft.</td>
</tr>
<tr>
<td>1</td>
<td>Scaling Function Control</td>
<td>“0” = Disable Scaling Function. The full resolution of 65,536 counts per turn is used for the Measuring Units per Span. “1” = Enable Scaling Function. The number of counts per turn is set by the Measuring Units of Span parameter below.</td>
</tr>
<tr>
<td>2</td>
<td>Counts per Turn</td>
<td>Sets the number of counts generated over a single turn if the Scaling Function Control parameter equals “1”. This value requires four bytes and ranges from 1 to 65,536. A value of 39,370 (16#99CA) is shown to the right. (See note 1 below.)</td>
</tr>
<tr>
<td>3</td>
<td></td>
<td>CA 99 00 00</td>
</tr>
<tr>
<td>4</td>
<td></td>
<td>CA 99 00 00</td>
</tr>
<tr>
<td>5</td>
<td></td>
<td>CA 99 00 00</td>
</tr>
<tr>
<td>6</td>
<td>Velocity Format</td>
<td>Format of the velocity data. Byte 7 must always equal “1F”. Byte 6 = “04” for pulses/second, “05” for pulses/millisecond, “07” for pulses/minute or “0F” for revolutions/minute. A value of “1F04” to the right would set the unit of measure to pulses/second.</td>
</tr>
<tr>
<td>7</td>
<td></td>
<td>04 1F</td>
</tr>
</tbody>
</table>

Table 4.4 Assembly Instance 102 Configuration Bits

More information on these configuration parameters can be found in chapter 1, starting with the section *Programmable Parameters*, starting on page 14.

NOTE: 1) A valid Counts per Turn value must be entered even if you have disabled the Counts per Turn value by setting the Scaling Function Control set to zero. The default value of 65,536 is a suggested value. (Bytes 2, 3, 5 = 0. Byte 4 = 1.)

2) Once connected, the NR25 will not lose communications with the processor if the configuration data becomes invalid. However, it will not be able to establish communications on the next power up. The error code will be 16#0110

3) If the configuration data is invalid, correcting it is all that is required to establish communications between the NR25 and the processor. Power does not have to be cycled to either device.
Configuring the NR25 (continued)

Assembly Instance = 103 (revision 2.3+ only)

The NR25 is configured through the twelve bytes in the Configuration Assembly Instance assigned to it when you added the encoder to your project. These bytes are accessed through the data tags assigned to the NR25. Table 4.5 below shows the layout of the parameters programmed through the configuration bytes.

<table>
<thead>
<tr>
<th>Byte #</th>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Direction Counting Toggle</td>
<td>“0” = Clockwise increasing counts looking at shaft.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>“1” = Counter-Clockwise increasing counts looking at shaft.</td>
</tr>
<tr>
<td>1</td>
<td>Scaling Function Control</td>
<td>“0” = Disable Scaling Function. The full resolution of 65,536 counts per turn is used for the Measuring Units per Span.</td>
</tr>
<tr>
<td></td>
<td></td>
<td>“1” = Enable Scaling Function. The number of counts per turn is set by the Measuring Units of Span parameter below.</td>
</tr>
<tr>
<td>2</td>
<td>Counts per Turn</td>
<td>Sets the number of counts generated over a single turn if the Scaling Function Control parameter equals “1”. This value requires four bytes and ranges from 1 to 65,536. A value of 39,370 (16#99CA) is shown to the right. (See note 1 below.)</td>
</tr>
<tr>
<td>3</td>
<td></td>
<td></td>
</tr>
<tr>
<td>4</td>
<td></td>
<td></td>
</tr>
<tr>
<td>5</td>
<td></td>
<td></td>
</tr>
<tr>
<td>6</td>
<td>Total Measurement Range</td>
<td>Sets the number of counts before returning to zero. This value is used regardless of the state of the Scaling Function Control parameter. Parameter ranges:</td>
</tr>
<tr>
<td></td>
<td></td>
<td>▶ Single Turn NR25: Range of 0, 2 to 65,536</td>
</tr>
<tr>
<td></td>
<td></td>
<td>▶ 28 bit Multi-turn NR25: Range of 0, 2 to 268,435,456</td>
</tr>
<tr>
<td></td>
<td></td>
<td>▶ 30 bit Multi-turn NR25: Range of 0, 2 to 1,073,741,824</td>
</tr>
<tr>
<td></td>
<td></td>
<td>A value of 648,000 (16#0009E340) is shown to the right.</td>
</tr>
<tr>
<td>7</td>
<td></td>
<td></td>
</tr>
<tr>
<td>8</td>
<td></td>
<td></td>
</tr>
<tr>
<td>9</td>
<td></td>
<td></td>
</tr>
<tr>
<td>10</td>
<td>Velocity Format</td>
<td>Format of the velocity data. Byte 11 must always equal “1F”. Byte 10 = “04” for pulses/second, “05” for pulses/millisecond, “07” for pulses/minute or “0F” for revolutions/minute. A value of “1F04” to the right would set the unit of measure to pulses/second.</td>
</tr>
<tr>
<td>11</td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

Table 4.5 Assemble Instance 103 Configuration Bits

More information on these configuration parameters can be found in chapter 1, starting with the section Programmable Parameters, starting on page 14.

**NOTE**

1) A valid Counts per Turn value must be entered even if you have disabled the Counts per Turn value by setting the Scaling Function Control set to zero. The default value of 65,536 is a suggested value. (Bytes 2, 3, 5 = 0. Byte 4 = 1.)

2) Once connected, the NR25 will not lose communications with the processor if the configuration data becomes invalid. However, it will not be able to establish communications on the next power up. The error code will be 16#0110

3) If the configuration data is invalid, correcting it is all that is required to establish communications between the NR25 and the processor. Power does not have to be cycled to either device.

4) If the Total Measurement Range parameter is set to zero, the parameter is ignored by the NR25 and the position rolls over at its mechanical zero point.
Configuring the NR25  (continued)

Module Fault Code 16#0110

If any of the parameter values are incorrect or missing, the NR25 will respond with a Module Fault Code of 16#0110, Connection Request Error. As shown in the figure to the right, this error can be view under the Connections tab of the Module Properties window.

The NR25 will not communicate with the network if the configuration data is incorrect. The only error indication that you will receive is the 16#0110 Fault Code.

Reading Data from the NR25

All NR25 encoders offer the following Input Assembly Instances:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>2</td>
<td>32 bit Position Value</td>
</tr>
<tr>
<td>3</td>
<td>4</td>
<td>32 bit Position Value and 32 bit Velocity Data</td>
</tr>
</tbody>
</table>

Table 4.6  Input Assembly Instances

NR25 encoders that are revision 2.3 and above offer the following additional Input Assembly Instances:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
</tr>
</thead>
<tbody>
<tr>
<td>104</td>
<td>4</td>
<td>32 bit Position Value and 32 bit Time Stamp</td>
</tr>
<tr>
<td>105</td>
<td>4</td>
<td>32 bit Position Value and 32 bit Actual Sensor Reading</td>
</tr>
</tbody>
</table>

Table 4.7  Rev 2.3+ Additional Input Assembly Instances

If you plan to preset the position value and store the resulting internal position offset to Flash memory, then AMCI strongly suggests using Assembly Instances 3, 104, or 105. The NR25 uses the second data register to notify the processor when the data has been stored in the Flash memory of the NR25. See Storing Configuration Data and the Internal Position Offset on page 57 for more information.

Buffering Read Data

Ethernet Data is read asynchronously to the scan at the RPI time, therefore, you must buffer the data from the NR25. Data must be buffered with Synchronous Copy instructions (CPS) to ensure that the data is not updated during the copy. If the data is not buffered, it can change during a program scan, resulting in logical errors that may result in machine malfunction.
Reading Data from the NR25 (continued)

Assembly Instance = 1
As shown in the table below, when you set the Input Assembly Instance to 1, the input data consists of the position value transferred as two 16 bit words.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Position Value. The maximum position value depends on your NR25 model and the programmed counts per turn. The maximum value in all cases is 1,073,741,823 (16#3FFF FFFF). Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the position value is 1,274,237 (16# 0013 717D)</td>
<td>16#717D</td>
</tr>
<tr>
<td>1</td>
<td></td>
<td>16#0013</td>
</tr>
</tbody>
</table>

Table 4.8  Input Data, Position Only

Assembly Instance = 3
As shown in the table below, when you set the Input Assembly Instance to 3, the input data consists of the position value and velocity data transferred in a total of four 16 bit words.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Position Data. The maximum position value depends on your NR25 model and the programmed counts per turn. The maximum value in all cases is 1,073,741,823 (16#3FFF FFFF). Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the position value is 1,274,237 (16# 0013 717D)</td>
<td>16#717D</td>
</tr>
<tr>
<td>1</td>
<td></td>
<td>16#0013</td>
</tr>
<tr>
<td>2</td>
<td>Velocity Data. The units of measure of the velocity data is set by the Velocity Format parameter in the Configuration Data. If the Scaling Function Control bit is ever set to “1”, the position data used to calculate the velocity data is always scaled by the Measuring Units per Span parameter. Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the velocity value is 461,725 (16# 0007 0B9D)</td>
<td>16#0B9D</td>
</tr>
<tr>
<td>3</td>
<td></td>
<td>16#0007</td>
</tr>
</tbody>
</table>

Table 4.9  Input Data, Position and Velocity

Assembly Instance = 104
(Revision 2.3+ only)
As shown in the table below, when you set the Input Assembly Instance to 104, the input data consists of the position value and time stamp transferred in a total of four 16 bit words.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Position Data. The maximum position value depends on your NR25 model and the programmed counts per turn. The maximum value in all cases is 1,073,741,823 (16#3FFF FFFF). Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the position value is 1,274,237 (16# 0013 717D)</td>
<td>16#717D</td>
</tr>
<tr>
<td>1</td>
<td></td>
<td>16#0013</td>
</tr>
<tr>
<td>2</td>
<td>Time Stamp. The time stamp is an unsigned double integer value with an interval of 400 nanoseconds. It will roll over every 1717.9869184 seconds. The time stamp can be used to verify active communications between the NR25 and your host controller. The values on the right show the register values in hexadecimal if the time stamp is 204,813,002 (16# 0C35 32CA)</td>
<td>16#32CA</td>
</tr>
<tr>
<td>3</td>
<td></td>
<td>16#0C35</td>
</tr>
</tbody>
</table>

Table 4.10  Input Data, Position and Time Stamp
Reading Data from the NR25 (continued)

Assembly Instance = 105
(Revision 2.3+ only)

As shown in the table below, when you set the Input Assembly Instance to 105, the input data consists of the position value and the actual sensor position reading transferred in a total of four 16 bit words.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>16#717D</th>
<th>16#0013</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Position Data. The maximum position value depends on your NR25 model and the programmed counts per turn. The maximum value in all cases is 1,073,741,823 (16#3FFF FFFF). Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the position value is 1,274,237 (16# 0013 717D)</td>
<td>16#717D</td>
<td>16#0013</td>
</tr>
<tr>
<td>1</td>
<td>Actual Sensor Reading. This unsigned double integer value is the raw position data from the NR25. Changing the position scaling parameters have no effect on this value. The values on the right show the register values in hexadecimal if the Actual Sensor Reading value is 637,091,550 (16# 25F9 3EDE)</td>
<td>16#3EDE</td>
<td>16#25F9</td>
</tr>
</tbody>
</table>

Table 4.11 Input Data, Position and Actual Sensor Reading

Writing Data to the NR25

The three output words assigned to the NR25 are used to preset the position value and to save the resulting offset into non-volatile memory. Configuration data is also saved. The format of the output assembly words is shown below.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>16#BF2F</th>
<th>16#000A</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Command Word. Transitions on bits in this word will either preset the position value or store the resulting position offset in non-volatile memory.</td>
<td>16#BF2F</td>
<td>16#000A</td>
</tr>
<tr>
<td>1</td>
<td>Preset Value. The value that you want the position to become when you issue the Preset Command. The Preset Value can be any number between 0 and the configured full scale count of the encoder. The values on the right show the register values in hexadecimal if the Preset Value is 704,303 (16# 000A BF2F)</td>
<td>16#BF2F</td>
<td>16#000A</td>
</tr>
</tbody>
</table>

Table 4.12 Output Assembly Instance Data Format

Presetting the Position Value

The position value is preset when the NR25 detects the proper bit transitions in the Command Word. You begin the process by writing the desired Preset Value into words 1 and 2 and setting the Command Word to 16#0002. (2 decimal, the last four bits in binary are 0010). You must then hold these values for a length of time greater than the RPI time you programmed for the NR25 when you added it to your project. This is to guarantee that these values have been written to the NR25. After the RPI time has elapsed, change the Command Word value to 16#000D. (13 in decimal, the last four bits in binary are 1101.) The NR25 will respond by changing the position value to the Preset Value by calculating and applying an internal position offset.

The internal position offset is stored in volatile RAM memory and is lost when power is cycled to the NR25. This is acceptable in some applications because the machine has to be aligned on every power up. If you want to preset the position value once and have it apply the internal position offset on every power up, then you must command the NR25 to store the internal offset in non-volatile memory. NR25 encoders with a firmware revision 2.3 and above will automatically store the internal position offset to non-volatile memory if the value of the Total Measurement Range parameter is non-zero.

The AMCI RSLogix 5000 sample program for the NR25 includes the code to preset the position value. The sample program is available on our website, www.amci.com.
Writing Data to the NR25  (continued)

Storing Configuration Data and the Internal Position Offset

The data sent to the NR25 through the configuration tags, as well as the internal position offset, is stored when the NR25 detects the proper bit transitions in the Command Word. The parameters that are set with the configuration data are listed in the Configuring the NR25 section of this chapter, starting on page 52.

1) You begin the process by setting the Command Word to 16#0020. (32 decimal, the last eight bits in binary are 0010 0000).

2) You must then hold this value for a length of time greater than the RPI time you programmed for the NR25 when you added it to your project. This guarantees that the value is written to the NR25.

3) After the RPI time has elapsed, change the Command Word value to 16#00D0. (208 in decimal, the last eight bits in binary are 1101 0000.)

4) The NR25 will store the values. If you are using Assembly Instances 3, 104, or 105 the NR25 responds by changing the Velocity, Time Stamp, or Actual Sensor Reading to a value of 16#EEEE EEEE on a successful write or a value of 16#AAAA AAAA on an error. The data in the second 32 bit word will remain at this value until power to the NR25 is cycled.

**NOTE**

1) Once the command to store the internal position offset is accepted, the NR25 will ignore all further save commands until power is cycled to the unit. This is to prevent damage to the Flash memory of the NR25 by attempting to write to it too many times. Preset commands will be accepted and acted upon, but you will not be able to store the new internal offset to Flash memory and the internal offset will be lost during the next power cycle.

2) If you are using Assembly Instance 1 for your input tags, then you are only receiving the position data and the NR25 will not be able to indicate that the store command was completed successfully. Because of this, AMCI strongly suggests that you use Assembly Instances 3, 104, or 105 for your input tags if your application requires you to store the configuration data or internal position offset.

3) If your NR25 encoder is revision 2.3 or greater, the unit will automatically store the internal position offset in non-volatile FRAM memory if the Total Measurement Range parameter is non-zero.

The AMCI RSLogix 5000 sample program for the NR25 includes the code to store the internal offset in Flash memory. The sample program is available on our website, www.amci.com.

**NOTE**

You have two options if you need to store the internal offset in non-volatile memory every time you preset the position. The first is to use a configuration assembly instance of 103 and set the Total Measurement Range parameter to a non-zero value. The second option is to use an explicit message instruction that is added to your ladder logic. Programming explicit message instructions is covered in the next chapter, with parameter values given in the Save Configuration and Offset Message Instruction section on page 71.
Explicit Messaging

Every PLC that is programmed using RSLogix 500 software, such as the MicroLogix platform, must use explicit messaging to communicate with the NR25. In explicit messaging, the PLC processor will only communicate with the NR25 when explicitly told to through Message Instructions that are programmed into your ladder logic.

The other form of communication is implicit messaging. Implicit messaging is only supported by Allen Bradley PLC platforms that are programmed using the RSLogix 5000 software. Implicit messaging means that the PLC processor will automatically exchange data with the NR25 at the programmed RPI time, thereby simplifying the use of the NR25. Implicit messaging is explained in the previous chapter, RSLogix 5000 EtherNet/IP Configuration, which started on page 49.

You can use explicit messaging on platforms that are programmed using the RSLogix 5000 software. The configuration and use of Message Instructions given here are also applicable to the RSLogix 5000 software.

RSLogix 500 Configuration

When using the MicroLogix platforms, you have to configure the Ethernet port that is built into some processors before adding the NR25 to your project.

Only RSLogix 500 version 8.0 or above can be used to configure Message Instructions to communicate with an Ethernet IP device.

Configuring a Built-in Ethernet Port

You have to set an IP address for the built in Ethernet port before communicating with the NR25. Right click on the port name in the I/O Configuration screen and select “Properties”. A Module Properties window similar to the one shown in figure 5.1 will open. In this window you must set the IP Address for the port, not the IP address of the NR25.
Read Data Format

The Assembly Instance of a Message Instruction that is used to read data from an NR25 defines the data that is transferred. All NR25 encoders respond to the following Input Assembly Instances:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>2</td>
<td>32 bit Position Value</td>
</tr>
<tr>
<td>3</td>
<td>4</td>
<td>32 bit Position Value and 32 bit Velocity Data</td>
</tr>
</tbody>
</table>

Table 5.1 Input Assembly Instances

NR25 encoders that are revision 2.3 and above respond to the following additional Input Assembly Instances:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
</tr>
</thead>
<tbody>
<tr>
<td>104</td>
<td>2</td>
<td>32 bit Position Value and 32 bit Time Stamp</td>
</tr>
<tr>
<td>105</td>
<td>4</td>
<td>32 bit Position Value and 32 bit Actual Sensor Reading</td>
</tr>
</tbody>
</table>

Table 5.2 Rev 2.3+ Additional Input Assembly Instances

Assembly Instance = 1

When you use an Assembly Instance to 1, the input data consists of the position value transferred as two 16 bit words.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Position Value. The maximum position value depends on your NR25 model and the programmed counts per turn. The maximum value in all cases is 1,073,741,823 (16#3FFF FFFF). Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the position value is 1,274,237 (16# 0013 717D)</td>
<td>16#717D</td>
</tr>
<tr>
<td>1</td>
<td></td>
<td>16#0013</td>
</tr>
</tbody>
</table>

Table 5.3 Input Data, Position Only

Assembly Instance = 3

When you use an Assembly Instance to 3, the input data consists of the position value and velocity data transferred in a total of four 16 bit words.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>Position Data. The maximum position value depends on your NR25 model and the programmed counts per turn. The maximum value in all cases is 1,073,741,823 (16#3FFF FFFF). Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the position value is 1,274,237 (16# 0013 717D)</td>
<td>16#717D</td>
</tr>
<tr>
<td>1</td>
<td></td>
<td>16#0013</td>
</tr>
<tr>
<td>2</td>
<td>Velocity Data. The units of measure of the velocity data is set by the Velocity Format parameter in the Configuration Data. If the Scaling Function Control bit is ever set to a “1”, the position data used to calculate the velocity data is always scaled by the Measuring Units per Span parameter. Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the velocity value is 461,725 (16# 0007 0B9D)</td>
<td>16#0B9D</td>
</tr>
<tr>
<td>3</td>
<td></td>
<td>16#0007</td>
</tr>
</tbody>
</table>

Table 5.4 Input Data, Position and Velocity
**Read Data Format (continued)**

**Assembly Instance = 104 (revision 2.3+ only)**

When you use an Assembly Instance to 104, the input data consists of the position value and time stamp transferred in a total of four 16 bit words.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td><strong>Position Data.</strong> The maximum position value depends on your NR25 model and the programmed counts per turn. The maximum value in all cases is 1,073,741,823 (16#3FFF FFFF). Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the position value is 1,274,237 (16# 0013 717D).</td>
<td>16#717D</td>
</tr>
<tr>
<td>1</td>
<td><strong>Time Stamp.</strong> The time stamp is an unsigned double integer value with an interval of 400 nanoseconds. It will roll over every 1717.9869184 seconds. The time stamp can be used to verify active communications between the NR25 and your host controller. The values on the right show the register values in hexadecimal if the time stamp is 204,813,002 (16# 0C35 32CA).</td>
<td>16#32CA</td>
</tr>
<tr>
<td>2</td>
<td><strong>Actual Sensor Reading.</strong> This unsigned double integer value is the raw position data from the NR25. Changing the position scaling parameters have no effect on this value. The values on the right show the register values in hexadecimal if the Actual Sensor Reading value is 637,091,550 (16# 25F9 3EDE).</td>
<td>16#25F9</td>
</tr>
</tbody>
</table>

Table 5.5 Input Data, Position and Time Stamp

**Assembly Instance = 105 (revision 2.3+ only)**

When you use an Assembly Instance to 105, the input data consists of the position value and the actual sensor position reading transferred in a total of four 16 bit words.

<table>
<thead>
<tr>
<th>Word #</th>
<th>Description</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td><strong>Position Data.</strong> The maximum position value depends on your NR25 model and the programmed counts per turn. The maximum value in all cases is 1,073,741,823 (16#3FFF FFFF). Note that the two 16 bit registers are combined into a single 32 bit data word. The values on the right show the register values in hexadecimal if the position value is 1,274,237 (16# 0013 717D).</td>
<td>16#717D</td>
</tr>
<tr>
<td>1</td>
<td><strong>Actual Sensor Reading.</strong> This unsigned double integer value is the raw position data from the NR25. Changing the position scaling parameters have no effect on this value. The values on the right show the register values in hexadecimal if the Actual Sensor Reading value is 637,091,550 (16# 25F9 3EDE).</td>
<td>16#25F9</td>
</tr>
</tbody>
</table>

Table 5.6 Input Data, Position and Actual Sensor Reading

**Write Data Format**

The Assembly Instance of a Message Instruction that is used to write configuration data to an NR25 defines the data that is transferred. All NR25 encoders respond to the following Input Assembly Instances:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
</tr>
</thead>
<tbody>
<tr>
<td>102</td>
<td>8</td>
<td>Direction Counting Toggle, Scaling Function Control, Counts per Turn, Velocity Format</td>
</tr>
</tbody>
</table>

Table 5.7 Write Assembly Instances

NR25 encoders that are revision 2.3 and above respond to the following additional Input Assembly Instances:

<table>
<thead>
<tr>
<th>Assembly</th>
<th>Size</th>
<th>Data</th>
</tr>
</thead>
<tbody>
<tr>
<td>103</td>
<td>12</td>
<td>Direction Counting Toggle, Scaling Function Control, Counts per Turn, Total Measurement Range, Velocity Format</td>
</tr>
</tbody>
</table>

Table 5.8 Rev 2.3+ Additional Write Assembly Instances
**Write Data Format (continued)**

Assembly Instance = 102

Table 5.9 below shows the layout of the programmed parameters when you use an Assembly Instance of 102. If you have an NR25 revision 2.3 or greater, the Total Measurement Range parameter stays at its last value.

<table>
<thead>
<tr>
<th>Byte#</th>
<th>Word #</th>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0.0</td>
<td>Direction Counting Toggle</td>
<td>“0” = Clockwise increasing counts looking at shaft. “1” = Counter-Clockwise increasing counts looking at shaft.</td>
</tr>
<tr>
<td>1</td>
<td>0.8</td>
<td>Scaling Function Control</td>
<td>“0” = Disable Scaling Function. The full resolution of 65,536 counts per turn is used for the Measuring Units per Span. “1” = Enable Scaling Function. The number of counts per turn is set by the Measuring Units of Span parameter below.</td>
</tr>
<tr>
<td>2</td>
<td>1</td>
<td>Measuring Units per Span (Counts per Turn)</td>
<td>Sets the number of counts generated over a single turn if the Scaling Function Control parameter equals “1”. This value requires four bytes and ranges from 1 to 65,536. A value of 39,370 (16#99CA) is shown to the right.</td>
</tr>
<tr>
<td>3</td>
<td>2</td>
<td>Velocity Format</td>
<td>Format of the velocity data. Byte 7 must always equal “1F”. Byte 6 = “04” for pulses/second, “05” for pulses/millisecond, “07” for pulses/minute or “0F” for revolutions/minute. A value of “1F04” to the right would set the unit of measure to pulses/second.</td>
</tr>
<tr>
<td>4</td>
<td>3</td>
<td>Velocity Format</td>
<td></td>
</tr>
</tbody>
</table>

Table 5.9 Configuration Data: Assembly Instance 102

More information on these configuration parameters can be found in chapter 1, starting with the section *Programmable Parameters*, starting on page 14.

**NOTE**

A valid Counts per Turn value must be entered even if you have disabled the Counts per Turn value by setting the Scaling Function Control set to zero. The default value of 65,536 is a suggested value. (Bytes 2, 3, 5 = 0. Byte 4 = 1.)
**Write Data Format (continued)**

Assembly Instance = 103 (revision 2.3+ only)

Table 5.10 below shows the layout of the programmed parameters when you use an Assembly Instance of 103.

<table>
<thead>
<tr>
<th>Byte #</th>
<th>Word #</th>
<th>Parameter</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0.0</td>
<td>Direction Counting Toggle</td>
<td>“0” = Clockwise increasing counts looking at shaft. “1” = Counter-Clockwise increasing counts looking at shaft.</td>
</tr>
<tr>
<td>1</td>
<td>0.8</td>
<td>Scaling Function Control</td>
<td>“0” = Disable Scaling Function. The full resolution of 65,536 counts per turn is used for the Measuring Units per Span. “1” = Enable Scaling Function. The number of counts per turn is set by the Measuring Units of Span parameter below.</td>
</tr>
<tr>
<td>2</td>
<td>1</td>
<td>Measuring Units per Span</td>
<td>Sets the number of counts generated over a single turn if the Scaling Function Control parameter equals “1”. This value requires four bytes and ranges from 1 to 65,536. A value of 39,370 (16#99CA) is shown to the right.</td>
</tr>
<tr>
<td>3</td>
<td>2</td>
<td>Total Measurement Range</td>
<td>Sets the number of counts before returning to zero. This value is used regardless of the state of the Scaling Function Control parameter. Parameter ranges:</td>
</tr>
<tr>
<td>4</td>
<td>3</td>
<td>Velocity Format</td>
<td>Format of the velocity data. Byte 11 must always equal “1F”. Byte 10 = “04” for pulses/second, “05” for pulses/millisecond, “07” for pulses/minute or “0F” for revolutions/minute. A value of “1F04” to the right would set the unit of measure to pulses/second.</td>
</tr>
</tbody>
</table>

Table 5.10 Configuration Data: Assembly Instance 103

More information on these configuration parameters can be found in chapter 1, starting with the section Programmable Parameters, starting on page 14.

**NOTE**

A valid Counts per Turn value must be entered even if you have disabled the Counts per Turn value by setting the Scaling Function Control set to zero. The default value of 65,536 is a suggested value. (Bytes 2, 3, 5 = 0. Byte 4 = 1.)
**Presetting the Position Value**

A custom Message Instruction with the Generic Set_Attribute_Single service type is used to preset the position value of the NR25. The format of the data for this Message Instruction is shown below.

<table>
<thead>
<tr>
<th>Byte #</th>
<th>Word #</th>
<th>Description</th>
<th>Value</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>1</td>
<td><strong>Preset Value.</strong></td>
<td>2F</td>
</tr>
<tr>
<td>1</td>
<td></td>
<td></td>
<td>BF</td>
</tr>
<tr>
<td>2</td>
<td>2</td>
<td></td>
<td>0A</td>
</tr>
<tr>
<td>3</td>
<td></td>
<td></td>
<td>00</td>
</tr>
</tbody>
</table>

1) The internal position offset is stored in volatile RAM memory and is lost when power is cycled to the NR25. This is acceptable in some applications because the machine has to be aligned on every power up. If you want to preset the position value once and have it apply the internal position offset on every power up, then you must issue a Message Instruction with the Save command. (See the Saving Configuration Data and Position Offset section below.) This command stores the configuration data and the internal position offset in non-volatile memory.

2) The Flash memory in the NR25 revision 1.9 or less is guaranteed for a minimum of 10,000 write cycles.

3) The FRAM memory in the NR25 revision 2.3 and above does not have a limited number of write cycles.

NR25 encoders with a firmware revision 2.3 and above will automatically store the internal position offset to non-volatile memory if the value of the Total Measurement Range parameter is non-zero. You do not have to issue a Save command to store the internal position offset if the Total Measurement Range parameter is non-zero.

The AMCI RSLogix 500 sample program for the NR25 includes the code to preset the position value. The sample program is available on our website, www.amci.com.

**Saving Configuration Data and Position Offset**

The internal position offset, as well as the configuration data, is stored in non-volatile memory when the NR25 detects a Save command. The Message Instruction that sends the Save command is a custom instruction that has no data. (The Class and Service Code of the Message Instruction are used by the NR25 to determine that the instruction is a Save command.).

Once the command is issued, the data is stored when the Done bit of the Message Instruction is set. You must cycle power to the NR25 before another Save command will be accepted.

1) The Flash memory in the NR25 revision 1.9 or less is guaranteed for a minimum of 10,000 write cycles.

2) The FRAM memory in the NR25 revision 2.3 and above does not have a limit on the number of permitted write cycles.
**Determining Needed Registers**

Before adding the logic needed to communicate with the NR25 and use the data from it, you have to assign registers that will be used to hold the data. The top of the following table lists the types and sizes of all of the data that can be read from or written to the NR25.

The center section of the table lists the additional registers needed to buffer the data from the Message Instructions that read data from the NR25. These registers are required because the Message Instructions complete asynchronously to the program scan.

**WARNING** If data read with Message Instructions is not buffered, this data can change during a program scan, resulting in logical errors that may result in machine malfunction.

The bottom section of the table lists the Message (MG) data file and Extended Routing Information (RIX) data file types needed to control the Message Instructions. Each NR25 requires a separate file of each type, and these files must have one element for each Message Instruction associated with the NR25.

<table>
<thead>
<tr>
<th>Value</th>
<th>Type</th>
<th>Size</th>
<th>Availability</th>
</tr>
</thead>
<tbody>
<tr>
<td>Position</td>
<td>Integer</td>
<td>2 Words</td>
<td>All NR25 encoders</td>
</tr>
<tr>
<td>Position and Velocity</td>
<td>Integer</td>
<td>4 Words</td>
<td>All NR25 encoders</td>
</tr>
<tr>
<td>Position and Time Stamp</td>
<td>Integer</td>
<td>4 Words</td>
<td>NR25 revision 2.3+ only</td>
</tr>
<tr>
<td>Position and Actual Sensor Reading</td>
<td>Integer</td>
<td>4 Words</td>
<td>NR25 revision 2.3+ only</td>
</tr>
<tr>
<td>Direction Counting Toggle</td>
<td>Upper byte of Integer</td>
<td>1/2 Word</td>
<td>All NR25 encoders</td>
</tr>
<tr>
<td>Scaling Function Control</td>
<td>Lower byte of Integer</td>
<td>1/2 Word</td>
<td>All NR25 encoders</td>
</tr>
<tr>
<td>Measuring Units per Span</td>
<td>Integer</td>
<td>2 Words</td>
<td>All NR25 encoders</td>
</tr>
<tr>
<td>Total Measurement Range</td>
<td>Integer</td>
<td>2 Words</td>
<td>NR25 revision 2.3+ only</td>
</tr>
<tr>
<td>Velocity Format</td>
<td>Integer</td>
<td>2 Words</td>
<td>All NR25 encoders</td>
</tr>
<tr>
<td>Preset Value</td>
<td>Integer</td>
<td>2 Words</td>
<td>All NR25 encoders</td>
</tr>
<tr>
<td>Buffered Position</td>
<td>Integer</td>
<td>2 Words</td>
<td></td>
</tr>
<tr>
<td>Buffered Velocity</td>
<td>Integer</td>
<td>2 Words</td>
<td></td>
</tr>
<tr>
<td>Buffered Time Stamp</td>
<td>Integer</td>
<td>2 Words</td>
<td></td>
</tr>
<tr>
<td>Buffered Actual Sensor Reading</td>
<td>Integer</td>
<td>2 Words</td>
<td></td>
</tr>
<tr>
<td>Message Element</td>
<td>Message (MG)</td>
<td>–</td>
<td>Each NR25 requires a separate file, and each Message Instruction requires a separate element in that file.</td>
</tr>
<tr>
<td>RIX Element</td>
<td>(RIX)</td>
<td>–</td>
<td>Each NR25 requires a separate file, and each Message Instruction requires a separate element in that file.</td>
</tr>
</tbody>
</table>

*Table 5.12  Suggested Register Allocation*

Additional registers will most likely be needed in your application. For example, the NR25 sample program available on the AMCI website uses a block of seven Long integers to convert the buffered data from 16-bit integers to 32-bit long values. An additional Long integer is used to store the Preset Value that is then converted to the two integers listed above before it is written to the NR25.
Configuring a Message Instruction

Figure 5.2 shows Message Instructions as they appear in your ladder logic.

1) Start to configure the Message Instruction by double clicking on the Setup Screen text that is inside the Message Instruction. The window in figure 5.3 will open. Note that this is the default window and its appearance will change considerably as you progress through these steps.

2) Double click in the Channel field, click on the ▼, select “1 (Integral)”, and press Enter.

3) Double click in the Communication Command field, click on the ▼, select “CIP Generic” and press Enter.
Configuring a Message Instruction (continued)

The rest of this section is broken down into four parts. Continue with the sub-section that is specific to the Message Instruction you are programming.

- **Read Message Instructions**: See below
- **Write Configuration Message Instructions**: Starts on page 68
- **Apply Preset Message Instruction**: Starts on page 70.
- **Save Configuration and Offset Message Instruction**: Starts on page 71.

Read Message Instructions

As shown in the table below, the NR25 will respond to four different Read Message Instructions. NR25 encoders with a revision of 1.9 or less will only respond to Assembly Instances 1 and 3. An error will result if you attempt to read from one of these NR25 encoders with an Assembly Instance 104 or 105. NR25 encoders with a revision of 2.3 or higher will respond to all four types of Assembly Instances.

<table>
<thead>
<tr>
<th>Position Value Only</th>
<th>Position Value and Velocity Data</th>
<th>Position Value and Time Stamp</th>
<th>Position Value and Actual Sensor Reading</th>
</tr>
</thead>
<tbody>
<tr>
<td>Size in Bytes</td>
<td>4 bytes</td>
<td>8 bytes</td>
<td>8 bytes</td>
</tr>
<tr>
<td>Instance</td>
<td>1 (decimal)</td>
<td>3 (decimal)</td>
<td>104 (decimal)</td>
</tr>
<tr>
<td></td>
<td></td>
<td></td>
<td>105 (decimal)</td>
</tr>
</tbody>
</table>

Table 5.13 Attributes: Explicit Read Message Instructions

1) Enter the integer file address where the data will be placed in the Data Table Address (Received) field and press Enter.
2) Enter the correct value in the ‘Size in Bytes (Receive)’ field. The size is determined by the data you wish to transfer from the NR25. Refer to table 5.13 above to determine the correct value for this field.
3) Enter a RIX address in the Extended Routing Info field. Please note that each Message Instruction must have its own RIX address.
4) Double click in the Service field, select “Read Assembly” for a Message Instruction type and press Enter.
5) The Service Code field will change to “E” (hex), the Class field will change to “4” (hex), and the Attribute field will change to “3” (hex).
6) Enter the correct value in the ‘Instance’ field. This value determines the data that will be transferred by the NR25. Refer to table 5.13 above to determine the correct value for this field.
Configuring a Message Instruction (continued)

Read Message Instructions (continued)

The figure below shows a typical configuration for a Message Instruction that reads data from an NR25. Please note that the Data Table Address (Receive), Size in Bytes (Receive), and RIX fields may be different in your application.

Figure 5.4 Read Message Instruction Setup Screen

7) Jump to the section, Setting the MultiHop Address, which is on page 72, to finish configuring the Message Instruction.

Write Configuration Message Instructions

Write Message Instructions are used to write programmable parameters to the NR25. As shown in the table below, the NR25 will respond to two different Write Message Instructions. NR25 encoders with a revision of 1.9 or less will only respond to Assembly Instance 102. An error will result if you attempt to write to one of these NR25 encoders with an Assembly Instance 103. NR25 encoders with a revision of 2.3 or higher will respond to both types of Assembly Instances.

<table>
<thead>
<tr>
<th>Attribute Name</th>
<th>Value 1</th>
<th>Value 2</th>
</tr>
</thead>
<tbody>
<tr>
<td>Length</td>
<td>8 bytes</td>
<td>12 bytes</td>
</tr>
<tr>
<td>Instance</td>
<td>102 (decimal)</td>
<td>103 (decimal)</td>
</tr>
</tbody>
</table>

Table 5.14 Attributes: Explicit Write Message Instructions

1) Enter the integer file address where the source data is located into the ‘Data Table Address (Send)’ field and press Enter.

2) Enter the correct value in the ‘Size in Bytes (Send)’ field. The size is determined by the data you wish to transfer to the NR25. Refer to table 5.14 above to determine the correct value for this field.

3) Enter a RIX address in the Extended Routing Info field. Please note that each Message Instruction must have its own RIX address.
**Configuring a Message Instruction (continued)**

Write Configuration Message Instructions (continued)

4) Double click in the Service field, select “Write Assemble”, and press Enter.

5) The Service Code field will change to “10” (hex). The Class field will change to “4” (hex), and the Attribute field will change to “3” (hex).

6) Enter the correct value in the ‘Instance’ field. This value determines the data that will be transferred to the NR25. Refer to table 5.14 above to determine the correct value for this field.

The figure below show a typical Message Instruction for writing configuration data to an NR25. Please note that the Data Table Address (Send) field and RIX field may be different in your application.

![Figure 5.5 Configuration Message Instruction Setup Screen](image)

7) Jump to the section, *Setting the MultiHop Address*, which is on page 72, to finish configuring the Message Instruction.
Configuring a Message Instruction (continued)

Apply Preset Message Instruction

A Generic Message Instruction is used to preset the position value of the NR25.

1) Enter the integer file address where the desired position preset value is located into the ‘Data Table Address (Send)’ field and press Enter.

2) Enter a value of “4” in the Size In Bytes (Send) field.

3) Enter a RIX address in the Extended Routing Info field. Please note that each Message Instruction must have its own RIX address.

4) Double click in the Service field, select “Generic Set Attribute Single”, and press Enter.

5) The Service Code field will change to “10” (hex).

6) Enter a value of 16#23 into the Class field.

7) Enter a value of 1 into the Instance field.

8) Enter a value of 16#13 into the Attribute field.

The figure below show a typical Message Instruction for issuing a Preset Command to an NR25. Please note that the Data Table Address (Send) field and RIX field may be different in your application.

9) Jump to the section, Setting the MultiHop Address, which is on page 72, to finish configuring the Message Instruction.
**Configuring a Message Instruction (continued)**

**Save Configuration and Offset Message Instruction**

A Custom Message Instruction is used to save the present configuration of the NR25. The instruction will also save the internal position offset that is modified by an Apply Preset Message Instruction.

If your NR25 is revision 2.3 or above, setting the *Total Measurement Range* parameter to a non-zero value will force the NR25 to automatically store the internal position offset to non-volatile FRAM. Using the *Total Measurement Range* parameter this way only affects how the internal position offset is stored. You must still issue this Message Instruction to save the programmable parameters to non-volatile memory. See *Storage of Internal Position Offset* found on page 16 for information on how to set the *Total Measurement Range* parameter.

1) The Save Configuration and Offset Message Instruction does not write any data to the NR25 so you can ignore the Data Table Address and Size in Byte parameters. Once you save this instruction and re-open the window, you will see that the address field has been removed and the length fields are set to zero.

2) Enter a RIX address in the Extended Routing Info field. Please note that each Message Instruction must have its own RIX address.

3) Double click in the Service field, select “Custom”, and press Enter.

4) Change the Service Code field to 16#16.

5) Change the Class field to 16#23 (35 decimal).

6) Change the Instance field and Attribute field to zero.

The figure below show a typical Message Instruction for issuing a Save Command to an NR25. Please note that the RIX field may be different in your application.

![Figure 5.7 Save Message Instruction Setup Screen](image)

7) Continue to the section, *Setting the MultiHop Address*, which is on the next page, to finish configuring the Message Instruction.
Configuring a Message Instruction  (continued)

Setting the MultiHop Address

After setting the fields on the General tab, click on the MultiHop tab in the setup window. You must enter the IP address of the NR25 in the “To Address” field. The default NR25 address is shown in the figure below.

![Figure 5.8 Message Instruction MultiHop Settings](image)

Troubleshooting Message Instructions

These are the main causes of communication errors when using an NR25:

- The IP address or netmask are not set correctly when the processor’s Ethernet port was configured.
- The Message Instruction Instance or Length parameters are not set correctly.
- The To Address field of the Message Instruction, found under the MultiHop tab, is not set to the address the NR25 is configured for.
- The Configuration data is not formatted correctly. The proper format of the Configuration data is shown in the next section.

Configuration Error Response

If any of the parameter values are incorrect, the NR25 will respond by setting the Message Instruction’s Error bit. As shown in the figure below, the error can be view under the General tab of the Message Instruction Setup Window. The following message is in response to an invalid Velocity Format parameter.

![Figure 5.9 Configuration Error Response](image)
NR25 Memory Layout

All NR25 encoders, regardless of revision, use six 16-bit input registers and seven 16-bit output registers to communicate through the Modbus protocol. NR25 encoders with revision 2.3+ require eight 16-bit input registers and nine 16-bit output registers to access the time stamp value and to program the Total Measurement Range parameter. Figure 6.1 shows how these registers are mapped to the Modbus data reference. The complete specification for the Modbus protocol can be downloaded at http://www.modbus.org/specs.php.

![Register Map for All NR25 Encoders
Must be used by NR25 revision 1.9 or less](image1)

![Optional Register Map for NR25 Encoders
of revision 2.3 or greater](image2)

Figure 6.1 Modbus Data Reference Map

Supported Modbus Functions

<table>
<thead>
<tr>
<th>Function Code</th>
<th>Function Name</th>
<th>NR25 Register</th>
<th>Addressing method</th>
</tr>
</thead>
<tbody>
<tr>
<td>1</td>
<td>Read Coils</td>
<td>OUTPUT</td>
<td>Bit: Address 16,384 through 16,527</td>
</tr>
<tr>
<td>2</td>
<td>Read Discrete Inputs</td>
<td>INPUT</td>
<td>Bit: Address 0 through 127</td>
</tr>
</tbody>
</table>
| 3             | Read Holding Registers   | OUTPUT & INPUT| Word: Out Regs. 1024 through 1032
In Regs. 0 through 7 |
| 4             | Read Input Registers     | INPUT         | Word: Registers 0 through 7            |
| 5             | Write Single Coil        | OUTPUT        | Bit: Address 16,384 through 16,527     |
| 6             | Write Single Register    | OUTPUT        | Word: Registers 1024 through 1032      |
| 15            | Write Multiple Coils     | OUTPUT        | Bit: Address 16,384 through 16,527     |
| 16            | Write Multiple Registers | OUTPUT        | Word: Registers 1024 through 1032      |
| 22            | Mask Write Register      | OUTPUT        | Word: Registers 1024 through 1032      |
| 23            | Read/Write Registers     | INPUT/OUTPUT  | Word: Out Regs. 1024 through 1032
In Regs. 0 through 5 |

Table 6.1 Supported Modbus Functions
Supported Modbus Exceptions

<table>
<thead>
<tr>
<th>Code</th>
<th>Name</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>01</td>
<td>Illegal function</td>
<td>The NR25 does not support the function code in the query</td>
</tr>
<tr>
<td>02</td>
<td>Illegal data address</td>
<td>The data address received in the query is outside the initialized memory area</td>
</tr>
<tr>
<td>03</td>
<td>Illegal data value</td>
<td>The data in the request is illegal</td>
</tr>
</tbody>
</table>

Table 6.2 Supported Modbus Exceptions

Multi-Word Format

The Modbus protocol uses 16 bit registers, which limits the range of values from -32,768 to 32,767 or 0 to 65,535. Many parameters and data values from the NR25 exceed this range. These parameters are transmitted in two separate registers. The table below shows how values are split.

<table>
<thead>
<tr>
<th>Value</th>
<th>First Register</th>
<th>Second Register</th>
</tr>
</thead>
<tbody>
<tr>
<td>12</td>
<td>12 (0x0000 000C)</td>
<td>0 (0x0000)</td>
</tr>
<tr>
<td>1,234,567</td>
<td>54,919 (0x0012 D687)</td>
<td>18 (0x00012)</td>
</tr>
</tbody>
</table>

Table 6.3 Multi-Word Format Examples

Output Data Format

Table 6.4 shows the correct format for the Network Output Registers that are written to the NR25. Registers 1031 and 1032 are only available if the revision of the NR25 is 2.3 or greater.

<table>
<thead>
<tr>
<th>Register</th>
<th>Description</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>1024</td>
<td>Command Word</td>
<td>See Description</td>
</tr>
<tr>
<td>1025</td>
<td>Preset Value:</td>
<td>0xBF2F</td>
</tr>
<tr>
<td>1026</td>
<td></td>
<td>0x000A</td>
</tr>
<tr>
<td>1027</td>
<td>Configuration Word</td>
<td>See Description</td>
</tr>
<tr>
<td>1028</td>
<td>Counts per Turn:</td>
<td>0x99CA</td>
</tr>
<tr>
<td>1029</td>
<td></td>
<td>0x0000</td>
</tr>
<tr>
<td>1030</td>
<td>Velocity Format:</td>
<td>0x1F04</td>
</tr>
<tr>
<td>1031</td>
<td>Total Measurement Range:</td>
<td>0x3283</td>
</tr>
<tr>
<td>1032</td>
<td></td>
<td>0x007B</td>
</tr>
</tbody>
</table>

Table 6.4 Output Registers Data Format
Output Data Format  (continued)

Command Word

<table>
<thead>
<tr>
<th>15</th>
<th>14</th>
<th>13</th>
<th>12</th>
<th>11</th>
<th>10</th>
<th>09</th>
<th>08</th>
<th>07</th>
<th>06</th>
<th>05</th>
<th>04</th>
<th>03</th>
<th>02</th>
<th>01</th>
<th>00</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>0</td>
<td>Store Parameters to Flash</td>
<td>Apply Preset Value</td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
<td></td>
</tr>
</tbody>
</table>

RESERVED: Bit must equal zero.

Figure 6.2  Command Word Format

Apply Preset Value: These four bits control when the Preset Value in registers 1025 and 1026 is applied to the position value. In order for the position to be preset, the value in these four bits must transition from 0x2 (0b0010), to 0xD (0b1101). When these four bits make this transition, the NR25 calculates the position offset needed to bring the position to the Preset Value.

The NR25 will not respond to an error in the Preset Value. Specifically, a Modbus Exception Code 03 is not returned. The only response from the NR25 is to ignore the value and not preset the position. After issuing a preset command, read back the position value and verify that the position has been preset correctly.

Store Parameter to Flash: These four bits control when the programmable parameters and the internal position offset are stored to non-volatile memory. These values are not automatically written to this memory whenever they are changed. In order to store these parameter values and internal position offset, the value in these four bits must transition from 0x2 (0b0010), to 0xD (0b1101). Note that these bits are in locations 04 - 07. The actual register values when issuing this command are 0x20 and 0xD0.

1) The Flash memory in the NR25 revision 1.9 or less is guaranteed for a minimum of 10,000 write cycles.

2) The FRAM memory in the NR25 revision 2.3 and above does not have a limit on the number of permitted write cycles.

If your NR25 is revision 2.3 or above, setting the Total Measurement Range parameter to a non-zero value will force the NR25 to automatically store the internal position offset to non-volatile FRAM. Using the Total Measurement Range parameter this way only affects how the internal position offset is stored. You must still issue this Message Instruction to save the programmable parameters to non-volatile memory. See Storage of Internal Position Offset found on page 16 for information on how to set the Total Measurement Range parameter.
Output Data Format  (continued)

Configuration Word

<table>
<thead>
<tr>
<th>Register</th>
<th>Data Value</th>
<th>Example</th>
</tr>
</thead>
<tbody>
<tr>
<td>0</td>
<td><strong>32 bit Scaled Position Value.</strong> This data is the calculated position data. Its value is affected by the Measuring Units per Span parameter if the Scaling Function Control bit equals “1”. This value can also be preset to any value within its range by using the Apply Preset Value command. The lower 16 bits of this value are in register 0. A Position Value of 84,742,977 (0x050D 1341) is shown as an example.</td>
<td>0x1341</td>
</tr>
<tr>
<td>1</td>
<td></td>
<td>0x050D</td>
</tr>
<tr>
<td>2</td>
<td><strong>32 bit Velocity data.</strong> This data is the calculated change in position over time. The unit of measure is set with the Velocity Format parameter. If the Scaling Function Control bit is ever set to a “1”, the position data used to calculate the velocity data is always scaled by the Measuring Units per Span parameter. The lower 16 bits of this value are in register 2. A Velocity reading of 76,754 (0x0001 2BD2) is shown as an example.</td>
<td>0x2BD2</td>
</tr>
<tr>
<td>3</td>
<td></td>
<td>0x0001</td>
</tr>
<tr>
<td>4</td>
<td><strong>32 bit Raw Position Value.</strong> This data is the actual position value read from the resolver. The resolution is always 65,536 counts per turn. This data is not affected by the value of the Measuring Units per Span parameter nor the Scaling Function Control bit. This value is also not affected by the Preset Value. The lower 16 bits of this value are in register 4. A Raw Position Value of 571,942,153 (0x2217 2509) is shown as an example.</td>
<td>0x2509</td>
</tr>
<tr>
<td>5</td>
<td></td>
<td>0x2217</td>
</tr>
<tr>
<td>6</td>
<td><strong>32 bit Time Stamp data.</strong> This register is incremented every 400 nanoseconds while power is applied to the NR25. This register rolls over every 1717.9869184 seconds. The time stamp can be used to verify active communications between the NR25 and your host controller.</td>
<td>0x2BD2</td>
</tr>
<tr>
<td>7</td>
<td></td>
<td>0x0001</td>
</tr>
</tbody>
</table>

Table 6.5 Modbus Input Data Format

DCTog: Direction Control Toggle bit. When this bit equals “0”, the position value will increase with clockwise rotation when looking at the front of the shaft. When this bit equals “1” the position value will increase with counter-clockwise rotation when looking at the front of the shaft.

SFCtrl: Scaling Function Control bit. When this bit equals “0”, the position resolution will be 65,536 counts per turn. When this bit equals “1”, the position resolution will be set by the Measuring Units per Span parameter value contained in registers 1028 and 1029. As explained in the Calculating Position and Velocity Data section found on page 15, once the Measuring Units per Span parameter is applied, the velocity data will always be scaled by this parameter, regardless of the state of the Scaling Function Control bit. NR25 encoders with a revision of 2.3 and above have the Total Measurement Range parameter. This parameter is not affected by the state of the Scaling Function Control bit.
APPENDIX A

IP ADDRESS SETUP WITH BOOTP

If your NR25 is firmware 1.4 or below, then you cannot use the AMCI Net Configurator software to set the IP address of your unit. You must use a Bootp server to set the IP address of these units. This appendix explains how to use the Bootp server from Rockwell Automation to set the IP address.

Initial Configuration

Starting at the beginning of chapter 3, NR25 Configuration, follow the instructions up to the point where you have the NR25 attached to your computer. This is explained in the Attach the NR25 section on page 42.

Start Your Bootp Server

If needed, start your Bootp server. The Bootp-DHCP server software, version 2.3, from Rockwell Automation is used in this example. As shown in figure A.1, the R.A. Bootp server window is broken down into two panes, “Request History” and “Relation List”. “Request History” tells you what responses come over the network and the “Relation List” shows the setup data you have entered.

Set the Default Gateway Address

In order to conform with the ODVA specification, all NR25 encoders require a valid default gateway address setting when changing their IP address. AMCI suggests using the address of your processor as the default gateway address. Figure A.2 shows an example default gateway address of 192.168.1.250.

The default gateway address must be on the subnet that the NR25 will be assigned to, which may or may not be the 192.168.0 subnet that the NR25 is assigned to by its factory default settings.
Changing the IP Address

Changing the IP address of the NR25 requires you to enable the Bootp protocol on the encoder before you can change the IP address. The NR25 has the Bootp protocol disabled by default. This decreases the boot time by about 30 seconds when power is applied to the device because it doesn’t have to wait for the Bootp request to time out before continuing with its stored address.

Enabling Bootp Protocol

1) Make sure power is removed from the NR25.

2) In the “Relation List” pane of the RA Bootp Server software, click on [New]. In the window that opens, enter the MAC address of the NR25 which is printed on a white label near the serial number tag. You do not have to enter the “:” or “-” characters when entering the address on the screen. You must also enter the current IP address of the NR25. The factory default address is 192.168.0.50. The hostname and Description fields can be left blank. Click [OK].

3) Apply power to the NR25 and wait for the Module Status LED to come on solid green and the Network Status LED to be flashing green.

4) Click on your new entry in the “Relation List”. This will activate the buttons in the pane. Click on the [Enable BOOTP] button. The message “[Enable BOOTP] Command successful” should appear instantly in the status line at the bottom of the window.

5) The BOOTP protocol is now enabled on the NR25. Remove power from the encoder before continuing.
Changing the IP Address (continued)

Setting the IP Address

With the Bootp protocol now enabled, you can now change the IP address of the NR25.

1) Double click on your new entry in the “Relation List”. This will bring up the Properties window again. Enter the new IP address for the NR25 and click [OK].

2) Apply power to the NR25 and wait for the Module Status LED to come on solid green and the Network Status LED to be flashing green. At this point, you should also have a message in the “Request History” pane that lists the MAC address of the NR25 along with the IP address you requested.

Disabling the Bootp Protocol

Even though not strictly necessary, disabling the Bootp protocol will allow the NR25 to boot up faster and prevent inadvertent changes to the IP address of the NR25 if there is a network misconfiguration on your machine or plant floor.

1) With power still applied to the NR25, click on your new entry in the “Relation List”. This will enable the buttons above it.

2) Click on the [Disable BOOTP/DHCP] button. The message “[Disable BOOTP] Command successful” should appear instantly in the status line at the bottom of the window.

The new IP address for the NR25 is now configured.
**Testing the New IP Address**

The easiest way to test the new address of the NR25 is with the “ping” command. Before you can use the command, you have to be sure the NR25 and your computer are still on the same subnet. For example, if the new address of the NR25 is 192.168.0.42 and your computer has an address of 192.168.0.1, with a subnet mask of 255.255.255.0, then the two pieces of equipment are on the same subnet. (In this case, the first three numbers of the IP address must match.) If the new address of the NR25 is 192.168.50.50, then the computer and NR25 are not on the same subnet and you must go back into the Network Configuration panel and change your adapter’s TCP/IP settings. Refer back to the *Configure Your Network Interface Card (NIC)* section of this chapter, starting on page 40.

Once you are sure your computer and NR25 are on the same subnet, open the DOS terminal if necessary by clicking on the [Start] button, and clicking on [Run...]. A dialog box will open. Enter ‘cmd’ on the text line and press [Enter] on the keyboard.

Once the terminal is open, type in ‘ping aaa.bbb.ccc.ddd’ where ‘aaa.bbb.ccc.ddd’ is the new IP address of the NR25. The computer will ping the NR25 and the message “Reply from aaa.bbb.ccc.ddd: bytes=32 time<10ms TTL=128” should appear four times.

If the message “Request timed out.” or “Destination host unreachable” appears, then one of three things has occurred:

- You did not enter the correct address in the ping command.
- The new IP address of the NR25 was not set correctly.
- The NR25 and the computer are not on the same subnet and the gateway setting on the computer are not configured to correctly forward packets to the subnet the NR25 is on.

**Continue with Chapter 3**

If you haven’t already, you can now use the NR25 Configurator software to perform the initial setup of your NR25. Refer to *Using the AMCI Net Configurator* starting on page 43 for additional instructions.
CIP POSITION SENSOR OBJECT

Common Industrial Protocol

EtherNet/IP is a protocol stack that implements the Common Industrial Protocol (CIP) over Ethernet using TCP/IP. The CIP is sponsored by the Open DeviceNet Vendors Association (ODVA) and is implemented over a variety of networks. The NR25 follows the Encoder Device Profile that is defined in the CIP specification. The Configuration and Programming instances explained in chapters 4 and 5 are actually custom instances that simplify configuring and programming the encoder when using implicit messaging.

In addition to these custom instances, the NR25 implements the Position Sensor Object, which is a mandatory object for every product that implements the Encoder Device Profile as defined in the specification. The explicit messages that are used to preset the position value and save the programmed parameters are two commands defined in the Position Sensor Object.

The NR25 implements the CIP revision 2 definition of the Position Sensor Object.

Using the Position Sensor Object to communicate with the NR25 is completely optional. Most applications should communicate with the NR25 using the custom instances as explained in the previous two chapters because it will greatly simplify your PLC programming. The only reasons to use the Position Sensor Object is if you need extremely fine grain control over communications with the NR25 or if you use EtherNet/IP encoders from multiple vendors and you decide to write code that can be used with any of these sensors.

Supported Services

The following table lists the common services implemented by the NR25 for the Position Sensor Object.

<table>
<thead>
<tr>
<th>Service Code</th>
<th>Implemented</th>
<th>Service Name</th>
<th>Description of Service</th>
</tr>
</thead>
<tbody>
<tr>
<td>16#05</td>
<td>Yes</td>
<td>No</td>
<td>Reset</td>
</tr>
<tr>
<td>16#0E</td>
<td>Yes</td>
<td>Yes</td>
<td>Get_Attribute_Single</td>
</tr>
<tr>
<td>16#10</td>
<td>No</td>
<td>Yes</td>
<td>Set_Attribute_Single</td>
</tr>
<tr>
<td>16#15</td>
<td>Yes</td>
<td>No</td>
<td>Restore</td>
</tr>
<tr>
<td>16#16</td>
<td>Yes</td>
<td>No</td>
<td>Save</td>
</tr>
</tbody>
</table>

The services that are implemented only on the Class level (not on the Instance) should address Instance 0.

Service Code 16#0E, Get_Attribute_Single is used to read data from the Position Sensor Object class.

Service Code 16#10, Set_Attribute_Single is used to write data to the Position Sensor Object class.

Supported Class Attributes

The only supported Class attribute is 1 and it returns the revision number of the definition of the object. Because the NR25 implements the CIP revision 2 definition of the Position Sensor Object, this attribute will always return a value of “2”.

Table B.1 Supported Services
**Supported Instance Attributes**

Table B.3 on the following two pages lists all of instance attributes implemented by the NR25. Table B.2 below describes the Data Type values used in this table.

<table>
<thead>
<tr>
<th>Data Type</th>
<th>Length</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>BOOLEAN</td>
<td>8 bits</td>
<td>Holds single on/off (true/false) value</td>
</tr>
<tr>
<td>BYTE</td>
<td>8 bits</td>
<td>Holds up to 8 bits of data which should not be considered to be a scalar value</td>
</tr>
<tr>
<td>USINT</td>
<td>8 bits</td>
<td>Unsigned 8 bit value</td>
</tr>
<tr>
<td>WORD</td>
<td>16 bits</td>
<td>Holds up to 16 bits of data which should not be considered to be a scalar value</td>
</tr>
<tr>
<td>UINT</td>
<td>16 bits</td>
<td>Unsigned 16 bit integer value</td>
</tr>
<tr>
<td>DINT</td>
<td>32 bits</td>
<td>Signed 32 bit integer value</td>
</tr>
<tr>
<td>UDINT</td>
<td>32 bits</td>
<td>Unsigned 32 bit integer value</td>
</tr>
</tbody>
</table>

Table B.2  Explanation of Data Types

When programming these instances, always use a Class Code of 16#23.

<table>
<thead>
<tr>
<th>Attrib. ID</th>
<th>Access</th>
<th>Name</th>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>16#01 - 1</td>
<td>Get</td>
<td>Number of Attributes</td>
<td>USINT</td>
<td>Number of supported Attributes = 21</td>
</tr>
<tr>
<td>16#02 - 2</td>
<td>Get</td>
<td>Attribute List</td>
<td>Array of BYTE</td>
<td>List of supported Attributes = 01, 02, 0A, 0B, 0C …71hex</td>
</tr>
<tr>
<td>16#0A - 10</td>
<td>Get</td>
<td>Position Value Signed</td>
<td>DINT</td>
<td>Current position value</td>
</tr>
</tbody>
</table>
| 16#0B - 11 | Get    | Position Sensor Type      | WORD      | Specifies the device type 
1 = Single turn absolute rotary encoder 
2 = Multi-turn absolute rotary encoder |
| 16#0C - 12 | Set    | Direction Counting Toggle | BOOLEAN   | Controls the counting direction: 
0 = CW 1 = CCW |
| 16#0E - 14 | Set    | Scaling Function Control  | BOOLEAN   | Enables Scaling function 
0 = OFF (65,536 counts per turn) 
1 = ON (Scaling set by Measuring Units per Span, attribute 10hex) |
| 16#10 - 16 | Set    | Measuring Units per Span  | UDINT     | Resolution for one revolution: 
1 to 65,536 counts per turn |
| 16#11 - 17 | Set    | Total Measurement Range   | UDINT     | Counts before roll over to zero. 
Single Turn NR25: Range of 0, 2 to 65,536 
28 bit Multi-turn NR25: Range of 0, 2 to 268,435,455 
30 bit Multi-turn NR25: Range of 0, 2 to 1,073,741,823 |
| 16#13 - 19 | Set    | Preset Value              | DINT      | Sets the position to the specified value. 
Calculates an internal offset that will be saved to the non-volatile storage if Save service (code 16#16) is issued. |
| 16#18 - 24 | Get    | Velocity Value            | DINT      | Current speed. The value is in the format specified by attribute 16#19 |

(Table is continued on next page)
Supported Instance Attributes (continued)

<table>
<thead>
<tr>
<th>Attrib. ID</th>
<th>Access</th>
<th>Name</th>
<th>Data Type</th>
<th>Description</th>
</tr>
</thead>
<tbody>
<tr>
<td>16#19 - 25</td>
<td>Set</td>
<td>Velocity Format</td>
<td>WORD</td>
<td>Format of the velocity attribute: 16#1F04 = pulses/s 16#1F05 = pulses/ms 16#1F07 = steps/min 16#1F0F = RPM</td>
</tr>
<tr>
<td>16#29 - 41</td>
<td>Get</td>
<td>Operating Status</td>
<td>BYTE</td>
<td>Encoder diagnostic operating status. Bit 0 = Value of attribute 16#0C (12) Bit 1 = Value of attribute 16#0E (14)</td>
</tr>
<tr>
<td>16#2A - 42</td>
<td>Get</td>
<td>Physical Resolution Span</td>
<td>UDINT</td>
<td>Physical resolution of the single-turn resolver sensor</td>
</tr>
<tr>
<td>16#2B - 43</td>
<td>Get</td>
<td>Number of Spans</td>
<td>UINT</td>
<td>Maximum number of revolutions that could be measured.</td>
</tr>
<tr>
<td>16#2C - 44</td>
<td>Get</td>
<td>Alarms</td>
<td>WORD</td>
<td>Indicates a malfunction has occurred.</td>
</tr>
<tr>
<td>16#2D - 45</td>
<td>Get</td>
<td>Supported Alarms</td>
<td>WORD</td>
<td>Information about supported alarms</td>
</tr>
<tr>
<td>16#2E - 46</td>
<td>Get</td>
<td>Alarm Flag</td>
<td>BOOLEAN</td>
<td>Indicates that an alarm error occurred: 0 = No errors 1 = Alarm Error</td>
</tr>
<tr>
<td>16#33 - 51</td>
<td>Get</td>
<td>Offset Value</td>
<td>DINT</td>
<td>The internal position offset that is calculated after applying the Preset Value through attribute 13hex (19)</td>
</tr>
<tr>
<td>16#64 - 100</td>
<td>Set</td>
<td>Device Type</td>
<td>DINT</td>
<td>The way the device identifies itself: 16#22 (default) = Encoder device 16#00 = Generic device</td>
</tr>
<tr>
<td>16#70 - 112</td>
<td>Get</td>
<td>Actual Sensor Reading</td>
<td>UDINT</td>
<td>Raw position value read from NR25</td>
</tr>
<tr>
<td>16#71 - 113</td>
<td>Get</td>
<td>Time Stamp</td>
<td>UDINT</td>
<td>Value increments every 400 nanoseconds.</td>
</tr>
</tbody>
</table>

Table B.3 Supported Instance Attributes

For detailed description of the Attributes, see the CIP definition.

Supported Alarms

The NR25 supports the following operational alarm.

- **Diagnostic Error**

This alarm is set when the NR25 fails its power up diagnostics. The Position Error alarm is also set to indicate that the position data may be incorrect.

Attributes 16#2D, Supported Alarms, 16#2C, Alarms, and 16#2E Alarm Flag indicate something about the alarms supported by the NR25.

- **16#2D**: Supported Alarms – Reading this attribute returns a value of 3, indicating that the Position Error alarm and Diagnostic Error alarms are both used.
- **16#2C**: Alarms – Reading this attribute will return a value of zero if no alarms have occurred and a value of three if an alarm has occurred.
- **16#2E**: Alarm Flag – Reading this attribute will return a value of zero if no alarms have occurred and a value of one if an alarm has occurred.
**APPENDIX C**

**PARALLEL OUTPUT OPTION**

**Outline Drawings**

All NR25 transducers that have the additional parallel position outputs appear to be a hybrid of the side and end connect designs. The network connections are on the back of the unit and the parallel outputs are off of the side pedestal.

**2.5” Servo Mount**

![Diagram of 2.5” Servo Mount - Parallel Output Outline Drawing]

- 2.30” (58.6) max.
- 2.50” (63.5)
- 1.250” (31.75)
- 1.249” (31.72)
- 0.300” (7.62)
- 0.3744” (9.510)
- 0.3747” (9.517)
- 0.900” (22.86)
- 0.850” (21.59)
- 0.55” (14.0) max.
- 0.55” (14.0) max.
- 0.10” (2.5)
- 0.10” (2.5)
- 3.20” (81.3) max.
- Shaft Seal

( ) = Dimensions in millimeters

Figure C.1 2.5” Servo Mount - Parallel Output Outline Drawing
Outline Drawings (continued)

58 mm Servo Mount

Figure C.2 58 mm Servo Mount - Parallel Output Outline Drawing

Flange Mount

Figure C.3 Flange Mount - Parallel Output Outline Drawing
Outline Drawings (continued)

5/8" Shaft, Flange Mount

NOTES:
1) Integral Shaft Seal.
2) 1/4-20 UNC-2B 0.50" (12.7) minimum depth. Six Places.
3) Additional clearance needed for removal of mating connector.

KEYWAY SPECIFICATIONS

KEYWAY

\[ \begin{align*}
0.1895" \times 0.108" \ (4.813) \\
0.1885" \times 0.106" \ (4.788)
\end{align*} \]

Deep

\[ \begin{align*}
0.188" \times 0.187" \ (4.78) \\
0.187" \ (4.75)
\end{align*} \]

KEY

( ) = Dimensions in millimeters

Figure C.4 5/8" Shaft, Flange Mount - Parallel Output Outline Drawing
Outline Drawings (continued)

Hub Shaft Mount

( ) = Dimensions in millimeters

VIEW A

0.55" (14.0) max. Additional clearance needed for removal of mating connectors.

NR25
Ethernet Output
Hub Shaft Mount
End Connector
Parallel Position
Output Option

MS3112E-14-19P
Connector
Parallel Position Output

VIEW A

Customer Side

SEE CHART

Shaft Length
0.59" (15) min.
1.10" (27.9) max.

DIAMETER CHART

Nominal Hole
Diameters Available

<table>
<thead>
<tr>
<th>English</th>
<th>Metric</th>
</tr>
</thead>
<tbody>
<tr>
<td>0.375&quot;</td>
<td>10 mm</td>
</tr>
<tr>
<td>0.500&quot;</td>
<td>12 mm</td>
</tr>
</tbody>
</table>

Figure C.5 Hub Shaft Mount - Parallel Output Outline Drawing
**Connector Pin Out**

Figure 6.4 shows the pin designations on the MS3112E-14-19P connector. AMCI sells a straight mating connector under the AMCI part number: MS-19.

AMCI does not supply factory made cables because of the many possible configurations.

**Pin U: Latch Control** – The Latch Control input is level sensitive. The outputs will update continuously when this input is at a logic ‘1’ state or left unconnected. The outputs will freeze when this input is at a logic ‘0’ state.

- Logic ‘1’: Input voltage is greater than or equal to 2 Vdc
- Logic ‘0’: Input voltage between 0 and 0.8 Vdc
- Outputs will freeze within 10 microseconds of a 1→0 transition on the Latch Control Input.
- Outputs will begin to update within 100 microseconds of a 0→1 transition on the Latch Control Input.
- Position update time: 50 to 100 microseconds

**Pin S: Case GND** – This pin should be used to tie the body of the DuraCoder to chassis ground at the NR25 if the unit is not grounded through its mounting. This pin is not to be used as the power supply return. The power supply must be wired to pins T (DC Return) and V (+DC Input).

If the body of the NR25 is properly grounded, then this pin can be used to ground the shields of the cable from the NR25 to your controller. This should only be used if a proper chassis ground is not available at the controller. Do Not connect the cable shields at both ends, as this may lead to a ground loop that could damage the NR25, controller, or cable.

**Pins V & T: Power Supply Connections** – The power supply for the absolute parallel outputs is separate from the supply for the Ethernet interface. The power supply must be wired to pins V (+DC Input) and T (DC Return).
Specifications

Operating Voltage (External Supply)
10.8 Vdc to 26.4 Vdc (12 to 24 Vdc ± 10%)

Power Requirements
0.5 W max.
20 mA @ 24 Vdc typical
Power requirements do not include output load current, which can be up to 15 mA per output.

Output Format
Binary or Gray Code. This option is factory set and cannot be changed in the field.

Resolution
12 bit. (4,096 counts per turn)

Count Direction
CCW increasing when looking at the shaft

Output Drivers
Open Collector Sourcing:
Logic ‘0’: High Impedance
Logic ‘1’: Output equal to operating voltage.

Maximum ON Current:
15 mA

On State Resistance
100 ohm max. (1.5 Vdc drop @ 15 mA)

Leakage Current:
5 microamperes max.

Position Update Time
100 microseconds max.

Update Control
Latch Input
Level Sensitive
Logic ‘0’: 0 to 0.8 Vdc
Logic ‘1’: >2.0 Vdc or open circuit.

Outputs Frozen
Latch Input at logic ‘0’
Outputs stable within 10 microseconds of 1→0 transition.

Outputs Continuous Update
Latch Input at logic ‘1’
Outputs update within 100 microseconds of 0→1 transition.

Power Up Delay
35 milliseconds maximum
Outputs at logic ‘0’ during this time.
Notes