



DF family manual

DF family manual

Version 2.9

for product variants

- *DF plus*
- *DF ibex*
- *DF dual*

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1 Introduction

Thank you for choosing an ATESTEO quality product. Please read the system description carefully so you make the most of the versatile features of your product.

This operating manual is a component of the DF-series and should always be carefully kept with the DF series until it is disposed of.

It is impossible to eliminate every danger to people or material that the DF series might present. For this reason, every person working at the DF series or is involved in its transport, setting up, control, maintenance or repair must be properly instructed and be informed of the possible dangers.

For this purpose, the operating instructions and, especially, the safety instructions must be carefully read, understood and observed.

Company ATESTEO reserves the right to carry out changes regarding its products, which serve the technical further development the company ATESTEO. These changes are not documented expressly in every individual case.

This operator's manual and the information contained in it were compiled with the advisable care.

Company ATESTEO GmbH & Co.KG takes on no liability for misprints or other faults or damages resulting from it the company ATESTEO GmbH & Co.KG, however.

The brands mentioned in this operator's manual and product names are trademarks or registered trademarks of the respective titleholders.

Please do not miss contacting us if there is anything in the operating instructions that you cannot clearly understand. We are grateful for any

kind of suggestion or criticism that you may wish to make. Please let us know or write to us. This will help us to make the operating instruction still more user-friendly in taking account of your wishes and requirements.

1.1 Change log

V2.9 – 02.09.2025

- Product variants ibex and dual added
- Remark to connect Digital GND for CAN bus added
- Central cable pin count mistakes removed
- IIR filter explained more detailed
- Screenshots of web interface updated
- Fail safe channel: Description updated and cleaned up
- CAN debug signal description added

V2.8 – 31.05.2024

- Format fixed for better readability

V2.7 – 02.05.2024

- Format review
- Update of drawing "TCU5 dimensions"
- Output switch added to X770
- General filter description added

V2.6 – 06.03.2023:

- Rotation angle added
- Updates for RSS-Gen

V2.5 – 30.01.2023:

- Calibration certificate for DAKkS added.
- Calibration certificate of factory calibration added.
- Remark about sensitivities added to factory and DAKkS calibration.

- Information about FCC updated.

V2.4 – 22.09.2022:

- Mounting distances of speed detection updated.
- Information regarding ping protocol added.
- Description of some functions added in separate chapters.
- Description of zero adjustment added.
- Inline concept description removed.
- Document structure updated.
- Lifting & transport remarks for rotors added.
- IP reset description updated.
- Technical data added.
- Safety remarks enhanced (Fuse in building electricity, operation only inside, avoid oscillations).
- Pin assignment of central cable updated (X775/X776 instead of X773).
- CAN command correctly named.
- FCC ID added.
- ISEC IC added.
- Description of network setup simplified.
- Dimensions of stator updated.
- Tightening torques for DF1 titanium added.

V2.3 22.11.2021:

- First version with change log
- Contact details of service team updated
- Pin assignment: TTL3.3/5.0 corrected

1.2 Software versions

The software versions mentioned in Table 1 were the latest ones when this manual has been released (date of release see 1.1). The software is updated more frequently than the manuals. The latest versions incl. their change logs can be requested from the ATESTEO service.

Software	Version
TCU5 firmware	V2.6.0
TCU5 website	V2.12.0
TCU5 boot loader	V4.2.0
Rotor firmware (plus, ibex, dual)	V2.10.0

Table 1 Software versions

1.3 Manufacturer

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(Hereinafter referred to as manufacturer)

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Service:
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1.4 Manufacturer's Declaration

The manufacturer declaration can be requested at ATESTEO.

1.5 FCC certification

The components of DF series mentioned in Table 2 comply with part 15 of the FCC Rules. Operation is subject to the following two conditions: (1) This device may not cause harmful interference, and (2) this device must accept any interference received, including interference that may cause undesired operation.

Product changes are only allowed with the acceptance of ATESTEO. The FCC ID or a unique component ID is labelled on the components (see 3.6 and 3.7).

1.6 RSS-Gen — General Requirements for Compliance of Radio Apparatus (canada.ca)

This device contains licence-exempt transmitter(s)/receiver(s) that comply with Innovation, Science and Economic Development Canada's licence-exempt RSS(s). Operation is subject to the following two conditions:

1. This device may not cause interference.
2. This device must accept any interference, including interference that may cause undesired operation of the device.

This equipment should be installed and operated with minimum distance 50 cm between the radiator and users' bodies.

L'émetteur/récepteur exempt de licence contenu dans le présent appareil est conforme aux CNR d'Innovation, Sciences et Développement économique Canada applicables aux appareils radio exempts de licence. L'exploitation est autorisée aux deux conditions suivantes :

1. L'appareil ne doit pas produire de brouillage;

2. L'appareil doit accepter tout brouillage radioélectrique subi, même si le brouillage est susceptible d'en compromettre le fonctionnement

Cet équipement doit être installé et utilisé avec une distance minimale de 50 cm entre le radiateur et le corps des utilisateurs.

The ISSED IC or a unique component ID is labelled on the components (see 3.6 and 3.7).

Component	Torque range [Nm]	HVIN	IDs
DF1 plus	50, 100, 200, 500	DF1 plus	FCC ID: 2A6NX-DFS1TOS4 ISSED IC: 28805-DFS1TOS4
DF2 plus	500, 1,000	DF2 plus	
DF3 plus	1,000, 2,000, 3,000	DF3 plus	
DF4 plus	4,000, 5,000	DF4 plus	

Table 2 DF variants of FCC/RSS210 certification

1.7 Disposal and environment

Electrical and electronic products are subject to special conditions for disposal. Proper disposal of old equipment prevents health hazards and environmental damage.

Packaging

The original packaging of ATESTEO equipment can be recycled, as it is made of recyclable material. However, you should keep the packaging for at least the warranty period. In the event of a complaint,

the torque flange, as well as the accessories, must be returned in the original packaging.

Due to ecological aspects, the return of the empty packaging should be waived.

Legally prescribed labelling for disposal



Electrical and electronic devices bearing the symbol  are subject to the European Directive 2002/96 / EC on waste electrical and electronic equipment. The symbol indicates that waste equipment that is no longer usable must be disposed of separately from regular household waste in accordance with European environmental protection and recycling regulations.

However, the disposal regulations vary from country to country, which is why we ask you, if necessary, your supplier how to dispose your waste.

1.8 Scope of supply

The package contains the following terms:

1. Torque meter (Rotor)
2. DF plus stator without ring or DF ibex/dual stator with ring
3. TCU 5 (Torque Control Unit)
4. Central cable
5. 12-pin connector
6. 16-pin connector
7. Operating manual

8. Test report
9. Optional speed detection system

1.9 General functionality

The DF-series is suitable for the highly dynamic measurement of torques at high load and highest resolution. The following figure shows the measuring system, which consists of a torque measuring flange (rotor), a stator and an evaluation unit.

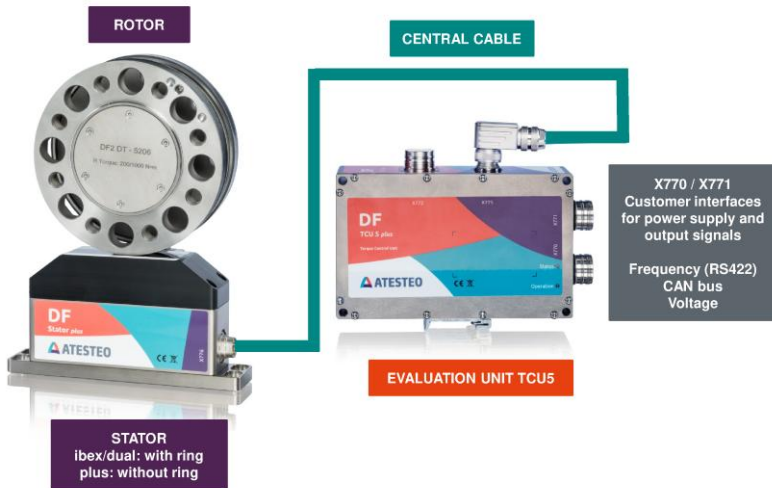


Figure 1 DF system overview (components of DF2 plus as example)

The torque measuring flange and the stator communicate via bidirectional telemetry, while the rotor is simultaneously powered inductively via the stator. The torque is detected via a strain gauge full bridge in the measuring body of the torque measuring flange.

The electrical difference voltage of the full bridge is amplified in the torque measuring flange and digital data words are converted. For error-free signal transmission, the data words are supplemented by a checksum and transmitted modulated to the stator. The stator demodulates the data words and transmits them via an RS422 interface to the evaluation unit. In the evaluation unit, the signals can additionally be filtered with an adjustable low-pass filter.

The evaluation unit also offers the connection options for the system peripherals. These include a CAN interface, two frequency outputs (Md1, Md2), three galvanically isolated analog outputs (Md1, Md2, Speed), three digital alarm outputs and five digital inputs. The measuring system can be comfortably configured via the Web interface. This also offers the possibility to easily and quickly check measured values and system functions.

A wide range of flange types allows easy connection to your application. The maximum load and the maximum measuring range can be individually adapted to your needs if wanted. Our dual variant uses a second measuring channel with a separately calibrated measuring range. The measured values of both measuring channels are transmitted at the same time.

The torque measuring flange additionally monitors the temperature of the measuring body, which is used to eliminate temperature influences and can be called up as an additional CAN message from the evaluation unit.

The exchange of torque measuring flange is enormously simplified and accelerated by the DF series. On the one hand, the stator does not enclose the torque measuring flange (plus variant) or has a separable ring (ibex/dual variant). On the other hand, an electronic data sheet is

sent from the measuring flange, which enables automatic configuration of the evaluation unit.

The new measuring flange is immediately ready for use.

Optionally, the measuring system can be equipped with a speed measurement. For the capture, a magnet ring on the rotor and a sensor head on the stator are in use. The magnetic ring has two pole tracks, which are offset by 90 ° to each other. So the speed can be determined as well as the direction of rotation. The two tracks can be tapped as RS422 signals at the system outputs. In addition, the speed is measured in the evaluation unit and made available as a digital value via CAN and as a voltage value via the third analog output.

**Note**

Please note that the torque meter is a high-precision measuring instrument. Mechanical effects, e.g. hammer impacts, lead to deformation of the measuring body, which changes its torsional behavior and thus worsens the measuring accuracy! Before mounting, make sure that the fits of your adapters comply with the specified installation tolerances and that they are free from contamination. Only in this way, precise measurements and optimum concentricity can be guaranteed.



Note

The magnet ring (for the optional speed detection) can be damaged by strong magnetic field, e.g. occur with a permanent magnet.

2 Safety Instructions

2.1 General safety instructions

The manual must be read carefully before start-up, maintenance work or any other work on the torque measuring system. Prerequisite for the safe and proper handling of the equipment knows all safety instructions and safety regulations of the attachment.

Every safeguard needs to be correctly mounted and fully functional before any start-up.

Shafts or adapters mounted to the torque meter must be properly designed, so that critical bending moment is avoided.

Exclusively qualified laborers are allowed to do maintenance work on any electrical components (see chapter Qualified personnel).
If the torque meter is sold on, these safety instructions must be included.

2.2 Explanation of symbols and notice

Warnings

Warnings are indicated by symbols in these safety instructions. The hints are going through

Signal words are introduced, which express the extent of the hazard. It is imperative that you follow the instructions and act with care to avoid accidents, personal injury and material damage.



Information

Draws attention to important information about correct handling.

**Caution**

Warns of a potentially dangerous situation in which failure to comply with safety requirements can result in slight or moderate physical injury.

2.3 **Appropriate use**

The torque meter is highly accurate and resistant to rotational speed. The signals from the flange serve to control the test bench and to analyses the components.

The torque flange is used just for torque measurement tasks within the load limits in the specification (see 3.1). Any other use is not permitted.



The torque meter is not allowed for use as a safety component.

**Note**

It's only permitted when the rotor is installed as described in the mounting instruction.

2.4 **Modifications/conversions**

Any modifications/ conversions of the design or safety engineering of the torque meter without the explicit agreement from ATESTEO will lead to the loss of warranty or liability. Any damages or injuries of personnel therefrom are in responsibility of the operator.

2.5 Operator's responsibility

Standards

The ATESTEO torque meter was designed and constructed taking account of a risk analysis and careful selection of harmonized standards and other technical specifications with which it complies. It represents the state of the art and guarantees a maximum degree of safety.

Qualified personnel

Qualified personnel are persons who by reason of their training, experience, instruction and their knowledge of the relevant standards, regulations, accident prevention rules and working conditions have been authorized by the person responsible for the safety of the machine/product to perform the appropriate activities required, and thereby are able to recognize and prevent potentially dangerous situations (For the definition of skilled workers see VDE 0 105 or IEC 364, which also regulate the prohibition of the employment of unqualified persons).

Knowledge of first aid and the local rescue organization must also be available.

Transportation, assembly, installation, commissioning, maintenance, and repair will be performed by qualified personnel or controlled by responsible skilled hands.

Safety relevant disconnecting device

The torque meter cannot implement any safety relevant cut-offs. It is in the operator's responsibility to integrate the torque meter into superior safety system.

The electronical conditioning the measurement signal should be designed so that measurement signal failure does not subsequently cause damage.

Residual risks

The power and scope of delivery of the torque meter covers only a subset of the torque measurement technology. Safety aspects of torque measurement technology must be planned, implemented and taken into account by the system planner, supplier or operator in such a way that residual risks are minimized. Each existing regulation must be observed. Attention should be drawn to residual risks associated with torque measuring technology

In the case of a shaft/flange break, you must ensure that there is no risk of injury. This should be done with a shaft protection cover in a closed test room with corresponding security doors. During the operation, no one should stay in the test room.

Usage recommendations for personal protective equipment



Working in a workshop generally requires wearing safety shoes.



Use suitable gloves when handling corrosive or irritating solutions and adhesives.

2.6 Transport and storage

Check the delivery immediately for completeness and shipping damage.



Use working gloves and shoes during transport/ assembly/ maintenance.



Storage

- Do not store outdoors
- Store dry and dust-free
- do not expose to aggressive media
- protect from sunlight
- avoid mechanical shocks
- Storage temperature according data sheet

If stored for more than 3 months, regularly check the general condition of all parts and packaging.

2.7 Safety notes for assembly



Tightening torque

When tightening the screws, the specified tightening torques (see mounting instruction) must be observed.

**Electric wire**

All cables must be professionally laid according to the actual standards.

**Rotating parts**

Rotating parts must be earthed- risk of static electricity.

2.8 Safety notes for operation

As accident prevention, a covering must be fitted once the torque meter has been mounted. This is the fact whether the torque meter is already fully protected by the design of the machine or by existing safety precautions. Please pay attention to the following requirements for the covering as accident prevention:

- The covering must not be free to rotate.
- Covering must be positioned at a suitable distance or be so arranged that there is no access to any moving parts within.
- Covering should prevent squeezing or shearing and provide sufficient protection against parts that might come loose.
- Covering must still be attached even if the moving parts of the torque flange are installed outside people's movement and working range.
- The torque meter system may only be used indoors in closed testing rooms.

**Note**

Improper use and handling as well as constructional changes will invalidate the EC declaration of conformity.

2.9 Load limits

Observe technical data sheets when using the torque meter. Pay particular attention to never exceed the respective maximum loads. For example:

- Load limits
- Torque oscillation width,
- Temperature limits,
- Longitudinal limit force, lateral limit force or limit bending moment,
- Limits of electrical load-carrying capacity,
- Limit rotation speed.

3 System description

3.1 Technical data

Description	Value
Power supply	24V DC max. 2A
Dynamic – Frequency output	≤ 6 kHz
Dynamic – Analogue voltage output	≤ 6 kHz
Dynamic – CAN bus	≤ 2,000 Samples/s
Modulation range – Voltage	-12 ... 12 V
Modulation range – Frequency	0 ... 420 kHz
CAN interface	CAN2B Max. 1 MBaud
Configuration interface	Ethernet (via integrated website)
Nominal temperature range (rotor / stator)	0 ... 80 °C
Operation temperature range (rotor / stator)	-20 ... 85 °C
Storage temperature range (rotor / stator)	-30 ... 85 °C
Nominal temperature range (TCU5)	0 ... 70 °C
Operation temperature range (TCU5)	-20 ... 70 °C
Storage temperature range (TCU5)	-30 ... 85 °C
Protection class	IP54
Frequency outputs	RS422 Torque Magnetic speed detection (optional)

Table 3 Technical data

3.2 System overview (electrical)

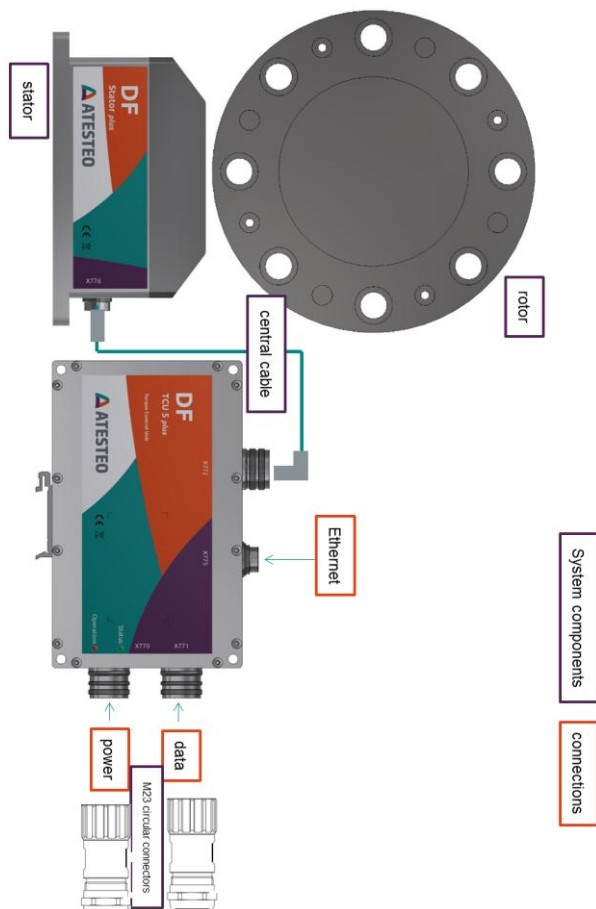


Figure 2 DF system overview (electrical)

3.3 System overview (central cable)

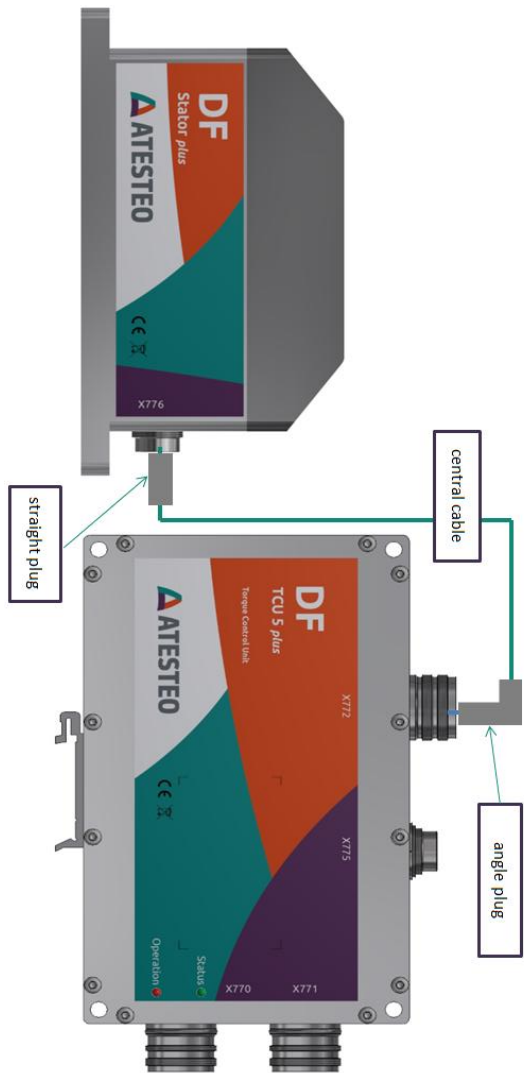


Figure 3 Central cable

3.4 System overview (functional areas)

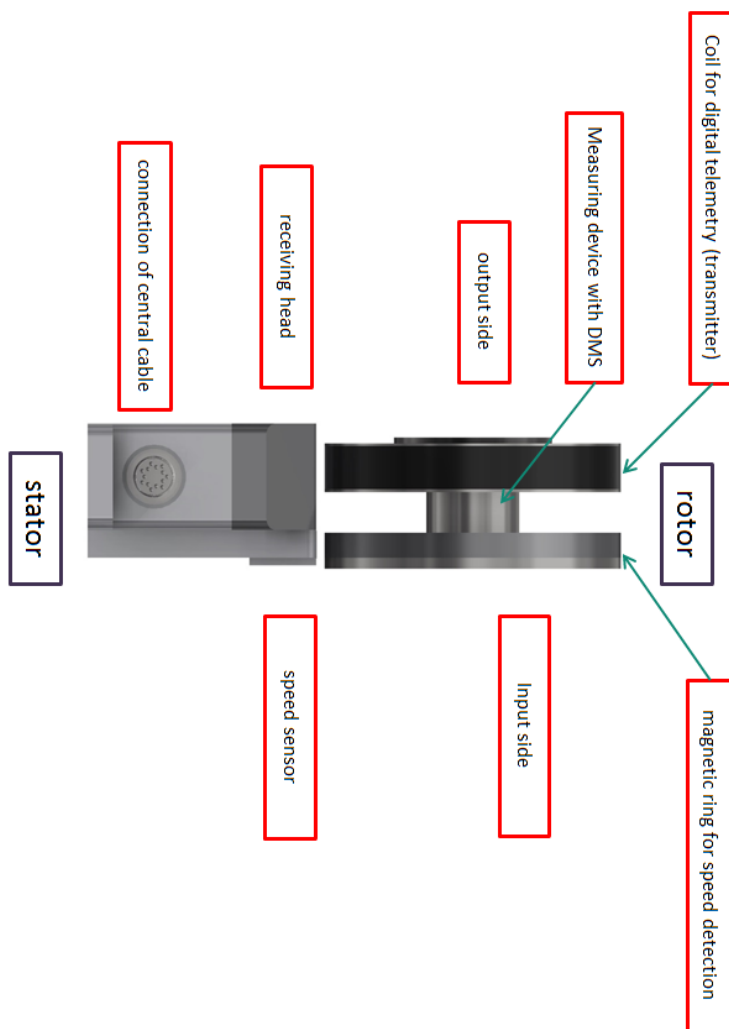


Figure 4 DF system overview (functional)

3.5 System overview (mechanical)

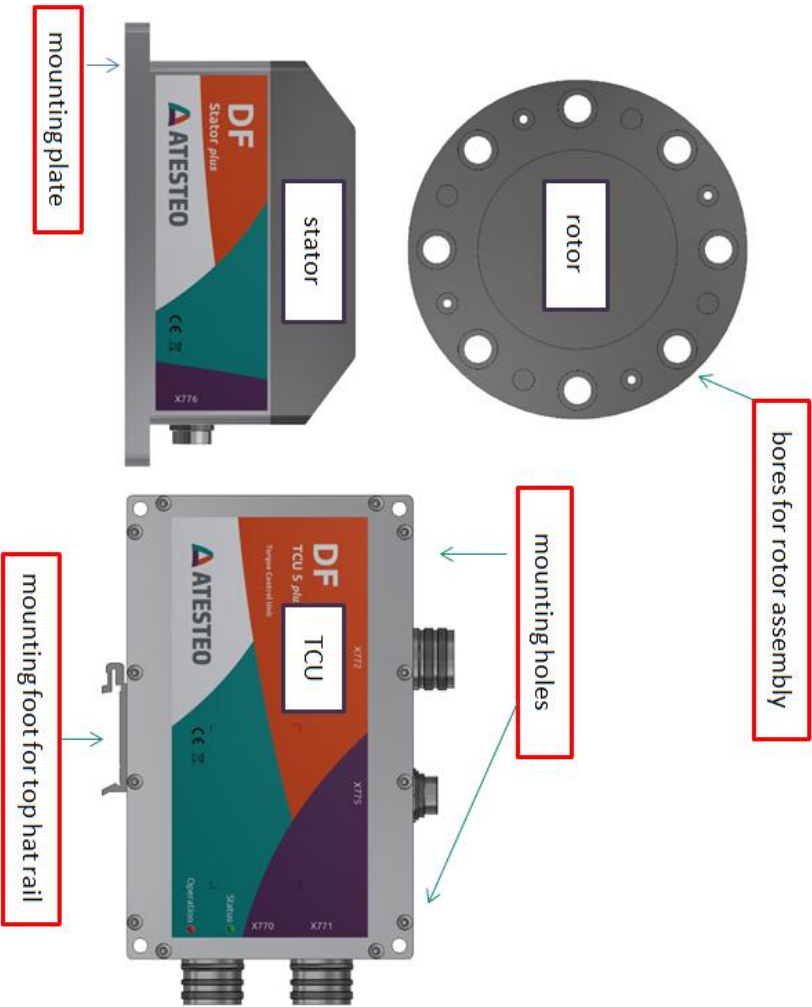


Figure 5 DF system overview (mechanical)

3.6 System overview (location nameplates)

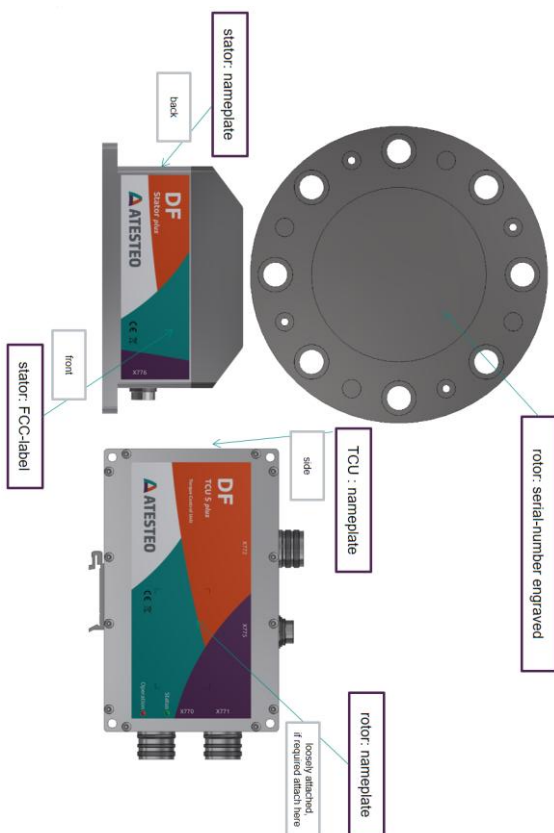


Figure 6 Position of nameplates

3.7 Content of nameplates

Rotor

	ATESTEO GmbH & Co. KG Konrad-Zuse-Str.3 52477 Alsdorf/Germany		
Serial number: DF1 plus DT-6579			
Accuracy class: 0,04 / 0,04			
Rated torque	100 / 500 Nm		
Max speed	14000 rpm		
Speed enc.	M680 ppr		

TCU

 ATESTEO GmbH & Co. KG Konrad-Zuse-Str.3 52477 Alsdorf/Germany		
Serial number: TCU5 Plus-5487		
Power Supply	24VDC 1A	
Default IP Address	172.16.86.3	
IP Address		

Stator

 ATESTEO	ATESTEO GmbH & Co. KG Konrad-Zuse-Str.3 52477 Alsdorf/Germany	
P/N: 11961-2 / 09.12.2022		
S/N: DF-Stator Plus-7596		
Power supply +7 V DC		

Stator FCC/ISED label (Example of DF1 plus)

Model: DF1 plus
FCC ID: 2A6NX-DFS1TOS4
ISED IC: 28805-DFS1TOS4
HVIN: DF1 plus

This device complies with part 15 of the FCC Rules.
 Operation is subject to the following two conditions:
 (1) This device may not cause harmful interference, and
 (2) this device must accept any interference received,
 including interference that may cause undesired operation.



Figure 7 Position of FCC/ISED label at Stator

3.8 Calibration documents

The measuring system of DF series is delivered with a test report. It shows the sensitivity in digits / Nm. The optional calibration protocol shows the calibration values in several stages.

On request, a calibration in accordance with DIN 51309 or VDI/VDE 2646 can be carried out in our in-house calibration laboratory, which is accredited by DAkkS according to DIN ISO 17025:2018.

Test report

The following figure shows the example of a standard test report:



Torque transducer test report

Serial number: DF2S DT - 5375

Range1

Rated Torque:	150	Nm
Calibrated Torque:	150	Nm
Sensitivity cw:	2623,5100	Digits/Nm
Sensitivity ccw:	2623,8430	Digits/Nm
Test signal:		Nm
Accuracy (Nonlinearity and hysteresis):	0,04% of rated torque	
Temperature effect on zero:	0,04% of rated torque / 10°C	

Range2

Rated Torque:	600	Nm
Calibrated Torque:		Nm
Sensitivity cw:	667,3792	Digits/Nm
Sensitivity ccw:	667,4242	Digits/Nm
Test signal:		Nm
Accuracy (Nonlinearity and hysteresis):	0,04% of rated torque	
Temperature effect on zero:	0,04% of rated torque / 10°C	

Compensated Temperatur Range (Rotor/Stator): 10°C/10°C to 70°C/70°C
 Gravitational Constant Alsdorf: 9,81106 m/s²
 Ambient Temperature: 21,2 °C

Remarks:

Maximum Speed: 20000 rpm
 Speed Disc: ppr
 Warming Up Time: 30 minutes

Date: Signed:

Figure 8 Test report example

Factory calibration certificate

The following figure shows a detailed calibration protocol, which is recommended as an option. Sensitivities are given in section “Case II, linear interpolation equation”, 1.2.1 and 1.2.2 (January 2023).



Seite 3 zum Kalibrierschein vom 2022-03-22
Page 3 of the calibration certificate of 2022-03-22

KSNr
WKS
2022-03

Kalibrieranordnung
Calibration installation

Einbaueinstellung
Mounting position: 1x120°

Drehmomentelektor
Torque transducer: vertical vertical

Elastische Kupplung
Flexible Coupling: Multi-plate coupling

Umgebungsbedingungen
Environment conditions

	Anfang Begin	Ende End
Lufttemperatur Air temperature	21,2 °C	21,1 °C
Rel. Luftfeuchte Rel. Humidity	44 %	44 %

Interpolation
Interpolation

Angegeben sind die linearen Interpolationsgleichungen, die der Berechnung der Linearitätsabweichungen zu Grunde liegen. Ermittelt nach der Methode der kleinsten Fehlerquadrate.
The linear interpolation equations, on which the calculation of the linearity deviations are based, are given. Determined according to the least-squares method.

Fall I: Lineare Interpolationsgleichung nur unter Berücksichtigung der Messwerte aus der Aufwärtsreihe ohne Wiederholmessreihe (ohne Berücksichtigung der Umkehrspanne h ohne Hysterese).
Case I: Linear interpolation equation only resulting of increasing torque without repeatability series are taken into account (without reversal error h / without hysteresis).

Fall II: Lineare Interpolationsgleichung unter Einbeziehung der Messwerte aus Aufwärts- und Abwärtsreihe (mit Umkehrspanne h mit Hysterese).
Case II: Linear interpolation equation taking into account the values from measurement series with increasing and decreasing torque (with reversal error h with hysteresis).

Interpolationsgleichungen
Interpolation equations

S in kHz M in N m

1.1 Fall I, Lineare Interpolationsgleichung Case I, Linear interpolation equation

1.1.1 Rechtsdrehmoment clockwise torque

$$\begin{matrix} S_p = & 0,006343 & - M_I \\ M_p = & 157,855 & - S_I \end{matrix}$$

1.1.2 Linksdrehmoment anticlockwise torque

$$\begin{matrix} S_p = & 0,0063392 & - M_I \\ M_p = & 157,748 & - S_I \end{matrix}$$

1.1.3 Rechts- und Linksdrehmoment clockwise and anticlockwise torque

$$\begin{matrix} S_p = & 0,0063411 & - M_I \\ M_p = & 157,701 & - S_I \end{matrix}$$

1.2 Fall II, Lineare Interpolationsgleichung Case II, Linear interpolation equation

1.2.1 Rechtsdrehmoment clockwise torque

$$\begin{matrix} S_p = & 0,0063434 & - M_I \\ M_p = & 157,644 & - S_I \end{matrix}$$

1.2.2 Linksdrehmoment anticlockwise torque

$$\begin{matrix} S_p = & 0,0063396 & - M_I \\ M_p = & 157,74 & - S_I \end{matrix}$$

1.2.3 Rechts- und Linksdrehmoment clockwise and anticlockwise torque

$$\begin{matrix} S_p = & 0,0063415 & - M_I \\ M_p = & 157,692 & - S_I \end{matrix}$$

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Rev. 3.0.0

Figure 9 Calibration certificate example (factory calibration)

Calibration certificate according to DAkkS

The DAKkS calibration certificate shows the sensitivities in “Case II, Linear interpolation equation”, section 3.3.1 and 3.3.2 (January 2023). For measurement systems supporting only one sensitivity, the value from 3.3.3 can be used (clockwise and anticlockwise torque).

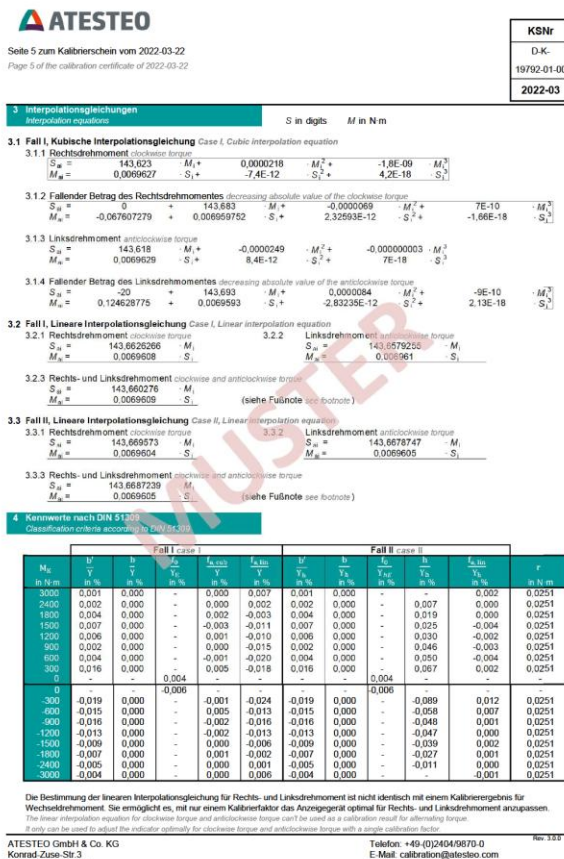


Figure 10 Calibration certificate according to DAkkS (extract)

3.9 Telemetry and measurement ranges

Most DF torque meter can optionally be purchased with a second (lower) torque range. This variant is called “dual”. The variants “pus” and “ibex” have one torque range.

3.9.1 Single range telemetry (plus/ibex)

The single range torque meter has one amplifier on the rotor. The measurement values are transferred by telemetry to the stator.

Available output signals:

- Frequency output proportional to torque
- Two frequency outputs proportional to the rotation speed (optional)
- Analogue voltage output proportional to torque
- Analogue voltage output proportional to rotation speed (optional)
- CAN interface (2B) with a torque signal and an optional rotational speed signal

3.9.2 Double range telemetry (dual)

The dual range telemetry or dual range telemetry has two amplifiers on the rotor. Parallel transfer of the two signals is generally possible. In most cases, the parallel transfer of two signals is counterproductive and thus deactivated by default. The parallel transfer can be activated on demand with the support of ATESTEO service.

Available output signals:

- Two frequency outputs proportional to torque

- Frequency output proportional to the rotation speed (optional)
- Two analogue voltage outputs proportional to torque
- Analogue voltage output proportional to rotation speed (optional)
- CAN interface (2B) with two torque signals and an optional rotational speed signal

3.9.3 Switch of measurement range

The second torque range was developed to realize measurement jobs with lower applied torques at higher accuracies. It is not to be used to measure the lower torques in a test cycle, which also contains high torque segments. The selection of the torque range must be done before starting a test cycle and should not be changed in it.

What must be considered before switching the torque range:

If a sensor during a test is mostly loaded in one direction, it can indicate a drift after the test is finished. This drift cannot be traced back to a temperature compensation problem but to the natural hysteresis of the sensor and strain gauges.

The change of the zero value depends on the torque applied or on the test duration. In any case, the value of the zero-drift variation will not be larger than the linearity and hysteresis specified in the technical data for the sensor.

Prior to switching the range, the sensor should be unloaded by a certain procedure. If technical possible, a zero-point adjustment should be done (see 3.10.1).

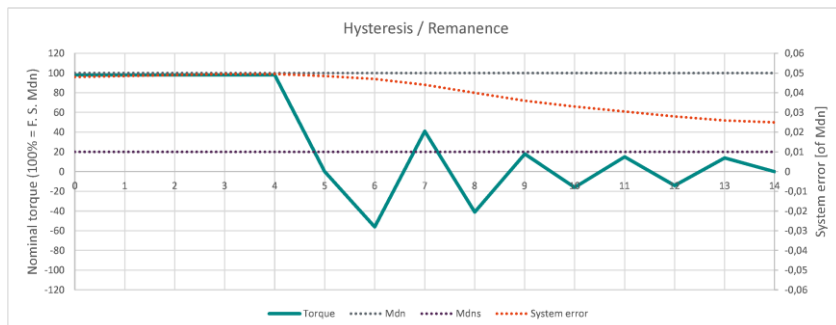


Figure 11 Unload procedure with low torque in positive & negative direction

The turquoise line shows the torque. 100% represents the maximum torque of the large torque range (see grey dotted line). After a long period with big torque, the hysteresis error (red line) might come close to the nominal hysteresis error of the sensor accuracy. Alternating (positive / negative) low torques will unload the measurement body. The hysteresis error will be reduced and the accuracy will be optimized for low torque measurements (purple dotted line).

3.9.4 Selection of measurement range

The user can choose the torque range by several measures:

- Via web interface (see 6.5),
- via digital input (see 7.2) or
- via CAN bus command (6.11.3.2)

The TCU5 will always determine the channel selection (torque range selection) at start-up via the digital input.

The applied channel selection can be checked with several functions:

- via web interface (see 6.5),
- via digital output (see 7.2) or

- via CAN bus state word (see “Active Channel” in 6.11.4)

3.10 Functions

3.10.1 Zero adjustment

Performing a zero (point) adjustment will take the current measured torque value as new zero torque value. Please read the important information in 8.1 before performing the zero adjustment. If the zero point has more than 5% (related to nominal torque) difference from the previous value, an error message will be shown.

Performing a zero-point adjustment for the rotation angle will set its value to 0°.

The torque zero-point can also be set to a self-defined value (see 6.1.1).

3.10.2 Test signals

The test signals generate an offset jump independent from the current measurement value. The test signal value is given on the test report, and it will apply to all signal output types.



Note:

Test signals must be disabled before measuring

3.10.2.1 Controller (TCU5)

The test signal will be applied in the TCU5 and set to all outputs.

3.10.2.2 Torque sensor

The test signal will be generated by an offset jump on the first amplifier in the rotor. From there it will follow the complete measurement chain to the output signals of TCU5.

3.10.3 Reset IP address

If the IP address was changed from standard and not written on the free area on the type label, the following two solutions will help you in case the IP address is lost:

- The tool “TCU Discover” can be used to search TCU5 in a local network. The tool can be downloaded from the ATESTEO website.
- Reset of IP address via digital input (see 7.1).

3.10.4 Filter

The torque inputs can be optionally filtered. As the filtering is carried out at the input, it is independent of the selection of the measuring range (see 3.9.4). All signal outputs are affected by the filter settings (see 6.10). An IIR filter is used (biquad filter in second direct form with 1st order). The adjustable filter frequency corresponds to the -3dB bend frequency of the respective filter.

CAN signals are also averaged via a block filter. The time window of the block filter is determined by the transmission rate of a message.

The longer the intervals between two messages, the larger the averaging time window (see 6.11).

3.10.5 Fail safe channel

The overload channel is used to better analyze misconduct at the test bench. While the standard measurement channels can capture torque values up to 110% of the nominal moment, the overload channel allows measurements of up to 300% of the nominal moment with an accuracy of 0.1%. Measurements of the overload channel are recorded at a speed of 2 kHz. The sensor determines the absolute maximum or minimum of the measured values in 800ms and then sends them to the TCU.

In addition to the web display, the overload values can also be issued via CAN.

The fail-safe channel is only used for subsequent error analysis in the event of unexpected problems. The limit torque may be less than 300%, depending on the rotor type.

3.11 LED coding

3.11.1 TCU5 (evaluation unit)

The TCU has a red and green LED on the top to display the system status. The coding is described in the following table:

Red LED	Green LED	State / Meaning
Off	Off	System switched off.

Off	On	Test signal of rotor or TCU is active.
On	Off	Critical system error. System will reboot.
On	On	System is starting.
Blinking every 2 seconds	Blinking every 2 seconds	TCU is receiving the digital data sheet from the rotor.
Blinking every second	Every state	Disturbance in data transfer or insufficient power supply of the rotor.
Every state	Blinking every second	Normal operating.

Table 4 TCU LEDs

3.11.2 DF stator

The DF stator has a green LED on the side to display the transmission status. The coding is described in the following table:

Green LED	State / Meaning
Off or sometimes off	The signal amplitude received by the torque sensor is too low. Please activate the power of the torque sensor on the website or readjust the stator.
Permanent on	The signal amplitude received by the torque sensor is sufficient for data transmission.

Table 5 DF stator LED

4 Mechanical & electrical installation

4.1 Transport

The torque meter of ATESTEO are high precise measurement sensors. Transport must be done with care. Try to use the original packaging whenever possible. When sending torque meter for calibration to ATESTEO, proper safety cases in most sizes are available at ATESTEO.

4.2 Lifting the rotor

The DF rotors typically have weights below 10 kg. Those can be lifted without a crane. If own or national regulations require a support (crane) for lifting, please contact ATESTEO service to get information about the proper mechanical lifting interface for each rotor.

4.3 Mechanical dimensions

4.3.1 Dimensions DF rotor

Please check the dimensions of the rotor from the drawings. They can be requested from ATESTEO or can be found in the product data sheets.

4.3.2 Dimensions DF stator plus

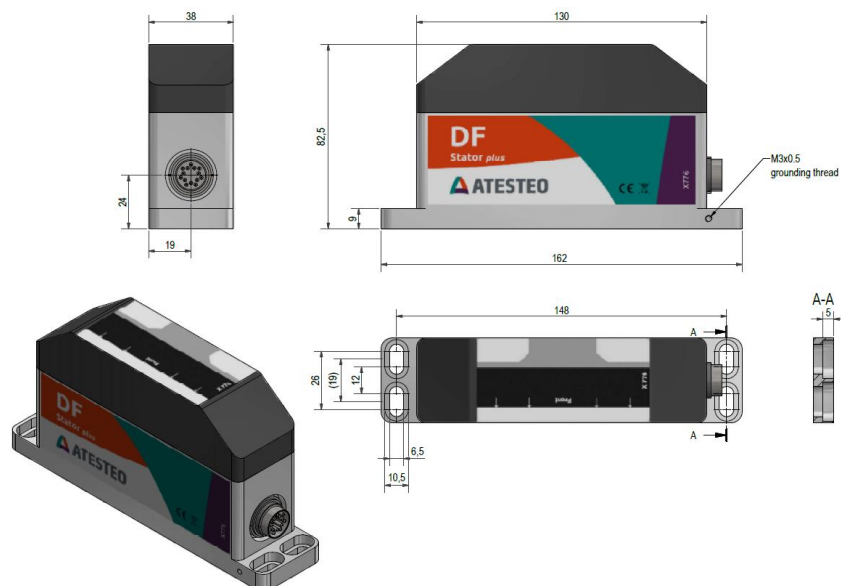


Figure 12 Dimensions of DF plus stator

4.3.3 Dimensions DF stator ibex/dual

The stator dimensions depend on the rotor variant (DF1-DF5).

For detailed information, see the drawings for your system. The base plate is identical for all stators. Figure 13 shows the dimensions using the DF1 as an example.

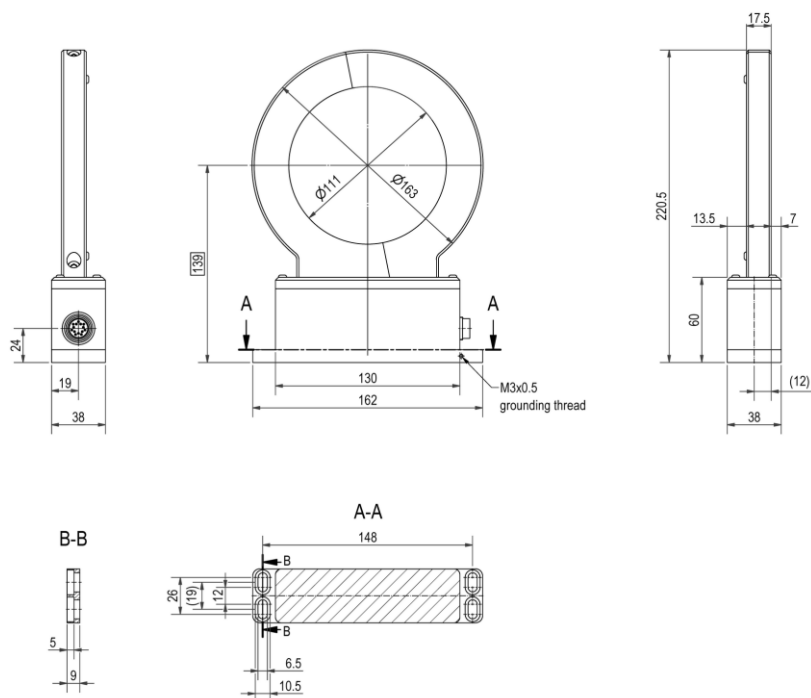


Figure 13 Dimensions of DF1 ibex/dual stator

4.3.4 Dimensions TCU5

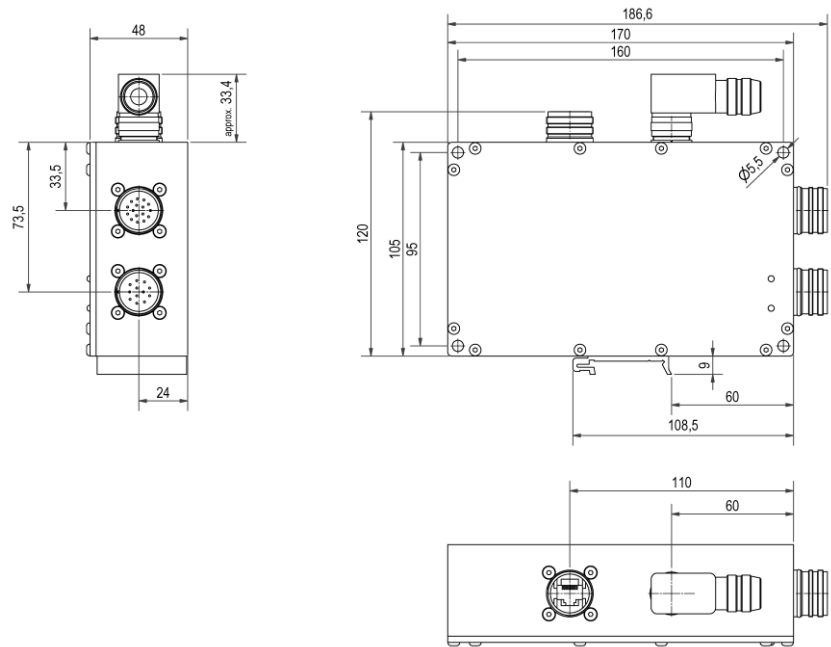


Figure 14 Dimensions of TCU5

4.4 Mounting the rotor

You need a torque wrench to mount the rotor.

Mounting torque meter with input side to drive train.

Type	Number of screws	Tightening torque
DF1 50 / 100 Nm (Titanium)	6x M8 10.9	36 Nm

DF1 200 / 500 Nm (Steel)	6x M8 12.9	43 Nm
DF2	8x M10 12.9	84 Nm
DF3	8x M12 12.9	145 Nm
DF4	8x M14 12.9	235 Nm
DF5	8x M16 12.9	360 Nm

Table 6 Rotor - Tightening torques

You can see the screwing depth in the following table:

Torque meter and thread size		Screw-in depth at torque meter flange [mm]		Screw-in depth at customer flange [mm]
		min.	max.	min.
DF1	M8x1.25	8	14	10
DF2	M10x1.5	10	14	12
DF3	M12x1.75	12	14	15
DF4	M14x2	14	17	17
DF5	M16x2	16	17	20

Table 7 Rotor - Screw dimensions & screw-in depth

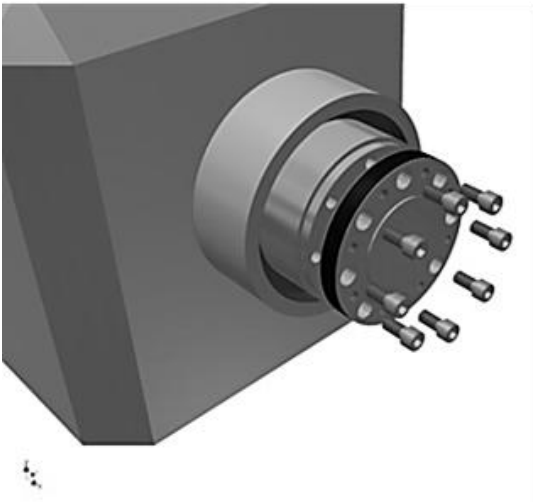
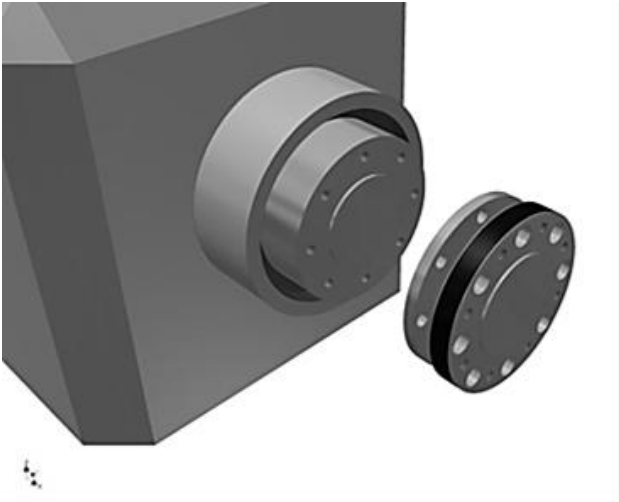


Figure 15 Rotor - Mounting

4.5 Mounting the plus stator

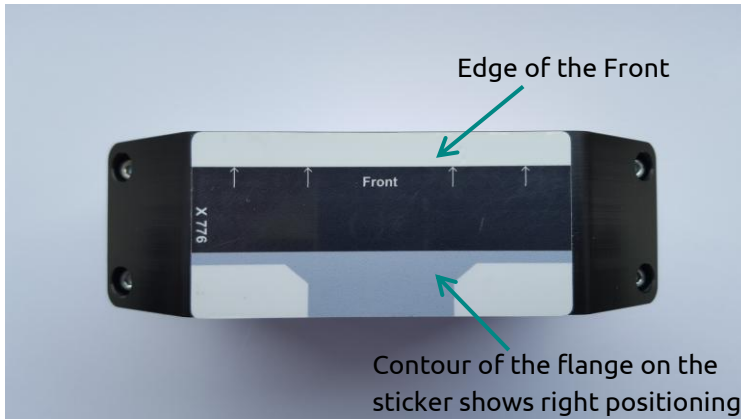


Figure 16 DF plus - Top-view of the stator

The DF plus stator must be positioned under the measuring flange that the output flange of the rotor covers the black area of the stator (sticker).

You need M6-screws for the mounting.

When mounting the stator, use all four slots.

First, the stator must be grounded. For details, see the section 4.9. The grounding screw should be used.



Figure 17 DF plus - Side view of the stator

You can find information on the dimensioning of the stator mounting to the rotor in chapter 4.5.1.

The following images show the right placement (of the rotor and the stator).

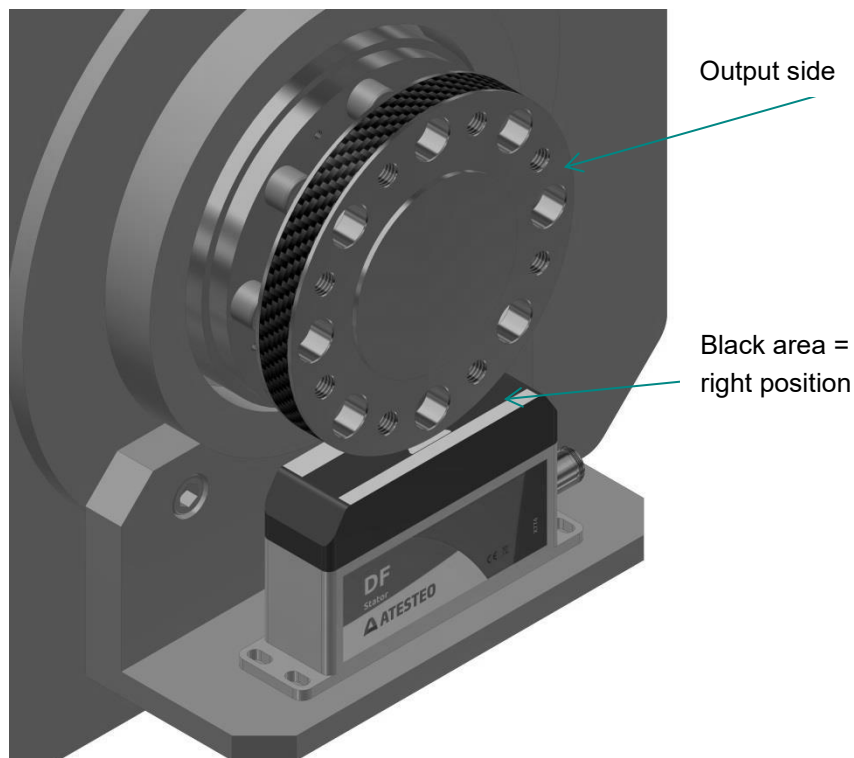


Figure 18 DF plus - Alignment stator and rotor 1

Right position: output side on the edge of the marking

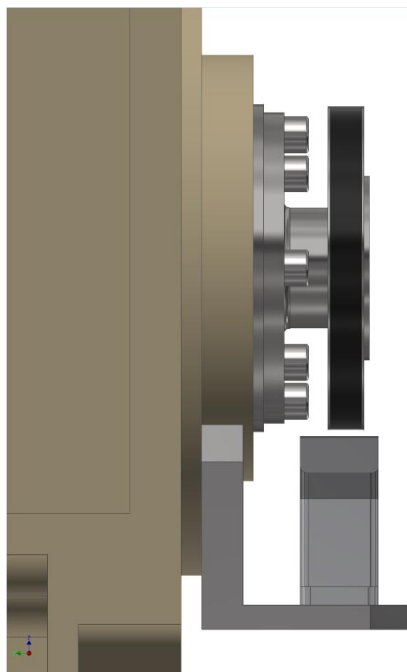


Figure 19 DF plus - Alignment stator and rotor 2

4.5.1 Mounting distances

The stator must be aligned to the rotor. Distances mention in Table 8 must be observed. Afterwards, an optional speed detection system can be aligned according to the mounting distances table.

Type		DF1 plus	DF2 plus	DF3 plus	DF4 plus	DF5 plus
Mounting distances (without optional speed detection system)						
Nominal axial displacement (rotor - stator)	mm	7				
Tolerance to nominal axial displacement (rotor - stator)	mm	±1				
Nominal radial displacement (rotor - stator)	mm	3				
Tolerance to nominal radial displacement (rotor - stator)	mm	+1/-2				
Distance stator to dyno	mm	14.00	17.00	18.00	19.00	29.00
Speed measuring system - Magneto resistive (2 tracks approx. 90 degree phase shifted)						
Nominal clearance (sensor - pole ring)	mm	0.7				
Working airgap (sensor - pole ring)	mm	0.1...2.0				
Nominal axial displacement (rotor - stator)	mm	7				
Tolerance to nominal axial displacement (rotor - stator)	mm	±0.5				

Table 8 DF plus - Mounting distances

4.6 Mounting the ibex/dual stator

The ring stator of the ibex/dual systems is divisible. Splitting it creates three main components.

Component	Description
A	Stator with fixed ring
B	Separated metal half ring
C	Separated plastic half ring

Table 9 DF ibex/dual - Components of the stator

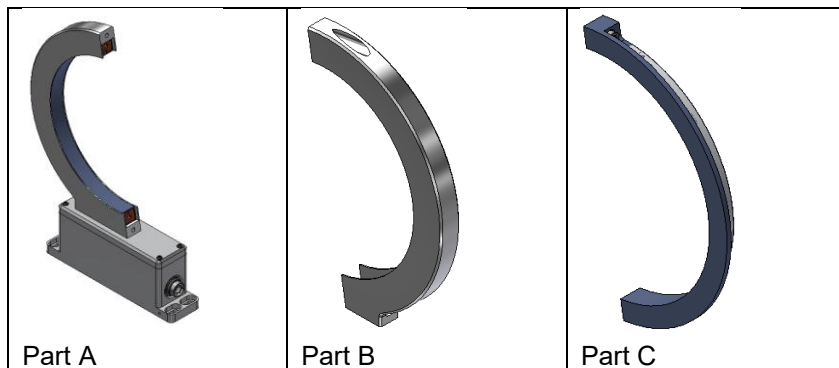


Table 10 DF ibex/dual - Figures of the three stator components

There are two mounting methods:

- Separate stator into its three components and mount them step by step (recommended).
- Install stator as one part and move it axial onto the rotor (not recommended).



WARNING:

The upper part of the permanently installed stator ring (part A) contains a strong magnet. It must be kept away from objects sensitive to magnets (e.g., the magnetic encoder of another stator, the magnetic ring on the rotor).

If your measuring system contains a magnetic speed detection, the stator ring (part A) must not be placed over the rotor! In this case, it must be separated for mounting.

4.6.1 Separate the stator

Loosen the two screws in the metal housing and remove the metal half ring (part B). A plastic inlay remains, containing the electronics.

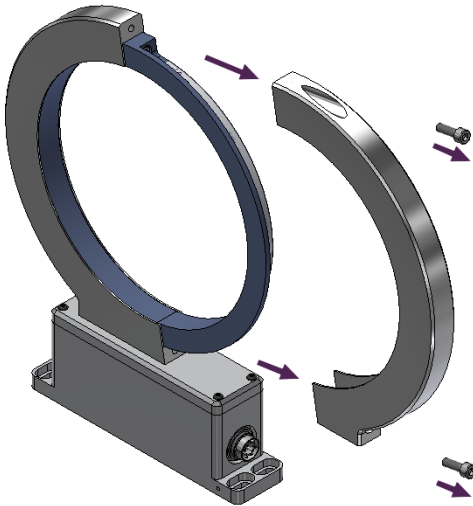


Figure 20 DF ibex/dual: Separate stator 1

The plastic inlay can also be divided into two half rings. Now loosen the two screws on the plastic inlay. When removing the plastic half ring (part C), be careful not to lose the (fan-shaped) lock washers.

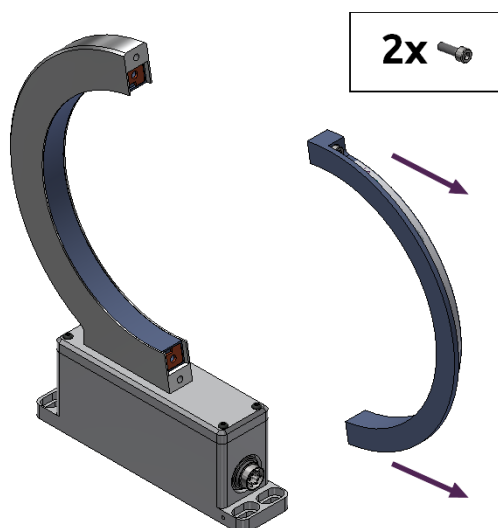


Figure 21 DF ibex/dual - Separate stator 2

4.6.2 Install and connect stator parts

The stator (part A) can now be installed without the removed half rings. Slide the stator housing sideways under the rotor. Be sure to observe the system alignment (see 4.6.3) and the instructions for the magnet (see 4.6).

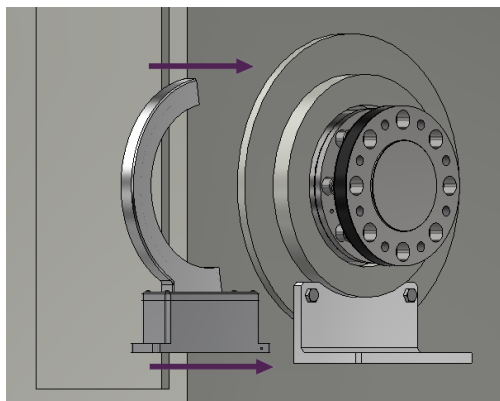


Figure 22 DF ibex/dual - Sideways installation of the stator 1

Secure the stator to a vibration-resistant base plate with four screws. The bracket shown is test bench-specific and not included in the scope of delivery.

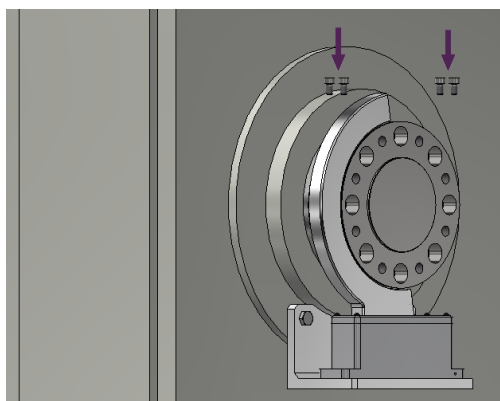


Figure 23 DF ibex/dual - Sideways installation of the stator 2

Now install the plastic half ring (part C). **The lock washers are necessary for trouble-free operation, as they ensure the electrical connection between the ring parts. Both must be installed.** The lock washers provided by ATESTEO must be used. The screws must be hand-tightened.

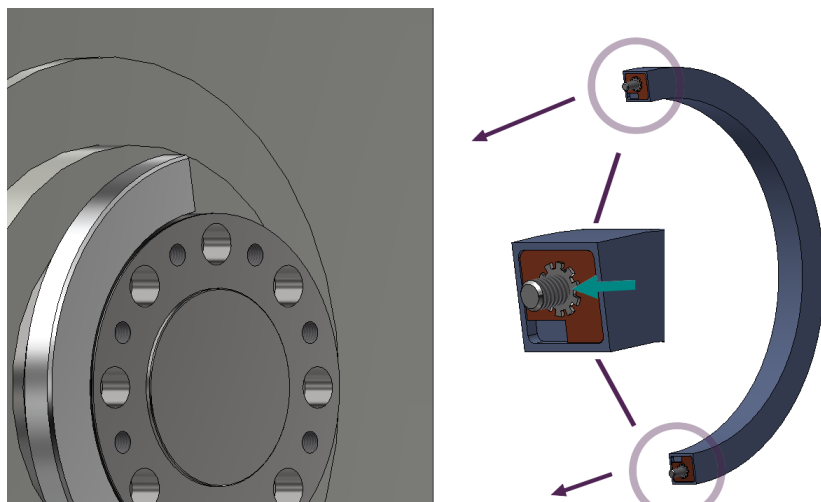


Figure 24 DF ibex/dual - Installation of the plastic half ring 1

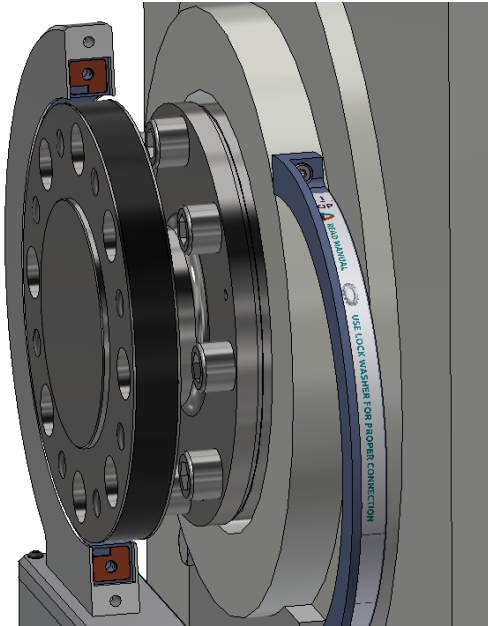


Figure 25 DF ibex/dual - Installation of the plastic half ring 2

Then slide the remaining metal half ring (part B) back over the plastic inlay. The metal ring is connected to the fixed half-ring with two M5 screws. Tighten the screws to 5.5 Nm.

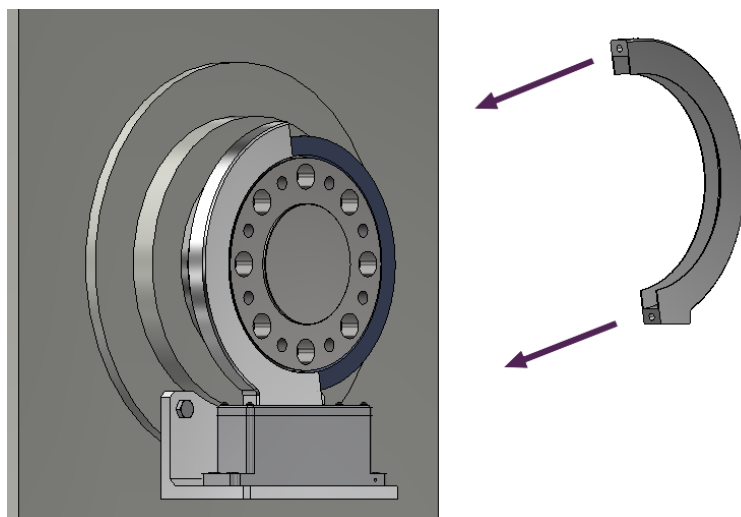


Figure 26 DF ibex/dual - Installation of the metal half ring 1

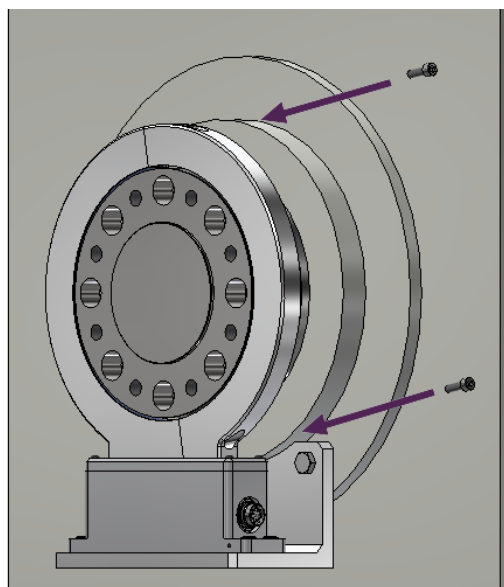


Figure 27 DF ibex/dual - Installation of the metal half ring 2

4.6.3 Mounting distances

During assembly, the stator must be aligned with the rotor. The distances specified in Table 11 must be observed. For further information, please always refer to the technical drawings. An optional speed sensor can then be aligned with the stator, observing the distances.

Type	-	DF1 ibex	DF2 ibex	DF3 ibex	DF4 ibex	DF5 ibex
Mounting distances (without optional speed detection system)						
Nominal axial displacement (rotor - stator)	mm			7,0		
Tolerance to nominal axial displacement (rotor - stator)	mm			±0.5		
Nominal radial displacement (rotor - stator)	mm	139,0	149,5	164,5	179,0	200,5
Tolerance to nominal radial displacement (rotor - stator)	mm			+0.2/-0.2		
Distance stator to dyno	mm	14,00	17,00	18,00	19,00	29,00
Speed measuring system - Magneto resistive (2 tracks approx. 90 degree phase shifted)						
Nominal clearance (sensor - pole ring)	mm			0,7		
Working airgap (sensor - pole ring)	mm			0.1...1.0		
Nominal axial displacement (rotor - stator)	mm			7,0		
Tolerance to nominal axial displacement (rotor - stator)	mm			±0.5		

Table 11 DF ibex/dual - Mounting distances

4.7 Speed-measuring system magnetic (optional)

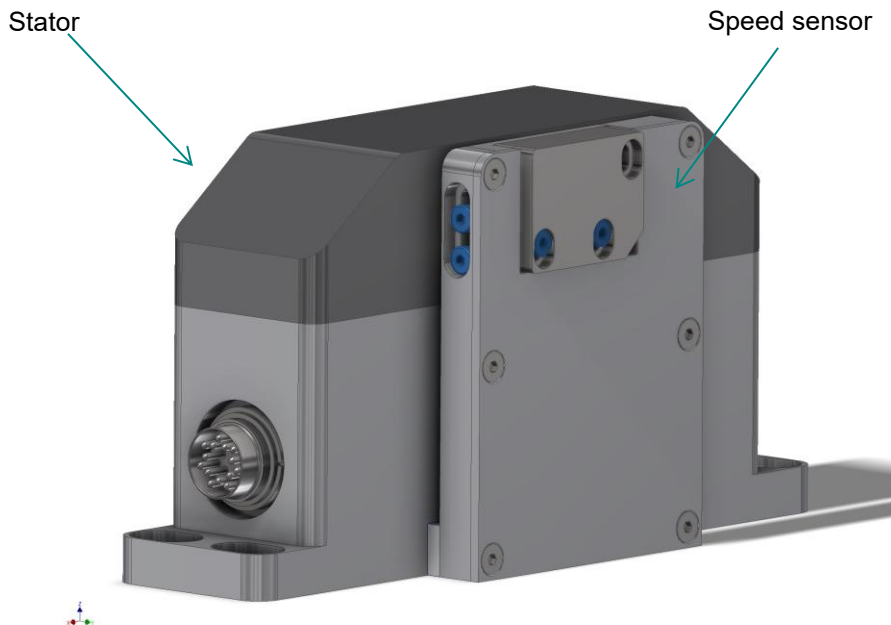


Figure 28 Optional speed detection system at stator

Delivery state

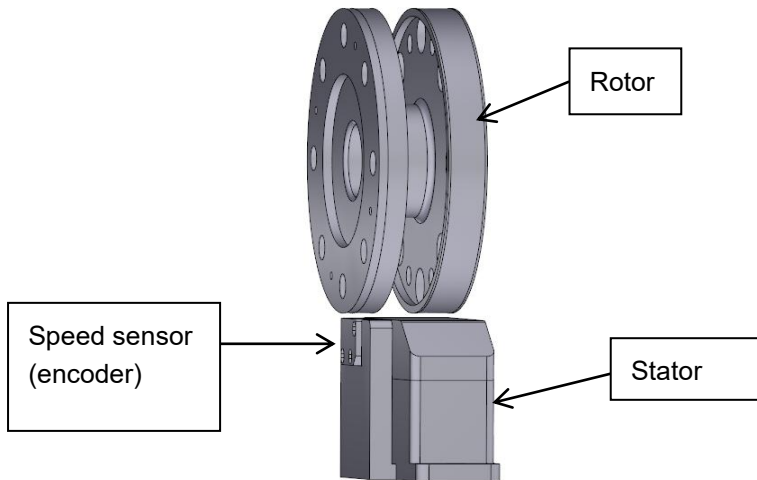
The speed measuring system is factory-set to nominal distance.
If an adjustment of the distance is necessary, please note:
Max. radial distance to the magnetic ring is 1 mm.

Speed sensor alignment

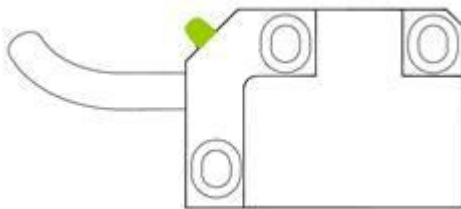
Release the two screws at the speed encoder and move the speed encoder into the correct position. Once the sensor is adjusted in range, fix the two screws again.

Remark:

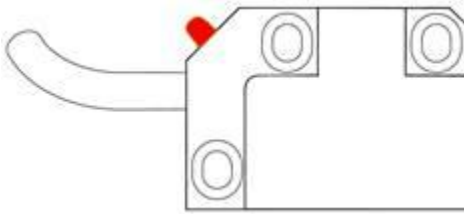
Stators of DF series are slightly different. A distance plate between stator backside and speed encoder varies in each stator (DF1, DF2, DF3, ...).



The speed-measuring system is equipped with an LED:
LED green: the signal strength is ok / Set-up



LED red: the signal strength is too low / Adjustment necessary



4.8 Assembly evaluation unit (TCU5)

The evaluation unit is not protected against splash or condensation water. That is why the evaluation unit should be assembled in a dry place with a maximum relative humidity of 80 %. The ambient temperature must be between -20 and +70 °C.

4.8.1 Type of installation

The evaluation unit can be mounted in two ways. It can be mounted on an electrically conductive 35 mm DIN rail (cap rail) or on an electrically conductive metal plate.

cap rail mounting

For mounting on a DIN rail, a metal clip is located on one side of the evaluation unit. The following figure shows the position of the metal clip:



Figure 29 Mounting of TCU5 (with clip)

The TCU can be easily hooked with the clip from top to bottom on the DIN rail. Please connect the DIN rail to the central ground point of the test bench via a grounding strap.

Metal plate installation

For mounting on a metal plate, there are four drill holes on the front of the evaluation unit. The following figure shows the position of the holes:

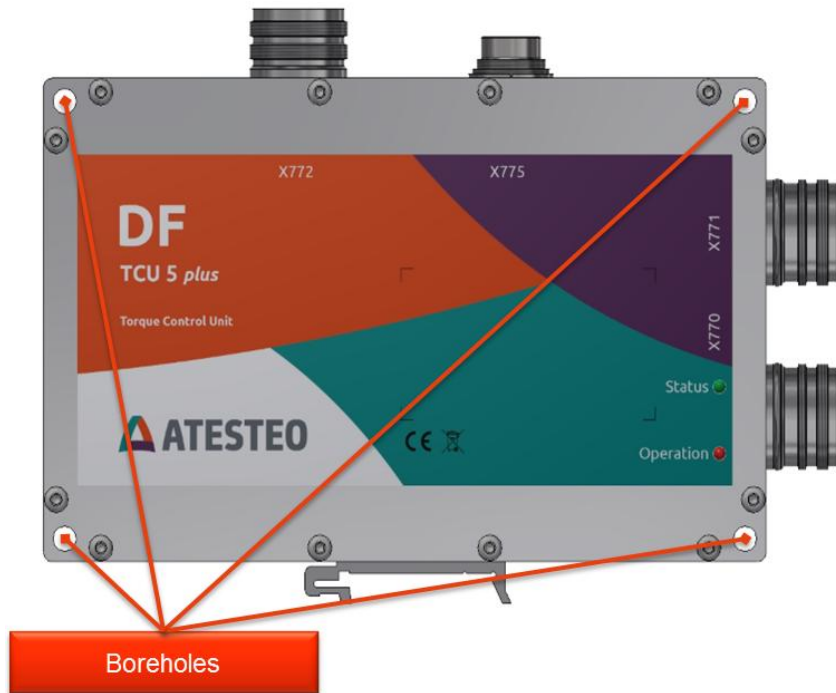


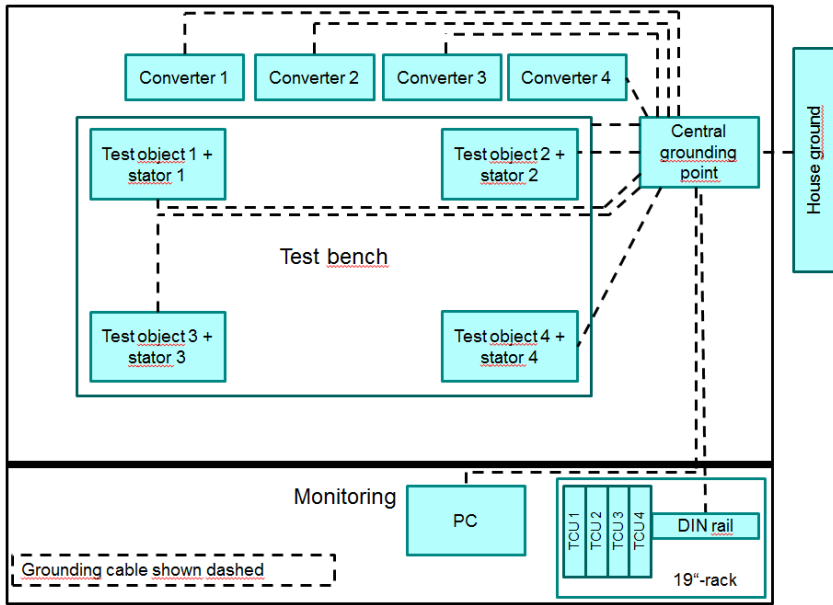
Figure 30 Mounting of TCU5 (with screws)

Attach the evaluation unit to the metal plate with four M5 cylinder head bolts. The drill holes for the screws each have a depth of 48 mm. Please connect the metal plate via a grounding strap to the central ground point of the test bench. The connection of the grounding strap should be placed as close as possible to the evaluation unit. For coated metal plates, the earth strap must be fastened to the evaluation unit via a ring cable lug on one of the four screws mentioned.

4.9 Grounding at the test bench

Today's demands of test stand claims require a powerful and high-frequency clocking hardware. Electronic components are sensitive towards electromagnetic emissions. That's why the avoiding of electromagnetic emissions is really important when it comes to test facility planning. The DF series hardware is designed to derive electromagnetic interference. These protection circuits only work if the stator and the evaluation unit are each connected via their own cables directly to a central mass point with the test bench ground. It is the same for the remaining hardware in the test bench. If all the components are directly connected to a mass point without detours it enables a low –impedance dissipation of broadband electromagnetic interference and at the same time it avoids unwanted ground loops by different line potentials.

The following illustration outlines the example of a point-to-point grounding concept:



In addition to a sophisticated earthing concept, it makes sense to separate all power cables using separate cable ducts from the sensitive signal lines of the test bench. A spatial separation of the power cables is the best option, but if it is not possible the cables should at least not be laid parallel to each other. The central cable between the stator and the TCU transmits sensitive signals. That's why it shouldn't be laid with the power cables. To add the cable shield protects the cable against external interference. A diligent planning of the grounding concept and the guideways can avoid costly error search and error correction on the fully assembled test bench!

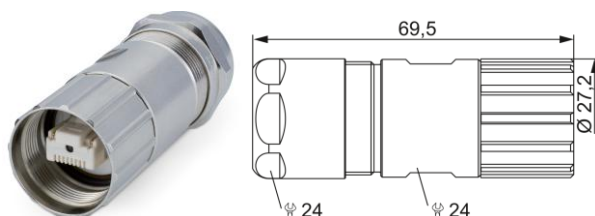
4.10 The wiring of the evaluation unit

The evaluation unit has four device plugs. The respective connector designation is written on the housing cover of the evaluation unit. Device connectors X770 and X771 connect the evaluation unit to the test bench peripherals. Device plug X772 connects the Ethernet interface to the evaluation unit. The central cable connects the device plug X775 of the evaluation unit with the stator. The central cable is not allowed to be longer than 50m. Only use the following cable connectors:

Device plugs	Cable connector (manufactures – manufacturer part number)
X770 (12-polig)	Hummel – 7106500000 + Hummel - 7001912104
X771 (16-polig)	Hummel – 7106500000 + Hummel - 7001916103
X772 (Rj45)	Hummel – 7R10400000* ¹ + Hummel – A7RJ-821M51* ¹ Or protective cap: Hummel – 7010900102
X775	Binder – 99 5629 75 12

*¹) not included in the scope of supply

Cable connector for connection X772



If you do not use the housing plug X772, please use the protective cap (included in the delivery) to protect it from electromagnetic field and dirt particles. You can find the pin assignment of the individual plugs in the appendix.

4.11 Power and data cable

In order to comply with the EMC standards EN61000-6-4 / VDE 0839 parts 6 to 4, the following procedure for connecting and lying the power/data cable is recommended:

Please use a shielded cable with 4x 2x 0.14mm² (twisted pair) + 4x 0.5mm² for connection to X770 and a shielded cable with 8x 2x 0.25mm² wire (twisted pair) for connection to X771. The shielding of the cables must be placed on both ends. The shield must also be placed on the measuring flange side and in the measuring cabinet.

Pin assignment see 7.



Information

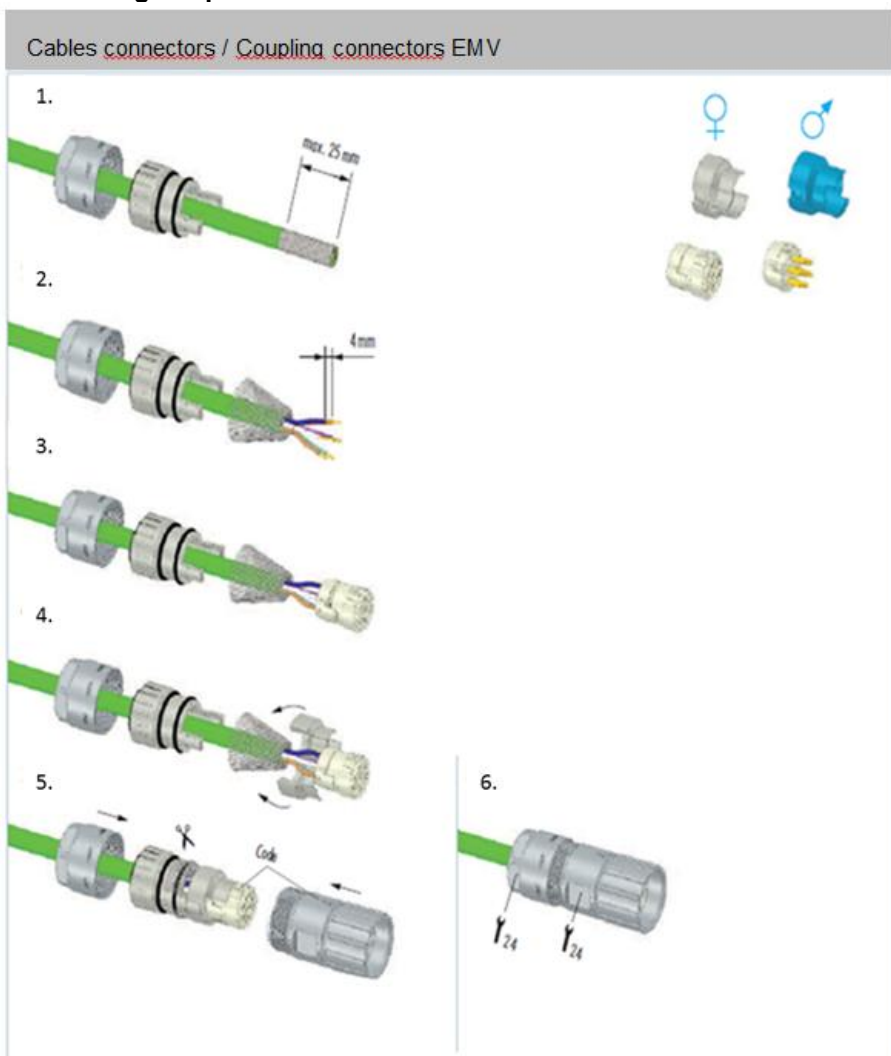
We recommend installing a fuse in the control cabinet with an on-and off-switch.



Information

Prefabricated cables are optionally available ex works.

Assembling the power and data cable



5 Start-up

5.1 The first switch on

Before you switch on for the first time, make sure that all system components have been connected and aligned in accordance with the installation instructions in this manual. Check all cable connections for correct and safe mounting. The DF series has three LEDs, which indicate the respective operating status. Two LEDs are located on the evaluation unit and one LED on the side of the DF stator.

You will find an overview of all flashing codes with the associated system states in the chapter 3.10.5.

The following chapter describes the setup of the web interface needed to configure the measuring system.

5.2 Installation of a Web browser

Use a common web browser for your system such as Firefox, Chrome, Edge or Safari.



Note

Please use the latest version of the browser

5.3 Network connection

You need a CAT5-Patchcable and an RJ35-connection to connect the TCU5 to an evaluation computer.

Three options to connect to network:

1. Connect directly

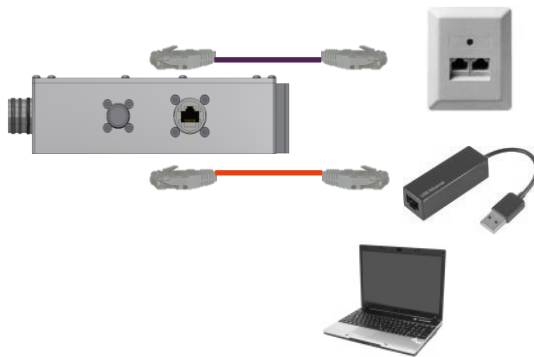
Connect with a patch cable directly from the Ethernet socket of the computer.

2. Connect with network-to-USB adapter:

The adapter needs to be installed on the computer. Now connect the TCU5 with a patch cable to the adapter.

3. Connect in domain network:

Connect the TCU5 using the patch cable with a free network socket.



The TCU5 does not support the ping protocol. Even with correct IP settings, the TCU5 will not reply on ping requests.

5.4 Network settings

Network settings need to be changed, if the system (torque meter, computer) is not connected to each other with a domain.

Ask your IT department to set up the following IP settings on your computer:

- ID address: 172.16.86.2
- Subnet mask: 255.255.255.0

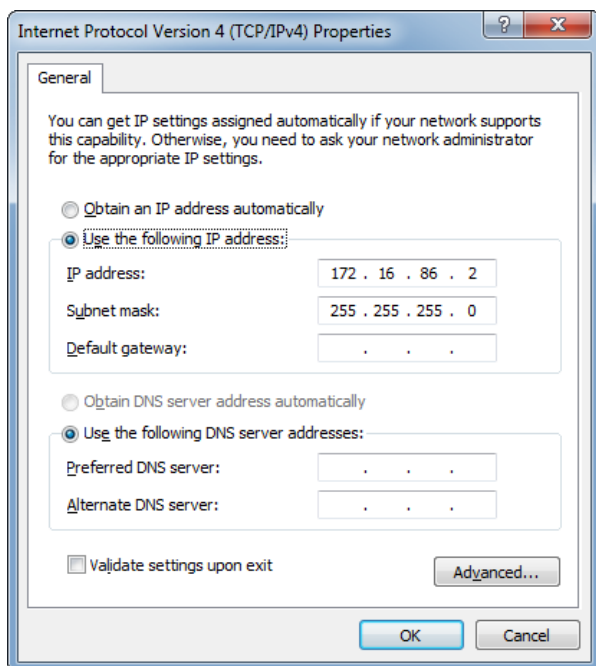


Figure 31 IP configuration (Windows)

5.5 Proxy configuration

Add a new exception for the proxy system for the following address space: 172.16.86.*

5.6 Web interface

The web address of the TCU 5 is needed to open the web interface. There are three different ways to open it.

The web address contains "tcuv-" and [SERIAL NUMBER].



Or you can use the following IP address to open the web interface:

http://172.16.86.3



In case the IP address is unknown and not default, the IP address can be reset (see 3.10.3).

6 Using the web interface

LOGIN

**LOGIN**

The password must be entered to log in. If the password is not changed, the password is: **admin**.

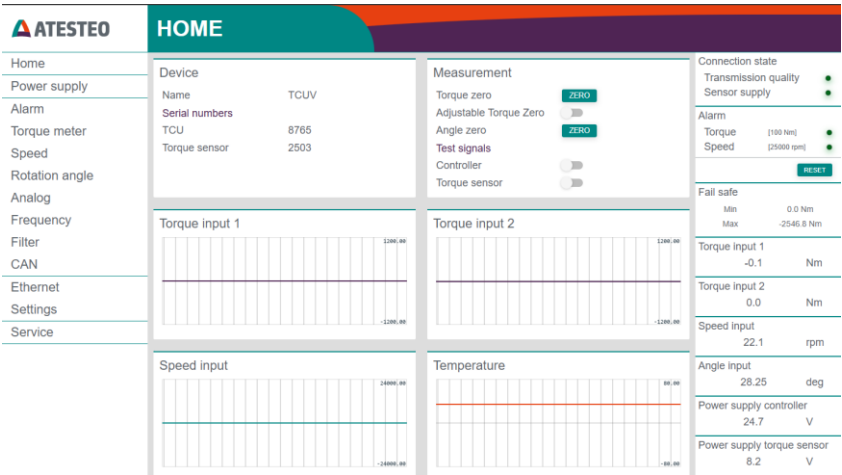


Important

The password can be changed in the item settings menu. Protect your measuring system from unauthorized access!

The web interface is only available in English language.

6.1 Home Menu



The Web-Interface is divided into different parts:

Device information:

Device	
Name	TCUV
Serial numbers	
Stator	5282
Torque sensor	4818

This overview of currently connected devices includes information about the name of the TCU 5 and the serial number of the stator and the torque sensor. The device name is editable in the Settings menu.

Measurement features:

Measurement

Torque zero

ZERO

Adjustable Torque Zero

Angle zero

ZERO

Test signals

Controller

Torque sensor

The measuring signal is set to zero (see 3.10.1) by pushing the “ZERO” button. Zero adjustment can be done for the signals “torque” and “rotation angle”.

Activating “Adjustable Torque Zero” will give the opportunity to enter a self-defined torque zero value (see 6.1.1).

The test signals (see 3.10.2) are enabled or disabled by the two related slider buttons.

6.1.1 Self-defined zero-point

First, activate the “Adjustable Torque Zero” option (see above). Then click the “Zero” button. A dialog appears for entering the zero-point (one value per measurement channel).

Adjustable torque zero input

Offset input 1 [Nm]:

-0.08

Offset input 2 [Nm]:

0.00

CANCEL

APPLY

Figure 32 Entering the manual zero point (adjustable torque zero)

In the dialog, enter the value to be added to the current measured value. If the current measured value is 21 Nm, enter -21 Nm. Click

"Apply" to apply the setting. The software calculates the absolute offset internally. This can be displayed by clicking "Zero" again.

Important: After restarting the TCU5, the setting will be lost and must be made again!

6.1.2 Graph overview



Different signals are displayed in the main part of the home page. These signals graphically represent Torque input 1, Torque input 2¹, Acceleration input¹, the Speed input¹ and the Temperature of the torque sensor. Graphs are automatically scaled according to their nominal value.



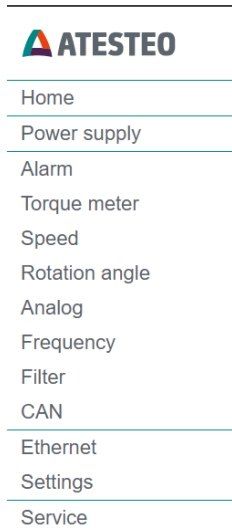
Note

Signals are not displayed in real-time. This may lead to delayed representations.

¹ Depending on the configuration of the current system

6.1.3 Navigation menu

If the navigation bar is closed, click on the company logo to open it again.



6.2 System overview

The signal bar is shown on the right-hand side of the website.

Connection state		
Transmission quality		A
Sensor supply		B

Alarm		
Torque	[1000 Nm]	
Speed	[25000 rpm]	

RESET

Fail safe		
Min	0.0 Nm	
Max	15.6 Nm	

Torque input 1		
0.7	Nm	

Torque input 2		
0.0	Nm	

Speed input		
0.0	rpm	

Power supply controller		
23.8	V	

Power supply torque sensor		
8.2	V	

Temperature		
25	°C	

- A** Transmitting (green) | No Transmitting (gray)
B Optimal (green) | Okay (yellow) | Bad (red)
C Value below threshold (green) | Value above threshold (red)



Note

Signals are not displayed in real-time. This may lead to delayed representations.



Important

Check the supply voltage and the orientation between torque sensor and stator-antenna to guarantee an optimal transmission quality.

Connection state

The “Connection state” tab contains information about the transmission status of the system. The LED “Transmission quality” is an indicator of transmission quality of measured data from torque meter to torque control unit. The “Sensor supply” LED indicates the status of the torque sensor supply voltage.

Alarm states

Alarm values are displayed in the “Alarm” section. Red indicates that the threshold is exceeded. Alarms can be reset by pressing



-button. Alarm limits can be set in the “Alarm” settings menu.

Measured data

Below the alarm states the measured data of the different system inputs: Torque input 1, Torque input 2², Acceleration input², Speed input², Angle input², Power supply torque sensor, Power supply controller, Torque sensor Temperature and Fail safe² are displayed numerical.

Fail safe

Displays the minimum and maximum value of the fail safe channel (see 3.10.5).

² Depending on the configuration of the current system

6.3 Power supply



In the menu “Power supply”, the supply voltage of the torque sensor will be adjusted. The power-switch activates and deactivates the power supply. If the power supply is activated, a search is started automatically, which sets the optimum operating point. This also applies to system startup. Because the inductively transmitted power depends on the gap between torque sensor and stator-antenna the supply voltage must be readjusted after change of position. The optimal supply voltage of the torque sensor is $8.0\text{ V} \pm 0.5\text{ V}$. There are 2 methods for adjusting:

1. Manuel mode: By pressing the  button, the optimal supply voltage is automatically set.
2. Automatic search: The search always starts when the system relies on the working range of $8\text{V} \pm >1.5\text{V}$! If the search starts, the system is no longer ready to measure. System status must always be checked.

In the following section, the influence of the torque sensor voltage to the signal quality is shown:

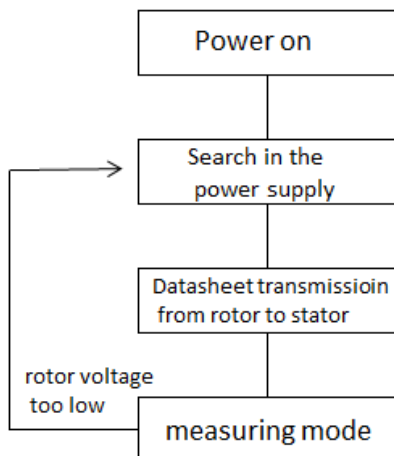
Sensor voltage	LED "Sensor supply"	Description
8.0 V $\pm$ 0.5 V	Green	Optimal supply voltage
8.0 V $\pm$ 1.0 V	Yellow	Supply voltage is OK. Interruption caused by fluctuation of supply voltage possible.
8.0 V $\pm$ > 1.0 V	Red	Poor supply voltage. Possibly interrupted transmission, possibly invalid measurement values

Table 12 Power supply of rotor

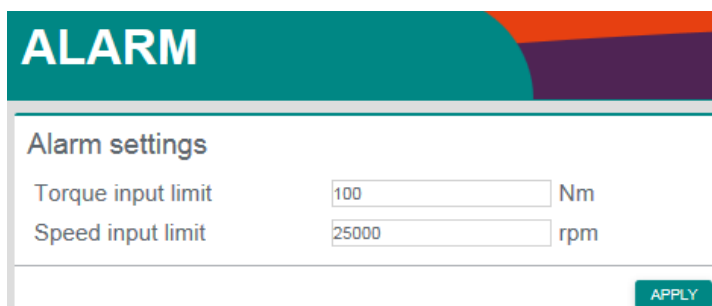


Important

The optimal torque sensor supply voltage should be at 8 V. Power supply will be deactivated and set back to zero, if a critical value is adjusted, to prevent damage of inductive power supply components. Measurement values can be invalid if the voltage drops



6.4 Alarm settings



ALARM

Alarm settings

Torque input limit Nm

Speed input limit rpm

APPLY

Alarm thresholds for speed³ and torque can be set.

Torque input limit

If the measuring signal exceeds the set limit value, the alarm is triggered. In dual-range systems, only the large measuring range is

³ Depending on the configuration of the current system

considered. Both alarms are transferred via the status word (CAN bus) and via the X771 plug.

6.5 Torque meter

TORQUE METER

Output switch

☒ In 1 - Out 1 | In 2 - Out 2
☐ In 1 - Out 2 | In 2 - Out 1

APPLY

Torque input 1

Rated torque
200 Nm

Sensitivity +
1914.2050 Dig/Nm

Sensitivity -
1913.6600 Dig/Nm

Torque input 2

Rated torque
1000 Nm

Sensitivity +
397.7765 Dig/Nm

Sensitivity -
397.6755 Dig/Nm

Fail safe input

Rated overload
3000 Nm

Sensitivity +
0.0171 Dig/Nm

Sensitivity -
0.0171 Dig/Nm



Important

Improper values can falsify measurements or in worst case damage the measurement device. Proper values can be found in the test report.

The “Torque meter” display is locked for input, as the rotor automatically adopts the values. Manual changes of the settings can be changed in the setting menu (see 6.13).

6.5.1 **Output switch**

Output / View	Effect of switched output
Website view (Chart / Single value)	None
Frequency output¹	Swapped
Analogue output (voltage)^{1(*)}	Swapped
CAN output¹	None

Table 13

Output switch

Analogue output channels without “output switch”:

Ana1_out	Torque1
Ana2_out	Torque2
Ana3_out	Speed
Ana4_out	Rotation angle

Analogue output channels with “output switch”:

Ana1_out	Torque2
Ana2_out	Torque1
Ana3_out	Speed
Ana4_out	Rotation angle

6.5.2 Selection of measurement range

For dual-channel torque transducers (dual) with only a single channel active (default setting) the active channel can be chosen. In addition, the current selection can be seen here.

Active channel

☒ Channel 1
☐ Channel 2

APPLY

This feature affects the following output signals:

The function of each inactive output is explained in 3.9.2.

6.6 Speed

The page „Speed“ shows the parameter of the optional speed detection system. The rated speed and the number of increments is read from the electronic data sheet of the rotor. If the automatic apply function is deactivated, the values can be defined manually. Please read chapter 6.13.



Important

Incorrect values will lead to wrong measurement values. Correct values are given on the test report.

The gate time is defined independently from the connected rotor. It will affect the averaging of the speed signal.

SPEED

Speed input

Rated speed

11000

rpm

Increments

808

ppr

Gate time

1000

µs

6.7 Rotation angle

ROTATION ANGLE

Angle input

Mode

0 - 360°

Revolution n

1

Increments 4x

120

ppr

APPLY

DF systems that have a speed detection system can also measure rotation angles. Two calculation methods are available to generate the rotation angle value:

Method	Description
0 – 360°	Rotation angle value will be generated in range from 0° to <360°. 360° is equivalent to 0° (unipolar mode).
±n * 360°	Rotation angle value will be calculated with sign and factor. “n” (0.5; 1...5). Factor “n” defines the number of rotations before value overload. The following rule applies: $-n * 360^{\circ} < x \leq n * 360^{\circ}$ Overload rule: The largest possible value will be followed by the smallest possible value and vice versa.

Table 14 Rotation angle calculation methods

The resolution of the rotation angle depends on the number of impulses of the magnetic speed detection system.

Rotor size	Impulse number	Rotation angle resolution [°]
DF1	680	0.132
DF2	808	0.111
DF3	1,000	0.090
DF4	1,176	0.077
DF5	1,448	0.062

Table 15 Resolution of the rotation angle signal

A zero-point adjustment of the rotation angle can be triggered in the main menu of the web interface or via CAN bus command.

Restarting the TCU5 also performs a zero-point adjustment. Changing the calculation method will come into effect after the first movement of the rotor.

The rotation angle is reset to zero if the connection between stator and rotor is lost. The same happens if the distance between magnet ring and speed sensor is too large. In both cases, the root cause must be solved to get a stable rotation angle value (see 4.7).

The rotation angle output is a CAN signal or an analogue voltage.

6.8 Analog settings

ANALOG

Voltage Range

Range

Output calibration

Perform a device calibration only if the effect of your changes are known.
Incorrect values may affect the functionality of the device.

Voltage range of analog outputs can be adjusted.

Voltage Range

Range

Output calibration



Important

The outputs may only be calibrated by trained personnel.
Incorrect values falsify measurements.

The outputs are calibrated at the factory and there is no need to recalibrate them.

6.9 Frequency settings

FREQUENCY

Frequency settings

Output 1 range

kHz

Output 2 range

kHz

Output calibration

Perform a device calibration only if the effect of your changes are known. Incorrect values may affect the functionality of the device.

Various output ranges can be set in the "Frequency" menu. For a dual-channel torque transducer, both ranges can be set separately.

Available frequencies: **10±5; 60±20; 60±30; 240±120 kHz**

Output calibration



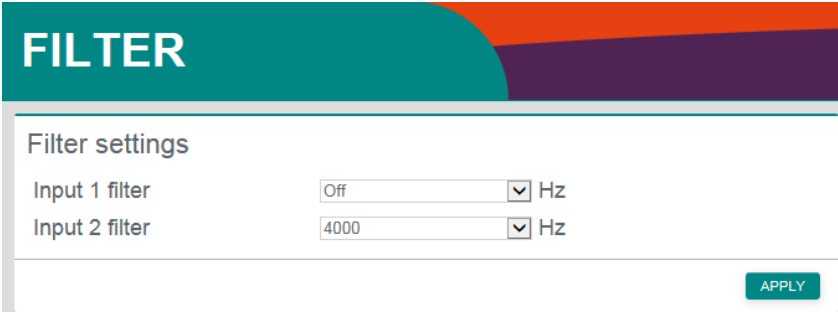
Important

The outputs may only be calibrated by trained personnel. Incorrect values falsify measurements.

The outputs are calibrated at the factory and there is no need to recalibrate them.

6.10 Filter settings

The filter-settings influence the analogue voltage output, frequency output and CAN bus output.



FILTER

Filter settings

Input 1 filter Hz

Input 2 filter Hz

APPLY

The TCU provides a digital IIR filter 1st order. It is related to the torque input channels. For each input channel, the filter can be activated, and the cut-off frequency can be set in the corresponding dropdown-box. The following cut-off frequencies between 1 Hz and 4000 Hz are supported:

1 Hz, 10 Hz, 50 Hz, 100 Hz, 150 Hz, 250 Hz, 500 Hz, 1000 Hz, 2000 Hz and 4000 Hz.

The  -button is clicked to save the settings.

6.11 CAN settings

CAN

Scaling factor

Torque input100
Speed input10

CAN state

BUS_HEAVY
CAN output
CAN terminator

CAN configuration

Data formatIntel
Baud500 kbit/s
Transmit interval100.0 ms
Identifier length11 bit

Send configuration

Message 1

Identifier100 [hex]
ContentNone [0..3]
ContentNone [4..7]

Message 2

Identifier101 [hex]
ContentNone [0..3]
ContentNone [4..7]

Send configuration

Message 3

Identifier102 [hex]
ContentNone [0..3]
ContentNone [4..7]

State message

Identifier103 [hex]
ContentState part 1 [0..3]
ContentState part 2 [4..7]

Receive configuration

Identifier104 hex

The CAN interface can be configured in the CAN menu.

6.11.1 Scaling factors

Scaling factor	
Torque input	1000
Speed input	10
Angle input	100

The torque value and other values are transmitted in integer format. To generate sufficient decimal places in the TCU, the measured value is multiplied by a scaling factor. To obtain the true measured value in the measurement data acquisition, the received value must be divided by this scaling factor. The exact scaling factor of system depending signals is shown in the web interface.

The signal “sensor supply” has always the factor 100.
The signal “temperature” has always the factor 1.

6.11.2 CAN transmission

CAN transmission is enabled and disabled by toggling the  -button. 120 Ohm terminator can be activated on demand. Terminator is not active by default.

The “CAN State” tab also contains information about the current state of the CAN bus. The different states are explained in the following sections.

MODULE_ACTIVE: The CAN bus is working without any significant problems. The *receive error counter (RX)* and the *transmit error counter (TX)* are < 128.

CAN state

MODULE_ACTIVE



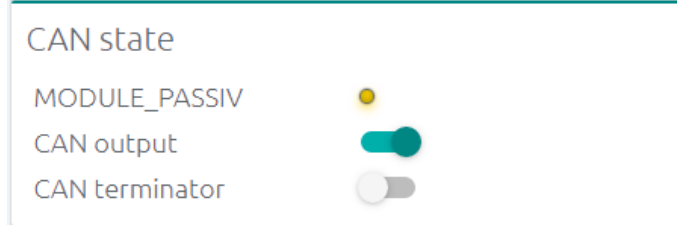
CAN output



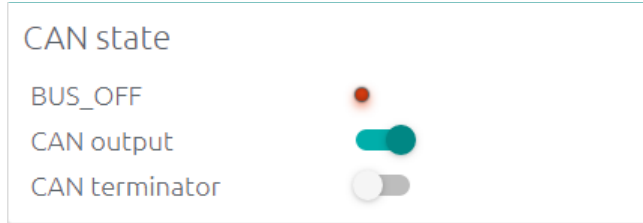
CAN terminator



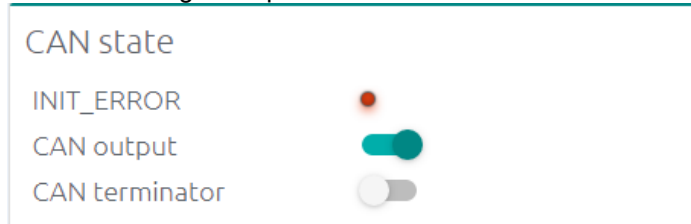
MODULE_PASSIV: The CAN bus works, however, a transmission or reception error occurred. TX or RX is > 127. In case that no more errors occurred, the counters are decremented and the status changes to **MODULE_ACTIVE**. Otherwise, the bus should be checked.



BUS_OFF: The CAN module has been disconnected due to many transmission errors (TX > 255). Check the CAN settings and perform a CAN reset.



INIT_ERROR: The CAN module cannot connect to the CAN bus. Check the CAN settings and perform a CAN reset.



NOTE: CAN State can be reset by switching the output off and on again.

CAN Terminator

Connectable 120 Ω CAN connection resistor.

6.11.3 CAN configuration

CAN configuration

Data format	Intel	v
Baud	500	v kbit/s
Transmit interval	1	ms
Identifier length	29	v bit

The general CAN transmission can be configured. Selected values need to fit the values of the current receiver system.

- ▶ Data format (Intel, Motorola)
- ▶ Baud rate (250kbit, 500kbit, 1Mbit)
- ▶ Transmit interval (between 0.5 and 1000 ms)
- ▶ Identifier-Length (11 Bit, 29 Bit)
- ▶ Message IDs

6.11.3.1 Configuration of measurement signals

Send configuration		Send configuration	
Message 1	☒	Message 3	☐
Identifier	100 [hex]	Identifier	102 [hex]
Content	Torque input 1 [0..3]	Content	Sensor supply [0..3]
Content	None [4..7]	Content	Temperature [4..7]
Message 2	☒	State message	☐
Identifier	101 [hex]	Identifier	103 [hex]
Content	Fail safe (min) [0..3]	Content	State part 1 [0..3]
Content	Fail safe (max) [4..7]	Content	State part 2 [4..7]
APPLY		APPLY	

CAN messages are formatted (dependent on configurations) in the following way:

Intel	Data byte 0-3				Data byte 4-7			
Identifier	D0	D1	D2	D3	D4	D5	D6	D7
Selectable	Torque 1 x Factor_torque				Torque 2 x Factor_torque			
Selectable	Speed x Factor_speed				0x00			

Motorola								
Identifier	D3	D2	D1	D0	D7	D6	D5	D4
Selectable	Torque 1 x Factor_torque				Torque 2 x Factor_torque			
Selectable	Speed x Factor_speed				0x00			

Up to four CAN messages can be configured depending on the CAN configuration. If the busload exceeds 90% due to the configuration, the 3rd CAN message is blocked. This ensures that the CAN messages can continue to be transmitted reliably.

$$CAN - Message\ length_{11\ Bit\ id} = 130\ Bit$$

$$CAN - Message\ length_{29\ Bit\ id} = 148\ Bit$$

$$\frac{(CAN - sampling\ rate * message\ length)}{1000} = Bus\ load\ in\ kBit/s$$

$$\frac{(\text{Bus load in } \frac{k\text{Bit}}{s} * \text{Number of messages})}{\text{Baud rate}} * 100 = \text{Bus load in } \%$$

CAN Messages can be enabled and disabled. Messages one, two and three can be manually chosen and adjusted. The fourth message cannot be configured. It is reserved for the system state.

“Heavy bus load” warning:

Heavy bus load

The CAN configuration of this system generates a bus load of 198.4%. We recommend reducing the bus load in order to guarantee a delay-free transmission.

Possibilities to reduce the bus load are:

- Increasing the baud rate
- Reduction of the transmission interval
- Switching off CAN messages

[CONFIRM](#)

6.11.3.2 Configuration of debug signals

None
Torque input 1
Torque input 2
Speed input
Temperature strain gauge
State part 1
State part 2
Sensor supply
Fail safe (min)
Fail safe (max)
Rotation angle
CRC-Error counter
Sync-Off counter
Timeout counter
Error-chain counter
Royer current
Transmitting rate

Figure 33 List of CAN transmitting signals

In addition to the measurement signals (torque, speed, angle of rotation), there are several signals that are useful for debugging.

Signal name	Description of the signal
Temperature strain gauge	Temperature of the strain gauges for monitoring the rotor temperature.
State part 1/2	CAN State message (see 6.11.4).
Sensor supply	Supply voltage of the rotor (see 6.3).
Fail safe (min/max)	Minimum and maximum value of the fail safe channel (see 3.10.5).

CRC error counter	Check sum error counter.
Sync-off counter	Error counter for invalid starting sequences of data packages.
Timeout counter	Timeout counter for received data packages.
Error-chain counter	Collective error counter over one second. Exceeding the threshold (adjustable, default: 8) will set the system into error mode.
Royer current	Current consumption of the stator. Expected value < 1.0 A (see 6.11.4).
Transmitting rate	Data transmitting rate between rotor and stator. Expected value 25,000 values/s.

Table 16 CAN debug signals

The error counters should be zero or in the low single digits. Increasing values indicate errors in the data transmission. In this case, the setup must be checked:

- Review the grounding concept.
- Check the rotor-stator alignment.
- Ground the stator correctly.
- Do not route the central cable parallel to the power lines of an electric motor.
- Contact ATESTEO Service.

6.11.3.3 Configuration of control (command / response)

Receive configuration

Identifier hex

APPLY

The receiving identifier for CAN command message can be chosen. The following CAN commands can be received:

Command	Command code	
	Hex	Dec
Zero adjustment “Torque”	0x4B1	1201
Test signal TCU5 (on)	0x4B2	1202
Test signal TCU5 (off)	0x4B3	1203
Counter reset (CRC error, Sync off, Timeout, Error chain)	0x4B4	1204
Channel selection MD1/MD2	0x4B5	1205
Channel selection MD2/MD1	0x4B6	1206
State reset	0x4BB	1211
Request state	0x4BC	1212
Zero adjustment “Angle”	0x4BD	1213
Power supply (off)	0x514	1300
Power supply (on)	0x515	1301

Alarm reset	0x578	1400
Request settings	Ethernet 0xD05	3333

Table 17 CAN command list

The command must be included in the first 4 bytes [data bytes 0-3]. While receiving, distinction is made between Motorola and Intel. A response message is sent if a message is successfully received. The response message is formatted in the following way:

Response message		
Identifier	Data byte [0-3]	Data byte [4-7]
receive identifier +1	last command	State part 1

6.11.4 Status word

The status word of DF series uses all 8 Byte of one CAN-Message and is separated into two parts. These are available separately in the selection menu for the CAN messages. The assignment within the CAN status message is fixed. The following table shows the assignment:

State Part 2	State Part 1
Byte 7 - 4	Byte 3 - 0

Each State Part is 32 bits long. The following table describes the functions of the individual bits:

State Part 2			
Bit	Name	Description	Category
31	Rotor connected	Voltage search completed and nominal voltage reached	Connectivity
30	CAN active	CAN output activated	
29	-	Reserved	
28	-	Reserved	
27	-	Reserved	
26	-	Reserved	
25	-	Reserved	
24	-	Reserved	
23	-	Reserved	
22	-	Reserved	
21	Power supply	Rotor power supply activated	System supply
20	Voltage search	System is in voltage search	
19	-	Reserved	
18	-	Reserved	
17	-	Reserved	
16	-	Reserved	
15	-	Reserved	
14	-	Reserved	
13	-	Reserved	
12	-	Reserved	
11	Test signal rotor	Test signal rotor was triggered (half measuring range)	Test/Service

State Part 2			
Bit	Name	Description	Category
10	Test signal controller	Test signal controller was triggered (full measuring range)	
9	Configuration mode	Controller is in configuration mode (Service)	
8	Calibration mode	Controller is in calibration mode (service, fixed CAN messages, no calculation)	
7	Watchdog	Counter 0-255 (Increments in transmission speed)	
6			
5			
4			
3			
2			
1			
0			

Table 18 CAN status word part 2

State Part 1			
Bit	Name	Description	Category
31	Alarm RX	System not ready for operation	Alarm/Error
30	Alarm MD	Torque exceeded	
29	Alarm N	Speed exceeded	
28	Alarm ACC	Acceleration exceeded	

State Part 1			
Bit	Name	Description	Category
27	-	Reserved	
26	-	Reserved	
25	Alarm Overcurrent	Royer current $\geq 1.4A$ Royer current $\geq 1.2A$ (~ 5 minutes)	
24	Positioning error	Overcurrent during voltage search	
23	Version error	Incompatible equipment combination	
22	OS error	Fatal system error	
21	Current warning W1	Royer current $\geq 1.2A$ (~ 1 minute)	Warning
20	Current warning W2	Royer current $\geq 1.2A$ (~ 4 minute)	
19	Signal quality warning	Transmission rate < 24000 SPS	
18	-	Reserved	
17	-	Reserved	
16	-	Reserved	
15	-	Reserved	
14	-	Reserved	
13	-	Reserved	
12	-	Reserved	
11	System ready	System ready for operation	Measurement

State Part 1			
Bit	Name	Description	Category
10	Output switched	Signal input 1 is linked to measurement output 2	
9	Zeroed outputs	The measuring system has been zeroed by the user	
8	Rotor rotating	Internal rotor speed > 0	
7	-	Reserved	
6	-	Reserved	
5	-	Reserved	
4	-	Reserved	
3	-	Reserved	
2	-	Reserved	
1	-	Reserved	
0	-	Reserved	

Table 19 CAN status word part 1

6.12 Ethernet settings

ETHERNET

Ethernet settings

Enable DHCP ☐

Host name

MAC address

IP address

Subnet mask

Gateway

Primary DNS

Secondary DNS

APPLY

Relevant adjustments for embedded measurement system in the intranet can be configured.



Important

Improper settings can break the device. In some cases, the device cannot be reconfigured! In that case, the torque control unit must be reprogrammed in the factory. Administration must be consulted before configuring to get the proper settings.

If the network settings of the TCU have been forgotten, the settings can be queried via the following CAN command:

Command		Command code	
		Hex	Dec
Request	Ethernet	0xD05	3333
settings			

Table 20 CAN command to request Ethernet settings

The response of the TCU has the structure IP address, subnet mask:

Type	IP Address				Subnet Mask			
Byte i	Byte 0	Byte 1	Byte 2	Byte 3	Byte 4	Byte 5	Byte 6	Byte 7
Content (HEX)	AC	10	56	2	FF	FF	FF	0
Result (DEC)	172	16	86	3	255	255	255	0

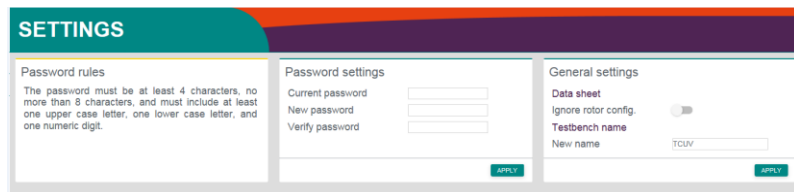
Table 21 CAN Response code of TCU

6.13 General settings

Username and password for first access:

Username: **customer**

Password: **admin**



A password and a device name for the measurement system can be adjusted.

Following password characteristics must be fulfilled:

- ▶ Total length between 4 and 8 signs
- ▶ At least one upper-case letter
- ▶ At least one lower-case letter
- ▶ At least one digit



Important

Write down your password and keep it in a safe place. Please contact the service if you cannot remember your password anymore.

Ignore rotor configuration:

Deactivates the automatic data sheet transfer and allows manual entry of parameters.

Test bench name allows defining a customized name for the TCU5.

6.14 Service information

SERVICE

Service information

Versions

Torque sensor

2.6.0

Torque control unit

2.0.0

Service contact

Phone

+49 (0)2404/9870-570

Fax

+49 (0)2404/5870-109

Email

service-PM@Atesteo.com

Web

www.atesteo.com

Parameter export

DOWNLOAD

Service login

LOGIN

The installed firmware version of the device and manufacturer's contact details can be found on the Service page.
For service purposes, it is also possible to export a list of system parameters.

7 Pin allocations

7.1 X770 Power supply / Frequency output

12-pin connector, type M23					
Pin	Signal	Description		Cable color	Cross-Section in mm
		State “Output switch” In1 = Out1 In2 = Out2 (s. 6.5.1)	State “Output switch” In1 = Out2 In2 = Out1 (s. 6.5.1)		
1	F2_out- *1	Frequency output ch. 2 – RS422	Frequency output ch. 1 – RS422	White	0.25
2	F2_out+ *1			Brown	0.25
3	N2_out+ *1	Speed pulses output track 2 – RS422		Gray	0.25
4	N2_out- *1			Pink	0.25
5	N1_out+ *1	Speed pulses output track 1 – RS422		Blue	0.25
6	N1_out- *1			Red	0.25
7	F1_out-	Frequency output ch. 1 – RS422	Frequency output ch. 2 – RS422	Yellow	0.25
8	F1_out+			Green	0.25
9	IP-reset in	Reset IP-Configuration –3.3 – 30 V (via supply voltage)		White	0.5

10	Power+	Power supply 24 - 30 V / 1 A	Green	0.5
11	Power-		Yellow	0.5
12	Digital GND	Ground connection of digital signals	Brown	0.5

Table 22 X770

*1 Optional – depending on the configuration of the system

Frequency outputs

The frequency output F1 and F2 represents torque output 1 and 2. The second channel is only used if a DF system with dual telemetry was purchased (DFx dual).

The frequency span is declared by the web interface. The maxima represent positive and negative rated torque of the respective channel. When the output switch is activated, the two frequency outputs are switched. The frequency outputs must be connected to RS422 receivers. Connecting an output to ground will damage the TCU. It is irrelevant whether it is a positive or a negative output signal. RS422 signals have a signal level of around 3.7 V. It is not recommended to misuse the signal as TTL signal without a required converter.

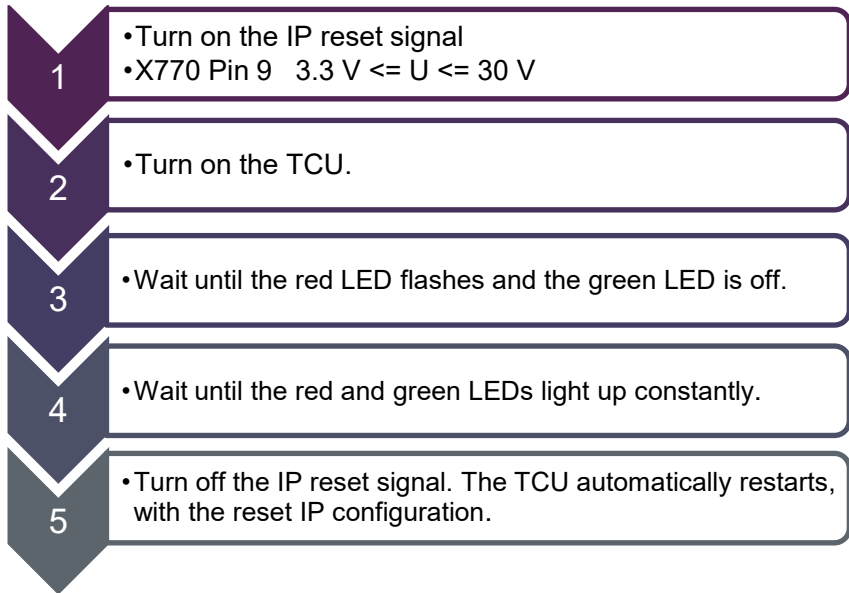
Using a dual variant torque meter with single channel is explained in 3.9.2.

Speed-pulses output

The speed-pulses-outputs N1 and N2 represent every single pulse of speed track 1 and 2. The number of pulses per round is dependent on the number of increments parameter of the speed ring. The increments numbers of both tracks are identical, and phase shifted by 90°. The speed-pulses output must be connected to RS422 receivers. Connecting an output to the ground will damage the TCU. It is irrelevant whether it is a positive or a negative output signal.

IP-reset_in

The IP reset signal resets the IP configuration of the Ethernet interface to the factory setting (see product label). For security reasons, the following procedure must be used for recovery:



Power supply

Connect the positive and negative power pins with an external power supply. The power supply must have a supply voltage between 24 and 30 Volt and must be able to supply 1 A constant current.

7.2 X771 Analogue / CAN / Alarm / Input

16-pin connector, type M23				
Pin	Signal	Description	Cable color (cable optional)	Cross-Section in mm
1	Test_in	Activates controller test signal	White	0.25
2	Zero_in	Zero balance input – 3.3 – 30 V (via supply voltage)	Brown	0.25
3	Digital GND	Ground connection of digital signals and CAN bus	Green	0.25
4	Digital GND		Yellow	0.25
5	CAN_H	CAN HIGH connection	Grey	0.25
6	CAN_L	CAN LOW connection	Pink	0.25
7	An4_out *1	Galvanic isolated analog voltage output	Blue	0.25
8	An2_out *1	Galvanic isolated analog voltage output	Red	0.25
9	An3_out *1	Galvanic isolated analog voltage output	Black	0.25

16-pin connector, type M23				
10	An1_out *1	Galvanic isolated analog voltage output	Purple	0.25
11	Alarm-MD_out	Alarm torque limit – open-collector	Grey/Pink	0.25
12	Analog GND	Ground connection of analog signals	Red/Blue	0.25
13	Alarm-N_out	Alarm speed limit – open-collector	White/Green	0.25
14	Output-switch_out / Err-state_out	State of output-switch – open-collector / State of system-errors – open-collector. Depending on software version	Brown/Green	0.25
15	Alarm-reset_in	Reset all alarms – 3.3 – 30 V (via supply voltage)	White/Yellow	0.25
16	Channel_select	See below	Yellow/Brown	0.25

Table 23 X771

Connect “Digital GND” in any case to avoid disturbances on the CAN bus!

*1 Optional – depending on the configuration of the system

Test_in

The test_in signal activates the controller test signal as soon as the circuit is closed for at least one second until the signal is switched off again. The test signal produces a positive full-scale at all outputs for measured values. A voltage level 3.3 – 30 V (via supply voltage) between test_in pin and digital GND is applied for the control. The signal is active high. Function description see 3.10.2.

Zero_in

The zero_in signal activates the zeroing as soon as the circuit is closed for at least one second. The zeroing is executed only once after triggering. The zeroing sets the instantaneous values of the torque inputs as a new zero points. A voltage level 3.3 – 30 V (via supply voltage) between zero_in pin and digital GND is applied for the control. The signal is active high. Function description see 3.10.1.

CAN

The CAN interface allows the customer to receive the measured data in digital form and simultaneously sends control signals to the TCU. The CAN_High and CAN_Low pins must be connected with a 120 Ohm terminated CAN-Bus.

Analog_out

The analog outputs 1 and 2 represents torque output 1 and 2. The analog output 3 represents speed output. The analog output 4 represents the rotation angle (for systems with magnetic speed detection). The voltage span and channel configuration are declared by the web interface (see 6.5 & 6.7). The maxima represent positive and negative rated values of the respective channel. The rotation angle in unipolar calculation mode will only use positive voltages.

The analog outputs 1-4 are single ended galvanic isolated voltage outputs with separately analog GND.

Using a dual torque meter with single channel is explained in 3.9.2.

Alarm-MD_out

The alarm-MD output indicates that the torque threshold is exceeded. The threshold value is set in the Web Interface. The alarm remains

active until the Alarm_Reset signal is triggered. The alarm output consists of an open collector circuit. In the active state, it connects the Alarm-MD_out pin with digital GND directly.

Alarm-N_out

The alarm-N output indicates that the speed threshold is exceeded. The threshold value is set in the Web Interface. The alarm remains active until the Alarm_Reset signal is triggered. The alarm output consists of an open collector circuit. In the active state, it connects the Alarm-N_out pin with digital GND directly.

Output-switch_out / Err-state_out / Channel_state_out

The function of this pin depends on the TCU firmware version. All are open-collectors.

Output_switch_out:

The output-switch output indicates the state of the output-switch. On active state the output-switch is active.

Err_state_out:

The error state output indicates whether the system is disturbed. On active state the system works without faults and full transmission.

Channel_state_out:

Active channel

Firmware less than V1.6.10:

Output-switch_out

Firmware equal to V1.6.10 or less than V2.2.0:

Err-state_out

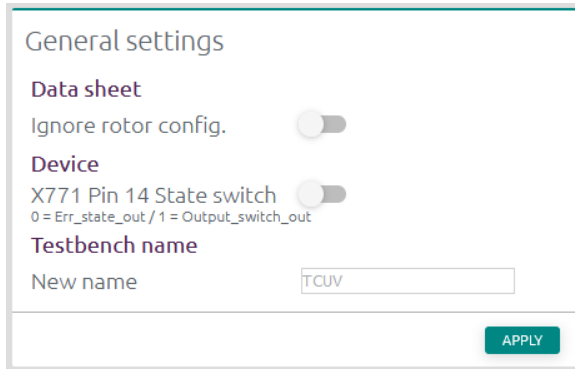
Firmware equal or greater than V2.2.0:

Function of the pin can be defined in the web interface under "Settings".

With dual variant torque meter and a single active channel:

Err_state_out or Channel_state_out

With dual variant torque meter and two active channels:
Err_state_out or _Output_switch_out



General settings

Data sheet

Ignore rotor config. ☐

Device

X771 Pin 14 State switch ☐

0 = Err_state_out / 1 = Output_switch_out

Testbench name

New name

APPLY

Figure 34 Function selection for X771.Pin14 (dual with 2 active channels)

The signal output consists of an open collector circuit. In the active state, it connects the output pin with digital GND directly.

Alarm-reset_in

The alarm-reset signal resets all alarm-signals as soon as the circuit is closed for at least one second. The reset is executed only once after triggering. A voltage level 3.3 – 30 V (via supply voltage) between alarm-reset_in pin and digital GND must be applied for the control. The signal is active high.

Channel_select

The “Channel_select” signal defines the selection of the active channel for dual variant torque meter.

Not connected (0 V):	2. Channel
Connected (3.3 – 30 V):	1. Channel

TCU5 will check the state of “Channel_state” during start up and it will arrange the channel selection accordingly.

7.3 X772 Ethernet

Can be connected with a standard Kat 5e cable for diagnostics or setup.

For permanent installation inside the test bench use the special connector.

Hummel - 7R10400000

7.4 X775 / X776 Central cable

12-pin connector, Type M16 Not for outdoor usage				
Pin	Signal	Description	Cable color	Cross-Section in mm ² / Type
A	Power-	Supply voltage	Black	0.25 / straight
B	7V- Power+	Supply voltage	Purple	0.25 / straight
C	Data-in+	Digital rotor data – RS422	Yellow	0.14 / twisted
D	N0+	Speed-pulses – zero position	Grey	0.14 / twisted
E	N0-	Speed-pulses – zero position	Pink	0.14 / twisted
F	7V- Power-	Supply voltage	Grey/Pink	0.25 / straight
G	Power+	Supply voltage	Red/Blue	0.25 / straight
H	N1-	Speed-pulses – track 1	Red	0.14 / twisted

J	N2+	Speed-pulses – track 2	White	0.14 / twisted
K	N2-	Speed-pulses – track 2	Brown	0.14 / twisted
L	Data-in-	Digital rotor data – RS422	Green	0.14 / twisted
M	N1+	Speed-pulses – track 1	Blue	0.14 / twisted

Table 24 X775/X776

The following applies to double telemetry systems:

Channel 1 corresponds to the measuring channel with the **lower rated torque**.

Channel 2 corresponds to the measuring channel with the **higher rated torque**.

8 Appendix

8.1 Recommendations for zero adjustment

Each measuring element, containing flexible spring elements, which is measured by its elastic deformation, will always generate a zero drift even if no load is applied.

Related to strain gauge based torque measuring systems, zero-drifts in a load-free condition can be caused by the following circumstances:

8.1.1 Thermal influences

Despite of a complex temperature compensation a zero-drift related to high temperature fluctuations can always be observed. Due to various temperature influences interacting permanently with the torque meter, another reason for exiguous zero-drifts is given.

The temperature stability defined in the technical specifications (e.g. 0.05%/10K) is determined by the allowed temperature drift of $\pm 0.05\%$ of the rated torque per 10 Kelvin difference. The temperature difference it related to the difference from the current flange temperature and the flange temperature of the last zero adjustment.

8.1.2 Influences of hysteresis

If a sensor during a test is mostly loaded in one direction, it can indicate a drift after the test is finished. This drift cannot to be traced back to a temperature compensation problem but to the natural hysteresis of the sensor and strain gauges.

The change of the zero value depends on the torque applied or on the test duration. In any case, the value of the zero-drift variation will not

be larger than the linearity and hysteresis specified in the technical data for the sensor.

8.1.3 Aging

If a strain gauge based sensor is dynamically loaded for a long period of time a zero-drift can occur. This value depends on the cycle count and the strain amplitude. This zero-drift will affect the sensitivity of the sensor.

Even though this is a natural effect for strain gauge sensors, ATESTEO torque sensors drift is very low due to a low sensitivity at nominal torque.

8.1.4 Influence of lateral forces

Considering that each torque sensor is part of a powertrain, every component linked to the sensor generates a lateral force. This load will be influenced by the size and installation of the components. This lateral force will be added to the measuring signal. If the installation is performed as specified in the technical specifications, this influence will be extremely small.

8.1.5 General

All the above mentioned items that influence the zero-drift are still in the range of calibration tolerance, as long as the sensor is properly maintained and handled and no transportation damages occurred to the sensor or strain gauges.

Due to the fact that all the above mentioned zero-drifts can happen in different situations at the same time it is very difficult to suggest a general zero-reset procedure.

After considering all the information acquired through our experience and customers feedback we can suggest and comment different scenarios for a proper zero-reset of the torque sensor.

- A zero-reset is only allowed if the torque (real load) is zero.
- If a great zero shift (>10 Hz) is observed during the mounting of the torque meter please check the adapter flange due to the mechanical properties. A lower zero-shift can be reset.
- The test bench engineer has to decide, whether the accuracy request of the actual test requires a reset of the zero point. Generally it is possible to improve the accuracy by resetting the zero torque after the warming-up period of the test stand and before starting the measurement.
- If the zero shift is greater than 2% of the rated torque, the torque meter must be checked. These tests (recalibration and other tests) have to be done by ATESTEO to find out the reason for the malfunction.

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