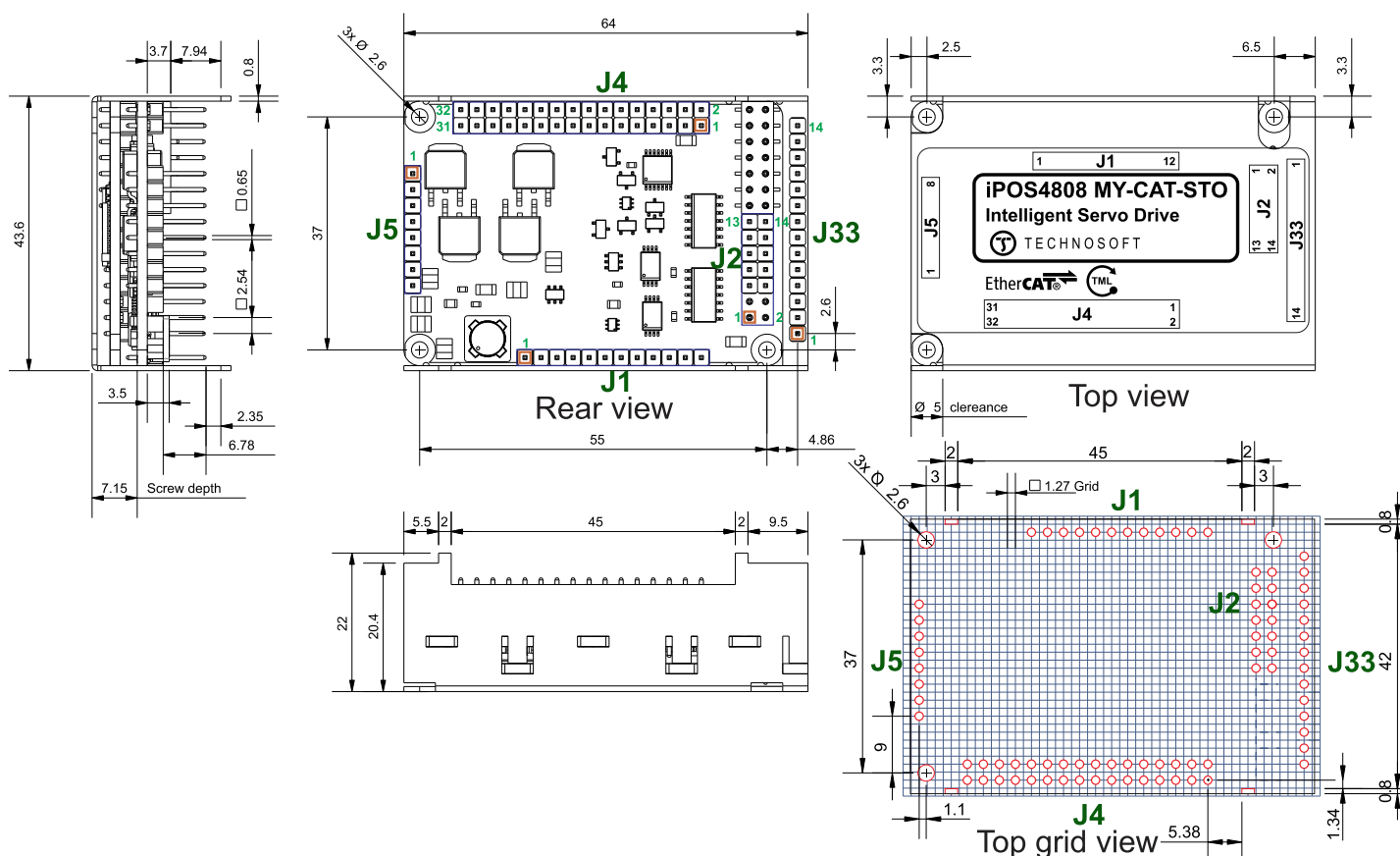




Rear view; Pins facing upwards; All dimensions are in mm; Header pitch is 2.54 mm. Drawing not to scale.

Motor – sensor configurations

Sensor \ Motor	PMSM	BLDC	DC BRUSH	STEP (2-ph)	STEP (3-ph)
Incr. Encoder	✓		✓	✓	
Incr. Encoder + Hall	✓	✓			
Analog Sin/Cos encoder	✓	✓	✓	✓	
SSI	✓	✓	✓	✓	
BiSS-C	✓	✓	✓	✓	
Linear Halls	✓				
Tacho			✓		
Open-loop (no sensor)				✓	✓

Features

- Motion controller and drive in a single compact unit based on MotionChip™ technology
- Universal solution for control of rotary and linear brushless, brushed and 2 or 3-phase step motors
- Advanced motion control capabilities (PVT, S-curve, electronic cam)
- Motor supply: 11-50V; Logic SELV/ PELV supply: 9-36V; STO SELV/ PELV supply: 18-40V
- Output current: 8A cont. (BLDC mode); 20A_{PEAK}, up to 100kHz PWM
- Feedback Devices (dual-loop support)
 - 1st feedback devices supported:
 - Incremental encoder interface (single ended or differential)
 - Analogue sin/cos encoder interface (differential 1V_{pp})
 - Digital Hall sensor interface (single-ended and open collector)

Linear Hall sensors interface

- pulse & direction interface (single ended) for external (master) digital reference

2nd feedback devices supported:

- Incremental encoder interface (differential)
- pulse & direction interface (differential) for external (master) digital reference

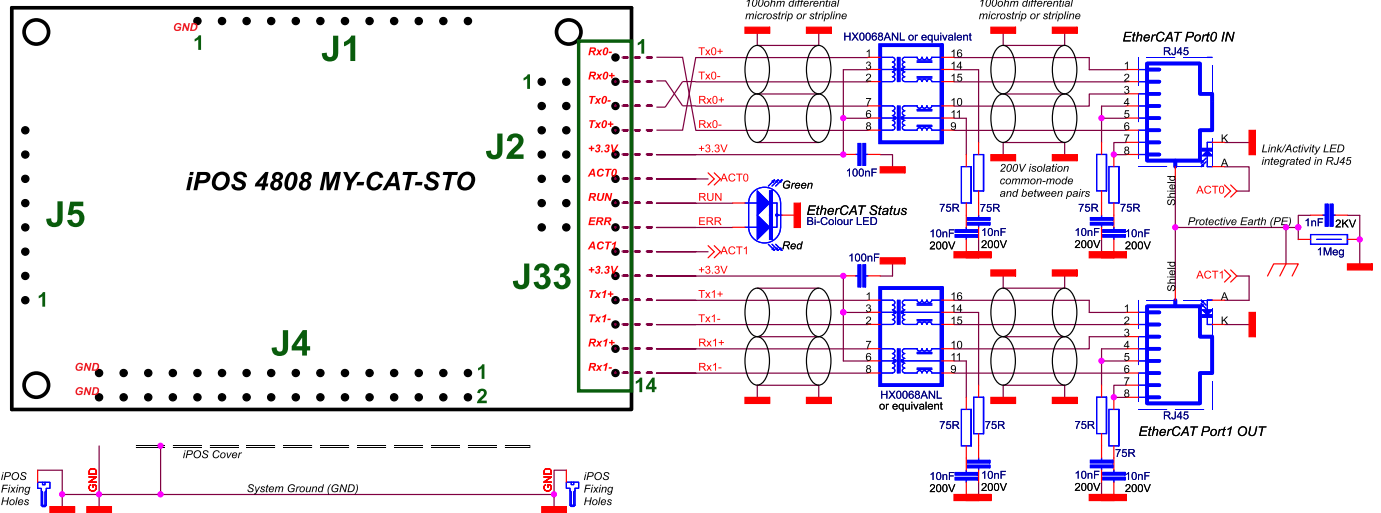
BISS / SSI encoder interface

- STO: 2 safe torque-off inputs, safety integrity level (SIL3/Cat3/PLe) acc. to EN61800-5-1;-2/ EN61508-3;-4/ EN ISO 13849-1.
- 6 digital inputs, 5-36V, PNP/NPN programmable: 2 for limit switches, 4 general-purpose
- 5 digital outputs, 5-36V, 0.5A, NPN open-collector: Ready, Error, 3 general-purpose
- 2 analogue inputs: 12-bit, 0-5V: Reference, Feedback or general purpose
- RS-232 serial & dual 100Mbps EtherCAT® interfaces
- 127 h/w addresses selectable by h/w pins configuration
- 16k x 16 SRAM memory for data acquisition
- 16k x 16 E²ROM to store setup data, TML motion programs, cam tables and other user data
- Operating ambient temperature: 0-40°C (over 40°C with derating)
- NTC/PTC analogue Motor Temperature sensor input

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Recommended: PoE (Power Over Ethernet) compliant

Mating Connectors			
Ref	Producer	Part No.	Description
J1	Samtec	SSQ-112-01-G-S	1x12 contacts, socket 2.54mm-pitch accepting 0.635mm square pin
J2	FCI	87606-307LF	2x7 contacts, socket, 2.54mm-pitch accepting 0.635mm square pin
	TE Connectivity	534206-7	
J33	Samtec	SSQ-114-01-G-S	1x14 contacts, socket 2.54mm-pitch accepting 0.635mm square pin
J4	Samtec	SSQ-116-01-G-D	2x12 contacts, socket 2.54mm-pitch accepting 0.635mm square pin
J5	Samtec	SSQ-108-01-G-S	1x8 contacts, High-current socket 2.54mm-pitch accepting 0.635mm square pin

Pin	Name	Type	Description
1	GND	-	Return ground for all signals. Internally connected to J4 pins 31 and 32, to metallic cover, and to the 3 fixing screws
2	reserved	-	Reserved
3	Axis ID Bit6	I	8 bit H/W Axis ID register. Connect pin to GND to set bit to 1. Up to 127 H/W axis ID combinations.
4	Axis ID Bit5	I	
5	Axis ID Bit4	I	
6	Axis ID Bit3	I	
7	Axis ID Bit2	I	
8	Axis ID Bit1	I	Reserved for interface extensions*
9	Axis ID Bit0	I	
10	reserved	-	
11	reserved	-	
12	reserved	-	

Pin	Name	Type	Description
1,2	A/A+	O	Phase A for 3-ph motors, A+ for 2-ph steppers, Motor+ for DC brush motors
3,4	B/A-	O	Phase B for 3-ph motors, A- for 2-ph steppers, Motor- for DC brush motors
5,6	C/B+	O	Phase C for 3-ph motors, B+ for 2-ph steppers
7,8	Br/B-	O	Brake resistor / Phase B- for 2-ph steppers

Pin	Name	Type	Description
1	RX1-	I/O	Receive/Transmit negative, OUT port. Connect to magnetics PHY RX1.
2	RX1+	I/O	Receive/Transmit positive, OUT port. Connect to magnetics PHY RX1.
3	TX1-	I/O	Transmit/Receive negative, OUT port. Connect to magnetics PHY TX1.
4	TX1+	I/O	Transmit/Receive positive, OUT port. Connect to magnetics PHY TX1.
5	3.3V	O	Return for center tap of magnetics PHY TX1 and RX1. Internally connected to J33 pin 10.
6	ACT1	O	Anode of Link/Activity LED for port OUT.
7	RUN	O	Anode of Run LED (EtherCAT status machine).
8	ERR	O	Anode of Error LED (EtherCAT status machine).
9	ACT0	O	Anode of Link/Activity LED for port IN.
10	3.3V	O	Return for center tap of magnetics PHY TX0 and RX0. Internally connected to J33 pin 5.
11	TX0+	I/O	Transmit/Receive positive, IN port. Connect to magnetics PHY TX0.
12	TX0-	I/O	Transmit/Receive negative, IN port. Connect to magnetics PHY TX0.
13	RX0+	I/O	Receive/Transmit positive, IN port. Connect to magnetics PHY RX0.
14	RX0-	I/O	Receive/Transmit negative, IN port. Connect to magnetics PHY RX0.

Pin	Name	Type	Description
1	STO1+	I	Safe Torque Off input 1, positive input (opto-isolated, 18÷40V)
2	STO2+	I	Safe Torque Off input 2, positive input (opto-isolated, 18÷40V)
3	STO1-	I	Safe Torque Off input 1, negative return (opto-isolated, 0V)
4	STO2-	I	Safe Torque Off input 2, negative return (opto-isolated, 0V)
5	LH1	I	Linear Hall 1 input
6	LH2	I	Linear Hall 2 input
7	IN4	I	5-36V general-purpose digital PNP/NPN input
8	IN5	I	5-36V general-purpose digital PNP/NPN input
9	OUT0	O	5-36V 0.5A, general-purpose digital output, NPN open-collector/TTL pull-up
10	OUT3/Ready	O	5-36V 0.5A, drive Ready output, active low, NPN open-collector/TTL pull-up. Also drives the green LED.
11	OUT1	O	5-36V 0.5A, general-purpose digital output, NPN open-collector/TTL pull-up
12	OUT2/Error	O	5-36V 0.5A, drive Error output, active low, NPN open-collector/TTL pull-up. Also drives the red LED
13	REF	I	Analogue input, 12-bit, 0-5V. Reads analog reference, or general purpose analogue input
14	FDBK / LH3	I	Analogue input, 12-bit, 0-5V. Reads an analogue feedback (tacho), or general purpose/ or Linear Hall 3

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Pin	Name	Type	Description
1	IN0	I	5-36V general-purpose digital PNP/NPN input
2	IN1	I	5-36V general-purpose digital PNP/NPN input
3	IN2/LSP	I	5-36V digital PNP/NPN input. Positive limit switch input
4	IN3/LSN	I	5-36V digital PNP/NPN input. Negative limit switch input
5	B2-/Dir-/CLK-/MA-	I/O	Incr. encoder2 B- diff. input, or Dir-, or Clock- for SSI, or Master- for BiSS; has 150Ω resistor between pins 5 and 7
6	B1-/Cos-	I	Incr. encoder1 B- diff. input, or analogue encoder Cos- diff. input
7	B2+/Dir+/CLK+/MA+	I/O	Incr. encoder2 B+ diff. input, or Dir+, or Clock+ for SSI, or Master+ for BiSS; has 150Ω resistor between pins 5 and 7
8	B1+/Cos+	I	Incr. encoder1 B single-ended, or B+ diff. input, or analogue encoder Cos+ diff. input
9	A2+/Pulse+/Data+/SL+	I	Incr. encoder2 A+ diff. input, or Pulse+, or Data+ for SSI, or Slave+ for BiSS; has 150Ω resistor between pins 9 and 11
10	A1+/Sin+	I	Incr. encoder1 A single-ended, or A+ diff. input, or analogue encoder Sin+ diff. input
11	A2-/Pulse-/Data-/SL-	I	Incr. encoder2 A- diff. input, or Pulse-, or Data- for SSI, or Slave- for BiSS; has 150Ω resistor between pins 9 and 11
12	A1-/Sin-	I	Incr. encoder1 A- diff. input, or analogue encoder Sin- diff. input
13	Z2+	I	Incr. encoder2 Z+ diff. input; has 150Ω resistor between pins 13 and 15
14	Z1+	I	Incr. encoder1 Z single-ended, or Z+ diff. input,
15	Z2-	I	Incr. encoder2 Z- diff. input; has 150Ω resistor between pins 13 and 15
16	Z1-	I	Incr. encoder1 Z- diff. input
17	Hall 1	I	Digital input Hall 1 sensor
18	Reserved	-	Reserved. Do not connect.
19	Hall 2	I	Digital input Hall 2 sensor
20	Reserved	-	Reserved. Do not connect.
21	Hall 3	I	Digital input Hall 3 sensor
22	232TX	O	RS-232 Data Transmission
23	+5V _{OUT}	O	5V output supply for I/O usage
24	232RX	I	RS-232 Data Reception
25	Temp Mot	I	NTC/PTC input. Used to read an analog temperature value
26	Reserved	-	Reserved. Do not connect.
27	+V _{LOG}	I	Positive terminal of the logic supply input: 9 to 36V _{DC} from SELV/ PELV type power supply.
28	OUT4	O	5-36V 0.5A, general-purpose digital output, NPN open-collector/TTL pull-up
29	+V _{MOT}	I	Positive terminal of the motor supply: 11 to 48V _{DC} .
30	+V _{MOT}	I	Positive terminal of the motor supply: 11 to 48V _{DC} .
31	GND	-	Return ground for all signals. Internally connected to J4 pin 32, to J1 pin 1, to metallic cover, and to the 3 fixing screws
32	GND	-	

† leave unconnected if interface extensions are not used

Electrical characteristics

All parameters measured under the following conditions (unless otherwise specified):

- V_{LOG} = 24 VDC; V_{MOT} = 48VDC
- Supplies start-up / shutdown sequence: -any-
- Load current (sinusoidal amplitude / continuous BLDC, DC, stepper) = 8A

Operating Conditions	Min.	Typ.	Max.	Units
Ambient temperature	0		40 ¹	°C
Ambient humidity	0		90	%Rh
Altitude / pressure ²	Altitude (vs. sea level)	-0.1	0 ÷ 2.5	² Km

¹Operating temperature at higher temperatures is possible with reduced current and power ratings

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	Ambient Pressure	0 ²	0.75 ÷ 1	10.0	atm
Storage Conditions		Min.	Typ.	Max.	Units
Ambient temperature		-40		100	°C
Ambient humidity	Non-condensing	0		100	%Rh
Ambient Pressure		0		10.0	atm
ESD capability (Human body model)	Not powered; applies to any accessible part			±0.5	kV
	Original packaging			±15	kV
Mechanical Mounting		Min.	Typ.	Max.	Units
Airflow		natural convection ³ , closed box			
Spacing required for vertical mounting	Between adjacent drives	30			mm
	Between drives and nearby walls	30			mm
	Between drives and roof-top	20			mm
Spacing required for horizontal mounting	Between adjacent drives	4			mm
	Between drives and nearby walls	5			mm
	Space needed for drive removal	10			mm
	Between drives and roof-top	15			mm
Insertion force	Using recommended mating		TBD	TBD	N
Extraction force	connectors	TBD	TBD		N
Environmental Characteristics		Min.	Typ.	Max.	Units
Size (Length x Width x Height)	Global size	64 x 43.6 x 22			mm
		~2.52 x 1.72 x 0.87			inch
Weight		45			g
Cleaning agents	Dry cleaning is recommended	Only Water- or Alcohol- based			
Protection degree	According to IEC60529, UL508	IP20			-
Logic Supply Input (+V_{LOG})		Min.	Typ.	Max.	Units
Supply voltage	Nominal values	9		36	V _{DC}
	Absolute maximum values, drive operating but outside guaranteed parameters	8		40	V _{DC}
	Absolute maximum values, continuous	-0.6		42	V _{DC}
	Absolute maximum values, surge (duration ≤ 10ms) [†]	-1		+45	V
Supply current	+V _{LOG} = 12V		130		mA
	+V _{LOG} = 24V		90	280	
	+V _{LOG} = 40V		85		
Motor Supply Input (+V_{MOT})		Min.	Typ.	Max.	Units
Supply voltage	Nominal values	11		50	V _{DC}
	Absolute maximum values, drive operating but outside guaranteed parameters	9		52	V _{DC}
	Absolute maximum values, continuous	-0.6		54	V _{DC}
	Absolute maximum values, surge (duration ≤ 10ms) [†]	-1		57	V
Supply current	Idle		1	5	mA
	Operating	-20	±8	+20	
	Absolute maximum value, short-circuit condition (duration ≤ 10ms) [†]			26	
Supply Output (+5V)		Min.	Typ.	Max.	Units
Output voltage	Current sourced = 250mA	4.8	5	5.2	V
Output current		200	250		mA
Short-circuit		NOT protected			
Over-voltage		NOT protected			
ESD protection	Human body model	±1			kV

² iPOS4808 can be operated in vacuum (no altitude restriction), but at altitudes over 2,500m, current and power rating are reduced due to thermal dissipation efficiency.

³ In case of forced cooling (conduction or ventilation) the spacing requirements may drop substantially down to zero as long as the ambient temperature is kept below the maximum operating limit

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Motor Outputs (A/A+, B/A-, C/B+, BR/B-)			Min.	Typ.	Max.	Units
Nominal output current, continuous ¹	for DC brushed, steppers and BLDC motors with Hall-based trapezoidal control				8	A
	for PMSM motors with FOC sinusoidal control (sinusoidal amplitude value)				8	
	for PMSM motors with FOC sinusoidal control (sinusoidal effective value)				5.66	
Motor output current, peak	maximum 2.5s		-20		+20	A
Short-circuit protection threshold			±22	±26	±30	A
Short-circuit protection delay			5	10		µs
On-state voltage drop	Nominal output current; including typical mating connector contact resistance			±0.3	±0.5	V
Off-state leakage current				±0.5	±1	mA
Motor inductance (phase-to-phase)	Recommended value, for current ripple max. ±5% of full range; +V _{MOT} = 36 V	F _{PWM}				µH
		20 kHz	330			
		40 kHz	150			
		60 kHz	120			
		80 kHz	80			
		100 kHz	60			
	Minimum value, limited by short-circuit protection; +V _{MOT} = 36 V	20 kHz	120			µH
		40 kHz	40			
		60 kHz	30			
		80 kHz	15			
100 kHz		8				
Motor electrical time-constant (L/R)	Recommended value for ±5% current measurement error	20 kHz	250			µs
		40 kHz	125			
		60 kHz	100			
		80 kHz	63			
		100 kHz	50			
Current measurement	FS = Full Scale accuracy			±4	±8	%FS
Digital Inputs (IN0, IN1, IN2/LSP, IN3/LSN, IN4, IN5) ²			Min.	Typ.	Max.	Units
Mode compliance			PNP			
Default state	Input floating (wiring disconnected)		Logic LOW			
Input voltage	Logic "LOW"		-10	0	2.2	V
	Logic "HIGH"		6.3		36	
	Floating voltage (not connected)			0		
	Absolute maximum, continuous		-10		+39	
	Absolute maximum, surge (duration ≤ 1s) [†]		-20		+40	
Input current	Logic "LOW"; pulled to GND			0		mA
	Logic "HIGH"			1.3	2	
Mode compliance			NPN			
Default state	Input floating (wiring disconnected)		Logic HIGH			
Input voltage	Logic "LOW"		-10		2.2	V
	Logic "HIGH"		6.3		36	
	Floating voltage (not connected)			3		
	Absolute maximum, continuous		-10		+36	
	Absolute maximum, surge (duration ≤ 1s) [†]		-20		+40	
Input current	Logic "LOW"; Pulled to GND		-1.6	0.6	1	mA
	Logic "HIGH"; Pulled to +24V				0.3	
Input frequency			0		150	kHz
Minimum pulse			3.3			µs
ESD protection	Human body model		±2			kV

Digital Outputs (OUT0, OUT1, OUT2/Error, OUT3/ Ready, OUT4)		Min.	Typ.	Max.	Units
Mode compliance	All outputs (OUT0, OUT1, OUT2/Error, OUT3/Ready)	NPN 24V			
Default state	Not supplied (+V _{LOG} floating or to GND)	High-Z (floating)			
	Immediately after power-up	OUT0, OUT1, OUT4	Logic "HIGH"		
		OUT2/Error, OUT3/ Ready	Logic "LOW"		
	Normal operation	OUT0, OUT1, OUT2/Error	Logic "HIGH"		
Output voltage	Logic "LOW"; output current = 0.5A			0.8	V
	Logic "HIGH"; output current = 0, no load	OUT2/Error, OUT3/ Ready	2.9	3	
		OUT0, OUT1, OUT4	4	4.5	
	Logic "HIGH", external load to +V _{LOG}		V _{LOG}		
	Absolute maximum, continuous	-0.5		V _{LOG} +0.5	
	Absolute maximum, surge (duration ≤ 1s) [†]	-1		V _{LOG} +1	
Output current	Logic "LOW", sink current			0.5	A
	Logic "LOW", sink current, pulse ≤ 5 sec.			1	A
	Logic "HIGH", source current; external load to GND; V _{OUT} ≥ 2.0V	OUT2/Error, OUT3/ Ready		2	mA
		OUT0, OUT1, OUT4		4	mA
	Logic "HIGH", leakage current; external load to +V _{LOG} ; V _{OUT} = V _{LOG} max = 40V		0.1	0.2	mA
	Minimum pulse width		2		µs
ESD protection	Human body model	±15			kV
Digital Hall Inputs (Hall1, Hall2, Hall3)		Min.	Typ.	Max.	Units
Mode compliance		TTL / CMOS / Open-collector			
Default state	Input floating (wiring disconnected)	Logic HIGH			
Input voltage	Logic "LOW"		0	0.8	V
	Logic "HIGH"	2	5		
	Floating voltage (not connected)		4.4		
	Absolute maximum, surge (duration ≤ 1s) [†]	-10		+15	
	Logic "LOW"; Pull to GND			1.2	
Input current	Logic "HIGH"; Internal 4.7KΩ pull-up to +5	0	0	0	mA
	Minimum pulse width	2			µs
ESD protection	Human body model	±5			kV
Linear Hall Inputs (LH1, LH2, LH3)		Min.	Typ.	Max.	Units
Input voltage	Operational range	0	0.5÷4.5	4.9	V
Input voltage	Absolute maximum values, continuous	-7		+7	V
	Absolute maximum, surge (duration ≤ 1s) [†]	-11		+14	
Input current	Input voltage 0...+5V	0		0.2	mA
Interpolation Resolution	Depending on software settings			11	bits
Frequency		0		1	kHz
ESD protection	Human body model	±1			kV

¹ @20kHz F_{PWM}

² The digital inputs are software selectable as PNP or NPN

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Encoder1 Inputs (A1/A1+, A1-, B1/B1+, B1-, Z1/Z1+, Z1-)		Min.	Typ.	Max.	Units
Single-ended mode compliance	Leave negative inputs disconnected	TTL / CMOS / Open-collector			
Input voltage, single-ended mode A/A+, B/B+	Logic "LOW"			1.6	V
	Logic "HIGH"	1.8			
	Floating voltage (not connected)		3.3		
Input voltage, single-ended mode Z/Z+	Logic "LOW"			1.2	V
	Logic "HIGH"	1.4			
	Floating voltage (not connected)		4.7		
Input current, single-ended mode A/A+, B/B+, Z/Z+	Logic "LOW"; Pull to GND		5.5	6	mA
	Logic "HIGH"; Internal 2.2KΩ pull-up to +5	0	0	0	
Differential mode compliance	For full RS422 compliance, see ¹	TIA/EIA-422-A			
Input voltage, differential mode	Hysteresis	±0.06	±0.1	±0.2	V
	Common-mode range (A+ to GND, etc.)	-7		+7	
Input impedance, differential	A1+ to A1-, B1+ to B1-		1		kΩ
	Z1+ to Z1-		1		
Input frequency	Single-ended mode, Open-collector / NPN	0		5	MHz
	Differential mode, or Single-ended driven by push-pull (TTL / CMOS)	0		10	MHz
Minimum pulse width	Single-ended mode, Open-collector / NPN	1			μs
	Differential mode, or Single-ended driven by push-pull (TTL / CMOS)	50			ns
Input voltage, any pin to GND	Absolute maximum values, continuous	-7		+7	V
	Absolute maximum, surge (duration ≤ 1s) [†]	-11		+14	
ESD protection	Human body model	±1			kV
Encoder2 Inputs (A2+/Data+, A2-/Data-, B2+/Clk+, B2-/Clk-, Z2+, Z2-) ²		Min.	Typ.	Max.	Units
Differential mode compliance	For full RS422 compliance, see ¹	TIA/EIA-422-A			
Input voltage	Hysteresis	±0.06	±0.1	±0.2	V
	Differential mode	-14		+14	
	Common-mode range (A+ to GND, etc.)	-11		+14	
Input impedance, differential	A2+, B2+, Z2+ A2-, B2-, Z2-		150		Ω
Input frequency	Differential mode	0		10	MHz
Minimum pulse width	Differential mode	50			ns
Sin-Cos Encoder Inputs (Sin+, Sin-, Cos+, Cos-)		Min.	Typ.	Max.	Units
Input voltage, differential	Sin+ to Sin-, Cos+ to Cos-		1	1.25	V _{PP}
Input voltage, any pin to GND	Operational range	-1	2.5	4	V
	Absolute maximum values, continuous	-7		+7	
	Absolute maximum, surge (duration ≤ 1s) [†]	-11		+14	
Input impedance	Differential, Sin+ to Sin-, Cos+ to Cos- ³	4.2	4.7		kΩ
	Common-mode, to GND		2.2		kΩ
Resolution with interpolation	Software selectable, for one sine/cosine period	2		10	bits
Frequency	Sin-Cos interpolation	0		450	kHz
	Quadrature, no interpolation	0		10	MHz
ESD protection	Human body model	±1			kV

Analog 0...5V Inputs (REF, FDBK)		Min.	Typ.	Max.	Units
Input voltage	Operational range	0		5	V
	Absolute maximum values, continuous	-12		+18	
	Absolute maximum, surge (duration ≤ 1 s) [†]			± 36	
Input impedance	To GND		28		k Ω
Resolution			12		bits
Integral linearity				± 2	bits
Offset error			± 2	± 10	bits
Gain error			$\pm 1\%$	$\pm 3\%$	% FS ⁴
Bandwidth (-3Db)	Software selectable	0		1	kHz
ESD protection	Human body model	± 5			kV
RS-232		Min.	Typ.	Max.	Units
Compliance		TIA/EIA-232-C			
Bit rate	Software selectable	9600		115200	Baud
Short-circuit	232TX short to GND		Guaranteed		
ESD protection	Human body model	± 2			kV
Safe torque OFF (STO1+, STO1-, STO2+, STO2-) ⁴		Min.	Typ.	Max.	Units
Safety function	According to EN61800-5-2	STO (Safe Torque OFF)			
EN 61800-5-1/-2 and EN 61508-5-3/-4 Classification	Safety Integrity Level	safety integrity level 3 (SIL3)			
	PFHD (probability of dangerous failures per hour)	tbd			hour ⁻¹
EN13849-1 Classification	Performance Level	Cat3/PLe			
	MTTFM (meantime to dangerous failure)	tbd			years
Mode compliance		PNP			
Default state	Input floating (wiring disconnected)	Logic LOW			
Input voltage	Logic "LOW"	-20		2.2	V
	Logic "HIGH"	18		36	
	Absolute maximum, continuous	-20		+40	
Input current	Logic "LOW"; pulled to GND		0		mA
	Logic "HIGH", pulled to +Vlog		9	13	
Pulse duration	Ignored low-high-low			1	ms
	Ignored high-low-high			1.5	
	Accepted pulse	tbd			
Fault reaction time	From internal fault detection to register DER bit 14 =1 and OUT2/Error high-to-low			tbd	ms
ESD protection	Human body model	± 2			kV
Ethernet Ports		Min.	Typ.	Max.	Units
Standard Compliance		EtherCAT (IEC61158-3/4/5/6-12)			
		Fast Ethernet 100BASE-TX (IEEE802.3u)			
		Auto-negotiation for 100Mbps/s full-duplex			
		Auto-detect MDI/MDI-X			
Power over Ethernet	NOT used by the iPOS4808MY, requires separate +Vlog SELV/ PELV supply	compliant to IEEE802.3af mode A "Mixed DC & Data"			
		NOT compliant to IEEE802.3af mode B "DC on Spares"			
Isolation GND0, GND1	Requirement for motherboard PCB routing	500			V _{rms}
		1.5			kV _{peak}
Maximum cable length	2-pair UTP Cat5	100	150		m
ESD protection	Human body model	± 4			kV
LED signals		Min.	Typ.	Max.	Units
LED connection		Common anode to 3.3V output			
		Direct, no series resistor			
LED current			8	10	mA
3.3 output voltage		3.15	3.3	3.45	V
3.3 output current				60	mA

[†] Stresses beyond values listed under "absolute maximum ratings" may cause permanent damage to the device. Exposure to absolute-maximum-rated conditions for extended periods may affect device reliability.

¹ For full RS-422 compliance, 150 Ω termination resistors must be connected across the differential pairs, as close as possible to the drive input pins.

² Encoder2 differential input pins have internal 150 Ω termination resistors connected across

³ For many applications, a 150 Ω termination resistor should be connected across SIN+ to SIN-, and across COS+ to COS-. Please consult the feedback device datasheet for confirmation.

⁴ "FS" stands for "Full Scale"

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