

DRIVE MODEL	MCB 60			
SIZE	2.5/5	5/10	8/16	10/20
CASE	PM1	PM1	PM1	PM1
Rated Current (ADC)	2.5	5	8*	10*
Peak Current x 2 sec (ADC)	5	10	16	20
FDC: Supply Line Fuse Type T (time-lag)	15A / 250V			
Supply (VDC)	63VDC <sup>1</sup>			

NOTE <sup>1</sup> : Recommended DC power supply

## STANDARD FEATURES

- ⇒ Driving motor range up to 1.5 Nm (212 oz.-in.)
- ⇒ Three phase trapezoidal brushless, four quadrant operation
- ⇒ Panel mount
- ⇒ Highly efficient and reliable power MOSFET output stage
- ⇒ Single DC power supply
- ⇒ **EC** Commutation encoder Feedback
- ⇒ **RD** Differential reference control mode
- ⇒ Ixt function
- ⇒ Five LED (Red/Green) operating status signals
- ⇒ Fully protected against:
  - External short circuit      - Over/under voltage
  - Over temperature              - Hall Signal absence
- ⇒ Wide load inductance range (1 - 30 mH)
- ⇒ 60 / 120 degree commutation phase setting
- ⇒ Five calibration potentiometers
- ⇒ Extractable screw terminal
- ⇒ Enable input available with both positive / negative logic level

## Specifications

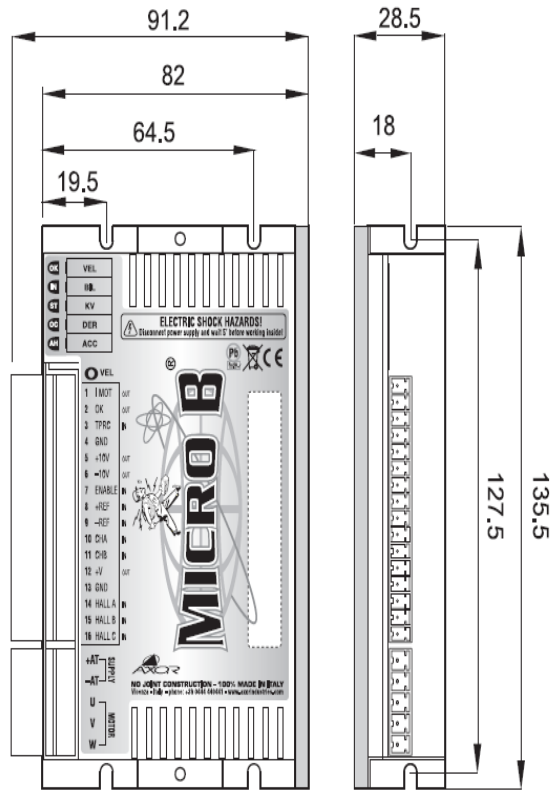
- ⇒ Supply voltage range:..... 20 - 82VDC
- ⇒ Operating frequency : ..... 20 KHz
- ⇒ Operating temperature: ..... 0 - 40 °C (32 - 104°F)
- ⇒ Input reference (differential):..... ± 10V
- ⇒ Motor current monitor:.. .. ±7,5V (At peak current)
- ⇒ Auxiliary output supply for encoder: +5V @ 130mA
- ⇒ Enable signals:..... +10 - 30VDC
- ⇒ Output voltage supply:..... +10V / -10V @ 4mA

## Options

- ⇒ **AH** Armature + hall Feedback
- ⇒ **EH** Encoder + external hall Feedback
- ⇒ **H0** Hall (only) Feedback
- ⇒ **IO** Demand current (torque mode)

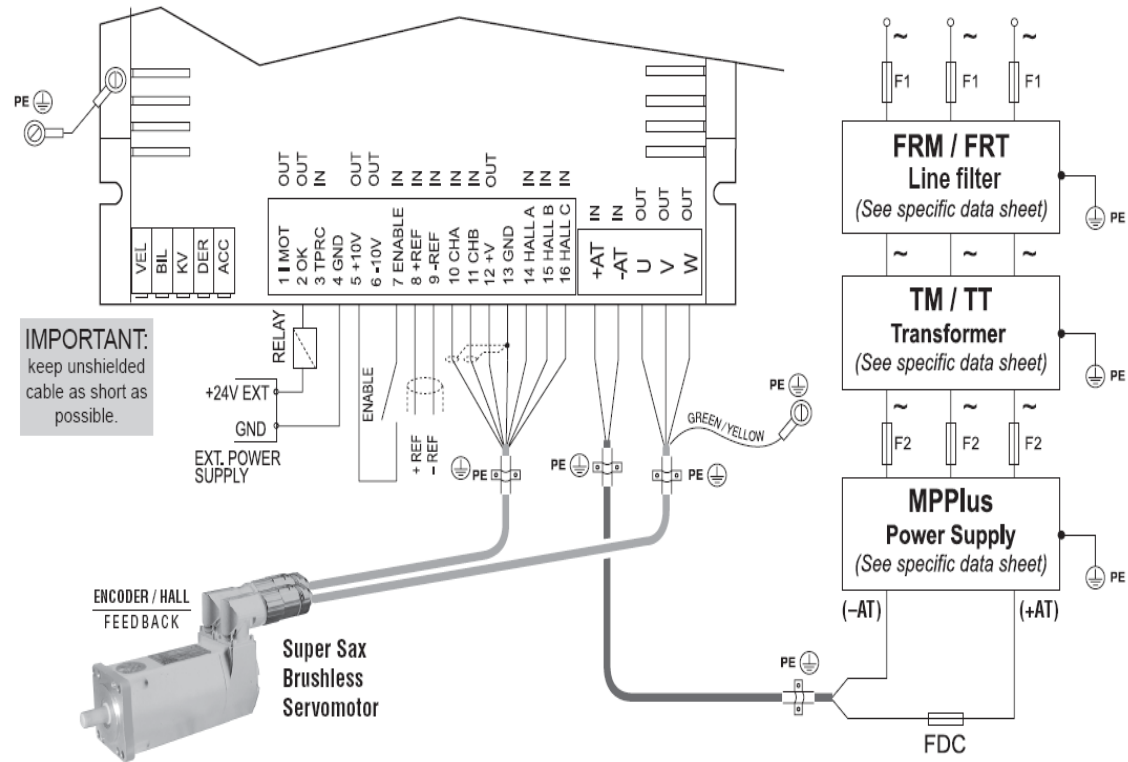


Dimensions in mm



CASE PM1 : Panel Mount 1

Weight: 0.35 Kg



**MCB - 60 - 10 / 20 - N - S - 1000 / EC - RD**

**DRIVE LINE**

**POWER SUPPLY:** 60 = 60 Vdc

**SIZE:** 2.5/05 - 05/10 - 08/16 - 10/20

**HEATSINK VERSIONS:** N = Normal (std)

**PROTECTION:**  
S = Standard  
T = Tropicalized

**AXOR**  
adjustment  
identification  
number

**FEEDBACK:**  
EC = Commutation encoder (std)  
AH = Armature+hall (opt)  
EH = Encoder+external hall (opt)  
HO = Hall (only) (opt)  
OO = No feedback  
(for IO control mode) (opt)

**CONTROL MODE:**  
RD = Differential reference (std)  
IO = Demand current  
(torque mode) (opt)