

Operating Instruction for | EN

EP1908

TwinSAFE EtherCAT Box with 8 fail-safe inputs

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1 Notes on the documentation

1.1 Disclaimer

Beckhoff products are subject to continuous further development. We reserve the right to revise the operating instructions at any time and without prior announcement. No claims for the modification of products that have already been supplied may be made on the basis of the data, diagrams and descriptions in these operating instructions.

In these operating instructions we define all permissible use cases whose properties and operating conditions we can guarantee. The use cases we define are fully tested and certified. Use cases beyond this, which are not described in these operating instructions, require the approval of Beckhoff Automation GmbH & Co KG.

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The EtherCAT technology is protected by patent rights through the following registrations and patents with corresponding applications and registrations in various other countries:

- EP1590927
- EP1789857
- EP1456722
- EP2137893
- DE102015105702



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All components in this product as described in the operating instructions are delivered in a specific configuration of hardware and software, depending on the application regulations. Modifications and changes to the hardware and/or software configuration that go beyond the documented options are prohibited and nullify the liability of Beckhoff Automation GmbH & Co. KG.

The following is excluded from the liability:

- Failure to observe these operating instructions
- Improper use
- Use of untrained personnel
- Use of unauthorized spare parts

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1.2 Documentation issue status

Version	Comment
3.0.0	<ul style="list-style-type: none"> • Foreword changed to Notes on the documentation [▶ 5] and For your safety [▶ 11] • In chapter Technical data [▶ 17] link to download page of certificates added • In chapter Technical data [▶ 17] “Power consumption U_s” changed in “Current consumption U_s” • Service life [▶ 46] moved • Maintenance and cleaning [▶ 47] and Decommissioning [▶ 48] adapted • Appendix adapted and expanded
2.2.0	<ul style="list-style-type: none"> • Characteristic curve of the inputs added • Note to earthing connection added • Description U_s updated
2.1.1	<ul style="list-style-type: none"> • Technical data <i>permissible air pressure</i> expanded
2.1.0	<ul style="list-style-type: none"> • Chapter <i>EP1908 process image</i> added
2.0.0	<ul style="list-style-type: none"> • Migration and structural adaptation • Reliability document updated • Safety parameters updated • Foreword revised
1.2.2	<ul style="list-style-type: none"> • Reliability document added • Description of the test pulses added • Reaction time updated in the technical data
1.2.1	<ul style="list-style-type: none"> • Certificate updated
1.2.0	<ul style="list-style-type: none"> • Company address amended • Documentation versions added • DateCode description added • HFT and element classification according to EN 61508:2010 added
1.1.2	<ul style="list-style-type: none"> • Clock output currents in the technical data amended • Notes regarding the M8 and M12 connectors expanded
1.1.1	<ul style="list-style-type: none"> • Reference to EN 60068-2-29 removed
1.1.0	<ul style="list-style-type: none"> • First released version

Currentness

Please check whether you are using the current and valid version of this document. The current version can be downloaded from the Beckhoff homepage at <http://www.beckhoff.de/twinsafe>. In case of doubt, please contact Technical Support (see [Beckhoff Support and Service \[▶ 10\]](#)).

Origin of the document

The original documentation is written in German. All other languages are derived from the German original.

Product features

Only the product properties specified in the current operating instructions are valid. Further information given on the product pages of the Beckhoff homepage, in emails or in other publications is not authoritative.

1.3 Staff qualification

These operating instructions are intended exclusively for trained specialists in control technology and automation with the relevant knowledge.

The trained specialist personnel must ensure that the applications and use of the described product meet all safety requirements. This includes all applicable and valid laws, regulations, provisions and standards.

Trained specialists

Trained specialists have extensive technical knowledge from studies, apprenticeships or technical training. Understanding of control technology and automation is available. Trained specialists can:

- Independently identify, avoid and eliminate sources of hazard.
- Apply relevant standards and directives.
- Implement specifications from accident prevention regulations.
- Evaluate, prepare and set up the workplaces.
- Evaluate, optimize and execute work independently.

1.4 Safety and instruction

Read the contents that refer to the activities you have to perform with the product. Always read the chapter [For your safety \[▶ 11\]](#) in the operating instructions.

Observe the warnings in the chapters so that you can handle and work with the product as intended and safely.

1.4.1 Explanation of symbols

Various symbols are used for a clear arrangement:

1. The numbering indicates an action that should be taken.
 - The bullet point indicates an enumeration.
- [...] The square brackets indicate cross-references to other text passages in the document.
- [1] The number in square brackets indicates the numbering of a referenced document.

1.4.1.1 Pictograms

In order to make it easier for you to find text passages, pictograms and signal words are used in warning notices:

DANGER

Failure to observe will result in serious or fatal injuries.

WARNING

Failure to observe may result in serious or fatal injuries.

CAUTION

Failure to observe may result in minor or moderate injuries.

NOTE

Notes

Notes are used for important information on the product. The possible consequences of failure to observe these include:

- Malfunctions of the product
- Damage to the product
- Damage to the environment

Information

This sign indicates information, tips and notes for dealing with the product or the software.

1.5 Beckhoff Support and Service

Support

Beckhoff Support offers technical advice on the use of individual Beckhoff products and system planning. The employees support you in the programming and commissioning of sophisticated automation systems.

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Download area

In the download area you can obtain product information, software updates, the TwinCAT automation software, documentation and much more.

Web: www.beckhoff.com/download

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For the addresses of our worldwide locations, please visit our website at [Global Presence](#).

2 For your safety

Read this chapter containing general safety information. In addition, always observe the safety instructions and warnings in these operating instructions for your own safety, the safety of other persons and the safety of the product.

When working with control and automation products, many dangers can result from careless or incorrect use. Work particularly thoroughly, not under time pressure and responsibly towards other people.

2.1 Duty of care



Read entire documentation for TwinSAFE component

- TwinSAFE application manual
- EL6910 TwinSAFE logic terminal operating manual
- TwinSAFE Logic FB documentation manual

The operator must comply with all the requirements and notes specified in these operating instructions in order to fulfill his duty of care. This includes in particular that you

- comply with the provisions defined in the chapter [Limitation of liability](#) [▶ 6].
- only operate the TwinSAFE component when it is in perfect working order.
- provide the operating instructions in a legible condition and complete at the place of use of the TwinSAFE component.
- do not remove the safety markings attached to the TwinSAFE component and maintain their legibility.

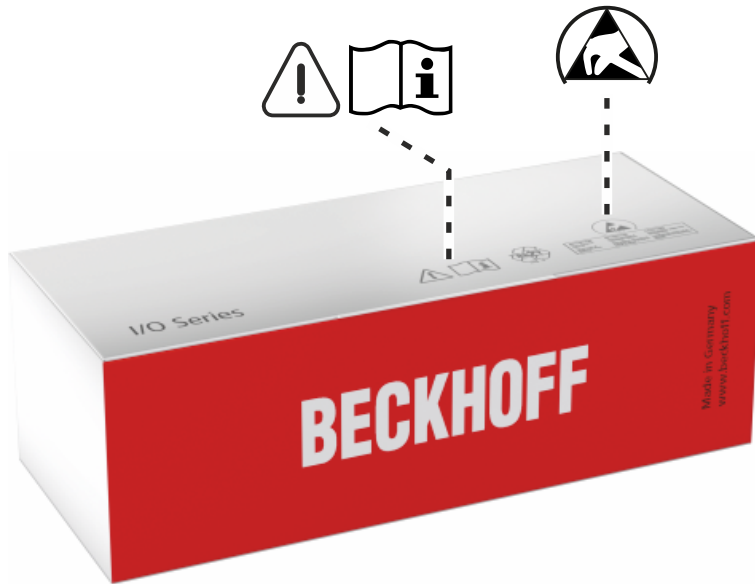



No disposal in domestic waste


Products marked with a crossed-out waste bin must not be disposed of with domestic waste. The device is considered waste electrical and electronic equipment when it is disposed of. Observe the national regulations for the disposal of waste electrical and electronic equipment.

2.2 Safety image signs

On Beckhoff products you will find attached or lasered safety pictograms, which vary depending on the product. They serve to ensure safety for people and to prevent damage to the products. Safety pictograms must not be removed and must be legible for the user.



-  **Read and observe the operating instructions**
Commissioning is only permitted if the operating instructions have been read and understood beforehand. This applies in particular to the safety instructions and warnings.

-  **Electrostatic sensitive components**
Work with and on the TwinSAFE component is only permitted in protected workplaces.

2.3 General safety instructions

2.3.1 Before operation

Use in machines according to the Machinery Directive

Only use the TwinSAFE component in machines that comply with the Machinery Directive. This is how you ensure safe operation.

Ensure traceability

Ensure the traceability of the TwinSAFE component via the serial number.

Use SELV/PELV power supply

Use a SELV/PELV power supply unit with an output-side voltage limit of $U_{\max} = 36 V_{DC}$ to supply the TwinSAFE component with $24 V_{DC}$.

Failure to observe this will endanger the safety function of the product. Depending on the machine, death and danger to life, serious physical injury and damage to the machine may result.

Carry out commissioning test

Before commissioning, wiring faults to the sensors must be excluded. Before commissioning, carry out a commissioning test. After a successful commissioning test, you can use the TwinSAFE component for the intended safety-related task.

In case of wiring errors, the safety function of the product is at risk. Depending on the machine, death and danger to life, serious bodily injury and damage to the machine may result.

2.3.2 In operation

Interference due to emitted interference

Do not operate the following devices in the vicinity of the TwinSAFE component: for example, radio telephones, radios, transmitters or high-frequency systems.

TwinSAFE components comply with the requirements of the applicable electromagnetic compatibility standards with regard to interference emission and immunity. If you exceed the limits for emitted interference specified in the standards, the function of the TwinSAFE component may be impaired.

2.3.3 After operation

De-energize and switch off components before working on them

Check all safety-relevant equipment for functionality before working on the TwinSAFE component. Secure the working environment. Secure the machine or plant against being inadvertently started up. Observe the chapter [Decommissioning](#) [► 48].

3 System description

3.1 EtherCAT Box Modules

The EtherCAT system has been extended with EtherCAT Box modules with protection class IP67. Through the integrated EtherCAT interface the modules can be connected directly to an EtherCAT network without an additional Coupler Box. The high-performance of EtherCAT is thus maintained into each module.

The extremely low dimensions of only e.g. 126 x 30 x 26.5 mm are identical to those of the Fieldbus Box extension modules. They are thus particularly suitable for use where space is at a premium. The small mass of the EtherCAT modules facilitates applications with mobile I/O interface (e.g. on a robot arm). The EtherCAT connection is established via screened M8 connectors.

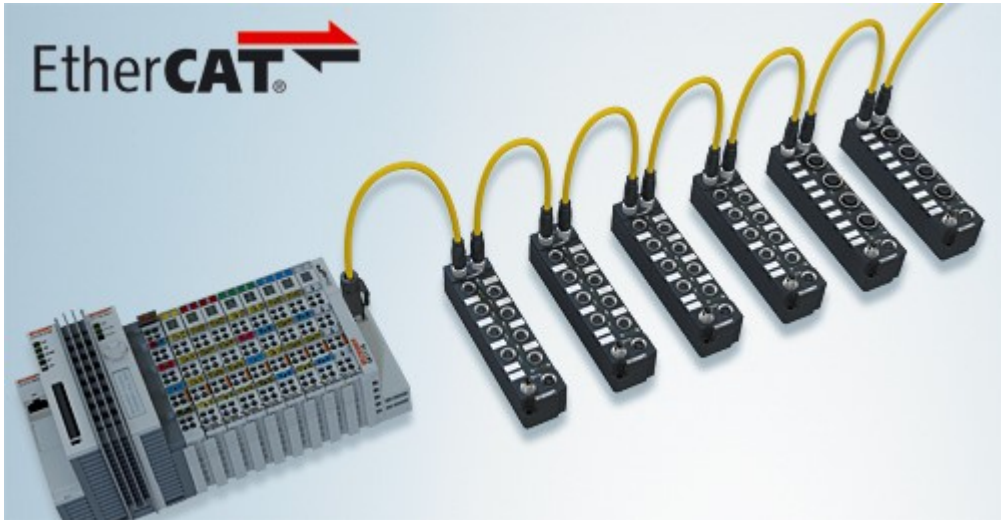


Fig. 1: EtherCAT Box modules extend the EtherCAT system with IP67 protection

The robust design of the EtherCAT Box modules enables them to be used directly at the machine. Control cabinets and terminal boxes are now no longer required. The modules are fully sealed and therefore ideally prepared for wet, dirty or dusty conditions.

Pre-assembled cables significantly simplify EtherCAT and signal wiring. Very few wiring errors are made, so that commissioning is optimized. In addition to pre-assembled EtherCAT, power and sensor cables, field-configurable connectors and cables are available for maximum flexibility. Depending on the application, the sensors and actuators are connected through M8 or M12 connectors.

● Basic EtherCAT documentation



You will find a detailed description of the EtherCAT system in the Basic System Documentation for EtherCAT, which is available for download from our website (www.beckhoff.com) under *Downloads*.

4 Product description

4.1 EP1908-0002

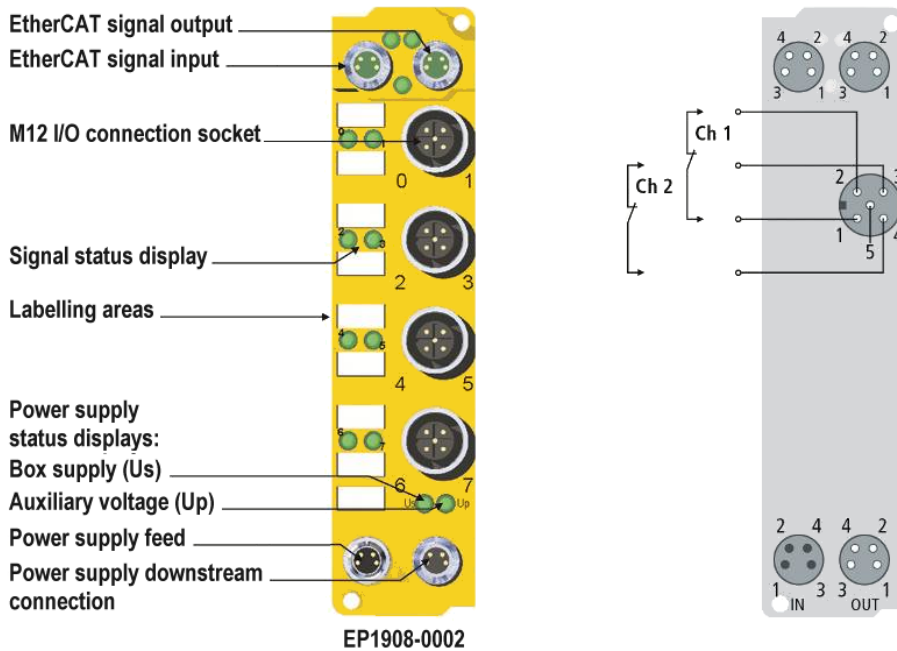


Fig. 2: EP1908-0002

The EP1908-0002 is an EtherCAT Box with digital inputs for 24 V_{DC} encoders or for potential-free contacts. The EtherCAT Box has eight fail-safe inputs.

In addition to the possibility to read potential-free contacts, the EP1908-0002 also supports the connection of encoders with OSSD signals whose test pulse length does not exceed 350 µs and of safety mats that operate based on the cross-circuit principle.

Frequency measurement is also supported, in order to enable standstill and speed monitoring. The frequency below which a logical 1 is reported at the input is specified in steps of 0.1 Hz. The module supports a minimum frequency of 2 Hz and a maximum frequency of 500 Hz. Frequencies above of 500 Hz result in a diagnostic message for the module. In this case all inputs are set to safe state (logical 0). This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.

With a two-channel connection, the EP1908-0002 meets the requirements of EN 61508-1:2010 SIL 3 and DIN EN ISO 13849-1:2006 (Cat 4, PL e).

The control voltage U_s supplies the module electronics. The sensors (test pulse outputs) are supplied from the control voltage U_p .

The TwinSAFE EtherCAT Box has the typical design of an EtherCAT Box.

4.2 Intended use

WARNING

Caution - Risk of injury!

TwinSAFE components shall only be used for the purposes described below!

The TwinSAFE EtherCAT Box expands the application range of the Beckhoff system with functions that enable it to be used for machine safety applications. The TwinSAFE Boxes are designed for machine safety functions and directly associated industrial automation tasks. They are therefore only approved for applications with a defined fail-safe state. This safe state is the wattless state. Fail-safety according to the relevant standards is required.

The TwinSAFE EtherCAT Box allows the connection of:

24 V_{DC} sensors such as

- emergency stop push buttons, pull cord switches, position switches, two-hand switches, safety mats, light curtains, light barriers, laser scanners etc.
- initiators and encoders for speed measurement (frequency) with a signal voltage of 24 V_{DC}

WARNING

The fail-safe principle

The basic rule for a safety system such as TwinSAFE is that failure of a part, a system component or the overall system must never lead to a dangerous condition. The safe state is always the switched off and wattless state.

WARNING

Power supply from SELV/PELV power supply unit!

The TwinSAFE components must be supplied with 24 V_{DC} by an SELV/PELV power supply unit with an output voltage limit U_{max} of 36 V_{DC}. Failure to observe this can result in a loss of safety.

CAUTION

Follow the machinery directive!

The TwinSAFE components shall only be used in machines as defined in the machinery directive.

CAUTION

Ensure traceability!

The buyer has to ensure the traceability of the device via the serial number.

4.3 Technical data

The current certificates of all TwinSAFE products with the underlying standards and directives can be found at <https://www.beckhoff.com/en-en/support/download-finder/certificates-approvals/>.

Product designation	EP1908-0002
Fieldbus	EtherCAT
Number of inputs	8
Connecting the inputs	M12
Status display	8 (one green LED per input)
Reaction time (Read input/write to E-bus)	typically: 5.5 ms, maximally: see error reaction time
Watchdog time	adjustable from 2 ms to 60 s
Error reaction time	≤ watchdog time
Frequency range for speed measurement	2 Hz to 500 Hz
Cable length between sensor and EtherCAT Box	Unshielded: 30 m max. (at 0.75 or 1 mm ²) Shielded: 30 m max. (at 0.75 or 1 mm ²)
Output current of the clock outputs	typically 10 mA, max. 15 mA
Input process image	6 bytes
Output process image	6 bytes
Supply voltage for the EP1908	24 V _{DC} (-15%/+20%)
Current consumption U _s (connected with eight potential-free contacts)	8 channels occupied: typically 87 mA 0 channel occupied: typically 80 mA
Current consumption U _p (connected with eight potential-free contacts)	8 channels occupied: approx. 27 mA 0 channel occupied: approx. 6 mA
Power dissipation of the EtherCAT Box	typically 3 watts
Electrical isolation (between the channels)	no
Electrical isolation (between the channels and EtherCAT)	yes
Insulation voltage (between the channels and EtherCAT, under common operating conditions)	insulation tested with 500 V _{DC}
Dimensions (W x H x D)	30mm x 126mm x 26.5mm
Housing material	PA6-F (polyamide)
Sealing compound	polyurethane
Weight	approx. 170 g
Permissible ambient temperature (operation)	-25°C to +60°C
Permissible ambient temperature (transport/storage)	-40°C to +85°C
Permissible air humidity	5% to 95%, non-condensing
Permissible air pressure (operation/storage/transport)	750 hPa to 1100 hPa (this corresponds to a height of approx. -690 m to 2450 m over sea level assuming an international standard atmosphere)
Impermissible operating conditions	TwinSAFE EtherCAT boxes must not be used under the following conditions: <ul style="list-style-type: none"> • under the influence of ionizing radiation (that exceeds the level of the natural environmental radiation) • in corrosive environments
EMC immunity/emission	conforms to EN 61000-6-2 / EN 61000-6-4
Vibration/shock resistance	conforms to EN 60068-2-6 / EN 60068-2-27
Shocks	15 g with pulse duration 11 ms in all three axes
Protection class (when screwed together)	IP65, IP66, IP67 (according to EN 60529)
Permissible installation position	variable
Approvals	CE, TÜV SÜD

4.4 Safety parameters

Key figures	EP1908-0002
Lifetime [a]	20
Proof test Interval [a]	not required ¹
PFH _D	1.56E-09
%SIL3	1,56%
PFD	1.06E-04
%SIL3	10,59%
MTTF _d	high
DC	high
Performance level	PL e
Category	4
HFT	1
Element classification ²	Type B

1. Special proof tests throughout the service life of the EtherCAT Box are not required.
2. Classification according to EN 61508-2:2010 (see chapters 7.4.4.1.2 and 7.4.4.1.3)

The EP1908-0002 EtherCAT Box can be used for safety-related applications according to IEC 61508 up to SIL3 and EN ISO 13849-1 up to PL e (Cat4).

For the calculation or estimation of the MTTF_d value from the PFH_D value, further information can be found in the TwinSAFE application manual or in ISO 13849-1:2015 Table K.1.

4.5 Characteristic curve of the inputs

The characteristic curve of the inputs is similar to type 3 according to EN 61131-2.

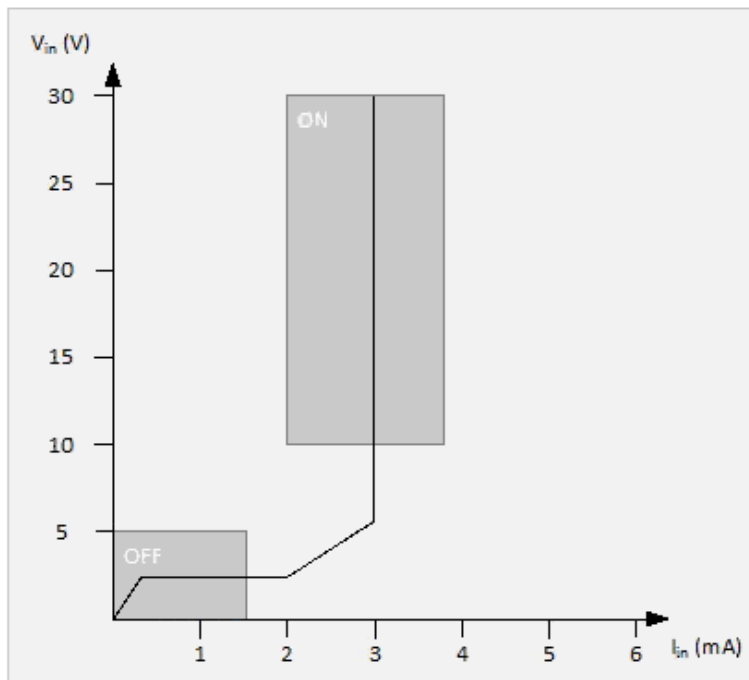


Fig. 3: Characteristic curve of the inputs

4.6 Dimensions

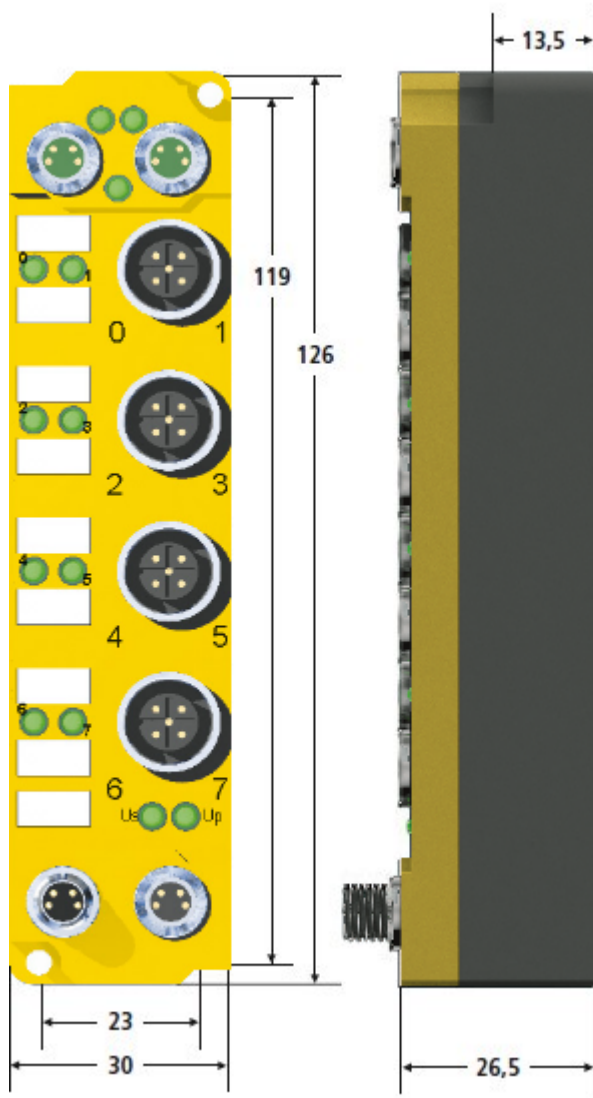


Fig. 4: Dimensions

The modules have the following dimensions.

Width: 30 mm

Height: 126 mm

Depth: 26.5 mm

When fully wired, the connected cables increase the total depth of the module.

5 Operation

5.1 Environmental conditions

Please ensure that the TwinSAFE Boxes are only transported, stored and operated under the specified conditions (see technical data)!

WARNING

Risk of injury!

The TwinSAFE EtherCAT boxes must not be used under the following conditions.

- under the influence of ionizing radiation (that exceeds the level of the natural environmental radiation)
- in corrosive environments

NOTE

Electromagnetic compatibility

The TwinSAFE components comply with the current standards on electromagnetic compatibility with regard to spurious radiation and immunity to interference in particular.

However, in cases where devices such as mobile phones, radio equipment, transmitters or high-frequency systems that exceed the interference emissions limits specified in the standards are operated near TwinSAFE components, the function of the TwinSAFE components may be impaired.

5.2 Installation

5.2.1 Safety instructions

Before installing and commissioning the TwinSAFE components please read the safety instructions in the foreword of this documentation.

5.2.2 Transport / storage

Use the original packaging in which the components were delivered for transporting and storing the TwinSAFE components.

CAUTION

Note the specified environmental conditions

Please ensure that the digital TwinSAFE components are only transported and stored under the specified environmental conditions (see technical data).

5.2.3 Address settings on the TwinSAFE EtherCAT Box

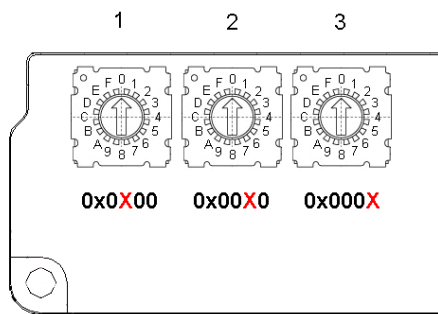


Fig. 5: Rotary switch for setting the TwinSAFE address

The TwinSAFE address of the box must be set using the three rotary switches at the bottom of the EP1908-0002 TwinSAFE EP Box. TwinSAFE addresses between 1 and 4095 are available.

Rotary switch			Address
1 (left)	2 (center)	3 (right)	
0	0	1	1
0	0	2	2
0	0	3	3
...
0	0	F	15
0	1	0	16
0	1	1	17
...
0	F	F	255
1	0	0	256
1	0	1	257
...
F	F	F	4095

⚠ WARNING

TwinSAFE address

Each TwinSAFE address may only be used once within a network!
The address 0 is not a valid address.

5.2.4 Mounting



Protect connectors against soiling

Protect all connections from contamination during module installation!

Protection class IP67 can only be guaranteed if all cables and connectors are connected!

Unused connections must be protected with the appropriate connectors (connector sets see catalogue)!

The modules are mounted with two M3 screws. The bolts must be longer than 15 mm. The fixing holes are not threaded. Note when mounting that the overall height is increased further by the fieldbus connections.

Mounting rail ZS5300-0001

The mounting rail ZS5300-0001 (500 mm x 129 mm) allows time-saving configuration of the modules. The rail is made of 1.5 mm thick stainless steel (V2A) and features ready-made M3 threads. Use M5 screws (5.3 mm oblong holes) to attach the rail to the machine.

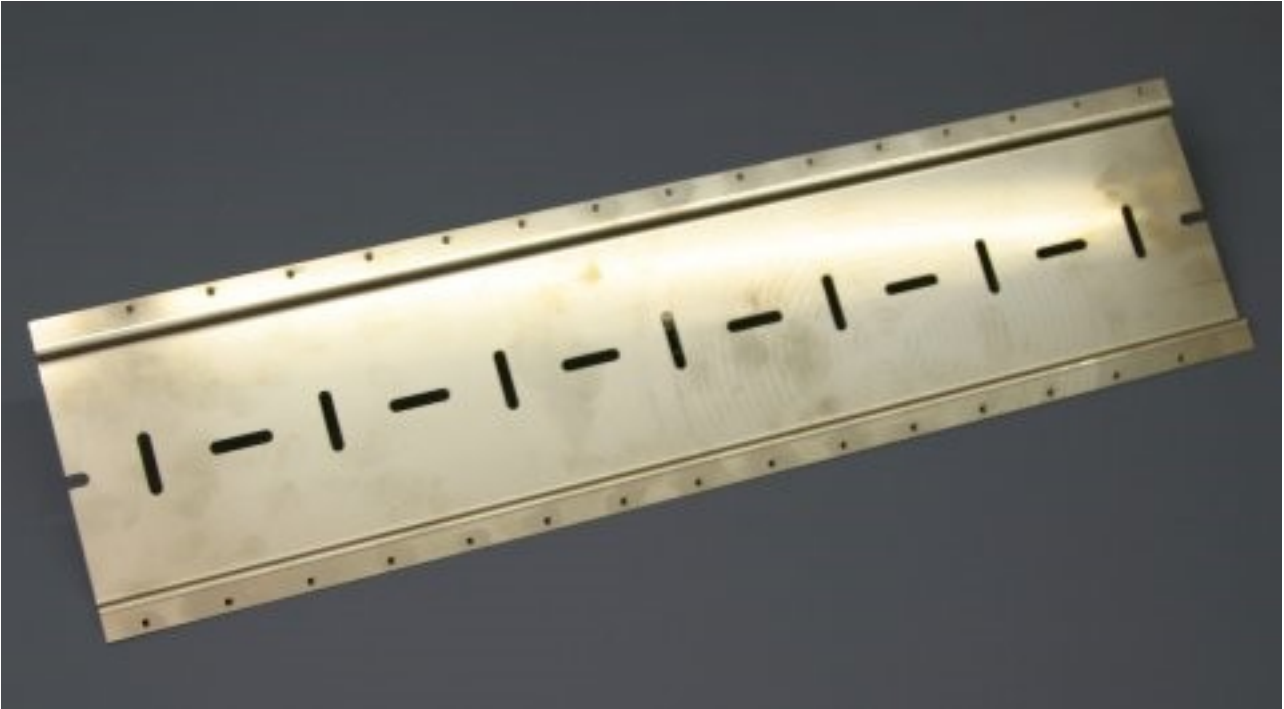


Fig. 6: Mounting rail ZS5300-0001

The rail is 500 mm long and enables the installation of 15 modules, with a distance of 2 mm between them. It can be shortened as required for your particular application.

5.2.5 Connection

5.2.5.1 Tightening torque for connectors

The plug connectors should be tightened with the recommended torque.

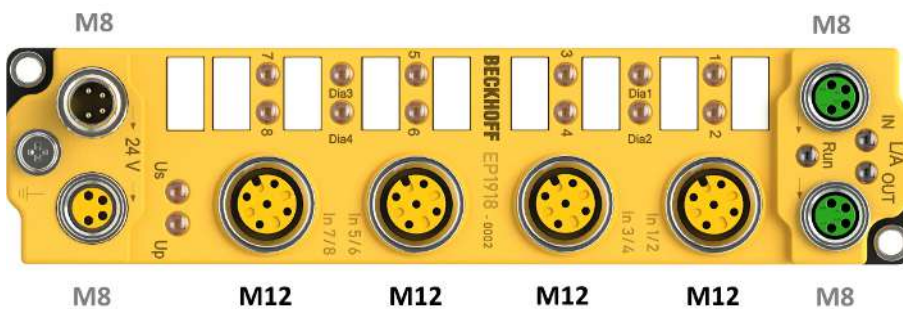


Fig. 7: EtherCAT Box with M8 and M12 connectors

Type	Connection	Nm	ft-lb
M8	Power supply, EtherCAT	0,4	0,3
M12	Input signals	0,6	0,44

Torque wrench



Fig. 8: Torque wrench ZB8801

- **Ensure the proper torque is used**
- i** Use torque wrenches available from Beckhoff to tighten the plug connectors (see accessories)!

5.2.5.2 EtherCAT connection

The EtherCAT Box (EPxxxx) has two M8 connectors marked **green** for the incoming and outgoing EtherCAT connection.

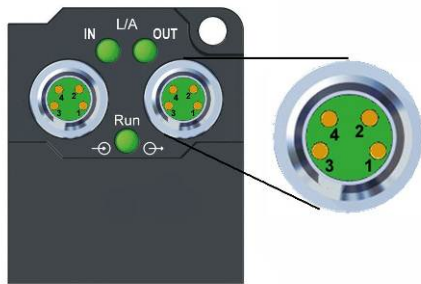


Fig. 9: EtherCAT Box: M8, 30 mm housing

Assignment

There are various different standards for the assignment and colors of connectors and cables for EtherCAT.

EtherCAT		Connector	Cable		Standard
Signal	Description	M8	ZB9010, ZB9020, ZK1090-6292	ZB903x, ZK1090-31xx	TIA-568B
Tx +	Transmit Data+	Pin 1	yellow1	orange/white2	white/orange
Tx -	Transmit Data-	Pin 4	orange1	orange2	orange
Rx +	Transmit Data-	Pin 2	white1	blue/white2	white/green
Rx -	Receive Data-	Pin 3	blue1	blue2	green
Shield	Shield	Housing	Shield	Shield	Shield

- 1) Wire colors according to EN 61918
- 2) Wire colors

5.2.5.3 EtherCAT- Fieldbus LEDs



Fig. 10: EtherCAT LEDs

LED indicators

LED	Display	Meaning
IN L/A	off	no connection to the preceding EtherCAT module
	lit	LINK: connection to the preceding EtherCAT module
	flashing	ACT: communication with the preceding EtherCAT module
OUT L/A	off	no connection to the following EtherCAT module
	lit	LINK: connection to the following EtherCAT module
	flashing	ACT: Communication with the following EtherCAT module
Run	-	See chapter 4.4.1 [▶ 34]

5.2.5.4 EtherCAT cables

For connecting EtherCAT devices only Ethernet cables that meet the requirements of at least **category 5 (CAT5) according to EN 50173 or ISO/IEC 11801** should be used.

● Wiring recommendations

i Detailed recommendations for EtherCAT wiring can be found in the documentation "Design recommendations for EtherCAT/Ethernet infrastructure", which is available for download from www.Beckhoff.de.

EtherCAT uses four cable wires for signal transmission. Due to automatic cable detection (auto-crossing) symmetric (1:1) or cross-over cables can be used between EtherCAT devices from BECKHOFF.

5.2.5.5 Power Connection

Two M8 connectors at the low-end of the modules are used for feeding and routing the supply voltages:

- IN: left M8 connector for feeding the supply voltages
- OUT: right M8 connector for routing the supply voltages
- Earthing screw: The earthing screw is installed in the factory. An additional M3 ring cable lug and the earthing cable are required for the installation.

● Earthing connection

i It is recommended to connect the earth connection to PE with low resistance.

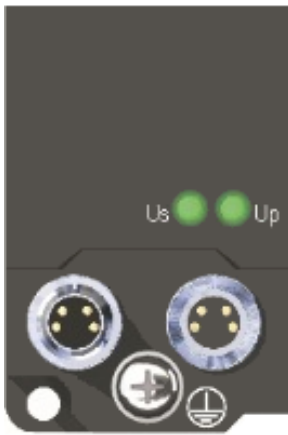


Fig. 11: Connections for the supply voltages

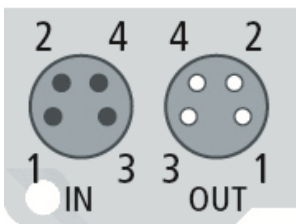


Fig. 12: Pin assignment of the M8 connector the supply voltages

Contact	Voltage
1	Control voltage U_s , +24 V _{DC}
2	Peripheral voltage U_p , +24 V _{DC}
3	GNDs*
4	GNDp*
PE	Earthing connection

The contacts of the M8 plug connectors can conduct a maximum current of 4 A.

Two LEDs indicate the status of the supply voltages.

NOTE

Do not confuse the power port with EtherCAT port!

Never connect the power cables (M8, 24 V_{DC}) to the green-marked EtherCAT sockets of the EtherCAT Box Modules. This can cause the destruction of the modules!

Control voltage U_s : 24 V_{DC}

Power is supplied to the fieldbus, the processor logic and also to the inputs from the 24 V_{DC} control voltage U_s . The control voltage is electrically isolated from the fieldbus circuitry.

Peripheral voltage U_p : 24 V_{DC}

The peripheral voltage U_p supplies the digital pulse outputs; it can be brought in separately. Hence, if the load voltage is switched off, the fieldbus function as well as the supply and function of the inputs are retained.

Redirection of the supply voltages

The power IN and OUT connections are bridged in the module. Hence, the supply voltages U_s and U_p can be passed from EtherCAT Box to EtherCAT Box in a simple manner.

NOTE**Note the maximum current!**

Ensure that the maximum permitted current of 4 A for the M8 plug connectors is not exceeded when routing the supply voltages U_s and U_p !

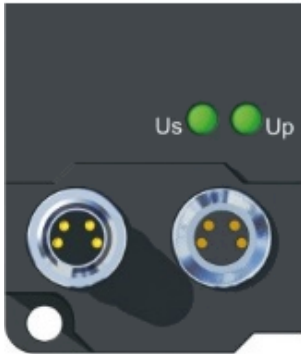
5.2.5.6 Status-LEDs for the power supply

Fig. 13: Status-LEDs for the power supply

LED	Display	Meaning
U_s (control voltage)	off	the power supply voltage, U_s , is not present
	green illuminated	the power supply voltage, U_s , is present
U_p (peripheral voltage)	off	the power supply voltage, U_p , is not present
	green illuminated	The power supply voltage, U_p , is present

5.2.5.7 Overvoltage protection

If protection against overvoltage is necessary in your system, provide a protective circuit (surge filter) against overvoltage for the power supply to the EtherCAT Box.

5.2.5.8 Signal connection

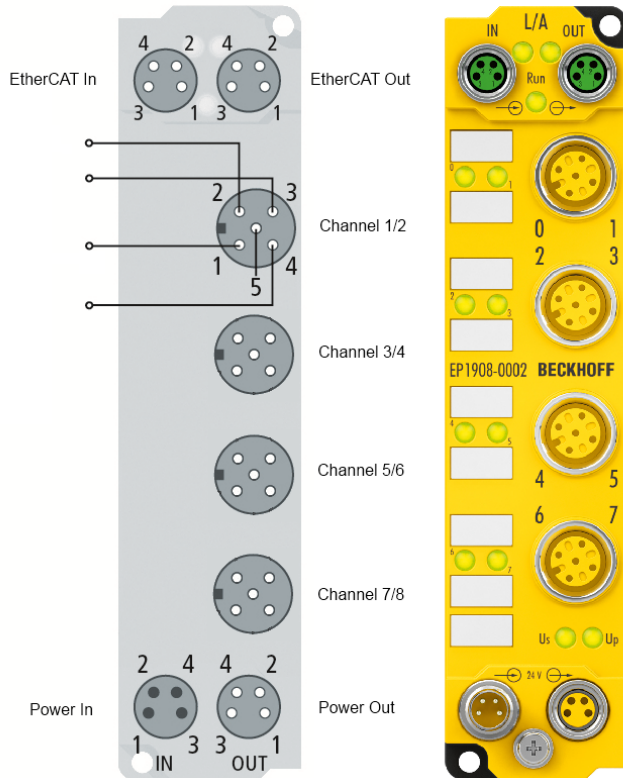


Fig. 14: Signal connection

M12 connection	Contact	Channel	Signal
1	1	1	Pulse output 1
	2		Input 1
	3	2	Pulse output 2
	4		Input 2
	5	-	not connected
2	1	3	Pulse output 3
	2		Input 3
	3	4	Pulse output 4
	4		Input 4
	5	-	not connected
3	1	5	Pulse output 5
	2		Input 5
	3	6	Pulse output 6
	4		Input 6
	5	-	not connected
4	1	7	Pulse output 7
	2		Input 7
	3	8	Pulse output 8
	4		Input 8
	5	-	not connected

i Configurable inputs

The inputs 1 to 8 can be occupied as you want with normally closed contacts or normally open contacts. The corresponding analysis is carried out in the safety PLC.

5.2.6 Signal cables

Permitted cable length

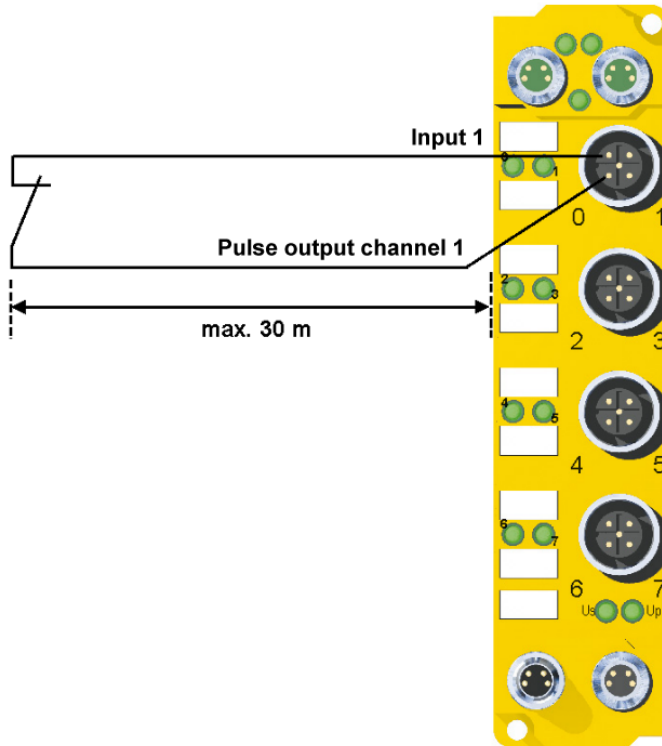


Fig. 15: Permitted cable length

When connecting a single switching contact via a dedicated continuous cable (or via a non-metallic sheathed cable), the maximum permitted cable length is 30 m if a sensor test is active.

The use of contact points, plug connectors or additional switching contacts in the cabling also reduces the maximum propagation.

Cable routing

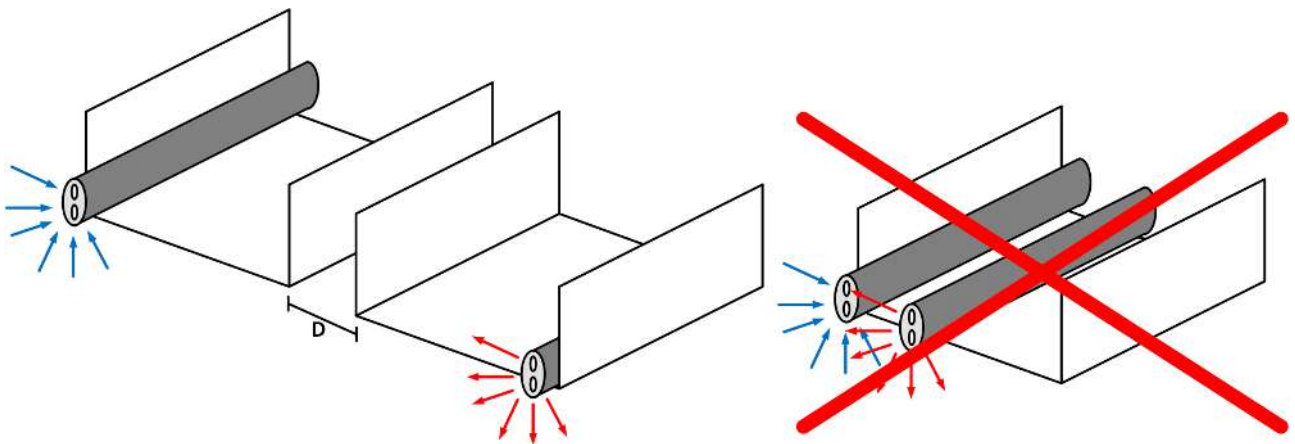


Fig. 16: Cable routing

NOTE**Route the signal cable separately**

The signal cable must be routed separately from potential sources of interference, such as motor supply cables, 230 V_{AC} power cables etc.!

Interference caused by cables routed in parallel can influence the signal form of the test pulses and thus cause diagnostic messages (e.g. sensor errors or OpenLoad errors).

D: Distance between the cable ducts should be as large as possible

blue arrows: signal line

red arrows: potential source of interference

The common routing of signals together with other clocked signals in a common cable also reduces the maximum propagation, since crosstalk of the signals can occur over long cable lengths and cause diagnostic messages.

The test pulses can be switched off (sensor test parameter) if the connection of a common cable is unavoidable. However, this then leads to a reduction in the degree of diagnostic cover when calculating the performance level.

5.2.7 Description of the EP1908 test pulses

The typical length of a test pulse (switching from 24 V to 0 V and back to 24 V) is 350 µs and takes place approx. 180 times per second.

The test pulses at the outputs Pulse Output 1 to Pulse Output 8 are generated separately for each channel in order to be able to detect cross-circuits between the individual channels of a terminal and also between channels of different terminals. In order to generate test pulses as shown in the diagram, the *Sensor test active* safety parameter must be set to *true* for the respective channels. The test cycle for all 8 channels is typically 5.5 ms. The times between the test pulses of different channels vary, thus allowing better diagnostic detection.

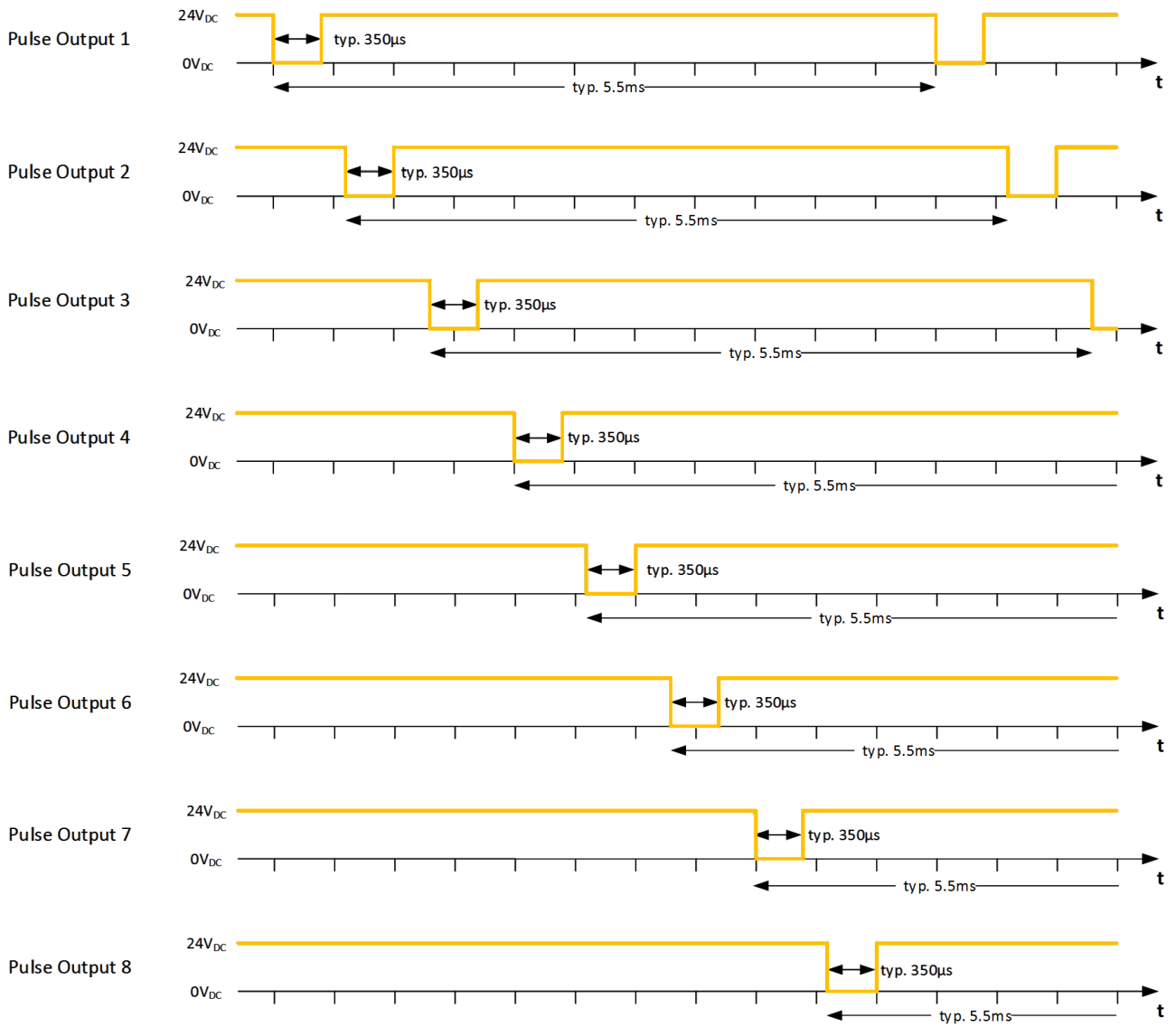


Fig. 17: EP1908 test pulses

If self-testing sensors are to be used on the safe inputs, please refer to chapter [4.5.3.1](#) [▶ 40].

5.2.8 TwinSAFE reaction times

The TwinSAFE terminals form a modular safety system that exchanges safety-oriented data via the Safety-over-EtherCAT protocol. This chapter is intended to help you determine the system's reaction time from the change of signal at the sensor to the reaction at the actuator.

Typical reaction time

The typical reaction time is the time that is required to transmit information from the sensor to the actuator, if the overall system is working without error in normal operation.

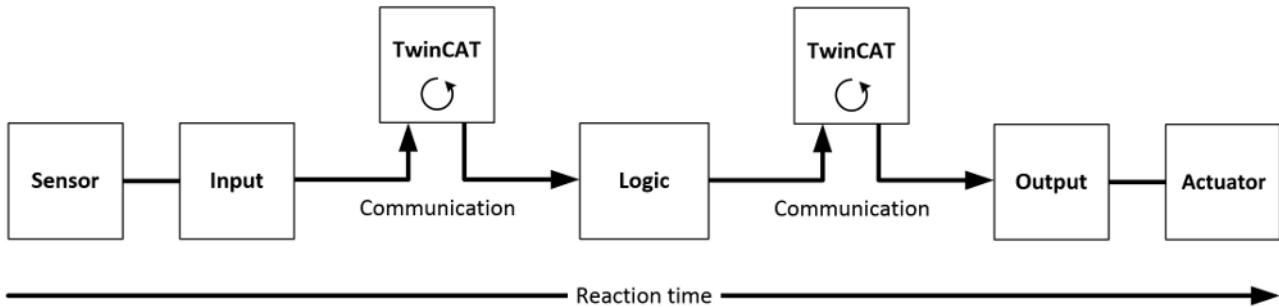


Fig. 18: Typical reaction time

Definition	Description
RTSensor	Reaction time of the sensor until the signal is provided at the interface. Typically supplied by the sensor manufacturer.
RTInput	Reaction time of the safe input, such as EL1904 or EP1908. This time can be found in the technical data. In the case of the EL1904 it is 4 ms.
RTComm	Reaction time of the communication This is typically 3x the EtherCAT cycle time, because new data can only be sent in a new Safety-over-EtherCAT telegram. These times depend directly on the higher-level standard controller (cycle time of the PLC/NC).
RTLogic	Reaction time of the logic terminal. This is the cycle time of the logic terminal and typically ranges from 500 µs to 10 ms for the EL6900, depending on the size of the safety project. The actual cycle time can be read from the terminal.
RTOutput	Reaction time of the output terminal. This typically lies within the range of 2 to 3 ms.
RTActor	Reaction time of the actuator. This information is typically supplied by the actuator manufacturer
WDComm	Watchdog time of the communication

This results in the following equation for the typical reaction time:

$$ReactionTime_{typ} = RT_{Sensor} + RT_{Input} + 3 * RT_{Comm} + RT_{Logic} + 3 * RT_{Comm} + RT_{Output} + RT_{Actor}$$

with, for example

$$ReactionTime_{typ} = 5ms + 4ms + 3 * 1ms + 10ms + 3 * 1ms + 3ms + 20ms = 48ms$$

Worst-case reaction time

The worst case reaction time is the maximum time required to switch off the actuator in the case of an error.

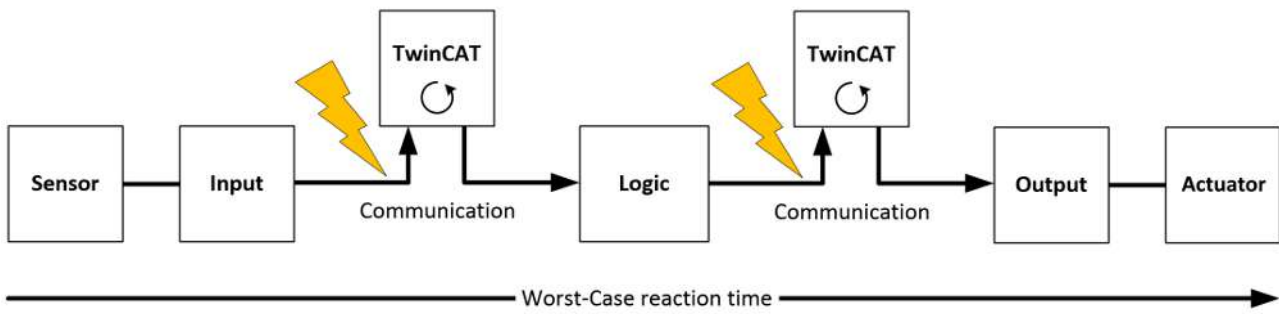


Fig. 19: Worst-case reaction time

This assumes that a signal change occurs at the sensor and is transmitted to the input. A communication error occurs at precisely the moment when the signal is to be transferred to the communication interface. This is detected by the logic following the watchdog time of the communication link. This information should then be transferred to the output, but a further communication error occurs here. This error is detected at the output following the expiry of the watchdog time and leads to the switch-off.

This results in the following equation for the worst-case reaction:

$$ReactionTime_{max} = WD_{Comm} + WD_{Comm} + RT_{Actuator}$$

with, for example

$$ReactionTime_{max} = 15\text{ ms} + 15\text{ ms} + 20\text{ ms} = 50\text{ ms}$$

5.3 Operation modes

Operation mode	Description
Single logic channel x/y	Each channel is evaluated individually
Asynchronous analysis OSSD, sensortest deactivated	Mode for connecting devices with OSSD signals. The test pulses of the OSSD devices must not occur simultaneously. The maximum supported test pulse length is 350 µs. In this mode the sensor test must be switched off for the input pair used.
Any pulse repetition OSSD, sensortest deactivated	Mode for connecting devices with OSSD signals. The test pulses of the OSSD devices may occur simultaneously. The maximum supported test pulse length is 350 µs. In this mode the sensor test must be switched off for the input pair used.
Short cut channel x/y is no module fault	Mode for connecting safety mats. In this mode the two inputs of the input pair used are monitored for cross-circuit. If a cross-circuit occurs a person has walked on the safety mat, and the inputs report logical 0 in pairs. The sensor test must be switched on for the inputs used.
Velocity control channel x / Single logic channel y	Speed monitoring channel x / individual evaluation channel y The first channel (x) returns a logical 1 if the current frequency is below the frequency set under <i>Velocity limit channel x</i> . The second channel (y) supplies the current signal state at input y. The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.
Single logic channel x / Velocity control channel y	Individual evaluation channel x / Speed monitoring channel y The first channel (x) reports the current signal state of input x. The second channel (x) returns a logical 1 if the current frequency is below the frequency set under <i>Velocity limit channel y</i> . The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.
Velocity control channel x/y	Speed monitoring channel x / speed monitoring channel y The first channel (x) returns a logical 1 if the current frequency is below the frequency set under <i>Velocity limit channel x</i> . The second channel (x) returns a logical 1 if the current frequency is below the frequency set under <i>Velocity limit channel y</i> .

Operation mode	Description
	The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.
Two channel sync. Velocity control channel x/y	Two-channel evaluation of the frequency, whereby at least one input signal always has to be at logical 1. The frequencies and the upper limit frequencies have to be the same. The two channels return logical 1 if the current frequency is below the frequency set under <i>Velocity limit channel x/y</i> . The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.
Two channel encoder velocity control channel x/y	Two-channel evaluation of the frequency. The upper limit frequencies are specified separately, but should be the same. The same frequencies have to be supplied, whereby all states are permitted that may occur at the encoder interface. The two channels return logical 1 if the current frequency is below the frequency set under <i>Velocity limit channel x/y</i> . The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.
Two channel async. velocity control channel x/y	Two-channel evaluation of the frequencies. In this mode is only the compliance with the limits for the two channels is monitored. The upper limit frequencies are specified separately. The two channels return logical 1 if both frequencies are below the frequency set under <i>Velocity limit channel x/y</i> . The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.

● Speed / frequency measurement

i The permitted frequency range is between 2 Hz and 500 Hz. Values below are reported as 0 Hz, values above result in a diagnostic messages of the EP1908-0002. This diagnostic message can be reset through a rising edge at the safe output signal ErrAck of the EP1908-0002.

5.4 EP1908 process image

The process image of the EP1908-0002 consists of 6 bytes of input data and 6 bytes of output data. These data contain the Safety over EtherCAT protocol. The eight safe input channels of the EP1908-0002 are contained in the safe input data. The first channel of the safe output data contains the ErrAck signal, which can be used to reset a diagnostic message of the EP1908, such as exceeding of the maximum allowable frequency.

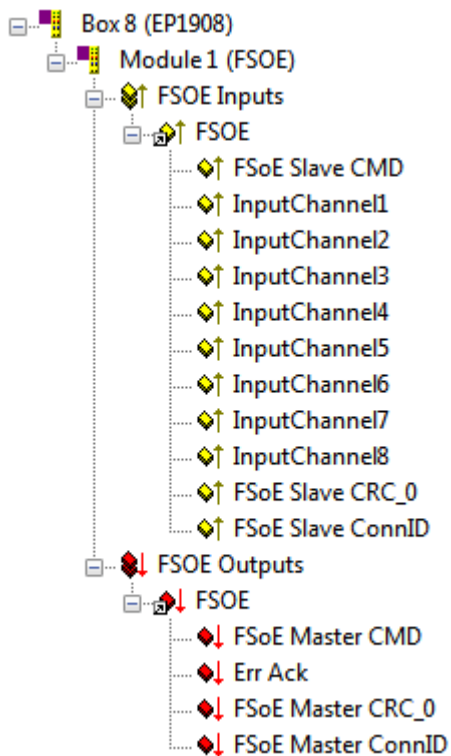


Fig. 20: EP1908 process image

5.5 Diagnostics

5.5.1 Run LED diagnostics

The Run LED shows diagnostic information for the EP1908-0002.



Fig. 21: Run LED diagnostics

Run LED (green)

The *Run* LED lights green when the EP1908-0002 has booted without error.

Run LED (red)

The *Run* LED lights red when the TwinSAFE EtherCAT Box has detected an error, such as cross-circuit, external feed or exceeding of the maximum frequency.

5.5.2 Diagnostic objects

The CoE objects indicate additional diagnostic information.

⚠ CAUTION

Do not change CoE objects!

Do not make any modifications to the CoE objects in the TwinSAFE components! Any modifications (e.g. using TwinCAT) of the CoE objects will permanently set the TwinSAFE components to the Fail-Stop state.

CoE object 0xA008: FSOE Velocity

Index	Name	Meaning	Flags	Default
0xA008:0	FSOE Velocity	The following sub-indices contain the currently measured frequencies in 0.1 Hz.	RO	
0xA008:01 ... 0xA008:08	Velocity 1 ... Velocity 8	Frequency at channels 1 to 8 in 0.1 Hz	RO	

CoE object 0xA009: FSOE max Velocity

Index	Name	Meaning	Flags	Default
0xA009:0	FSOE max Velocity	The following sub-indices contain the maximum frequencies (in 0.1 Hz) determined since the last startup of the TwinSAFE communication with the EP1908-0002.	RO	
0xA009:01 ... 0xA009:08	maxVelocity 1 ... maxVelocity 8	Maximum frequency at channels 1 to 8 in 0.1 Hz	RO	

CoE object 0x800E: Diagnostic objects

Index	Name	Meaning	Flags	Default
800E:0	FSOE Internal Data	The following sub-indices contain detailed diagnostic information.	RO	
800E:0A	Sensor test error	Bit Error during sensor test. This may be an external feed, for example.	RO	
		0 1 _{bin} Error at input 1		0 _{bin}
		1 1 _{bin} Error at input 2		0 _{bin}
		2 1 _{bin} Error at input 3		0 _{bin}
		3 1 _{bin} Error at input 4		00 _{bin}
		4 1 _{bin} Error at input 5		0 _{bin}
		5 1 _{bin} Error at input 6		0 _{bin}
		6 1 _{bin} Error at input 7		0 _{bin}
		7 1 _{bin} Error at input 8		0 _{bin}
800E:0B	Error during two-channel evaluation	Bit Error during the contiguous evaluation of two channels, i.e. the two channels contradict each other.	RO	
		0 1 _{bin} Error in the first input pair		0 _{bin}
		1 1 _{bin} Error in the second input pair		0 _{bin}
		2 1 _{bin} Error in the third input pair		0 _{bin}
		3 1 _{bin} Error in the fourth input pair		0 _{bin}
800E:0C	Error in the safety mat operation mode: input pair disagree	Bits Error in the input pair	RO	
		1, 0 11 _{bin} Error in the first input pair		00 _{bin}
		3, 2 11 _{bin} Error in the second input pair		00 _{bin}
		5, 4 11 _{bin} Error in the third input pair		00 _{bin}
		7, 6 11 _{bin} Error in the fourth input pair		00 _{bin}
800E:0D	Error in the safety mat operation mode: external supply	Bit Error in the test pulses in the safety mat operating mode; i.e. the EtherCAT Box has detected an external supply.	RO	
		0 1 _{bin} Error at input 1		0 _{bin}
		1 1 _{bin} Error at input 2		0 _{bin}
		2 1 _{bin} Error at input 3		0 _{bin}
		3 1 _{bin} Error at input 4		0 _{bin}
		4 1 _{bin} Error at input 5		0 _{bin}
		5 1 _{bin} Error at input 6		0 _{bin}
		6 1 _{bin} Error at input 7		0 _{bin}
		7 1 _{bin} Error at input 8		0 _{bin}

Index	Name	Meaning	Flags	Default		
800E:13	Speed monitoring error: Overspeed	Bit	Overspeed was detected at an input.	RO		
		0	1 _{bin}		Speed at input 1 is too high	0 _{bin}
		1	1 _{bin}		Speed at input 2 is too high	0 _{bin}
		2	1 _{bin}		Speed at input 3 is too high	0 _{bin}
		3	1 _{bin}		Speed at input 4 is too high	0 _{bin}
		4	1 _{bin}		Speed at input 5 is too high	0 _{bin}
		5	1 _{bin}		Speed at input 6 is too high	0 _{bin}
		6	1 _{bin}		Speed at input 7 is too high	0 _{bin}
		7	1 _{bin}		Speed at input 8 is too high	0 _{bin}
800E:14	Error in operating mode: <i>Two Channel Sync Velocity Control</i>	Bit	Both inputs of an input pair were read with inactive state.	RO		
		0	1 _{bin}		Error in the first input pair	0 _{bin}
		1	1 _{bin}		Error in the second input pair	0 _{bin}
		2	1 _{bin}		Error in the third input pair	0 _{bin}
		3	1 _{bin}		Error in the fourth input pair	0 _{bin}
800E:15	Error in operating mode: <i>Two Channel Sync Velocity Control</i> and <i>Two Channel Encoder Velocity Control</i>	Bit	Different speeds were identified for the two inputs of an input pair.	RO		
		0	1 _{bin}		Error in the first input pair	0 _{bin}
		1	1 _{bin}		Error in the second input pair	0 _{bin}
		2	1 _{bin}		Error in the third input pair	0 _{bin}
		3	1 _{bin}		Error in the fourth input pair	0 _{bin}

i Differing diagnostic messages possible

Due to the variable order or execution of the test series, diagnostic messages differing from those given in the table above are possible.

5.6 EP1908 configuration in TwinCAT

⚠ CAUTION

Do not change CoE objects!

Do not make any modifications to the CoE objects in the TwinSAFE components! Any modifications (e.g. using TwinCAT) of the CoE objects will permanently set the TwinSAFE components to the Fail-Stop state.

5.6.1 Adding an EtherCAT device

See TwinCAT automation software documentation.

5.6.2 Adding a EP1908

An EP1908-0002 is added in exactly the same way as any other Beckhoff EtherCAT Box. In the list open the item *Safety Terminals* and select the EP1908-0002.

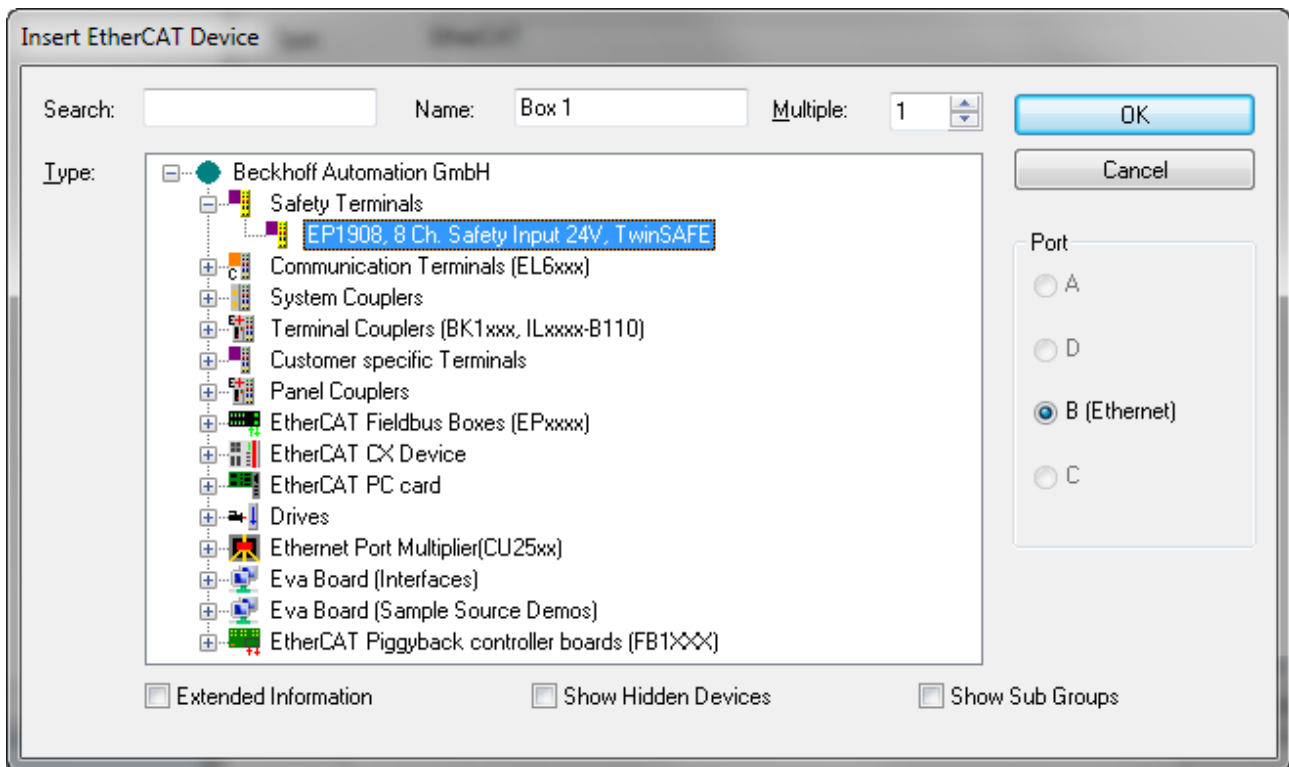


Fig. 22: TwinCAT - Adding a EP1908

5.6.3 Entering a TwinSAFE address and parameters in the System Manager

The TwinSAFE address set at the rotary switch must be entered under the tab *Safe Parameters (FSoE Address)* entry) below the EP1908-0002. All other parameters can also be set there. They can also be found under the respective TwinSAFE connection on the tab *Safe Parameters*.

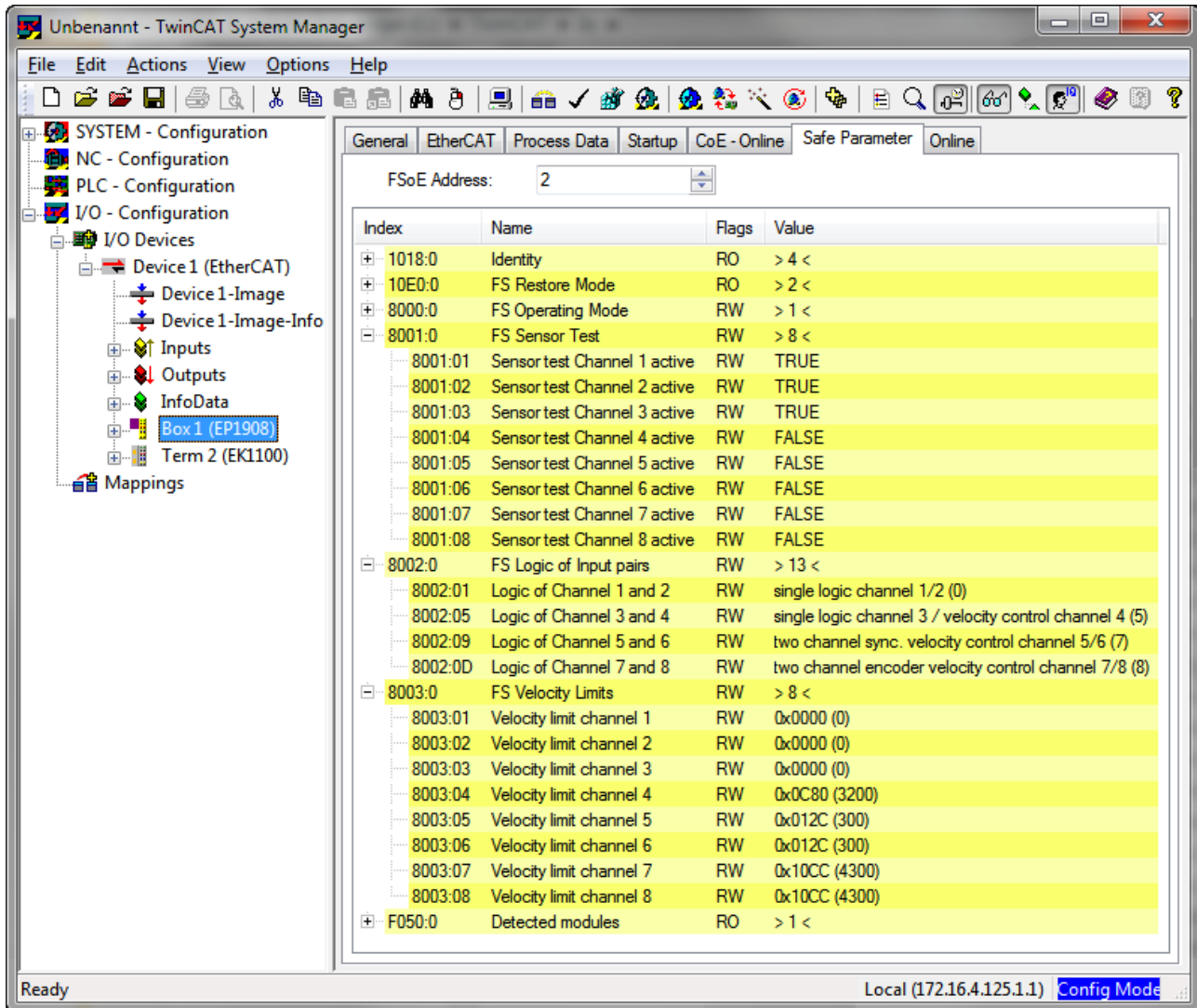


Fig. 23: Safe Parameter tab

The connection-specific parameters are set in the respective TwinSAFE connection on the *Connection* tab.

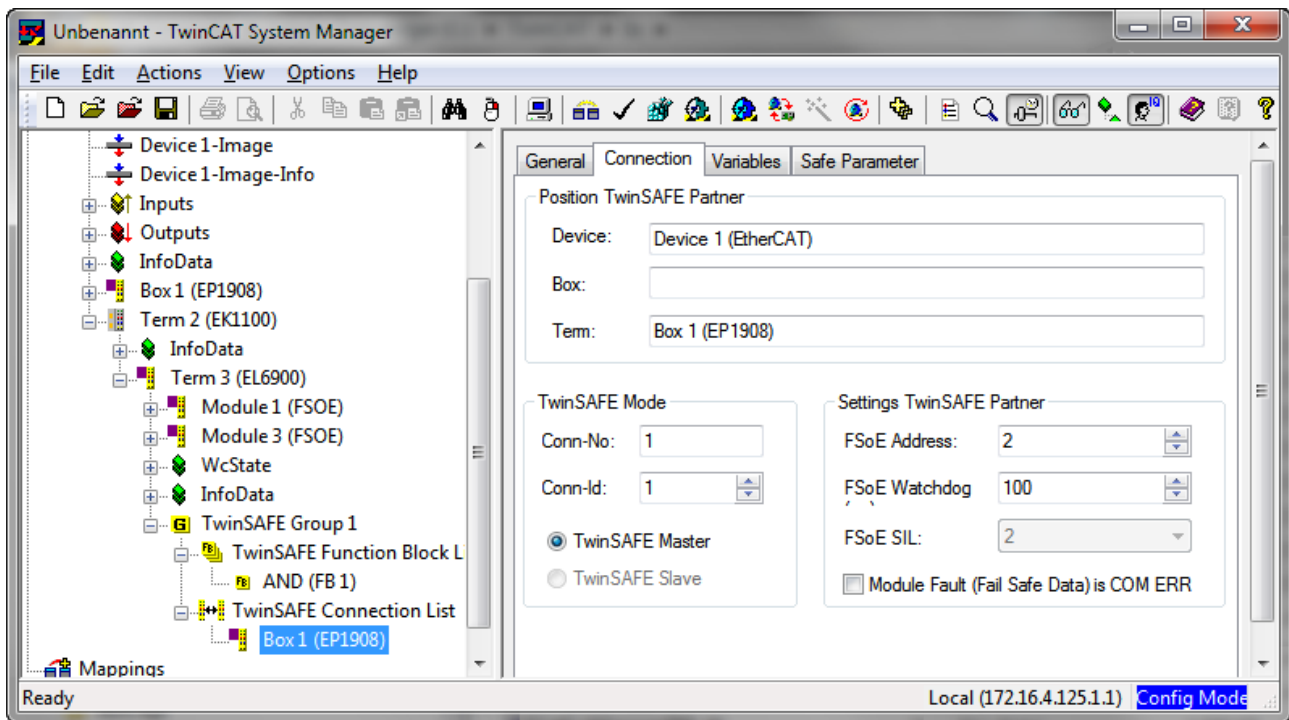


Fig. 24: Connection tab

Overview of the TwinSAFE parameters

Parameter name	Meaning	Values
FSOE_Address	Address of the rotary switch or the setting in the EP1908	1 to 4095
Operating Mode	Digital	Digital
Sensor test channel 1 active	The clock signal of channel 1 (pin 1) is checked at the channel 1 input (pin 2).	TRUE / FALSE
Sensor test channel 2 active	The clock signal of channel 2 (pin 3) is checked at the channel 2 input (pin 4).	TRUE / FALSE
Sensor test channel 3 active	The clock signal of channel 3 (pin 1) is checked at the channel 3 input (pin 2).	TRUE / FALSE
Sensor test channel 4 active	The clock signal of channel 4 (pin 3) is checked at the channel 4 input (pin 4).	TRUE / FALSE
Sensor test channel 5 active	The clock signal of channel 5 (pin 1) is checked at the channel 5 input (pin 2).	TRUE / FALSE
Sensor test channel 6 active	The clock signal of channel 6 (pin 3) is checked at the channel 6 input (pin 4).	TRUE / FALSE
Sensor test channel 7 active	The clock signal of channel 7 (pin 1) is checked at the channel 7 input (pin 2).	TRUE / FALSE
Sensor test channel 8 active	The clock signal of channel 8 (pin 3) is checked at the channel 8 input (pin 4).	TRUE / FALSE
Logic channel 1 and 2	Logic of channels 1 and 2	see operating modes table
Logic channel 3 and 4	Logic of channels 3 and 4	see operating modes table
Logic channel 5 and 6	Logic of channels 5 and 6	see operating modes table
Logic channel 7 and 8	Logic of channels 7 and 8	see operating modes table
Velocity limit channel 1	Upper frequency limit for channel 1	Frequency in 1/10 Hz
Velocity limit channel 2	Upper frequency limit for channel 2	Frequency in 1/10 Hz
Velocity limit channel 3	Upper frequency limit for channel 3	Frequency in 1/10 Hz
Velocity limit channel 4	Upper frequency limit for channel 4	Frequency in 1/10 Hz
Velocity limit channel 5	Upper frequency limit for channel 5	Frequency in 1/10 Hz
Velocity limit channel 6	Upper frequency limit for channel 6	Frequency in 1/10 Hz
Velocity limit channel 7	Upper frequency limit for channel 7	Frequency in 1/10 Hz
Velocity limit channel 8	Upper frequency limit for channel 8	Frequency in 1/10 Hz
Store Code	This parameter is required for the TwinSAFE Restore Mode	0x0000
Project CRC	This parameter is required for the TwinSAFE Restore Mode	0x0000
Identity	internal use (read only)	

Parameter name	Meaning	Values
Detected Modules	internal use (read only)	

5.6.3.1 EP1908-0002 configuration for light barriers, light grids, light curtains, etc.

The EP1908-0002 also supports direct connection of contact-free protective devices with two self-testing outputs such as light barriers, light grids, light curtains, laser scanners, etc.

⚠ CAUTION

Sensors with self-testing outputs

Only sensors with self-testing outputs and a maximum sensor self-test duration of 350 μ s may be connected to the EP1908-0002.

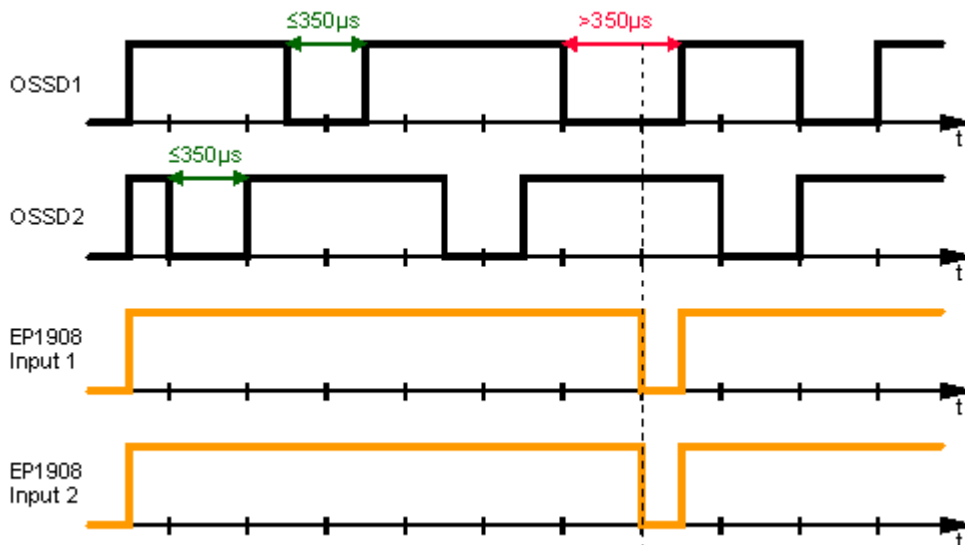


Fig. 25: Maximum permissible sensor self-test duration

Parameter

To connect these sensors please set the following parameters for the EP1908-0002 in the TwinCAT System Manager:

- Connect the two sensor signals either to channels 1 & 2, 3 & 4 and 5 & 6 or channels 7 & 8 and activate *asynchronous repetition OSSD* or *any pulse repetition* for the two inputs used under parameter *Logic for channel x and y*. The difference between these settings is that with *any pulse repetition* simultaneous tests of the OSSD signals up to 350 μ s are allowed.
- For the two inputs used set the sensor test for the EL1908-0002 to *false*.

5.6.3.2 EP1908-0002 configuration for safety switching mats

The EP1908-0002 also supports direct connection of safety mats that operate based on the cross-circuit principle.

Parameter

To connect these safety mats please set the following parameters for the EP1908-0002 in the TwinCAT System Manager:

- Connect the two sensor signals either to channels 1 & 2, 3 & 4 and 5 & 6 or channels 7 & 8 and activate the entry *short cut channel x/y is no module fault* for the two inputs used under parameter *Logic for channel x and y*.

5.6.3.3 Configuration of the EP1908-0002 for mode Velocity Control Channel x

The TwinSAFE EtherCAT Box also supports direct connection of initiators and encoders for speed measurement or frequency (24 V_{DC}).

If mode *Velocity Control Channel x* is set, a frequency is determined from two consecutive falling edges of the respective input signal. This mode can be set for each channel individually.

If the current frequency is below the set limit frequency, the corresponding input channel returns a logical 1. If the frequency is above the set limit frequency, the corresponding channel returns a logical 0.

The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.

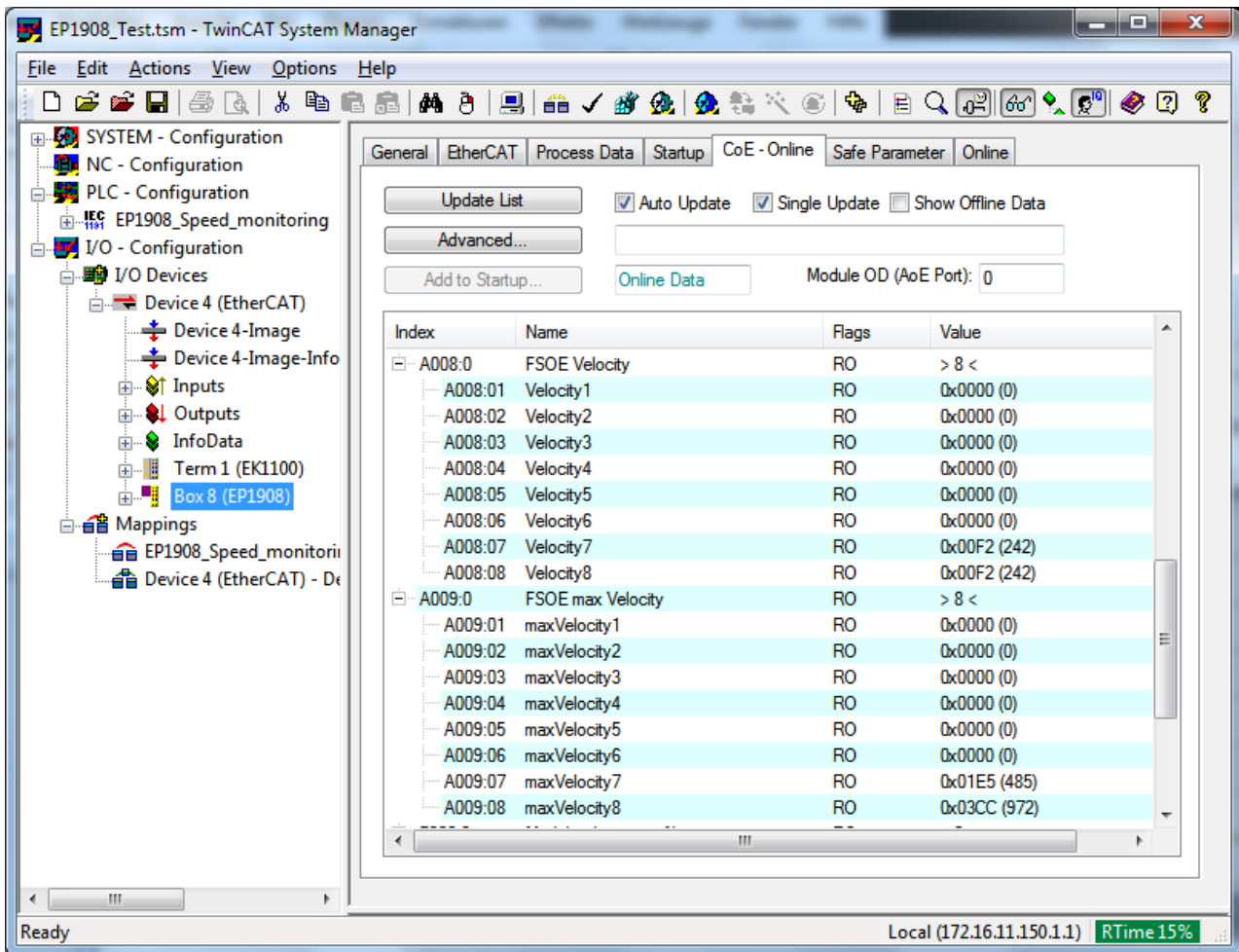
Parameter

- Connect the signals of the sensors used to the respective channel(s).
- Switch off the sensor test for the inputs used (*Sensor test Channel x active* = FALSE)
- Set the parameter *Logic of Channel x and y* to
 - *velocity control channel x / single logic channel y* or
 - *single logic channel x / velocity control channel y* or
 - *velocity control channel x/y*, depending on which channel(s) of the input pair is to be used for this mode.
- Set the parameter *Velocity limit channel x* of the used channel to the required value. The entered value has the unit 0.1 Hz.



Example of the signal curve of the input signal in the operating mode Velocity Control Channel x

Read the corresponding current frequencies via CoE Online (0xA008:01 to 0xA008:08).



Frequencies read out via CoE-Online

5.6.3.4 Configuration of the EP1908 for mode Two Channel Sync Velocity Control

The TwinSAFE EtherCAT Box also supports direct connection of initiators and encoders for speed measurement or frequency ($24 V_{DC}$).

The set mode *Two Channel SyncVelocity Control Channel x/y* determines a frequency from the signals of an input pair of the EP1908-0002, whereby one input signal always has to be set to logical 1. The frequencies of the two input signals must be the same.

If the current frequency is below the limit frequency set for both channels (*Velocity limit channel x/y*), the corresponding input pair returns a logical 1. If the frequency is above the set limit frequency, the corresponding input pair returns a logical 0. The limit frequencies must be the same.

The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.

Parameter

- Connect the signals of the used sensors to the input pairs
 - 1 and 2,
 - 3 and 4,
 - 5 and 6 or
 - 7 and 8

- Switch off the sensor test for the inputs used (*Sensor test Channel x active* = FALSE)
- Set the parameter *Logic of Channel x and y* to *Two Channel SyncVelocity Control Channel x/y*
- Set the parameters *Velocity limit channel x* and *Velocity limit channel y* of the used channels to the required value. The entered value has the unit 1/10 Hz.

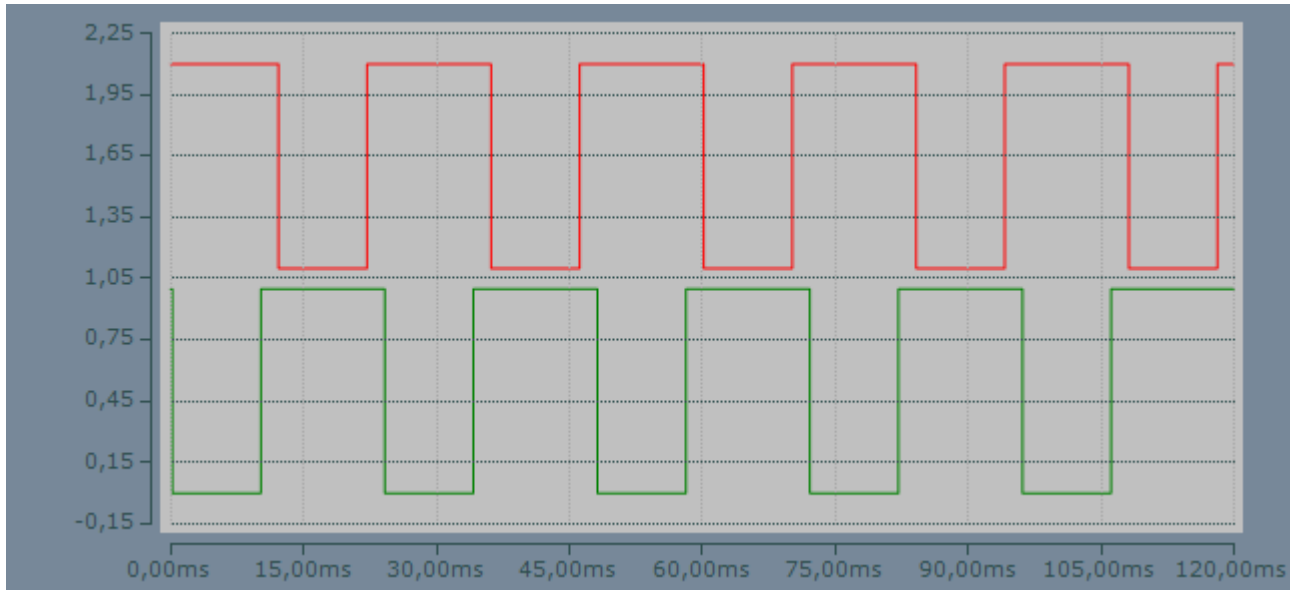


Fig. 26: Example of the signal curve of the input signal in the operating mode Two Channel Sync Velocity Control

5.6.3.5 Configuration of the EP1908 for mode Two Channel Encoder Velocity Control

The TwinSAFE EtherCAT Box also supports direct connection of initiators and encoders for speed measurement or frequency (24 V_{DC}).

The set mode *Two Channel Encoder Velocity Control Channel x/y* is used to determine a frequency from the signals of an input pair of the EP1908-0002. The upper limit frequencies are specified separately, but should be the same. The same frequencies have to be supplied, whereby all states are permitted that may occur at the encoder interface.

If the current frequency is below the limit frequency set for both channels (*Velocity limit channel x/y*), the corresponding input pair returns a logical 1. If the frequency is above the set limit frequency, the corresponding input pair returns a logical 0.

The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.

Parameter

- Connect the signals of the used sensors/encoders to the input pairs
 - 1 and 2,
 - 3 and 4,
 - 5 and 6 or
 - 7 and 8
- Switch off the sensor test for the inputs used (*Sensor test Channel x active* = FALSE)
- Set the parameter *Logic of Channel x and y* to *Two Channel SyncVelocity Control Channel x/y*

- Set the parameters *Velocity limit channel x* and *Velocity limit channel y* of the used channels to the required value. The entered value has the unit 1/10 Hz.



Fig. 27: Example of the signal curve of the input signal in the operating mode Two Channel Encoder Velocity Control

5.6.3.6 Configuration of the EP1908-0002 for mode Two Channel Async Velocity Control

The TwinSAFE EtherCAT Box also supports direct connection of initiators and encoders for speed measurement or frequency (24 V_{DC}).

The set mode *Two Channel Async Velocity Control Channel x/y* is used to determine a frequency from the signals of an input pair of the EP1908-0002. In this mode is only the compliance with the limits for the two channels is monitored. The upper limit frequencies are specified separately.

The two channels return logical 1 if both frequencies are below the frequency set under *Velocity limit channel x/y*.

If the current frequency of the two channels is below the set limit frequency (*Velocity limit channel x/y*) for the respective channel, the corresponding input pair returns a logical 1. If the current frequency of a channel is above the set limit frequency for this channel, the corresponding input pair returns a logical 0.

The minimum supported frequency is 2 Hz. Values below this are shown as 0. The maximum supported frequency is 500 Hz. Values above this result in a diagnostic messages of the EP1908-0002. This message can be reset through a rising edge of the safe output signal ErrAck of the EP1908-0002.

Parameter

- Connect the signals of the used sensors to the input pairs
 - 1 and 2,
 - 3 and 4,
 - 5 and 6 or
 - 7 and 8
- Switch off the sensor test for the inputs used (*Sensor test Channel x active* = FALSE)
- Set the parameter *Logic of Channel x and y* to *Two Channel Async Velocity Control Channel x/y*
- Set the parameters *Velocity limit channel x* and *Velocity limit channel y* of the used channels to the required value. The entered value has the unit 1/10 Hz.

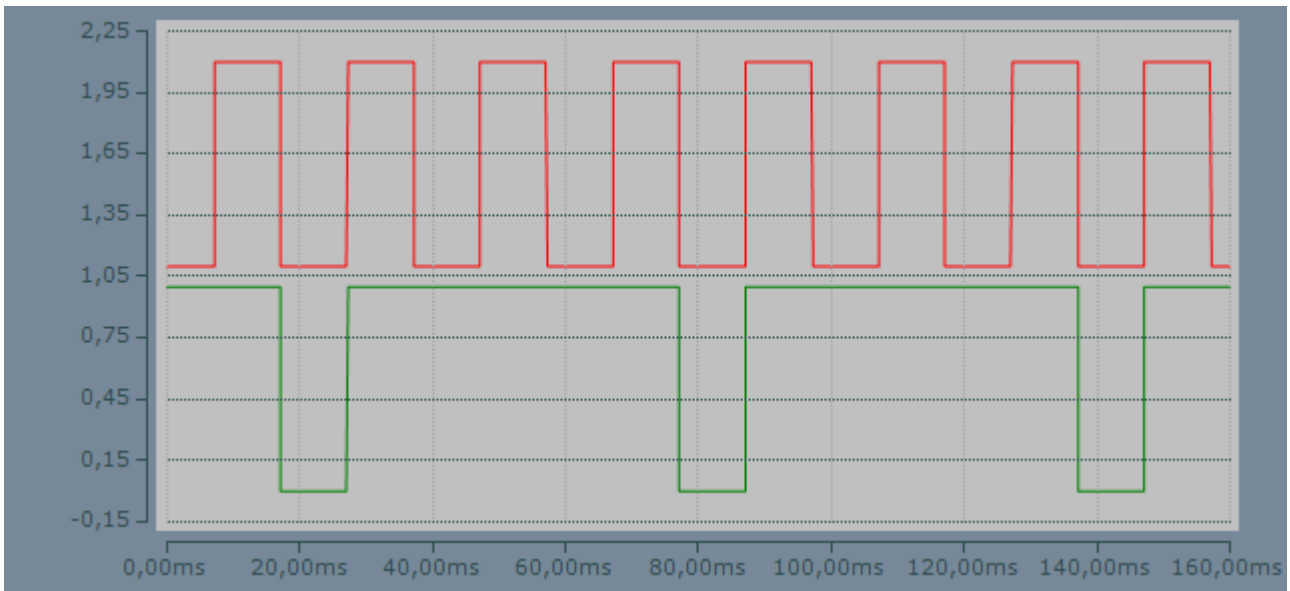


Fig. 28: Example of the signal curve of the input signal in the operating mode Two Channel Async Velocity Control

6 Service life

The TwinSAFE EtherCAT Boxes have a service life of 20 years.

Due to the high diagnostic coverage within the lifecycle no special proof tests are required.

Date code

The TwinSAFE EtherCAT Boxes have a date code (D:), which is structured as follows:

Date code: WW YY SW HW

Legend:	Sample: Date code 45 12 05 00
WW: Calendar week of manufacture	Calendar week: 45
YY: Year of manufacture	Year: 2012
SW: Software version	Software version: 01
HW: Hardware version	Hardware version: 00

Serial number (S.No.)

In addition, the TwinSAFE EtherCAT Boxes have a unique serial number (S.No.).

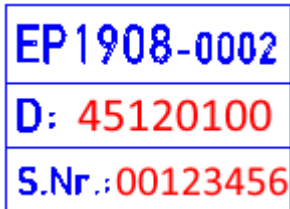


Fig. 29: Unique serial number (S.No.) of a TwinSAFE EtherCAT Box

7 Maintenance and cleaning

● Cleaning by the manufacturer only



Do not operate the TwinSAFE component if it is impermissibly dirty according to protection class IP20. Send impermissibly dirty TwinSAFE components to the manufacturer for cleaning.

TwinSAFE components are basically maintenance-free.

8 Decommissioning

8.1 Disposal

NOTE

Correct disposal

Observe the applicable national laws and guidelines for disposal.
Incorrect disposal may result in environmental damage.

Remove the TwinSAFE component for disposal.

Depending on your application and the products used, make sure that the respective components are disposed of properly:

Cast iron and metal

Hand over cast iron and metal parts to scrap metal recycling.

Cardboard, wood and polystyrene

Dispose of packaging materials made of cardboard, wood or Styrofoam in accordance with regulations.

Plastic and hard plastic

You can recycle parts made of plastic and hard plastic via the waste management center or reuse them in accordance with the component regulations and markings.

Oils and lubricants

Dispose of oils and lubricants in separate containers. Hand over containers to the waste oil collection point.

Batteries and accumulators

Batteries and accumulators may also be marked with the crossed-out wheeled garbage can symbol. You must separate these components from waste. You are legally obliged to return used batteries and accumulators within the EU. Outside the validity of the EU Directive 2006/66/EC, observe the respective regulations.

8.1.1 Returning to the vendor

In accordance with the WEEE-2012/19/EU directives, you can return used devices and accessories for professional disposal. The transport costs are borne by the sender.

Send the used devices with the note "For disposal" to:

Beckhoff Automation GmbH & Co. KG
Gebäude „Service“
Stahlstraße 31
D-33415 Verl

In addition, you have the option to contact a local certified specialist company for the disposal of used electrical and electronic appliances. Dispose of the old components in accordance with the regulations applicable in your country.

9 Appendix

9.1 Protection classes according to IP code

The levels of protection are defined and divided into different classes in the IEC 60529 standard (DIN EN 60529). The designation follows the scheme below.

1st digit: Protection against ingress of dust and access to hazardous parts

1 st digit	Meaning
0	Non-protected
1	Protection against access to hazardous parts with back of hand. Protection against ingress of solid foreign objects = 50 mm diameter
2	Protection against access to hazardous parts with a finger. Protection against ingress of solid foreign objects = 12.5 mm diameter
3	Protection against access to hazardous parts with a tool. Protection against ingress of solid foreign objects = 2.5 mm diameter
4	Protection against access to hazardous parts with a wire. Protection against ingress of solid foreign objects = 1 mm diameter
5	Protection against access to hazardous parts with a wire. Protection against ingress of dust. Ingress of dust is not prevented completely, although the quantity of dust able to penetrate is limited to such an extent that the proper function of the device and safety are not impaired
6	Protection against access to hazardous parts with a wire. Dust-proof. No ingress of dust

2nd digit: Protection against ingress of water*

2 nd digit	Meaning
0	Non-protected.
1	Protection against dripping water.
2	Protection against dripping water when housing tilted up to 15°.
3	Protection against spraying. Water sprayed at an angle of up to 60° from vertical must not have any adverse effect.
4	Protection against splashing. Water splashing against the housing from any direction must not have any adverse effects.
5	Protection against jetting.
6	Protection against powerful jetting.
7	Protection against the effects of temporary immersion. The quantity of water being able to penetrate if the housing is submerged in water for 30 minutes at a depth of 1 m must not have any adverse effects.

*) These protection classes only define protection against water, not against other liquids.

9.2 Volatility

If there are requirements concerning the volatility of products in your application, for example of the U.S. Department of Defense or similar authorities or security organizations, the following process applies:

The product has both volatile and non-volatile components. Volatile components lose their data immediately after removing power. Non-volatile components keep the data even after loss of power.

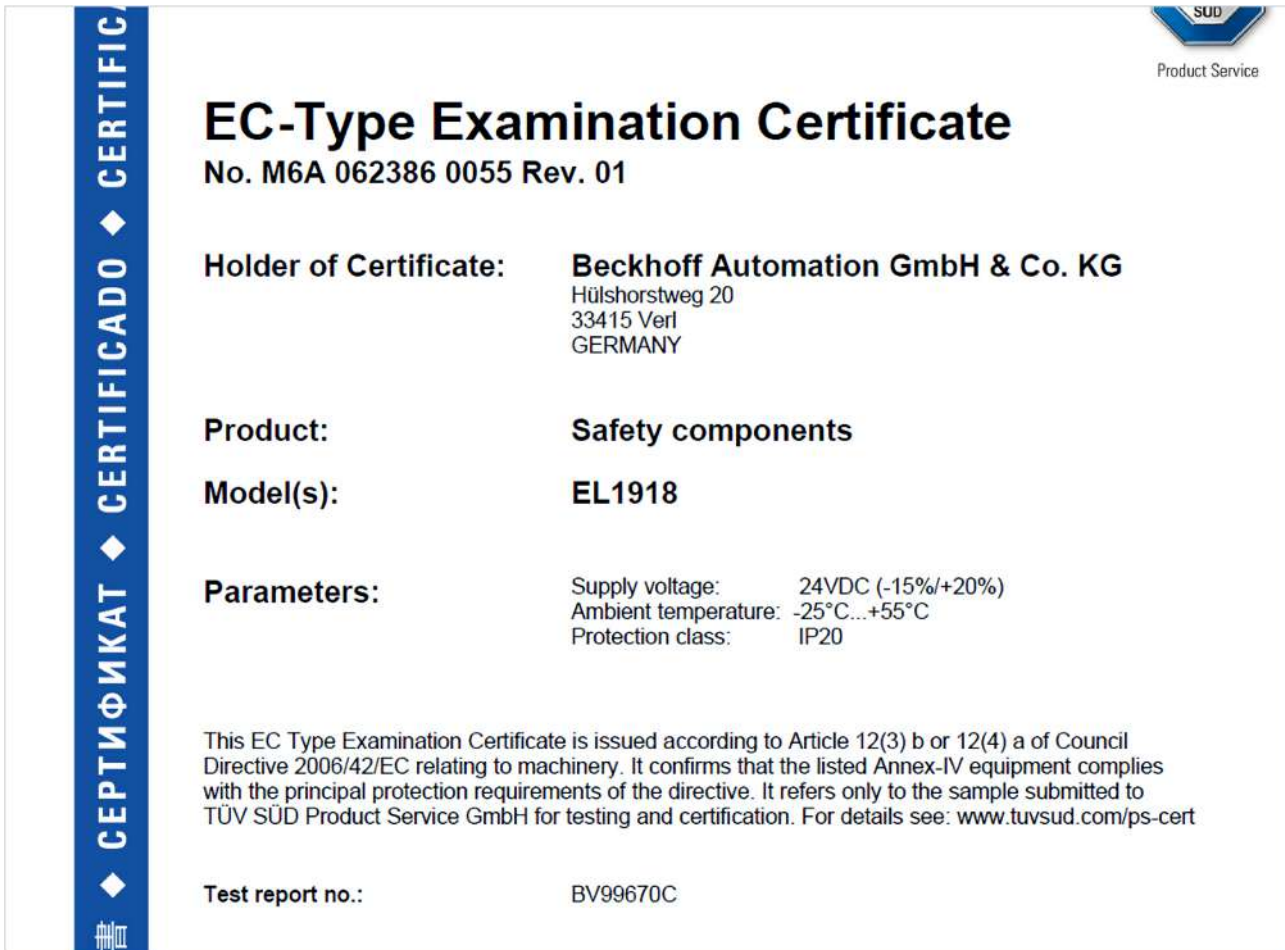
If there is customer specific data saved on the product, it cannot be ensured that this data might not be restored through for example forensic measures, even after the data is deleted through the provided tool chain. If this data is confidential, the scrapping of the product after usage is recommended to protect this data.

9.3 Focus of certificates

The most decisive document for certified components of the TwinSAFE department is the EC type examination certificate. The document contains both the test coverage and the regarded component and component family.

The current certificates of all TwinSAFE components with the underlying standards and directives can be found at <https://www.beckhoff.com/en-en/support/download-finder/certificates-approvals/>.

If the document refers only to the first four figures of a product (ELxxxx), the certificate is valid for all available variants of the component (ELxxxx-abcd). This is applicable for all components like EtherCAT Terminals, EtherCAT Boxes, EtherCAT plug-in modules and Bus Terminals.



If you regard the example EL1918 in the picture, the certificate is valid for both the EL1918 and the available variant EL1918-2200.

9.4 Certificate


BECKHOFF New Automation Technology		Originalerklärung Original declaration
EG-Konformitätserklärung <i>EC Declaration of Conformity</i>		
Nummer: 2017041EP1908-1, Datum: 31.07.2017 <i>Number, Date</i>		
Hersteller <i>Manufacturer</i>	Beckhoff Automation GmbH & Co. KG Hülshorstweg 20, 33415 Verl, Germany	
erklärt, dass das Produkt <i>declares that the product</i>	TwinSAFE EP1908 TwinSAFE-EtherCAT-Box mit 8 fehlersicheren Eingängen <i>TwinSAFE EtherCAT Box with 8 fail-safe inputs</i>	
Sicherheitsbauteil nach EG-Richtlinie 2006/42/EG, Anhang IV <i>safety component according to EC directive 2006/42/EC, annex IV</i>		
den einschlägigen Bestimmungen der Maschinenrichtlinie 2006/42/EG entspricht. <i>complies with the relevant requirements of the machinery directive 2006/42/EC.</i>		
Angewandte Normen <i>Applied Standards</i>		
EN 62061:2005+A1:2013	Sicherheit von Maschinen – Funktionale Sicherheit sicherheitsbezogener elektrischer, elektronischer und programmierbarer elektronischer Steuerungssysteme <i>Safety of machinery – Functional safety of safety-related electrical, electronic and programmable electronic control systems</i>	
EN61131-2:2007	Speicherprogrammierbare Steuerungen - Teil 2: Betriebsmittelanforderungen und Prüfungen <i>Industrial-process control systems - Instruments with analogue inputs and two- or multi-state outputs - Part 2: Guidance for inspection and routine testing</i>	
EN 50581:2012	Technische Dokumentation zur Beurteilung von Elektro- und Elektronikgeräten hinsichtlich der Beschränkung gefährlicher Stoffe <i>Technical documentation for the assessment of electrical and electronic products with respect to the restriction of hazardous substances</i>	
EN ISO 13849-1:2015	Sicherheit von Maschinen – Sicherheitsbezogene Teile von Steuerungen <i>Safety of machinery – Safety-related parts of control systems</i>	
EN 61000-6-2:2011	Elektromagnetische Verträglichkeit (EMV) – Störfestigkeit für Industriebereiche <i>Electromagnetic compatibility (EMC) – Immunity for industrial environments</i>	
EN 61000-6-4:2011	Elektromagnetische Verträglichkeit (EMV) - Störaussendung für Industriebereiche <i>Electromagnetic compatibility (EMC) - Emission standard for industrial environments</i>	
Die Übereinstimmung eines Baumusters des bezeichneten Produkts mit der EG-Richtlinie wurde bescheinigt von <i>The accordance of a production sample of the designated product with the EC directive is certified by</i>		
Benannte Stelle <i>Notified body</i>	TÜV SÜD Product Service GmbH Ridlerstraße 65, 80339 München, Germany	
EG-Baumusterprüfbescheinigung <i>EC-type examination certificate</i>	M6A 17 07 62386 041, 28.07.2017	
Verantwortlich für die Zusammenstellung der technischen Unterlagen <i>Responsible for the compilation of technical documentation</i>		
Bevollmächtigter <i>Authorised person</i>	Beckhoff Automation GmbH & Co. KG Hülshorstweg 20, 33415 Verl, Germany	
Verl, 31.07.2017		
Dipl.-Phys. Hans Beckhoff		
	Geschäftsführer Beckhoff Automation GmbH & Co. KG <i>CEO Beckhoff Automation GmbH & Co. KG</i>	

Fig. 30: EP1908 EC Declaration of Conformity

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More Information:
www.beckhoff.com/EP1908

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