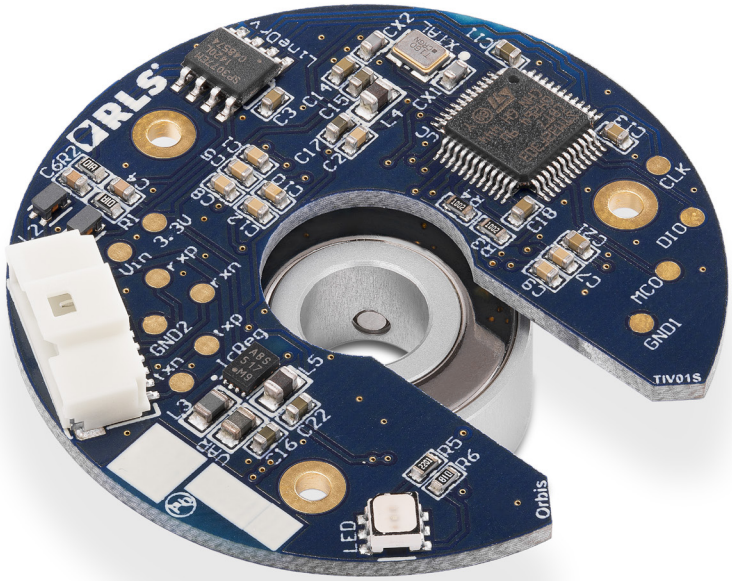
Preliminary product information
OrbisP01_07
Issue 7, 15th December 2016

Orbis™ true absolute rotary encoder



Orbis™ is a true absolute rotary encoder suitable for applications where a typical OnAxis encoder cannot be mounted at the end of the rotating shaft due to space constraints.

The encoder comprises a diametrically magnetized permanent ring magnet and a printed circuit board. Geometric arrangement of 8 RLS' proprietary Hall sensors on a PCB enables generation of one period of sine and cosine signals per mechanical magnet revolution. Moreover, it also enables cancellation of third harmonic component that becomes non-negligible at low magnet ride height.

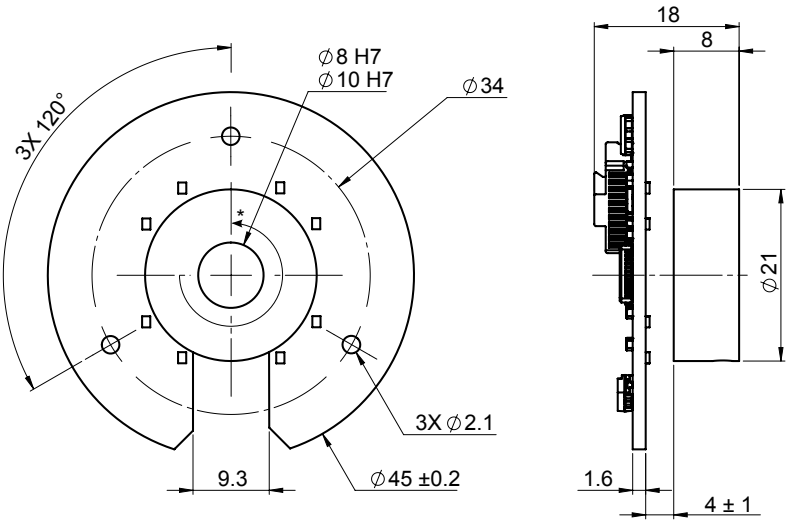
An adaptive filtering function ensures high resolution at low rotation speeds and low angle phase delay at high rotational speeds. Orbis™ also features an additional built-in self-calibration algorithm that improves encoder's accuracy after installation.

Orbis™ through-hole measuring principle allows customisation with various board and magnet sizes to suit your application.

- **True absolute encoder**
- **14 bit resolution**
- **Multi-turn counter option**
- **8 proprietary Hall sensor ASICs**
- **Through-hole design enables its mounting anywhere along the shaft**
- **Self-calibration after assembly**
- **Buit-in self-diagnostics**
- **Status LED**
- **SPI, SSI, BiSS-C, PWM, and asynchronous serial communication**
- **Wide installation tolerances**

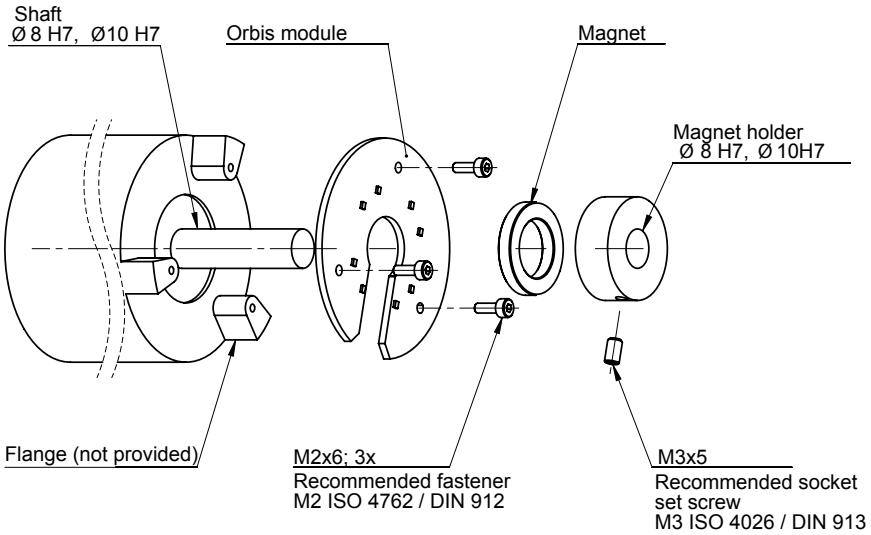
Dimensions

Dimensions and tolerances in mm.



*CCW - positive measuring direction

Installation drawing



Technical specifications

System data		
Reading type	Axial reading	
Resolution	14 bit	
Maximum speed	10,000 rpm	
Accuracy	±0.2° (optimal installation)	
Accuracy thermal drift	±0.01°/°C	
Repeatability	±2 LSB	
Electrical data		
Supply voltage	4 V to 6 V	
Set-up time	10 ms	
Power consumption	65 mA typically, 70 mA max.	
Output load	PWM, SPI	Max. ±20 mA at 3.3 V
	RS422	120 mA short term, 60 mA limited
ESD protection	HBM, Class 2, max. ±2 kV (as per Mil-Std 883 Method 3015.7)	
Mechanical data		
Available magnet size	OD: 19 mm, ID: 12 mm, thickness: 3 mm	
Available adapter sizes (inner diameter)	6 mm, 8 mm, 10 mm	
Encoder outer diameter	45 mm	
Encoder hole diameter	13 mm	
Mass	Module: SSI, BiSS, Async. ser.: 5.6 g SPI, PWM: 5.5 g	
	Magnet holders: 10 mm: 4.4 g 8 mm: 5.0 g 6 mm: 5.5 g	
	Magnet: 3.8 g	
Environmental data		
Operating temperature	0 °C to +85 °C	

Status indicator LED

The LED provides visual feedback of signal strength, error condition and is used for set-up and diagnostic use.

LED	Status
Green	Normal operation; position data is valid.
Orange	Warning; position is valid, but some operating conditions are close to limits.
Red	Error; position data is not valid.
No light	No power supply.

Multi-turn counter

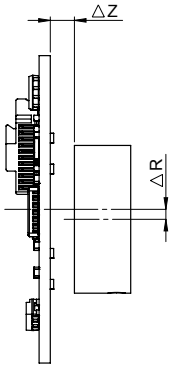
Multi-turn counter is available as an option on the following communication interfaces: BiSS, SSI, SPI and Asynchronous serial communication. Multi-turn counter is 16 bit (0 to 65535 counts). Counting is available only when the encoder is powered on, but the counter state is stored in a non-volatile memory at power off and is restored at power up.

Installation instructions

Installation tolerances

Precise magnet and board positioning is key to achieving good overall accuracy.

Axial (ΔZ) displacement (ride height)	4 mm nominal ±1 mm
Radial (ΔR) displacement	0.3 mm

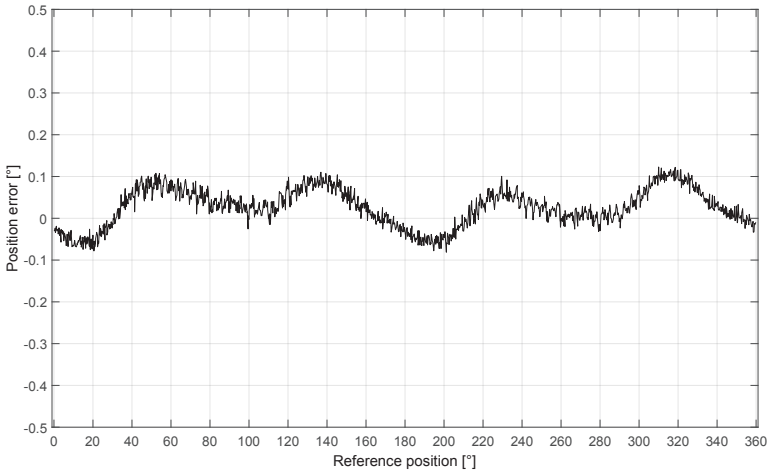


Axial position adjustment (ride height)

The nominal gap between the permanent magnet and the printed circuit board (opposite side of connector) is 4 mm ±1 mm. Any non-magnetic tool with 4 mm thickness can be used to check the correct ride height setting mechanically.
The integrated LED can be used as a coarse indicator. When the correct ride height is achieved, the LED glows green and does not change colour when the magnet rotates.

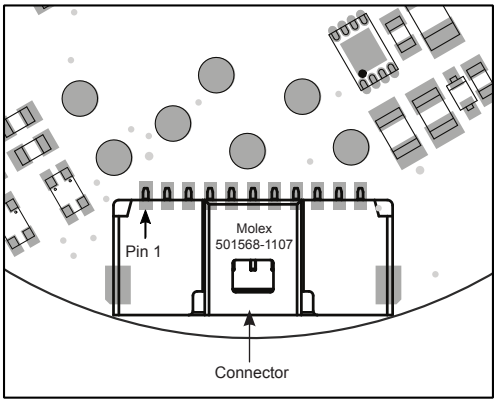
A typical accuracy plot after good installation of Orbis encoder is shown in the graph on the right.

For highest accuracy options contact RLS.

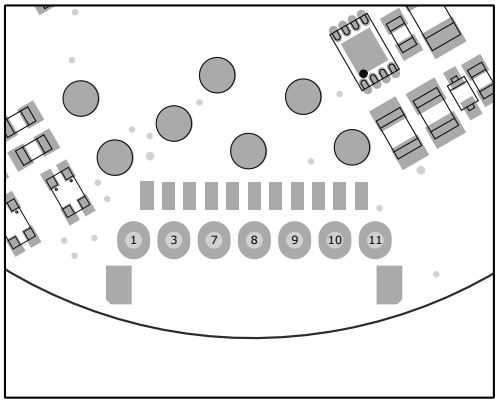


Electrical connections

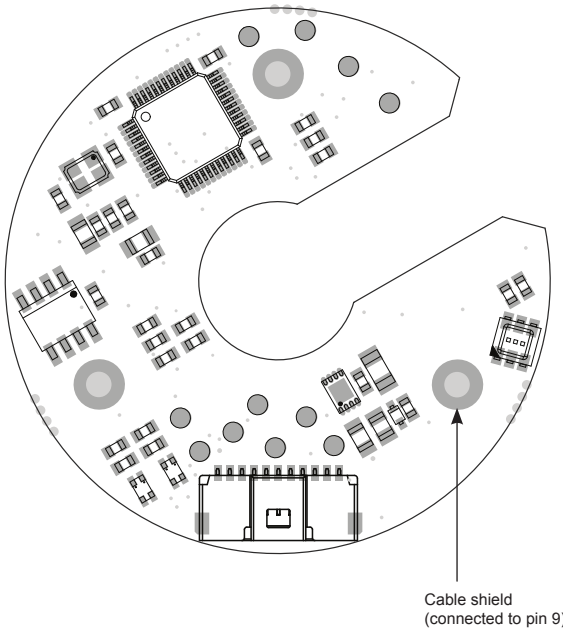
Pin	Wire Colour	Asynchronous serial	PWM	SSI	BiSS-C	SPI
1	Brown	5 V supply	5 V supply	5 V supply	5 V supply	5 V supply
2						
3	White	0 V (GND)	0 V (GND)	0 V (GND)	0 V (GND)	0 V (GND)
4						
5	Pink	-	-	-	-	-
6	Grey	-	-	-	-	-
7	Red	RX data in+	Status	Clock+	MA+	SCK
8	Blue	RX data in–	-	Clock–	MA–	$\overline{CS}$
9	Cable Shield	Cable Shield	Cable Shield	Cable Shield	Cable Shield	Cable Shield
10	Green	TX data out+	PWM Out	Data+	SLO+	MISO
11	Yellow	TX data out–	-	Data–	SLO–	MOSI



Option with Molex connector



Option without connector

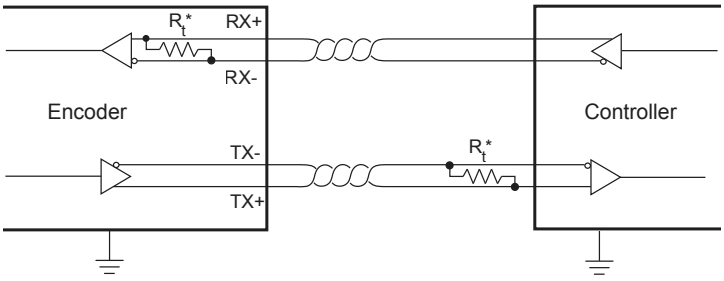


Communication interfaces

Asynchronous serial communication interface

Asynchronous serial communication is supported by a universal asynchronous receiver/transmitter commonly known as UART. It comprises two unidirectional communications channels, forming a full-duplex bidirectional data link. Every channel consists of a two wire differential twisted-pair connection conforming to the RS422 signalling standard.

Electrical connection



Line signals	
RX+	RX data in +
RX–	RX data in –
TX+	TX data out +
TX–	TX data out –

* The Command and Data signals are 5 V RS422 compatible differential pairs with RC termination inside the readhead.

Communication parameters

Character length	8 bits
Parity	None
Stop bits	1
Flow control	None

Communication speed is set with the *Communication interface variant* in the part number:

Communication interface variant	A	B	C	D	E	F
Value [kbps]	115.2	128	230.4	256	500	1000

Command set

Command "1" (0x31) – position request	
Response	1 byte ASCII "1" 2 bytes (4 for multi-turn) hex – see Encoder position data structure
Command "d" (0x64) – position request + detailed status	
Response	1 byte ASCII "d" 2 bytes (4 for multi-turn) hex – see Encoder position data structure 1 byte hex – see Detailed status data structure
Command "s" (0x73) – position request + speed	
Response	1 byte ASCII "s" 2 bytes (4 for multi-turn) hex – see Encoder position data structure 2 bytes hex – speed (in revolutions per second multiplied by 10)
Command "t" (0x74) – position request + temperature	
Response	1 byte ASCII "t" 2 bytes (4 for multi-turn) hex – see Encoder position data structure 2 bytes hex – temperature (temperature of the readhead in °C multiplied by 10)
Command "v" (0x76) – serial number	
Response	1 byte ASCII "v" 6 bytes ASCII – serial number

Encoder position data structure

Encoder position		
	b31 : b16	Multi-turn counter (optional) - Left aligned, MSB first.
	b15 : b2	Encoder position – Left aligned, MSB first.
General status		
	b1	Error - If low, the position data is not valid. The last valid position is sent out.
	b0	Warning - If low, the position data is valid, but some operating conditions are close to limits.
	Error and Warning bits can be set at the same time, in this case the Error bit has priority. The colour of the LED on the readhead housing indicates the value of the General status bits. LED is flashing (duty cycle 50 %, frequency 2.5 Hz), when the encoder is in idle state. If the controller requests the data every 200 ms or more often, the duty cycle of the LED is 100 % (always on).	
Detailed status		
	b7	Signal amplitude too high. The readhead is too close to the magnet or an external magnetic field is present.
	b6	Signal amplitude low. The distance between the readhead and the ring is too large.
	b5	The readhead temperature is out of specified range.
	b4	Speed too high.
	b3 : b0	Reserved.

PWM - Pulse width modulation interface

The PWM interface transmits the information about the absolute angle position over the pulse width modulated PWM Out signal. An additional digital Status signal indicates the encoder's error condition.

Electrical connection
The Status and PWM Out signals are 3.3 V TTL compatible. These signals have weak ESD protection. Handle with care. Maximum current sourced from or sunk into signal lines should not exceed 20 mA.

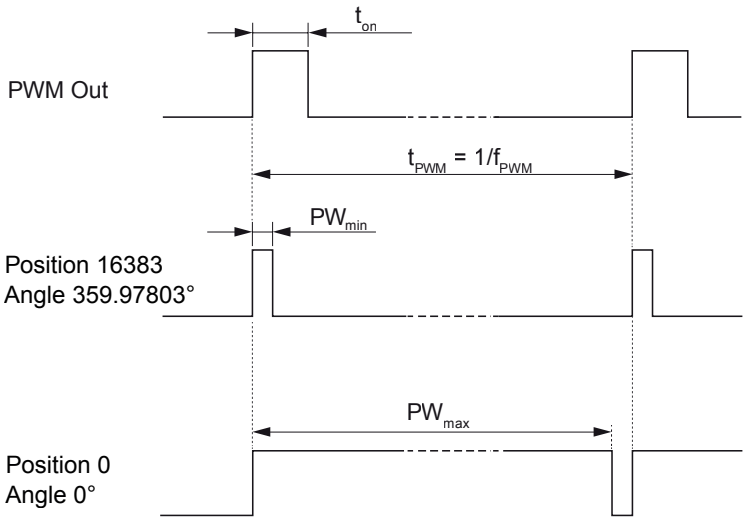
Status signal
The Status signal indicates the current status of the encoder. The Status signal is high for normal operation and valid position information. The low state of the Status signal indicates an error state of the encoder which can be caused by:

- Operation outside the installation tolerances
- Sensor malfunction
- System error
- No power supply

When the Status signal is low, the PWM Out signal is low and no pulses are output.
The encoder position is latched on the rising edge of the PWM Out signal. The Status signal should also be checked at the rising edge of the PWM Out signal. If the Status signal changes during the PWM period, it does not affect the currently transmitted position information.

PWM Out signal
The PWM Out is a pulse width modulated output with 14-bit resolution whose duty cycle is proportional to the measured position. The change of the pulse width by PW_{min} corresponds to a change in position by one count (change in angle for 360° / 65536 ≈ 0.00549°).

PWM Out signal timing diagram



Communication parameters
Communication interface variant in the part number defines the PWM frequency and all other dependent parameters.

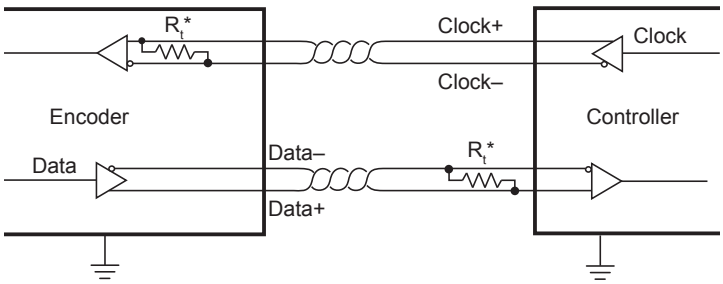
		Communication interface variant				
Parameter	**Symbol**	**A**	**D**	**E**	**Unit**	**Note**
PWM frequency	f_{PWM}	122.07	549.32	1098.63	Hz	
Signal period	t_{PWM}	8192	1820.44	910.22	µs	
Minimum pulse width	PW_{min}	0.5	0.111	0.0556	µs	Position 0 (Angle 0°)
Maximum pulse width	PW_{max}	8191.5	1820.33	910.17	µs	Position 16383
Min. counter frequency	f_{CNTR}	2	9	18	MHz	
Resolution		14	14	14	Bit	

$$\textit{Position}\ [\text{counts}] = \frac{(t_{on} - PW_{min}) \times 16383}{PW_{max} - PW_{min}}$$

SSI - Synchronous serial interface

The encoder position, in 14 bit natural binary code, and the encoder status are available through the SSI protocol. The position data is left aligned. After the position data there are two general status bits followed by the detailed status information.

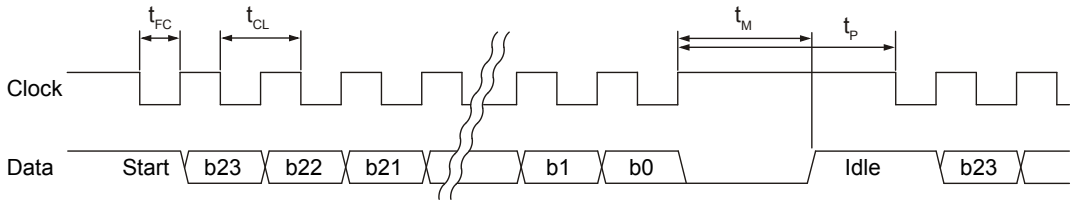
Electrical connection



Line signals	
Clock+	Clock non-inverted signal
Clock–	Clock inverted signal
Data+	Data non-inverted signal
Data–	Data inverted signal

* The Clock and Data lines are 5 V RS422 compatible differential pairs. The termination resistor on the Clock line is integrated inside the encoder. On the controller's side of Data line it should be added by the user or enabled in the controller.

SSI timing diagram (single-turn)



The controller requests the position and status data of the encoder by sending a pulse train to the Clock input. The Clock signal always starts from high. The first falling edge of the Clock latches the last position data available and on the first rising edge of the Clock the most significant bit (MSB) of the position is transmitted to the Data output. The Data output should then be read on the following falling or rising edge. On subsequent rising edges of the Clock signal the next bits are transmitted.

After the transmission of the last bit the Data output goes to low. When the t_M time expires, the Data output goes high. The Clock signal must remain high for at least t_P before the next reading can take place.

While reading the data, the half of a Clock period t_{CL} must always be less than t_M. However, reading the encoder position can be terminated at any time by setting the Clock signal to high for the duration of t_M.

Communication parameters

Parameter	Symbol	Min	Typ	Max
Clock period	t_{CL}	2 µs (400 ns *)		15 µs
Clock frequency	f_{CL}	70 kHz		500 kHz (2.5 MHz *)
Delay first clock	t_{FC}	1.25 µs		
Transfer timeout	t_M		16 µs	
Pause time	t_P		20 µs	

* With *Delay First Clock* function of the controller.

Structure of data packet

Bit	b39 : b24	b23 : b10	b9 : b8	b7 : b0
Data length	16 bits	14 bits	2 bits	8 bits
Meaning	Multi-turn counter (optional)	Encoder position	General status	Detailed status

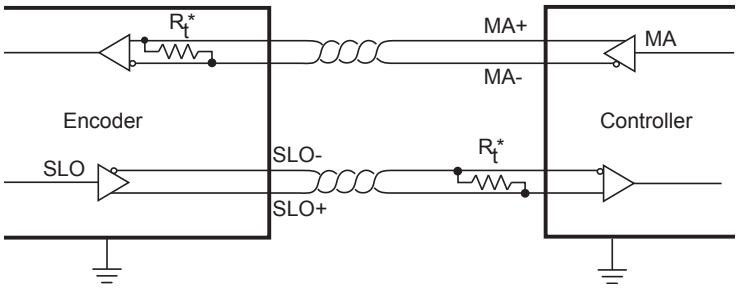
Encoder position	
b39 : b24	Multi-turn counter (optional) - Left aligned, MSB first.
b23 : b10	Encoder position – Left aligned, MSB first.
General status	
b9	Error - If set, the position data is not valid. The last valid position is sent out.
b8	Warning - If set, the position data is valid, but some operating conditions are close to limits.
Error and Warning bits can be set at the same time, in this case the Error bit has priority. The colour of the LED on the readhead housing indicates the value of the General status bits. LED is flashing (duty cycle 50 %, frequency 2.5 Hz), when the encoder is in idle state. If the controller requests the data every 200 ms or more often, the duty cycle of the LED is 100 % (always on).	
Detailed status	
b7	Signal amplitude too high. The readhead is too close to the magnet or an external magnetic field is present.
b6	Signal amplitude low. The distance between the readhead and the ring is too large.
b5	The readhead temperature is out of specified range.
b4	Speed too high.
b3 : b0	Reserved.

BiSS-C interface

The encoder position, in 14 bit natural binary code, and the encoder status are available through the BiSS-C protocol. The position data is left aligned. After the position data there are two status bits (active low) followed by CRC (inverted).

BiSS is implemented for point-to-point operation; multiple slaves are not supported.
Communication is unidirectional, the readhead is not user programmable, also custom parameters can not be stored into the readhead.

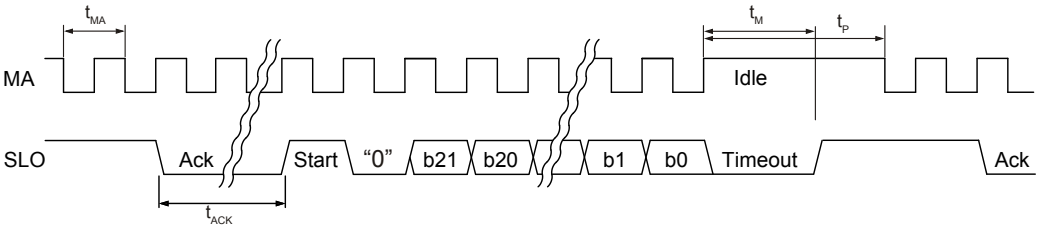
Electrical connection



Line signals	
MA+	Clock non-inverted signal
MA–	Clock inverted signal
SLO+	Data non-inverted signal
SLO–	Data inverted signal

* The MA and SLO lines are 5 V RS422 compatible differential pairs. The termination resistor on the MA line is integrated inside the encoder. On the controller's side of SLO line it should be added by the user or enabled in the controller.

BiSS-C timing diagram (single-turn)



MA is idle high. Communication is initiated with first falling edge.
The encoder responds by setting SLO low on the second rising edge on MA.
When the encoder is ready for the next request cycle it indicates this to the master by setting SLO high.
The absolute position and CRC data is in binary format, left aligned, MSB first.

Communication parameters

Parameter	Symbol	Min	Typ	Max
MA period	t_{MA}	200 ns		14 µs
MA frequency	f_{MA}	70 kHz		5 MHz
ACK length	t_{ACK}		5 bits	
Transfer timeout	t_M		14 µs	
Pause time	t_P		20 µs	

Structure of data packet

Bit	b37 : b22	b21 : b8	b7 : b6	b5 : b0
Data length	16 bits	14 bits	2 bits	6 bits
Meaning	Multi-turn counter (optional)	Encoder position	General status	CRC

Encoder position	
b37 : b22	Multi-turn counter (optional) - Left aligned, MSB first.
b21 : b8	Encoder position – Left aligned, MSB first.
General status	
b7	Error - If low, the position data is not valid. Bits b21 - b8 are replaced with error status bits.
b6	Warning - If low, the position data is valid, but some operating conditions are close to limits.
	Error and Warning bits can be set at the same time, in this case the Error bit has priority. The colour of the LED on the readhead housing indicates the value of the General status bits. LED is flashing (duty cycle 50 %, frequency 2.5 Hz), when the encoder is in idle state. If the controller requests the data every 200 ms or more often, the duty cycle of the LED is 100 % (always on)
CRC (inverted)	
b5 : b0	Polynomial for CRC calculation of position, error and warning data is: x6 + x1 + 1. Represented also as 0x43.

Error status	
b21 : b16	Reserved
b15	Signal amplitude too high. The readhead is too close to the magnet or an external magnetic field is present.
b14	Signal amplitude low. The distance between the readhead and the ring is too large.
b13	The readhead temperature is out of specified range.
b12	Speed too high.
b11 : b8	Reserved.

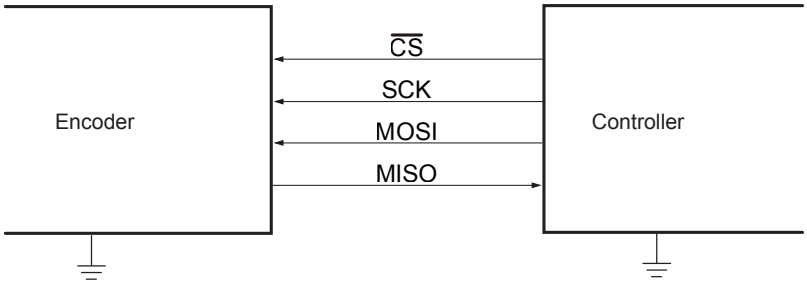
For more information regarding BiSS protocol see **www.biss-interface.com**.

SPI - Serial peripheral interface (slave mode)

The Serial Peripheral Interface (SPI) bus is a four wire bidirectional synchronous serial communication interface, typically used for short distance communication. It operates in full duplex mode, where master (controller) selects the slave with CS line, generates clock signal on SCK line, sends command over MOSI line and receives data over MISO line.

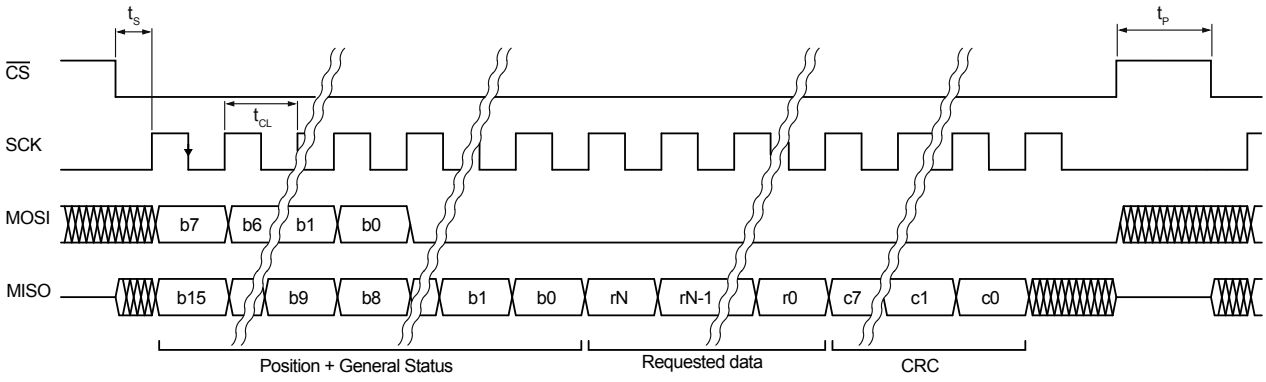
Electrical connection

All data signals are 3.3 V LVTTL. Inputs are 5 V tolerant. Maximum current sourced or sunk from signal lines should not exceed 20 mA.



Signal	Description
$\overline{CS}$	Active low. $\overline{CS}$ line is used for synchronisation between master and slave devices. During communication it must be held low. Idle is high. When $\overline{CS}$ is high, MISO line is in high-Z mode. This allows connection of multiple slaves in paralell, sharing all lines except $\overline{CS}$.
SCK	Serial clock. Shifts out the data on rising edge.
MOSI	Master output ⟶ Slave input. Command from the controller to encoder.
MISO	Master input ⟵ Slave output. Data is output on rising edge on SCK after $\overline{CS}$ low. When $\overline{CS}$ is high, MISO line is in high-Z mode.

SPI timing diagram (single-turn)



Controller starts the communication by setting the $\overline{CS}$ signal low. The last available position data is latched at the same time. A delay of t_s is required for the encoder to prepare the data which is shifted to MISO output on rising edges of clock signal SCK. The command is received on 8 consecutive rising edges of SCK. 16 bits of Position and General Status (active low) data are sent out regardless of the received command. The following Requested data length as well as the content depends on the command. The last eight bits contain CRC (inverted) of the complete data packet.

Communication parameters

Parameter	Symbol	Min	Typ	Max
Clock period	t_{CL}	250 ns		20 µs
Clock frequency	f_{CL}	50 kHz		4 MHz
Time after $\overline{CS}$ low to first SCK rising edge	t_S	1.25 µs		
Pause time	t_P		5 µs	

Structure of data packet

Bit	b31 : b16	b15 : b2	b1 : b0	rN : r0	c7 : c0
Data length	16 bits	14 bits	2 bits	Variable	8 bits
Meaning	Multi-turn counter (optional)	Encoder position	General status	Requested data	CRC

Encoder position - for all commands		
	b31 : b16	Multi-turn counter (optional) - Left aligned, MSB first.
	b15 : b2	Encoder position - Left aligned, MSB first.
General status - for all commands		
	b1	Error - If low, the position data is not valid. The last valid position is sent out.
	b0	Warning - If low, the position data is valid, but some operating conditions are close to limits.
	Error and Warning bits can be set at the same time, in this case Error bit has priority. The color of the LED on the readhead housing indicates the value of the General status bits. LED is flashing (duty cycle 50 %, frequency 2.5 Hz), when the encoder is in idle state. If the controller request the data every 20 ms or more often, the duty cycle of the LED is 100% (always on).	
Requested data - Command "v" (0x76) - serial number request		
	r47 - r0	6 bytes (48 bits) of ASCII serial number.
Requested data - Command "s" (0x73) - speed request		
	r15 - r0	16 bits, signed. The number represents speed in revolutions per second multiplied by 10.
Requested data - Command "t" (0x74) - temperature request		
	r15 - r0	16 bits, signed. The number represents temperature of the readhead in °C multiplied by 10.
Requested data - Command "d" (0x64) - detailed status request		
	r7	Signal amplitude too high. Readhead is too close to the magnet or an external magnetic field is present.
	r6	Signal amplitude low. Distance between the readhead and the magnet is too large.
	r5	Readhead temperature is out of range.
	r4	Speed is too high.
	r3 - r0	Reserved.
CRC (inverted)		
	c7 : c0	Polynomial for CRC calculation of the sent data is: x8 + x7 + x4 + x2 + x1 + 1. Represented also as 0x97.

Head office

RLS merilna tehnika d.o.o.
Poslovna cona Žeje pri Komendi
Pod vrbami 2
SI-1218 Komenda
Slovenia

T +386 1 5272100
F +386 1 5272129
E mail@rls.si
www.rls.si

Document issues

Issue	Date	Page	Corrections made
1	22. 1. 2016	-	New document
2	17. 2. 2016	4	Axial displacement amended
		5	SSI and SSI timing diagram images amended
		7, 8	BiSS interface description added
3	8. 4. 2016	9, 10	SPI interface added
4	4. 5. 2016	3	Technical specifications amended
		6	Structure of data packet amended
		9, 10	SPI description added and amended
		11	PWM description added
5	18. 7. 2016	5, 6	Asynchronous serial communication added
		General	Pages shuffeled
6	21. 7. 2016	3, 5, 6, 9, 11, 13	Multi-turn counter option added
7	15. 12. 2016	3	Technical specifications amended
		5	Electrical connections amended