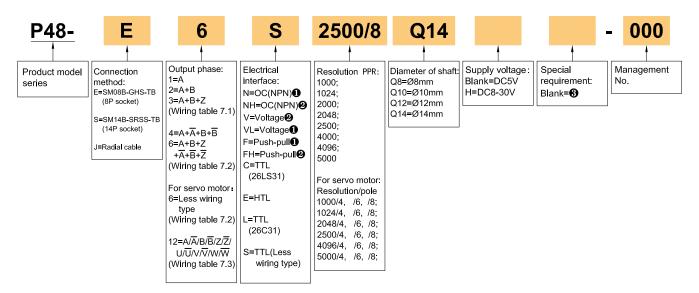


P48	INCREMENTAL	Ver. 2.0	Page 1/11
1.1 Introdu P48 wi single-l	h its unique through-shaft concentric locking device, bearing ultra-thin design, mechanical hard connection,		
	e electrical interfaces, and no dust protection, can solve allation problem of low space restrictions. e:	P48-E	
diamet • Adopt i	er external diameter Ø48mm、thickness min 11mm、 er of shaft up to Ø14mm; non-contact photoelectric principle; e polarity protection;		
 Multiple 	ircuit protection; e electrical interfaces available; tion per turn up to 5000PPR.	P48-S	
1.3 Applica Servo r 1.4 Conne	notor, robot and automation control fields.		
 Radial 	socket (8P & 14P) cable (standard length 1.0M)	P48-J	
1.5 Protec None			
1.6 Weight About 6			

2. Model Selection Guide

2.1 Model composition(select parameters)



2.2 Note

- 1. Z signal is low level active.
- 2. Z signal is high level active.
- 8. Blank means IP00, cable length is 1.0M, if need to change the length C+number, the longest is 100M (expressed by C100). For the specific length of use, pls refer to page P2 -P3 of the provision of output circuit.

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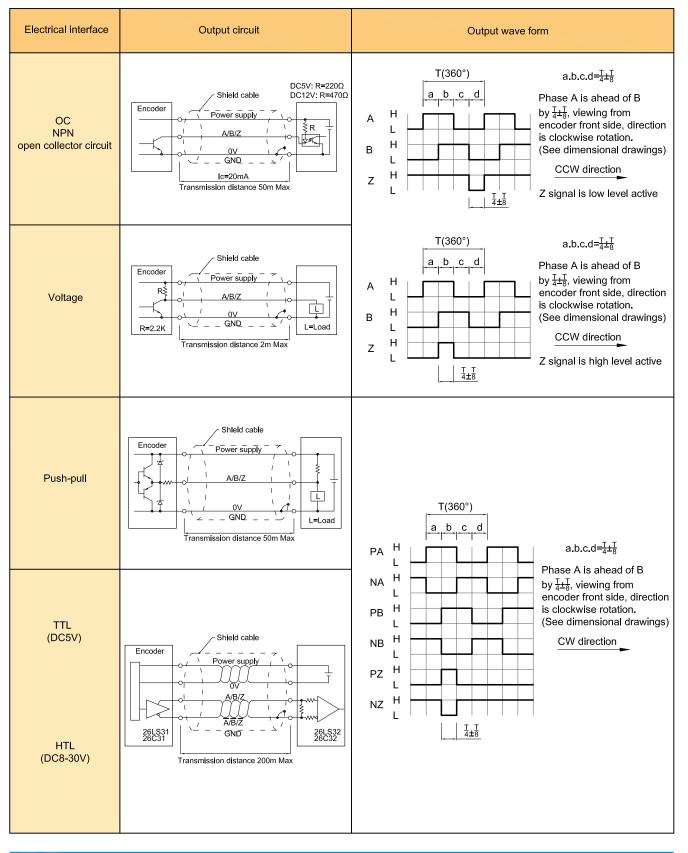
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3. Output Mode

3.1 Incremental signal



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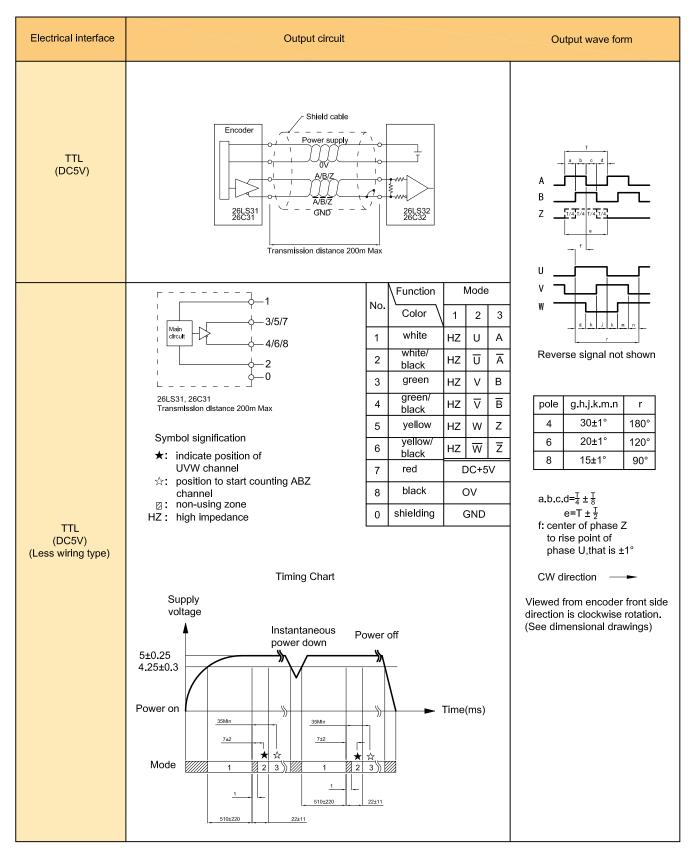
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3.2 For servo motor(with UVW)



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4. Electrical Parameters

Parameter Output type Item					Push-pull	TTL	TTL (Less wiring type)	HTL				
Supply voltage			DC+5V±5%; DC8\	/-30V±5%		DC+5V±5%	DC8-30V±5%					
Consumption current		١	100mA Max			120mA Max						
	Allowable ripple		≤3%rms									
Top freq	respons uency	e	100KHz			300KHz		500KHz				
	Output	Input	≤30mA	Load resistance	≤30mA	≤±20mA		≤±50mA				
acity	current	Output	_	2.2K	≤10mA							
Output capacity	Output	"H"	_	_	≥[(Supply voltage) -2.5V]	≥2 . 5V	≥Vcc-3 VDC					
utpu	voltage	"L"	≤0.4V	≤0.7V(less than 20mA)	≤0.4V(30mA)	≤0.5V	≤1V VDC					
O Load voltage		tage	≤DC30V	_		-						
Rise	e & Fall ti	me	Less than 2us(cabl	e length:2m)		Less than 1us(Cable length: 2m)						
Insu	lation str	ength	AC500V 60s									
	lation stance		10ΜΩ									
	k to space	· · · · · · · · · · · · · · · · · · ·	45% to 55%									
prot	erse pola tection	arity	v									
	rt-circuit ection		- v0									
	Phase shift		90°±10° (frequency in low speed)									
	ween A &	/	90°±20° (frequency	/ in high speed)								
Dela time	ay motion e 🕗		_				510±220ms	—				
GN	D	_	Not connect to encoder									

• Short-circuit to another channel or GND permitted for max.30s.

Phase A.B.Z are back of phase U.V.W when power on.

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5. Mechanical Specifications

Diameter of shaft	Ø8mm; Ø10mm; Ø12mm; Ø14mm(optional)				
Starting torque Less than 9.8×10 ⁻³ N·m					
Inertia moment	Less than 6.5×10 ⁻⁶ kg·m²				
Shaft load	Radial 20N; Axial 10N				
Slew speed	≤5000 rpm				
Bearing Life	1.5X10 ⁹ revs at rated load(100000hrs at 2500RPM)				
Material	Base: Die cast aluminum				
Weight	About 60g				

6. Environmental Parameters

Environmental temperature	Operating:-20~+85°C(repeatable winding cable: -10°C); Storage:-20~+90°C
Environmental humidity	Operating and storage: 35~85%RH(noncondensing)
Vibration(Endurance)	Amplitude 0.75mm,5~55Hz,2h for X,Y,Z direction individually
Shock(Endurance)	490m/s ² 11ms three times for X,Y,Z direction individually
Protection	None

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7. Wiring Table

7.1 OC / Voltage

P48

			Incremen	ntal signal			Supply voltage		
Socket pin No.	1	2	3	4	5	6	7	8	
Wire color	White	-	Green	-	Yellow	-	Red	Black	
Function	А	-	В	-	Z	-	Up	0V	

7.2 TTL / HTL / Push-pull / Less wiring type

			Incremen	ntal signal	Supply voltage				
Socket pin No.	1	2	3 4		5	6	7	8	
Wire color	White	White/BK	Green	Green Green/BK		Yellow/BK	Red	Black	
Function	$\mathbf{A+}~(\cup +)^*$	A+ (U+)* A- (U-)*		B+ (∀+)* B- (∀-)*		Z- (₩-)*	Up	0V	
Twisted-paired cable									

* For the functional status in less wiring mode, refer to the functional mode wiring table for output circuit on page3.

7.3 For servo motor

		Incremental signal									Supply voltage			
Socket pin No.	1	2	3	4	5	6	7	8	9	10	11	12	13	14
Wire color	Blue	Blue/Bk	Grey	Grey/Bk	Pink	Pink/Bk	Yellow	Yellow/BK	Green	Green/BK	White	White/BK	Black	Red
Function	U+	U-	V+	V-	W+	W-	Z+	Z-	B+	B-	A+	A-	0V	Up
Twisted- paired cable	aired 🖂													

Up=Supply voltage.

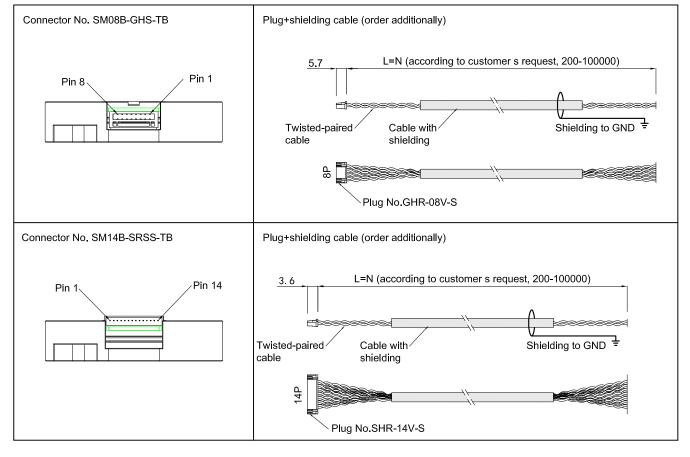
Shield wire is not connected to the internal circuit of encoder.

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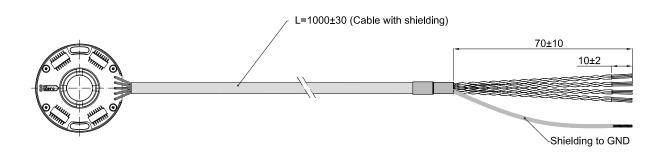
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8. Socket & Cable

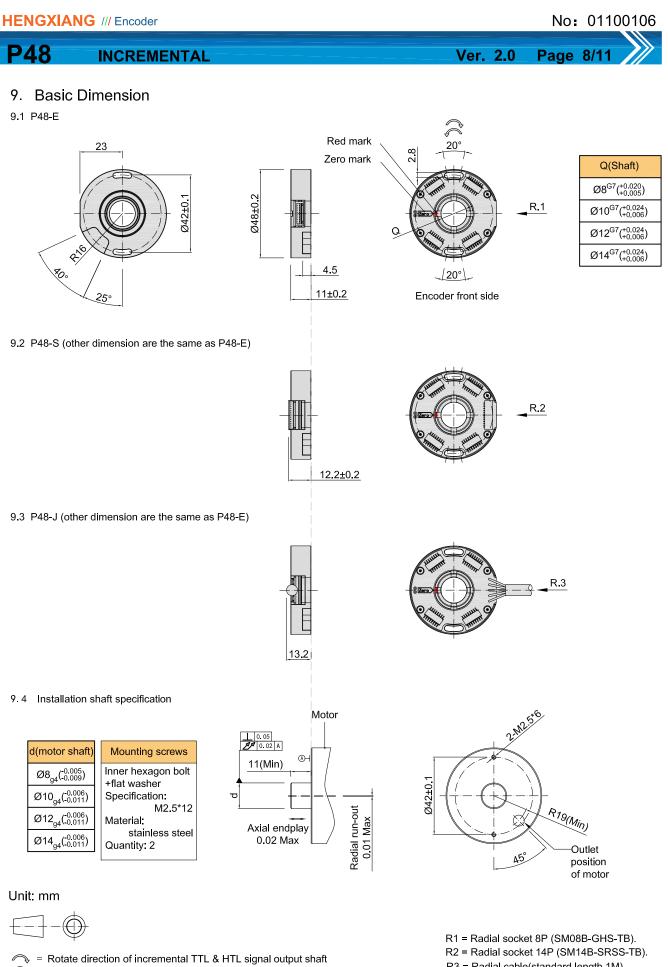
8.1 Socket pin definition



8.2 Radial Cable Schematic



Unit: mm



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= Rotate direction of OC signal output shaft G

R3 = Radial cable(standard length 1M).

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10. Assembly Steps

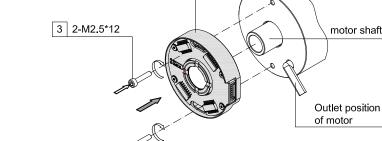
10.1 Assembling steps for encoder with UVW

Step 1

- a. Before installing the encoder, first to confirm the starting zero position of the motor and lock it tightly to ensure that the motor shaft is not moving until the encoder is finished installation, otherwise the encoder and the motor's zero position cannot be aligned.
- b. Put the encoder (2) directly on the motor shaft and gently push it to the motor platform by hand.
- Screwed the two M2.5*12 bolts (3) at the same time, c. but do not tighten, just enough to rotate the encoder by hand.

Note:

Please refer to page 8 for the matching tolerance of the encoder shaft sleeve and the motor shaft.



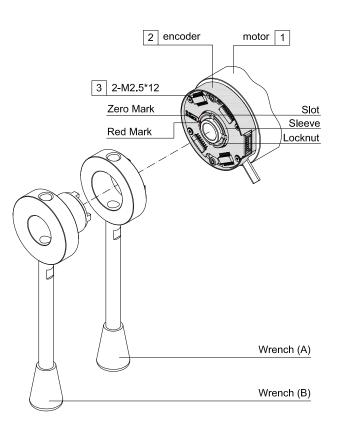
2 encoder

Step 2

- a. Fix the spanner (A) on the slot of the encoder shaft sleeve (outer ring) and then use the spanner (B) to tighten the lock nut (recommended tightening force is 8-13nm).
- b. Pls refer to the cable connection table on page 6-7, power on after checking all are correct, please confirm again that the motor is in the zero locked state, and then turn the encoder (2) left and right by hand, make sure the zero signal between encoder and motor is aligned, then screwed two M2.5 bolts(3).

Note:

- *. The red mark on the shaft sleeve is always aligned with the zero point.
- * After making sure that the lock nut has been tightened, put thread glue on the inner thread of the slot to prevent the screw from loosening.
- *. Because the width of the zero signal is relatively narrow, it is easy to cause displacement during the tightening process. please be patient to debug.



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motor 1

motor shaft

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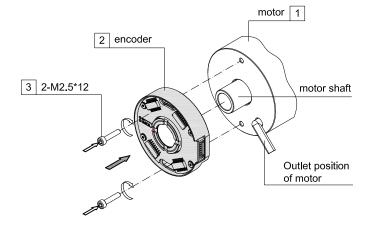
10.2 Assembling steps for encoder without UVW

Step 1

Put the encoder (2) directly on the motor shaft (1) and gently push it to the motor platform, then tighten the two M2.5*12 bolts (3) at the same time.

Note:

Please refer to page 8 for the matching tolerance of the encoder shaft sleeve and the motor shaft.

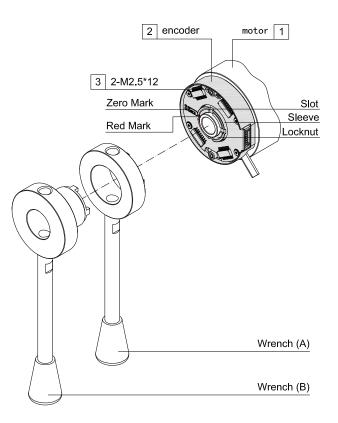


Step 2

Put the wrench (A) on the slot of the encoder sleeve (outer ring), and then use the wrench (B) to tighten the nut to ensure tightness (the recommended tightening force is 8-13N.m).

Note:

*. After ensuring that the locking nut is tightened, apply thread glue to the internal threads of the slot to prevent the threads from loosening.



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11. Caution

11.1 About vibration

Vibration act on encoder always cause wrong pulse, so we should pay attention to working place. More pulse per revolution, narrower groovy spacing of grating, more effect to encoder by vibration, when rev is low or stop, vibration act on shaft or main body would cause grating vibrating, so encoder might make wrong pulse.

- 11.2 Caution for wiring
 - Use the encoder under the specified supply voltage. Please note that the supply voltage range may drop due to the wiring length.
 - Do not put the encoder wiring and other power lines through the same duct, and do not use them by bundling in parallel.
 - Please do not apply excessive force to the cable of encoder, or it will may be damaged.



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