

RE16 / RM16

Super Small Incremental and Absolute Encoders

SUPER
SMALL SIZE

HIGH
OPERATING
SPEED

HIGH
ACCURACY

The RE16 and RM16 are compact, sealed, miniature, high speed rotary magnetic encoders designed for use in space limited applications. The encoder body is just 16 mm in diameter in aluminum housing.



Features and benefits

- ▶ Super small size – 16 mm diameter body
- ▶ Non-contact, frictionless design
- ▶ 5 V power supply versions
- ▶ High speed operation up to 30,000 rpm
- ▶ Industry standard incremental, SSI and linear voltage output formats
- ▶ Accuracy $\pm 0.3^\circ$
- ▶ RoHS compliant



General information

Rotation of the magnetic actuator is sensed by a custom encoder chip within the body, and processed to give incremental, SSI or linear voltage outputs. The encoder chips process the signals received to provide resolutions up to 12 bit (4,096 counts per revolution) with high operational speeds.

The RE16/RM16 encoders have been designed for direct integration in to high volume OEM applications and can be used in a wide range of applications including motor control and industrial automation.

Product range

RE16/RM16 I

Incremental with 8 to 1,024 pulses per revolution (32 to 4,096 counts per revolution).

RE16/RM16 S

Absolute with synchro serial interface (SSI) with 5 to 12 bit resolution (32 to 4,096 positions per revolution).

RE16/RM16 V

Linear voltage output with ramp from 0 V to 5 V.

RM16 encoder



Encoder body

+



Actuator

=



Encoder system

RE16 encoder



Storage and handling

Operating and storage temperature



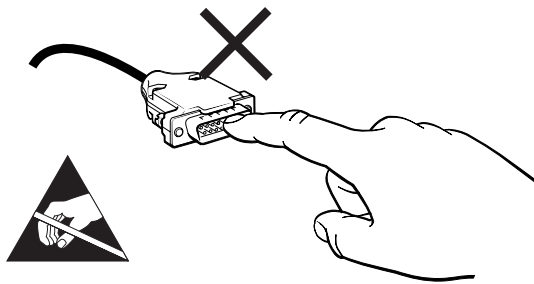
-40 °C to +125 °C

Humidity



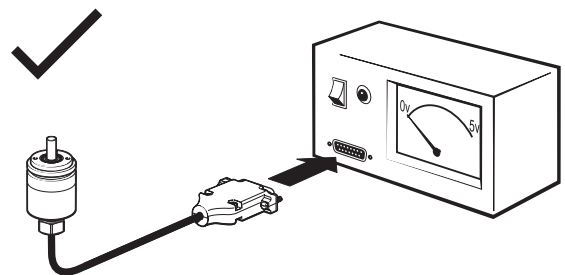
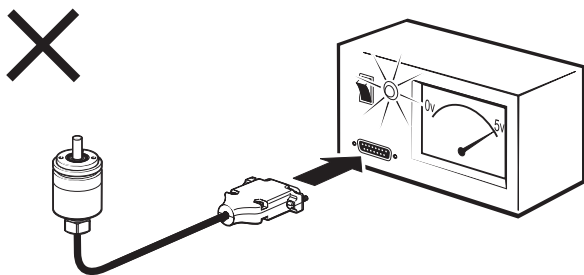
RM16: IP67, standard EMC grade

RE16: IP67 on electronic side, IP40 on mehanic side, standard EMC grade



Power to RE16/RM16 encoders must be supplied from a DC SELV supply complying with the essential requirements of EN (IEC) 60950 or similar specification.

The RE16/RM16 series encoders have been designed to the relevant EMC standards, but must be correctly integrated to achieve EMC compliance. In particular, attention to shielding arrangements is critical.



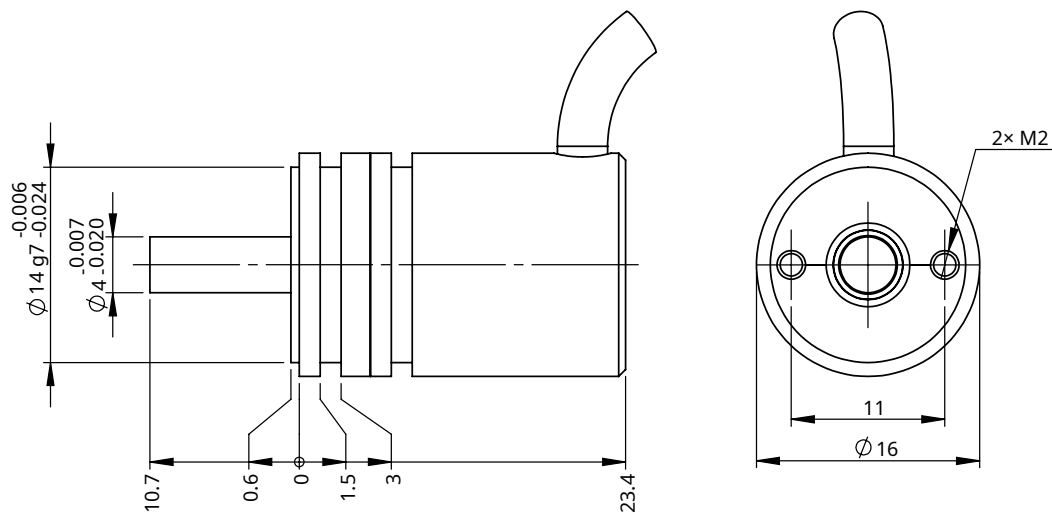
Packaging

Each encoder is packed in antistatic bag.

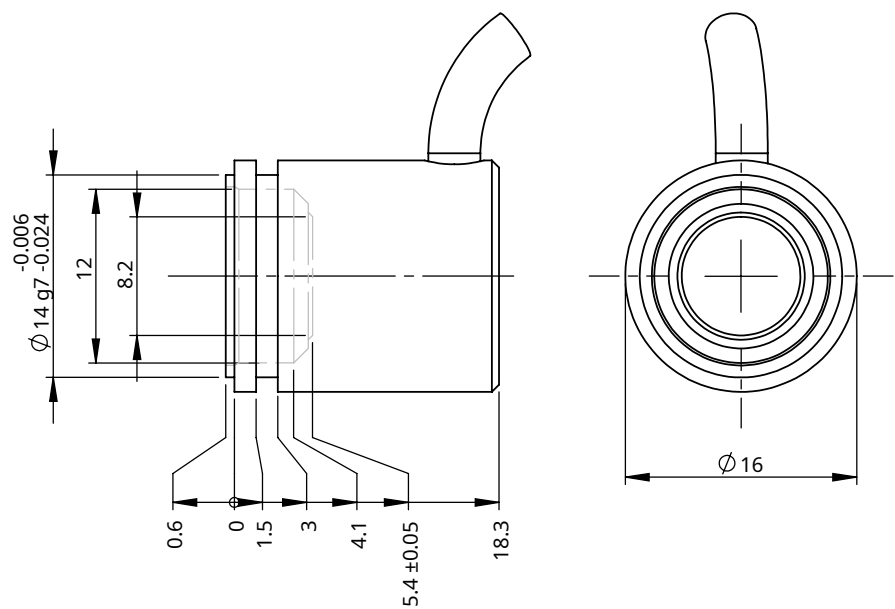
Dimensions

Dimensions and tolerances are in mm.

RE16



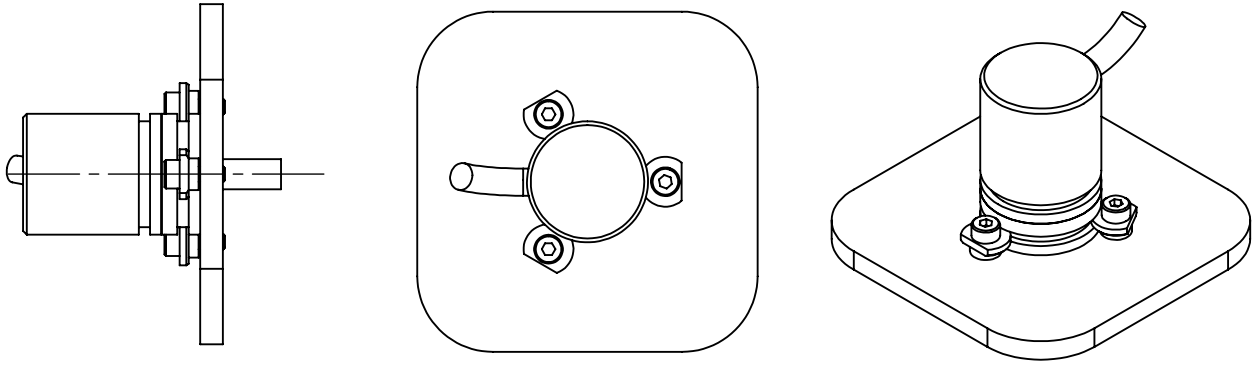
RM16



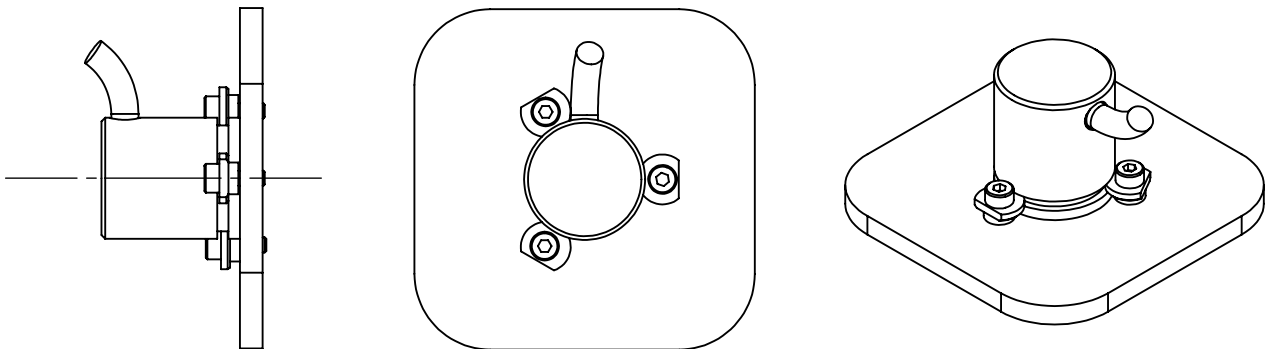
Installation drawings

Dimensions and tolerances are in mm.

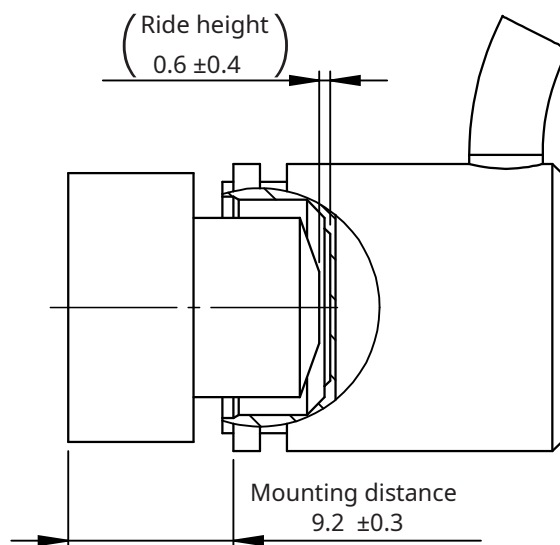
RE16



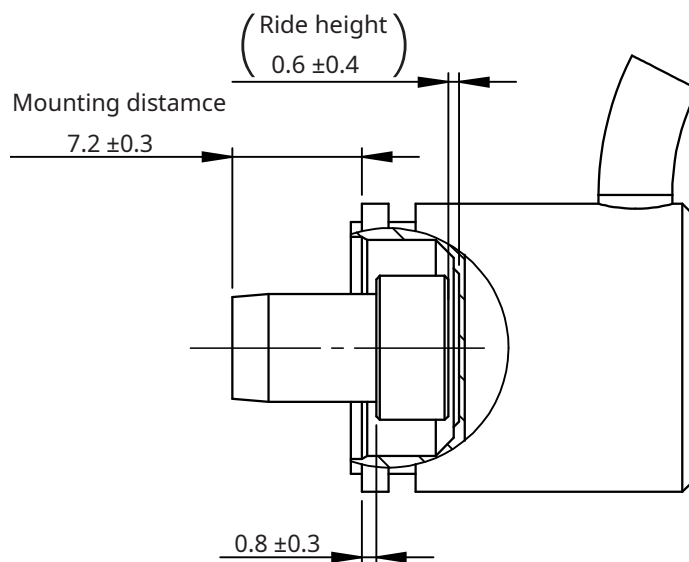
RM16



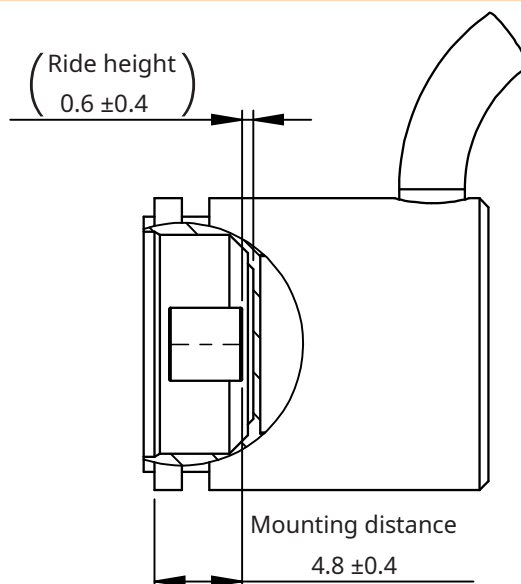
RM16 with RMA actuator



RM16 with RMH06 actuator



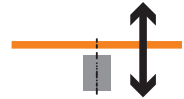
RM16 with RMM44Axx00 magnet



Installation tolerances

Installation tolerances for RM16

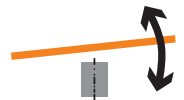
Mounting distance See installation drawings of encoder assemblies on **page 6.**



Radial displacement (concentricity) ± 0.3 mm



Perpendicularity $\pm 0.3^\circ$



— - Encoder ■ - Magnet

Technical specifications

System data

Accuracy	$\pm 0.3^\circ$ (RE16) ± 0.5 (RM16)
Hysteresis	0.17°

Mechanical data

Housing material	Aluminium
Mass	RE16 33 g (with 1m long cable) RM16 28 g (with 1m long cable)
Wire thickness	AWG28
Max. speed	30,000 rpm
Max. cable length	10 m

Environmental data

Operating and storage temperature	-40°C to $+125^\circ\text{C}$
Environmental sealing	RM16: IP67 RE16: IP67 on electronic side, IP40 mechanic

Electrical connections

	RE16/RM16 ID	RE16/RM16 SC	RE16/RM16 Vx
Wire colour	ABZ	SSI	Linear voltage
Shield - Connected to encoder body			
Brown	V _{dd}	V _{dd}	V _{dd}
White	GND	GND	GND
Green	A	Data+	V _{out}
Yellow	B	Data-	
Grey	Z	Clock-	
Pink		Clock+	

Output types

Incremental, single ended

RE16/RM16 ID

Specifications

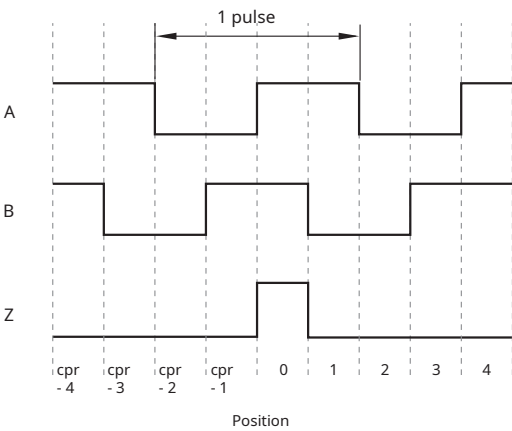
Power supply	V _{dd} = 5 V ± 5 %
Current consumption	Typ. 26 mA
Output signals	A, B, Z (single ended)
Resolution	32, 64, 128, 256, 512, 1024, 2048, 4096 cpr

There are three signals for the incremental output: A, B and Z. Signals A and B are quadrature signals, shifted by 90°, and signal Z is a reference mark. The reference mark signal is produced once per revolution. The width of the Z pulse is 1/4 of the quadrature signal period and it is synchronised with the A and B signals. The position of the reference mark is at zero. The graph on the right shows the timing diagram of A, B and Z signals with clockwise rotation of the magnet. B leads A for clockwise rotation.

With incremental outputs it is important to know the difference between ppr (pulses per revolution) and cpr (counts per revolution = 4 × ppr). **Pulses per revolution** is the number of periods on one of the quadrature signals in one revolution. **Counts per revolution** is the number of changes of state on both channels in one revolution and is achieved by electronically multiplying by four, using both the rising and the falling edges on both channels.

Timing diagram

Complementary signals not shown



Synchro serial interface (SSI)

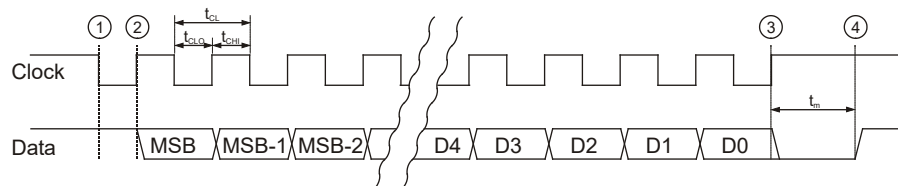
RE16/RM16 SC

Specifications

Power supply	$V_{dd} = 5\text{ V} \pm 5\%$
Current consumption	Typ. 26 mA
SSI Data output	Data, RS422
SSI Clock input	Clock, RS422
Resolution	5, 6, 7, 8, 9, 10, 11, 12 bit
Clock frequency	$\leq 4\text{ MHz}$

Serial output data is available in up to 12 bit natural binary code through the SSI protocol. With the clockwise magnet rotation, the value of the output data increases.

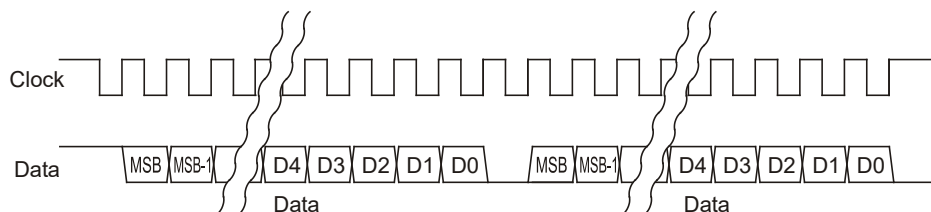
Parameter	Symbol	Min.	Typ.	Max.	Unit
Clock period	t_{CL}	0.25		$2 \times t_m$	μs
Clock high	t_{CHI}	0.1		t_m	μs
Clock low	t_{CLO}	0.1		t_m	μs
Monoflop time	t_m	15	19	25	μs



Timing diagram for SSI output

The controller interrogates the encoder for its positional value by sending a pulse train to the Clock input. The Clock signal must always start from high. The first high/low transition (point 1) stores the current position data in a parallel/serial converter and the monoflop is triggered. With each transition of the Clock signal (high/low or low/high) the monoflop is retrigged. At the first low/high transition (point 2) the most significant bit (MSB) of the binary code is transmitted through the Data pin to the controller. At each subsequent low/high transition of the Clock the next bit is transmitted to the controller. While reading the data the t_{CHI} and t_{CLO} must be less than t_{mMin} to keep the monoflop set. After the least significant bit (LSB) is output (point 3) the Data goes to low. The controller must wait longer than t_{mMax} before it can read updated position data. At this point the monoflop time expires and the Data output goes to high (point 4).

If the controller continues sending the Clock pulses after the data is read without waiting for t_m , the same data will be output again and between the two outputs one logic zero will be output. The length of the data depends on the resolution of the encoder.



SSI multi-read of the same position data

Linear voltage, single ended

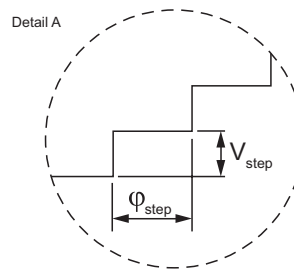
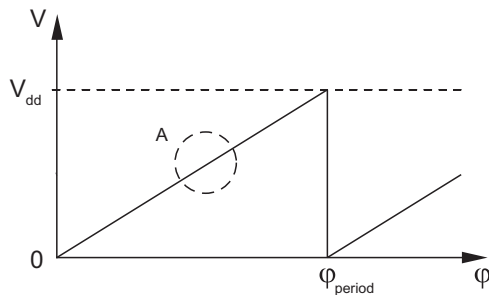
RE16/RM16 Vx

Specifications

Power supply	$V_{dd} = 5\text{ V} \pm 5\%$
Current consumption	Typ. 26 mA
Output voltage	0 V to V_{dd}
Output load	Max. 2 mA
Resolution of DAC	10 bit
Nonlinearity	1 %

The digital relative angular position information is converted into linear voltage with a built-in 10 bit D/A converter. The linear output voltage swing ranges from 0 V and V_{dd} (5 V). The number of periods within one revolution (N_{period}) can be 1, 2, 4 or 8, representing one full swing over an angle (φ_{period}) of 360°, 180°, 90° or 45° respectively. The signal is made up of steps which represent the angular movement needed to register a change in the position (φ_{step}) and the resulting change in the output voltage (V_{step}). The number of steps in one period (N_{step}) is given in the table below.

For clockwise rotation of the magnetic actuator, the output voltage increases. For counterclockwise rotation, the output voltage decreases.



Timing diagram for linear voltage output

$$\varphi_{\text{step}} = \frac{\varphi_{\text{period}}}{N_{\text{step}}} \quad V_{\text{step}} = \frac{V_{dd}}{N_{\text{step}}}$$

- φ_{period} = Angle covered in one period (one sawtooth)
- V_{period} = Output voltage range for one period
- φ_{step} = Step angle (angular movement needed to register a change in the position)
- V_{step} = Output voltage range for one step
- N_{period} = Number of periods in one revolution
- N_{step} = Number of steps in one period

φ_{period}	N_{period}	N_{step}	φ_{step}
360°	1	1024	0.35°
180°	2	1024	0.18°
90°	4	1024	0.09°
45°	8	512	0.09°

Output type and electrical variant

	φ_{period}	360°	180°	90°	45°
Rotation					
Clockwise		VA	VB	VC	VD
Counterclockwise		VE	VF	VG	VH

Part numbering

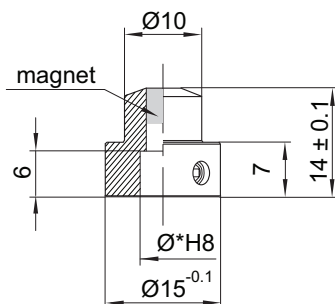
	RE16	ID	04	10B	10	F	2	E	10
Series									
RE16 - Rotary Magnetic encoder, 16 mm diameter body									
RM16 - Rotary Magnetic encoder, contactless, 16 mm diameter body									
Output type									
ID - Incremental, single ended, no driver, 5V									
SC - Synchro-serial (SSI), RS422, 5 V									
Vx - Linear voltage:									
	360°	180°	90°	45°					
CW	VA	VB	VC	VD					
CCW	VE	VF	VG	VH					
Shaft size									
00 - NA (for RM16 only)									
04 - 4 mm (for RE16 only)									
Resolution									
For ID and SC (counts per revolution)					For Vx (counts per revolution)				
12B - 4096	08B - 256				10B - 1024				
11B - 2048	07B - 128								
10B - 1024	06B - 64								
09B - 512	05B - 32								
Cable length									
10 - 1 m									
Connector									
F - Flying lead (no connector)									
Body style and cable exit									
2 - Cylindrical body, radial cable exit									
Environment and material									
F - IP67, standard EMC grade (for RM16 only)									
P - IP67 on electronic side, IP40 mechanic side, standard EMC grade (for RE16 only)									
Special requirements									
10 - No special requirements (standard)									

Table of available combinations

Series	Output type	Shaft size	Resolution	Cable length	Connector	Body style and cable exit	Environment and material	Special requirements	
RE16	ID / SC	04	12B / 11B / 10B / 9B / 8B / 7B / 6B / 5B	10	F	2	P	10	
	Vx		10B						
RM16	ID / SC	00	12B / 11B / 10B / 9B / 8B / 7B / 6B / 5B				F		
	Vx		10B						

Magnetic actuator and magnet ordering information

Actuator for integration onto shaft



Shaft = Ø*h7
Fixing: Grub screw provided

* Hole diameter for nominal shaft size.
See table on the right for more information on available shaft sizes.

Part numbers:

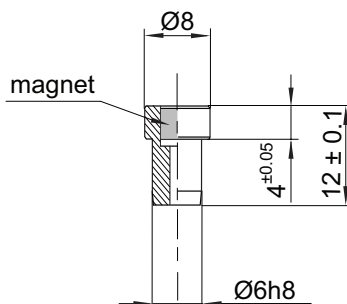
For resolutions up to 9 bit absolute (512 cpr incremental)

RMA04A2A00 – Ø4 mm shaft	RMA10A2A00 – Ø10 mm shaft
RMA05A2A00 – Ø5 mm shaft	RMA19A2A00 – Ø3/16" shaft
RMA06A2A00 – Ø6 mm shaft	RMA25A2A00 – Ø1/4" shaft
RMA08A2A00 – Ø8 mm shaft	RMA37A2A00 – Ø3/8" shaft

For resolutions from 10 bit absolute (800 cpr incremental) and above

RMA04A3A00 – Ø4 mm shaft	RMA10A3A00 – Ø10 mm shaft
RMA05A3A00 – Ø5 mm shaft	RMA19A3A00 – Ø3/16" shaft
RMA06A3A00 – Ø6 mm shaft	RMA25A3A00 – Ø1/4" shaft
RMA08A3A00 – Ø8 mm shaft	RMA37A3A00 – Ø3/8" shaft

Actuator for integration into shaft



with N-pole marker



Hole = Ø6G7
Fixing: Glue (recommended – LOCTITE 648 or 2701)

Part numbers:

For resolutions up to 9 bit absolute (512 cpr incremental)

RMH06A2A00

For resolutions from 10 bit absolute (800 cpr incremental) and above

RMH06A3A00

With N-pole marker scribed to a ±5° accuracy:

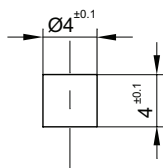
For resolutions up to 9 bit absolute (512 cpr incremental)

RMH06A2A02

For resolutions from 10 bit absolute (800 cpr incremental) and above

RMH06A3A02

Magnet for direct recessing in non-ferrous shafts



Fixing: Glue (recommended – LOCTITE 648 or 2701)

Part numbers:

For resolutions up to 9 bit absolute (512 cpr incremental)

RMM44A2A00 (individually packed) – for sample quantities only
RMM44A2C00 (packed in tubes)

For resolutions from 10 bit absolute (800 cpr incremental) and above

RMM44A3A00 (individually packed) – for sample quantities only
RMM44A3C00 (packed in tubes)

Accessories

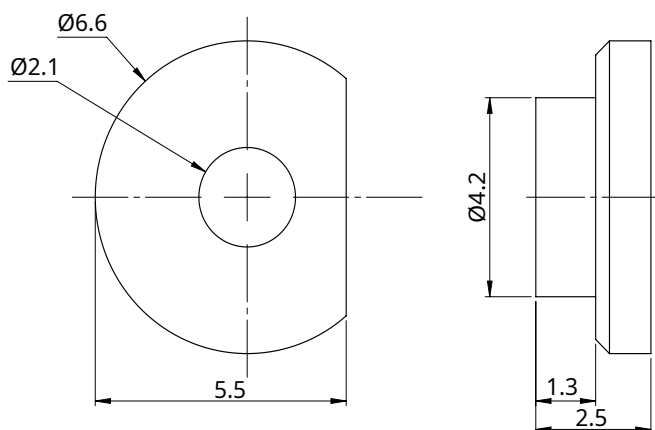


Installation accessory set

ACC072

ACC072 – Installation accessory set

Dimensions and tolerances are in mm. All dimensions are according to ISO2768-f.



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Document issues

Issue	Date	Page	Description
01	27. 10. 2022	-	New document

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