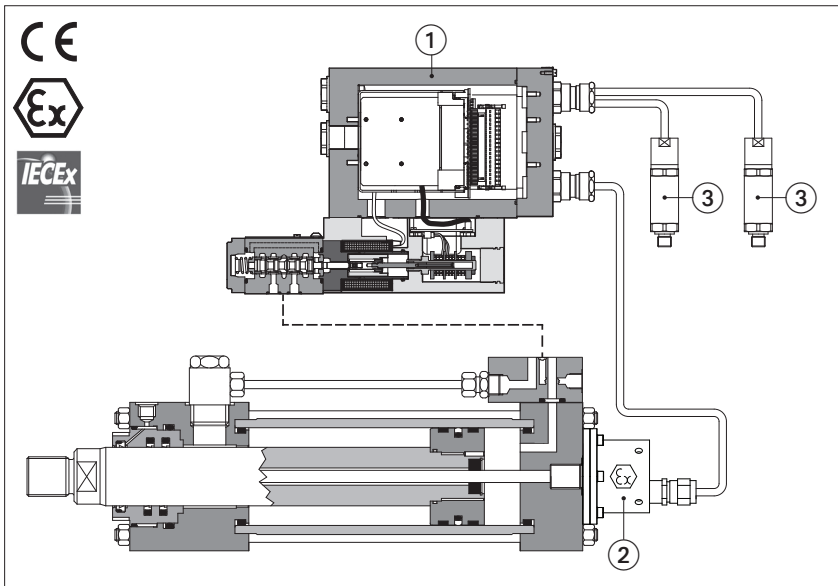


Ex-proof digital servoproportionals with on-board axis control

direct and pilot operated directional valves with LVDT transducer, zero spool overlap - ATEX IECEx



DLHZA-TEZ, DLKZA-TEZ

DHZA-TEZ, DKZA-TEZ, DPZA-LEZ

Ex-proof digital servoproportionals direct or pilot operated include valve's driver + axis card to perform the position closed loop of any linear or rotative hydraulic actuator.

The controlled actuator has to be equipped with integral or external ex-proof transducer (analog, potentiometer, SSI or Encoder) to feedback the axis position.

Directional servoproportionals are operated by an external or internally generated reference position signal, see [2].

Alternated P/Q control option, see [3]:

SP, SF, SL = alternated pressure/force control to the basic position one.

Atos also supplies complete servoactuators integrating servocylinder, digital servoproportional valve and axis controller, fully assembled and tested.

1 MODEL CODE

DLHZA	-	TEZ	-	D	-	SF	-	EH	-	0	4	0	-	L5	1 / *	Hydraulic and electronics options, see tech table FX150
<p>Ex-proof direct operated servoproportional sleeve execution:</p> <p>DLHZA = size 06 DLKZA = size 10</p> <p>TEZ = on-board digital driver + axis card, one LVDT transducer</p> <p>Fail safe type, only for configuration 4: 1 = A, B, P, T with positive overlapping (20% of spool stroke) 3 = P positive (20% of spool stroke); A, B, T negative overlapping</p> <p>Spool type: L0, L1, L3, L5, L7 = linear (L0, L1, L5, only for valve size 06) D7 = differential-linear (as L, but with P-A = Q, P-B = Q/2) DT7 = as D, but with non linear regulation T5, T7 = not linear regulation (T5 only for valve size 06)</p> <p>Spool overlapping in central position: 0 = zero</p> <p>Configuration: 4 = with fail safe 6 = without fail safe</p> <p>Valve size ISO 4401: 0 = 06 1 = 10</p>																

DHZA	-	TEZ	-	D	-	SF	-	EH	-	0	7	0	-	L5	/ *	Hydraulic and electronics options, see tech table FX135
<p>Ex-proof direct operated servoproportional:</p> <p>DHZA = size 06 DKZA = size 10</p> <p>TEZ = on-board digital driver + axis card, one LVDT transducer</p> <p>Spool type: L3, L5 = linear D5 = differential-progressive (P-A = Q, P-B = Q/2)</p> <p>Spool overlapping in central position: 0 = zero</p> <p>Configuration: 7 = 3 position, spring centered</p> <p>Valve size ISO 4401: 0 = 06 1 = 10</p>																

DPZA	-	LEZ	-	D	-	SF	-	EH	-	1	6	0	-	L5	/ *	Hydraulic and electronics options, see tech table FX235
<p>Ex-proof pilot operated servoproportional:</p> <p>DPZA</p> <p>LEZ = on-board digital driver + axis card, two LVDT transducers</p> <p>Position transducer type: A = Analog (standard, potentiometer) D = Digital (SSI, Encoder)</p> <p>Alternated P/Q control, see section [3]: SN = none SP = pressure control (1 pressure transducer) SF = force control (2 pressure transducers) SL = force control (load cell)</p> <p>Spool type: L3, L5 = linear (L3, only for valve size 16) DL5 = differential-linear (as L, but with P-A = Q, P-B = Q/2) T5 = not linear regulation (only for valve size 16)</p> <p>Spool overlapping in central position: 0 = zero</p> <p>Configuration: 6 = spring offset (only for spool L, DL) 7 = 3 position, spring centered</p> <p>Valve size ISO 4401: 1 = 10 2 = 16 4 = 25 4M = 27</p>																

Fieldbus interfaces, USB port always present:

- | | | |
|-------------------------|-------------------------|-----------------------------|
| NP = Not present | EH = EtherCAT | EW = POWERLINK |
| BC = CANopen | EI = EtherNet/IP | EP = PROFINET RT/IRT |
| BP = PROFIBUS DP | | |

2 POSITION REFERENCE MODE

2.1 External reference generation

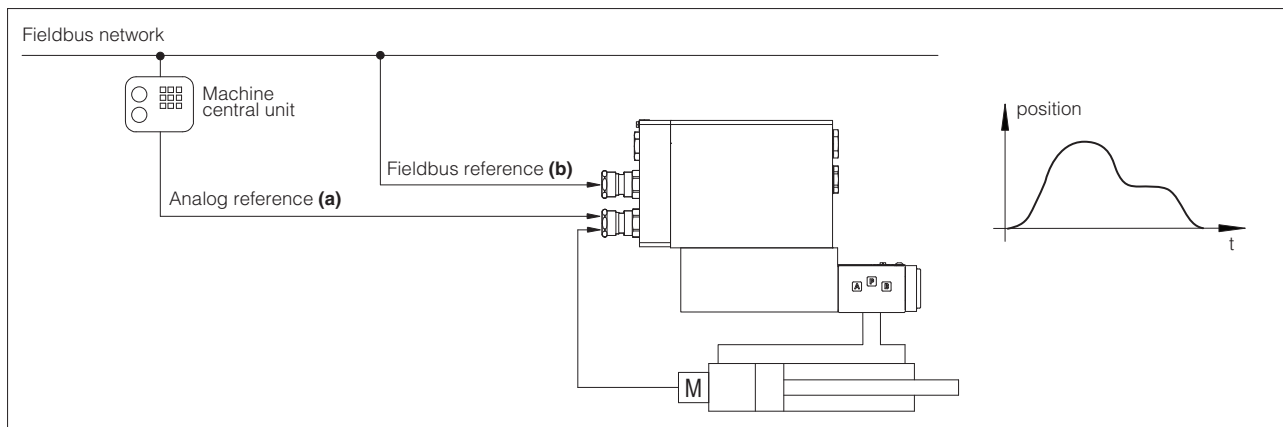
Axis controller regulates in closed loop the actuator position according to an external reference position signal and to the position feedback from the actuator transducer.

The external reference signal can be software selected among:

Analog reference (a) - the controller receives in real time the reference signal from the machine electronic central unit by means analog input on the terminal board.

Fieldbus reference (b) - the controller receives in real time the reference signal from the machine electronic central unit by means digital fieldbus communication.

For fieldbus communication details, please refer to the controller user manual.



2.2 Internal reference generation

Axis controller regulates in closed loop the actuator position according to an internally generated reference position signal and to the position feedback from the actuator transducer.

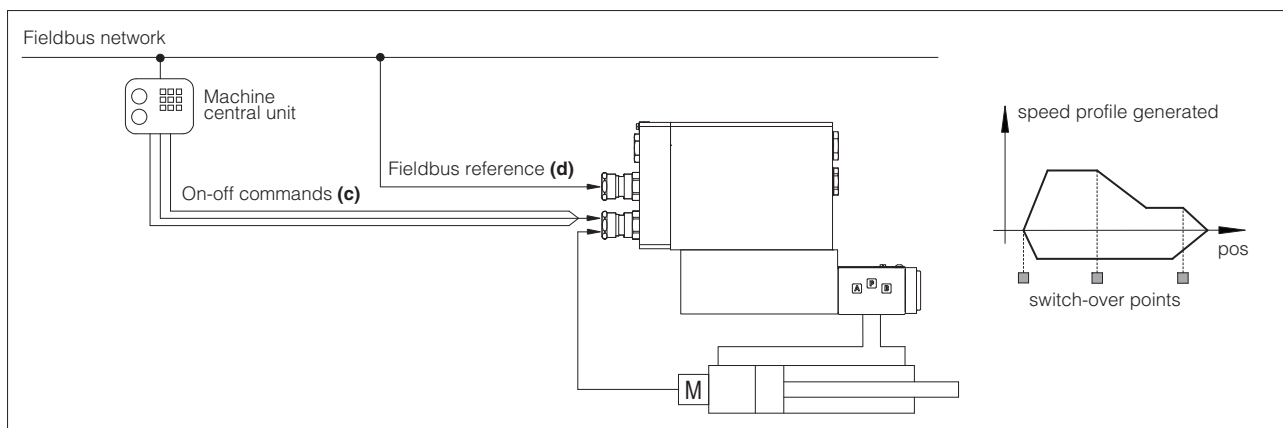
The internal reference signal is generated by a pre-programmed cycle; only start, stop and switch-over commands are required from the machine electronic central unit by means :

- on-off commands (c)

- fieldbus commands (d)

Atos PC software allows to design a customized sequence of motion phases adapted to the specific application requirements: a range of predefined standard sequences are available in the Z-SW software.

Start/stop/switch-over commands and reference generation type can be set for each phase in order to realize an automatic cycle according to the application requests. Refer to the controller user manual for further details on commands and reference generation type.



Start / stop / switch-over commands examples

External digital input on-off commands, on terminal board, are used to start/stop the cycle generation or to change the motion phase

External fieldbus input on-off commands, by fieldbus communication, are used to start/stop the cycle generation or to change the motion phase

Switch by position switch-over from actual to following motion phase occurs when the actual position reaches a programmed value

Switch by time switch-over from actual to following motion phase occurs after a fixed time, starting from the actual phase activation

Reference generation types examples

Absolute a target position reference signal is internally generated for each motion phase; maximum speed and acceleration can be set to obtain a smooth and precise position control

Relative as 'Absolute' but the target position corresponds to the actuator position plus a fixed quote internally set by software

Time as 'Absolute' type but the controller automatically determines the speed and acceleration in order to reach the target absolute position in the fixed time internally set by software

3 ALTERNATED POSITION / FORCE CONTROL

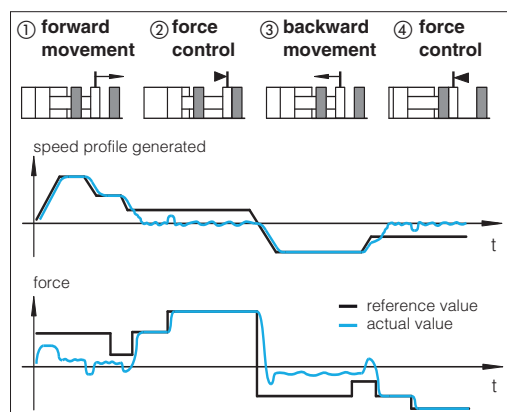
SP, SF, SL options allow to add the alternated force closed loop control to the actuator's standard position control, requiring one or two remote transducers (pressure or force) that have to be installed on the actuator, see below functional schemes.

The position/force controls are operated according to two separate reference signals and a dedicated algorithm automatically selects which control is active time by time.

The dynamics of the switching between the two controls can be regulated thanks to specific software setting, in order to avoid instability and vibrations.

Position control is active (see phase ① and ③ at side) when the actuator force is lower than the relevant reference signal - the valve controls the actuator position by closed-loop regulation.

Force control is active (see phase ② and ④ at side) when the actuator actual force, measured by remote transducers, grows up to the relevant reference signal - the controller reduces the valve's regulation in order to limit the actuator force; if the force tends to decrease under its reference signal, the position control returns active.



Alternated control configurations

SP	SF	SL	
one remote pressure transducer has to be installed on the actuator's port to be controlled	two remote pressure transducers have to be installed on the actuator's ports; the actuator force is calculated by the pressure feedbacks ($P_a - P_b$)	one load cell transducer has to be installed between the actuator and the controlled load	
T valve's spool transducer	M actuator's position transducer	P pressure transducer	L load cell

SP – position/pressure control

Adds pressure control to standard position control and permits to limit the max force in one direction controlling in closed loop the pressure acting on one side of the hydraulic actuator. A single pressure transducer has to be installed on hydraulic line to be controlled.

SF – position/force control

Adds force control to standard position control and permits to limit the max force in two directions controlling in closed loop the delta pressure acting on both sides of the hydraulic actuator. Two pressure transducers have to be installed on both hydraulic line.

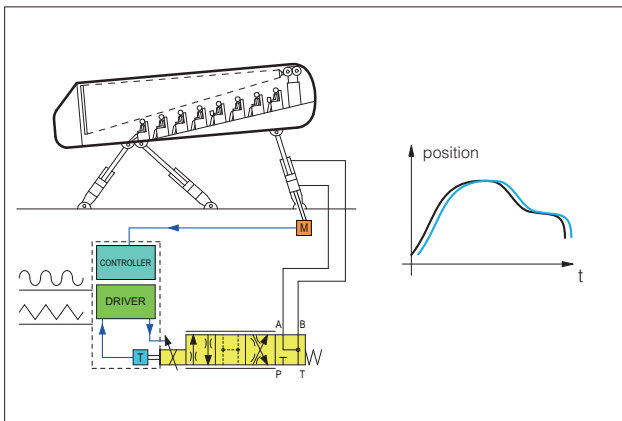
SL – position/force control

Adds force control to standard position control and permits to limit the max force in one or two directions controlling in closed loop the force performed by the hydraulic actuator. A load cell has to be installed on hydraulic actuator.

General Notes:

- servoproportional type DLHZA, DLKZA and DPZA-L are strongly recommended for high accuracy applications see tech tables **FX150, FX235**
- auxiliary check valves are recommended in case of specific hydraulic configuration requirements in absence of power supply or fault,
- for additional information about alternated P/Q controls configuration please refer to tech table **GS002**
- Atos technical service is available for additional evaluations related to specific applications usage

4 APPLICATION EXAMPLES



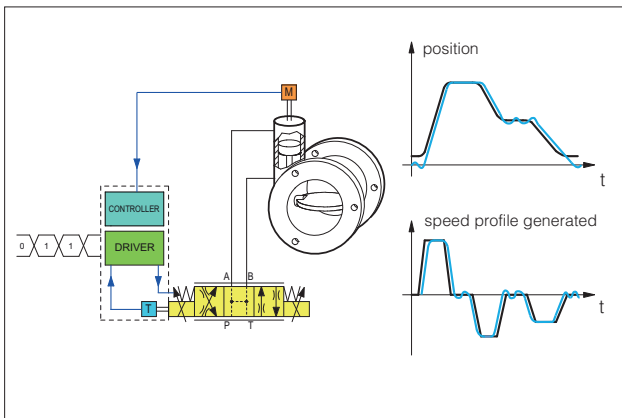
Multiaxis simulators

To obtain the desired simulation effects, the machine central electronic unit of multiaxis simulators generates the time-dependent motion profiles and synchronizes all the controlled axis.

DLHZA-T high performance servoproportional valve in steel sleeve execution allows to obtain fast, accurate and reliable movements of the system.

Axis controller allows high performance position control and easy optimization of the system architecture thanks to:

- analog position reference mode for real time motion profile synchronization
- analog position transducer for reliable and compact solution
- complete diagnostic functionalities for advanced system monitoring



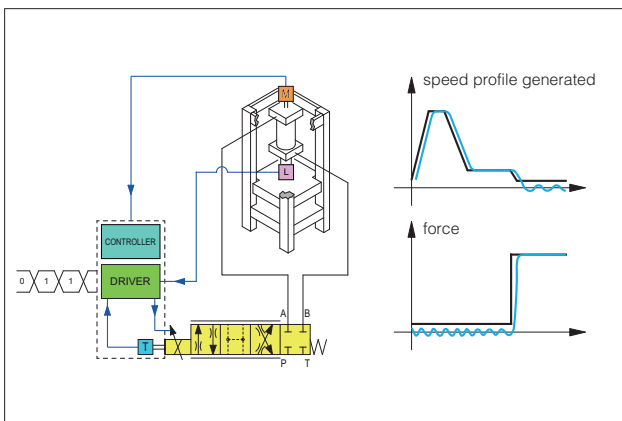
Process valves

Process valves motion regulation requires smooth and remote controls due to wide distributed applications.

DHZA-T proportional valve with spool position transducer allows smooth regulations and accurate movements.

Axis controller allows remote control thanks to:

- internal reference generation with maximum speed and acceleration settings for standing alone axis control
- potentiometer position transducer for compact and cost effective solution
- fieldbus connection for easy parameterization and remote commands



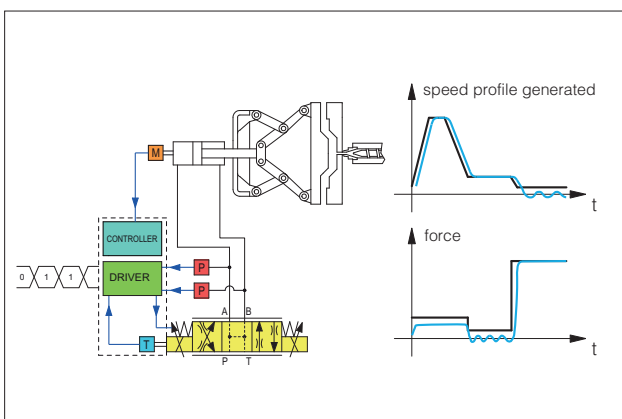
Hydraulic presses

Hydraulic presses perform shaft assembly with an accurate force and position control. Several set of motion parameters can be internally stored and selected by machine electronic control unit to adapt the presses performances to the specific production.

DLHZA-T high performance servoproportional valve in steel sleeve execution allows to obtain accurate position and force controls in a single device.

Axis controller with force control (SL control) performs position/force control thanks to:

- fieldbus reference mode for remote control
- encoder position transducer for accurate position control loop
- one load cell for alternated force control
- complete diagnostic functionalities for advanced system monitoring



Clamp control on plastic machines

Clamp movements involve fast/slow motion with accurate alternated position/force controls for the mould safety functions.

DKZA-T proportional valve allows to obtain quick and accurate regulations in the different working/control phases of the machine.

Axis controller with force control (SF control) simplifies the hydraulic + electronic system architecture and combines position/force regulation in a single device thanks to:

- internal reference generation for standing alone axis control
- SSI digital position transducer for high performance solution
- two pressure transducers for alternated force control
- fieldbus connection for machine remote control and advanced diagnostics

5 GENERAL NOTES

Atos digital proportionals valves are CE marked according to the applicable directives (e.g. Immunity and Emission EMC Directive). Installation, wirings and start-up procedures must be performed according to the general prescriptions shown in tech table **F003** and in the user manuals included in the Z-SW-* programming software.

6 VALVE SETTINGS AND PROGRAMMING TOOLS

Valve's functional parameters and configurations, can be easily set and optimized using Atos Z-SW programming software connected via USB port to the digital controller (see table **GS003**). For fieldbus versions, the software permits valve's parameterization through USB port also if the controller is connected to the central machine unit via fieldbus.

Z-SW-FULL support:

NP (USB)	PS (Serial)		
BC (CANopen)	BP (PROFIBUS DP)	EH (EtherCAT)	
EW (POWERLINK)	EI (EtherNet/IP)	EP (PROFINET)	

Note: Z-SW programming software supports valves with option SP, SF, SL for alternated control

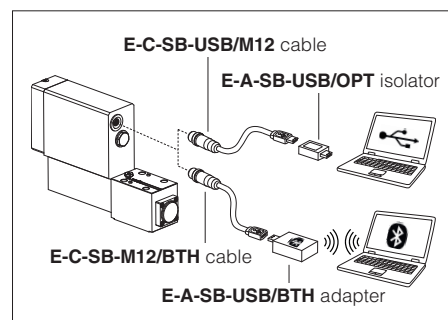


WARNING: drivers USB port is not isolated! For E-C-SB-USB/M12 cable, the use of isolator adapter is highly recommended for PC protection (see tech table **GS500**)



WARNING: Bluetooth adapter is available only for European, USA and Canadian markets! Bluetooth adapter is certified according RED (Europe), FCC (USA) and ISED (Canada) directives

USB or Bluetooth connection



7 FIELDBUS - see tech. table **GS510**

Fieldbus allows valve direct communication with machine control unit for digital reference, valve diagnostics and settings. These execution allow to operate the valves through fieldbus or analog signals available on the terminal board.

8 GENERAL CHARACTERISTICS

Assembly position	Any position		
Subplate surface finishing to ISO 4401	Acceptable roughness index: Ra ≤ 0,8, recommended Ra 0,4 – Flatness ratio 0,01/100		
MTTFd valves according to EN ISO 13849	DLHZA, DLKZA, DHZA, DKZA 150 years, see technical table P007	DPZA 75 years, see technical table P007	
Ambient temperature range	Standard = -20°C ÷ +60°C	/PE option = -20°C ÷ +60°C	/BT option = -40°C ÷ +60°C
Storage temperature range	Standard = -20°C ÷ +70°C	/PE option = -20°C ÷ +70°C	/BT option = -40°C ÷ +70°C
Surface protection	Zinc coating with black passivation		
Compliance	Explosion proof protection, see section 12		

9 HYDRAULIC CHARACTERISTICS - based on mineral oil ISO VG 46 at 50 °C

For hydraulic characteristics and performance diagrams, see tech tables of specific components:

DLHZA, DLKZA = ex-proof direct operated servoproportional sleeve execution, tech table **FX150**

DHZA, DKZA = ex-proof direct operated servoproportional, tech table **FX135**

DPZA = ex-proof pilot operated servoproportional, tech table **FX235**


10 ELECTRICAL CHARACTERISTICS

Power supplies	Nominal : +24 VDC Rectified and filtered : $V_{RMS} = 20 \div 32 V_{MAX}$ (ripple max 10 % VPP)			
Max power consumption	35 W			
Max. solenoid current	2,75 A			
Coil resistance R at 20°C	3,2 Ω			
Analog input signals	Voltage: range ± 10 VDC (24 VMAX tollerant) Current: range ± 20 mA		Input impedance: $R_i > 50$ k Ω Input impedance: $R_i = 500$ Ω	
Monitor outputs	Output range: voltage ± 10 VDC @ max 5 mA current ± 20 mA @ max 500 Ω load resistance			
Enable input	Range: 0 \div 5 Vdc (OFF state), 9 \div 24 Vdc (ON state), 5 \div 9 Vdc (not accepted); Input impedance: $R_i > 10$ k Ω			
Fault output	Output range: 0 \div 24 Vdc (ON state > [power supply - 2 V] ; OFF state < 1 V) @ max 50 mA; external negative voltage not allowed (e.g. due to inductive loads)			
Position transducers power supply	+24 Vdc @ max 100 mA and +5 Vdc @ max 100 mA are software selectable; ± 10 Vdc @ max 14 mA minimum load resistance 700 Ω			
Pressure/Force transducer power supply (only for SP, SF, SL)	+24Vdc @ max 100 mA (E-ATRA-7 see tech table GX800)			
Alarms	Solenoid not connected/short circuit, cable break with current reference signal, over/under temperature, valve spool transducer malfunctions, alarms history storage function			
Insulation class	H (180°) Due to the occuring surface temperatures of the solenoid coils, the European standards ISO 13732-1 and EN982 must be taken into account			
Protection degree to DIN EN60529	IP66 / IP67 with mating connectors			
Duty factor	Continuous rating (ED=100%)			
Tropicalization	Tropical coating on electronics PCB			
Additional characteristics	Short circuit protection of solenoid's current supply; 3 leds for diagnostic; spool position control by P.I.D. with rapid solenoid switching; protection against reverse polarity of power supply			
Electromagnetic compatibility (EMC)	According to Directive 2014/30/UE (Immunity: EN 61000-6-2; Emission: EN 61000-6-3)			
Communication interface	USB	CANopen	PROFIBUS DP	EtherCAT, POWERLINK, EtherNet/IP, PROFINET IO RT / IRT EC 61158
	Atos ASCII coding	EN50325-4 + DS408	EN50170-2/IEC61158	
Communication physical layer	not insulated	optical insulated	optical insulated	Fast Ethernet, insulated 100 Base TX
	USB 2.0 + USB OTG	CAN ISO11898	RS485	

Note: a maximum time of 800 ms (depending on communication type) have be considered between the controller energizing with the 24 VDC power supply and when the valve is ready to operate. During this time the current to the valve coils is switched to zero.

11 SEALS AND HYDRAULIC FLUIDS - for other fluids not included in below table, consult our technical office

Seals, recommended fluid temperature	NBR seals (standard) = -20°C \div +60°C, with HFC hydraulic fluids = -20°C \div +50°C FKM seals (/PE option) = -20°C \div +80°C HNBR seals (/BT option) = -40°C \div +60°C, with HFC hydraulic fluids = -40°C \div +50°C		
Recommended viscosity	20 \div 100 mm ² /s - max allowed range 15 \div 380 mm ² /s		
Max fluid contamination level	normal operation	ISO4406 class 18/16/13 NAS1638 class 7	see also filter section at www.atos.com or KTF catalog
	longer life	ISO4406 class 16/14/11 NAS1638 class 5	
Hydraulic fluid	Suitable seals type	Classification	Ref. Standard
Mineral oils	NBR, FKM, HNBR	HL, HLP, HLPD, HVLP, HVLPD	DIN 51524
Flame resistant without water	FKM	HFDU, HFDR	ISO 12922
Flame resistant with water	NBR, HNBR	HFC	

 The ignition temperature of the hydraulic fluid must be 50°C higher than the max solenoid surface temperature

(1) Performance limitations in case of flame resistant fluids with water:

- max operating pressure = 210 bar
- max fluid temperature = 50°C

12 CERTIFICATION DATA

Valve type	DHZA, DKZA				
Certifications	Multicertification and Group II ATEX IECEx				
Solenoid certified code	OZA-TES				
Type examination certificate (1)	• ATEX: TUV IT 18 ATEX 068 X		• IECEx: IECEx TPS 19.0004X		
Method of protection	• ATEX 2014/34/EU Ex II 2G Ex db IIC T6/T5 Gb Ex II 2D Ex tb IIIC T85°C/T100°C Db		• IECEx Ex db IIC T6,T5 Gb Ex tb IIIC T85°C/T100°C Db		
Temperature class	Single solenoid valve	T6	-	T5	T4
	Double solenoid valve	-	T4	-	T3
Surface temperature	≤ 85 °C	≤ 135 °C	≤ 100 °C	≤ 135 °C	≤ 200 °C
Ambient temperature (2)	-40 ÷ +40 °C		-40 ÷ +55 °C		-40 ÷ +70 °C
Applicable Standards	EN 60079-0: 2012+A11:2013 EN 60079-1:2014	EN 60079-31:2014	IEC 60079-0:2017 IEC 60079-1:2014	IEC 60079-31:2013	
Cable entrance: threaded connection	M = M20x1,5				

(1) The type examiner certificates can be downloaded from www.atos.com

(2) The driver and solenoids are certified for minimum ambient temperature -40°C.

In case the complete valve must withstand with minimum ambient temperature -40°C, select **/BT** in the model code.



WARNING: service work performed on the valve by the end users or not qualified personnel invalidates the certification.

13 CABLE SPECIFICATION AND TEMPERATURE - Power supply and grounding cables have to comply with following characteristics:

Power supply and signals: section of wire = 1,0 mm²

Grounding: section of external ground wire = 4 mm²

13.1 Cable temperature

The cable must be suitable for the working temperature as specified in the "safety instructions" delivered with the first supply of the products.

Max ambient temperature [°C]	Temperature class	Max surface temperature [°C]	Min. cable temperature [°C]
40 °C	T6	85 °C	80 °C
55 °C	T5	100 °C	90 °C
70 °C	T4	135 °C	110 °C

14 CABLE GLANDS

Cable glands with threaded connections M20x1,5 for standard or armoured cables have to be ordered separately, see tech table **KX600**


Note: a Loctite sealant type 545, should be used on the cable gland entry threads

15 POWER SUPPLY AND SIGNALS SPECIFICATIONS

Generic electrical output signals of the valve (e.g. fault or monitor signals) must not be directly used to activate safety functions, like to switch-ON/OFF the machine's safety components, as prescribed by the European standards (Safety requirements of fluid technology systems and components-hydraulics, EN-982).

15.1 Power supply (V+ and V0)


The power supply must be appropriately stabilized or rectified and filtered: apply at least a 10000 μ F/40 V capacitance to single phase rectifiers or a 4700 μ F/40 V capacitance to three phase rectifiers.

 A safety fuse is required in series to each power supply: 2,5 A time lag fuse.

15.2 Power supply for driver's logic and communication (VL+ and VL0)

The power supply for controller's logic and communication must be appropriately stabilized or rectified and filtered: apply at least a 10000 μ F/40 V capacitance to single phase rectifiers or a 4700 μ F/40 V capacitance to three phase rectifiers.

The separate power supply for controller's logic on pin 3 and 4, allow to remove solenoid power supply from pin 1 and 2 maintaining active the diagnostics, USB and fieldbus communications.

 A safety fuse is required in series to each driver's logic and communication power supply: 500 mA fast fuse.

15.3 Position reference input signal (P_INPUT+)

Functionality of P_INPUT+ signal (pin 10), depends on controller's reference mode, see section 2 :

External analog reference generation (see 2.1): input is used as reference for the controller axis position closed loop.

Reference input signal is factory preset according to selected valve code, defaults are ± 10 VDC for standard and $4 \div 20$ mA for /I option.

Input signal can be reconfigured via software selecting between voltage and current, within a maximum range of ± 10 VDC or ± 20 mA.

Fieldbus/internal reference generation (see 2.2): analog reference input signal can be used as on-off commands with input range $0 \div 24$ VDC.

15.4 Pressure or force reference input signal (F_INPUT+) - only for SP, SF, SL

Functionality of F_INPUT+ signal (pin 12), depends on selected controllers' reference mode and alternated control options, see section 3 :

SP, SL, SF controls and external analog reference selected : input is used as reference for the controller pressure/force closed loop.

Reference input signal is factory preset according to selected valve code, defaults are ± 10 VDC for standard and $4 \div 20$ mA for /I option.

Input signal can be reconfigured via software selecting between voltage and current, within a maximum range of ± 10 VDC or ± 20 mA.

SN control or fieldbus/internal reference selected: analog reference input signal can be used as on-off commands with input range $0 \div 24$ VDC.

15.5 Position monitor output signal (P_MONITOR)

The controller generates an analog output signal (pin 9) proportional to the actual axis position; the monitor output signal can be software set to show other signals available in the controller (e.g. analog reference, fieldbus reference, position error, valve spool position).

Monitor output signal is factory preset according to selected valve code, defaults are ± 10 Vdc for standard and $4 \div 20$ mA for /I option.

Output signal can be reconfigured via software selecting between voltage and current, within a maximum range of ± 10 VDC or ± 20 mA.

15.6 Pressure or force monitor output signal (F_MONITOR) - only for SP, SF, SL

The controller generates an analog output signal (pin 11) according to alternated pressure/force control option:

SN control: output signal is proportional to the actual valve spool position

SP, SL, SF controls: output signal is proportional to the actual pressure/force applied to the cylinder's rod end

Monitor output signals can be software set to show other signals available in the controller (e.g. analog reference, force reference).

The output range and polarity are software selectable within the maximum range ± 10 VDC or ± 20 mA.

Monitor output signal is factory preset according to selected valve code, defaults are ± 10 Vdc for standard and $4 \div 20$ mA for /I option.

Output signal can be reconfigured via software selecting between voltage and current, within a maximum range of ± 10 VDC or ± 20 mA.

15.7 Enable input signal (ENABLE)

To enable the controller, a 24VDC voltage has to be applied on pin 6.

When the Enable signal is set to zero the controller can be software set to perform one of the following actions:

- maintain the actuator actual position in close loop control
- move towards a predefined position in closed loop control and maintains the reached position (hold position)
- move forward or backward in open loop (only the valve's closed loop remain active)

15.8 Fault output signal (FAULT)

Fault output signal indicates fault conditions of the controller (solenoid short circuits/not connected, reference or transducer signal cable broken, maximum error exceeded, etc.). Fault presence corresponds to 0 VDC, normal working corresponds to 24 VDC.

Fault status is not affected by the Enable input signal.

Fault output signal can be used as digital output by software selection.

15.9 Position transducer input signal

A position transducer must be always directly connected to the controller. Select the correct controller execution depending on the desired transducer interface: digital SSI or Encoder (D execution), potentiometer or a generic transducer with analog interface (A execution).

Position digital input signal is factory preset to binary SSI, it can be reconfigured via software selecting between binary/gray SSI and Encoder.

Position analog input signal is factory preset according to selected valve code, defaults are ± 10 VDC for standard and $4 \div 20$ mA for /C option.

Input signal can be reconfigured via software selecting between voltage and current, within a maximum range of ± 10 VDC or ± 20 mA.

Refer to position transducer characteristics to select the transducer type according to specific application requirements (see 16.1).

15.10 Remote pressure/force transducer input signals - only for SP, SF, SL

Analog remote pressure transducers or load cell can be directly connected to the controller.

Analog input signal is factory preset according to selected valve code, defaults are ± 10 Vdc for standard and $4 \div 20$ mA for /C option.

Input signal can be reconfigured via software selecting between voltage and current, within a maximum range of ± 10 VDC or ± 20 mA.

Refer to pressure/force transducer characteristics to select the transducer type according to specific application requirements (see 16.2).

16 ACTUATOR'S TRANSDUCER CHARACTERISTICS

16.1 Position transducers

The accuracy of the position control is strongly dependent to the selected position transducer. Four different transducer interfaces are available on the controllers, depending to the system requirements: potentiometer or analog signal (A execution), SSI or Encoder (D execution). Transducers with digital interface allow high resolution and accurate measures, that combined with fieldbus communication grants highest performances. Transducers with analog interface grant simple and cost effective solutions.

16.2 Pressure/force transducers

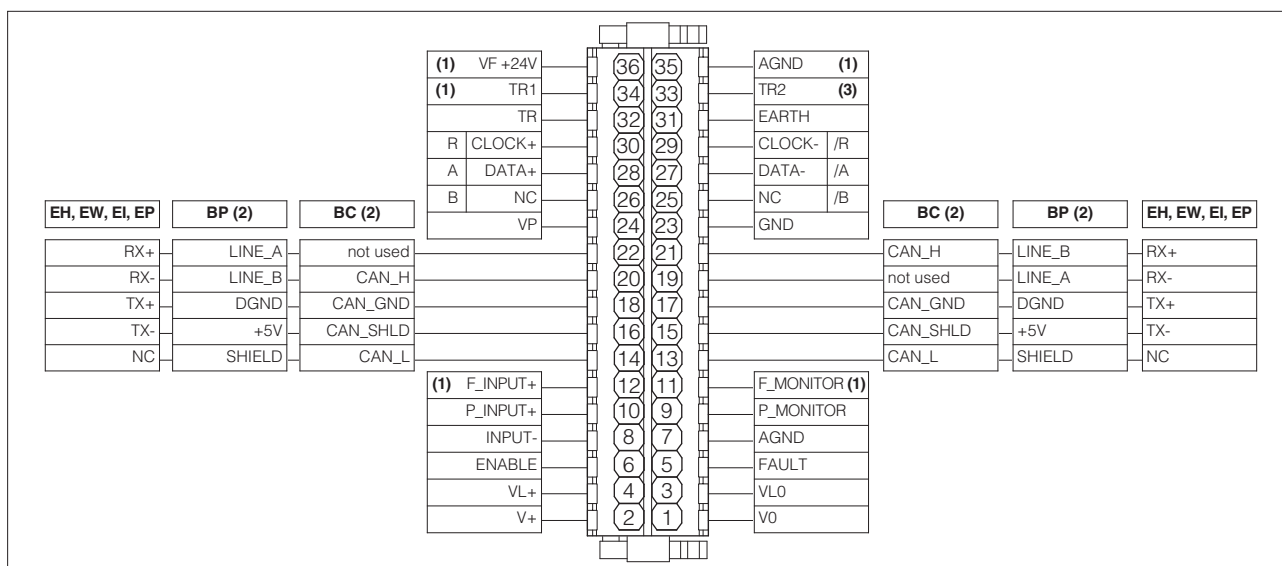
The accuracy of the pressure/force control is strongly dependent to the selected pressure/force transducer, see section 3. Alternated pressure/force controls require to install pressure transducers or load cell to measure the actual pressure/force values. Pressure transducers allow easy system integration and cost effective solution for both alternated position/pressure and position/force controls (see tech table **GX800** for pressure transducers details). Load cell transducers allow the user to get high accuracy and precise regulations for alternated position/force control. The characteristics of the remote pressure/force transducers must be always selected to match the application requirements and to obtain the best performances: transducer nominal range should be at least 115%÷120% of the maximum regulated pressure/force.

16.3 Transducers characteristics & interfaces - following values are just for reference, for details please consult the transducer's datasheet

Execution	Position				Pressure/Force
	A	Analog	SSI (3)	D	SP, SF, SL
Input type	Potentiometer	Analog	SSI (3)	Incremental Encoder	Analog
Power supply (1)	±10 Vdc	+24 Vdc	+5 Vdc / +24 Vdc	+5 Vdc / +24 Vdc	+24 Vdc
Controller Interface	±10V	0 ÷ 10V 4 ÷ 20 mA	Serial SSI binary/gray	TTL 5Vpp - 150 KHz	±10 Vdc 4 ÷ 20 mA
Max speed	0,5 m/s	1 m/s	2 m/s	2 m/s	-
Max Resolution	< 0.4 % FS	< 0.2 % FS	1 µm	1 µm (@ 0.15 m/s)	< 0.4 % FS
Linearity error (2)	± 0.1% FS	< ±0.03% FS	< ± 0.01 % FS	< ± 0.001 % FS	< ±0.25% FS
Repeatability (2)	± 0.05% FS	< ± 0.005% FS	< ± 0.001 % FS	< ± 0.001 % FS	< ±0.1% FS

(1) Power supply provided by Atos controller (2) Percentage of total stroke (3) For Balluff BTL7 with SSI interface only special code SA433 is supported

17 TERMINAL BOARD OVERVIEW



(1) Connections available only for **SP, SF, SL**

(2) For BC and BP executions the fieldbus connections have an internal pass-through connection

(3) Connection available only for **SF**

18 ELECTRONIC CONNECTIONS

18.1 Main connections signals

CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATIONS	NOTES
A	1	V0	Power supply 0 Vdc	Gnd - power supply
	2	V+	Power supply 24 Vdc	Input - power supply
	3	VL0	Power supply 0 Vdc for driver's logic and communication	Gnd - power supply
	4	VL+	Power supply 24 Vdc for driver's logic and communication	Input - power supply
	5	FAULT	Fault (0 Vdc) or normal working (24 Vdc), referred to VL0	Output - on/off signal
	6	ENABLE	Enable (24 Vdc) or disable (0 Vdc) the driver, referred to VL0	Input - on/off signal
	7	AGND	Analog ground	Gnd - analog signal
	8	INPUT-	Negative reference input signal for P_INPUT+ and F_INPUT+	Input - analog signal
	9	P_MONITOR	Position monitor output signal: ± 10 Vdc / ± 20 mA maximum range, referred to AGND Defaults are: ± 10 Vdc for standard and $4 \div 20$ mA for // option	Output - analog signal Software selectable
	10	P_INPUT+	Position reference input signal: ± 10 Vdc / ± 20 mA maximum range Defaults are: ± 10 Vdc for standard and $4 \div 20$ mA for // option	Input - analog signal Software selectable
	11	F_MONITOR	Pressure/Force (SP, SF, SL controls) or valve spool position (SN control) monitor output signal: ± 10 Vdc / ± 20 mA maximum range, referred to AGND Defaults are: ± 10 Vdc for standard and $4 \div 20$ mA for // option	Output - analog signal Software selectable
	12	F_INPUT+	Pressure/Force reference input signal (SP, SF, SL controls): ± 10 Vdc / ± 20 mA max. range Defaults are: ± 10 Vdc for standard and $4 \div 20$ mA for // option	Input - analog signal Software selectable
31	EARTH	Internally connected to driver housing		

18.2 USB connector - M12 - 5 pin always present

CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATIONS	Driver view	
B	1	+5V_USB	Power supply		
	2	ID	Identification		
	3	GND_USB	Signal zero data line		
	4	D-	Data line -		
	5	D+	Data line +		

18.3 BC fieldbus execution connections

CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATIONS
C1	14	CAN_L	Bus line (low)
	16	CAN_SHLD	Shield
	18	CAN_GND	Signal zero data line
	20	CAN_H	Bus line (high)
	22	not used	Pass-through connection (1)

CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATIONS
C2	13	CAN_L	Bus line (low)
	15	CAN_SHLD	Shield
	17	CAN_GND	Signal zero data line
	19	not used	Pass-through connection (1)
	21	CAN_H	Bus line (high)

(1) Pin 19 and 22 can be fed with external +5V supply of CAN interface

18.4 BP fieldbus execution connections

CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATIONS
C1	14	SHIELD	
	16	+5V	Power supply
	18	DGND	Data line and termination signal zero
	20	LINE_B	Bus line (low)
	22	LINE_A	Bus line (high)

CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATIONS
C2	13	SHIELD	
	15	+5V	Power supply
	17	DGND	Data line and termination signal zero
	19	LINE_A	Bus line (high)
	21	LINE_B	Bus line (low)

18.5 EH, EW, EI, EP fieldbus execution connections

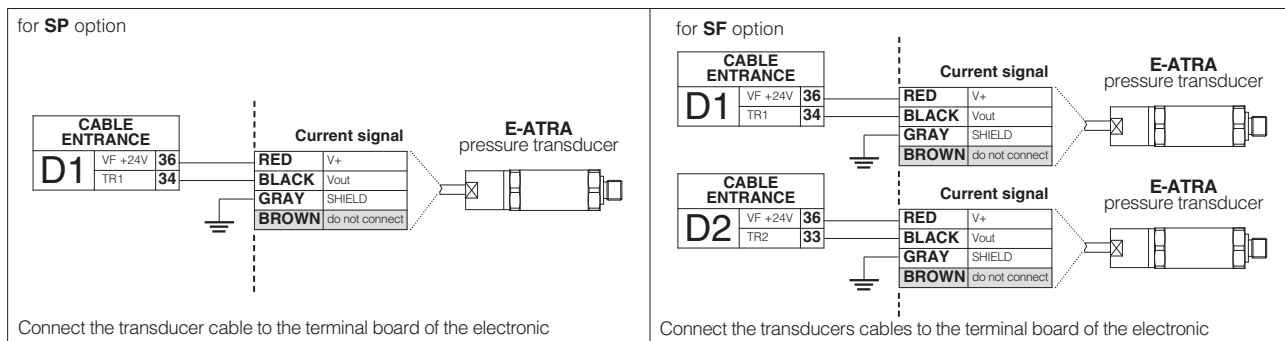
CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATIONS
C1 (input)	14	NC	do not connect
	16	TX-	Transmitter
	18	TX+	Transmitter
	20	RX-	Receiver
	22	RX+	Receiver

CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATIONS
C2 (output)	13	NC	do not connect
	15	TX-	Transmitter
	17	TX+	Transmitter
	19	RX-	Receiver
	21	RX+	Receiver

18.6 Remote pressure transducer connections - only for SP, SF, SL

CABLE ENTRANCES	PIN	SIGNAL	TECHNICAL SPECIFICATIONS	NOTES	SP, SL - Single transducer (1)		SF - Double transducers (1)	
					Voltage	Current	Voltage	Current
D1	33	TR2	2nd signal transducer ± 10 Vdc / ± 20 mA maximum range	Input - analog signal Software selectable	/	/	Connect	Connect
	34	TR1	1st signal transducer ± 10 Vdc / ± 20 mA maximum range	Input - analog signal Software selectable	Connect	Connect	Connect	Connect
D2	35	AGND	Common gnd for transducer power and signals	Common gnd	Connect	/	Connect	/
	36	VF +24V	Power supply +24Vdc	Output - power supply	Connect	Connect	Connect	Connect

E-ATRA remote pressure transducer connection - example

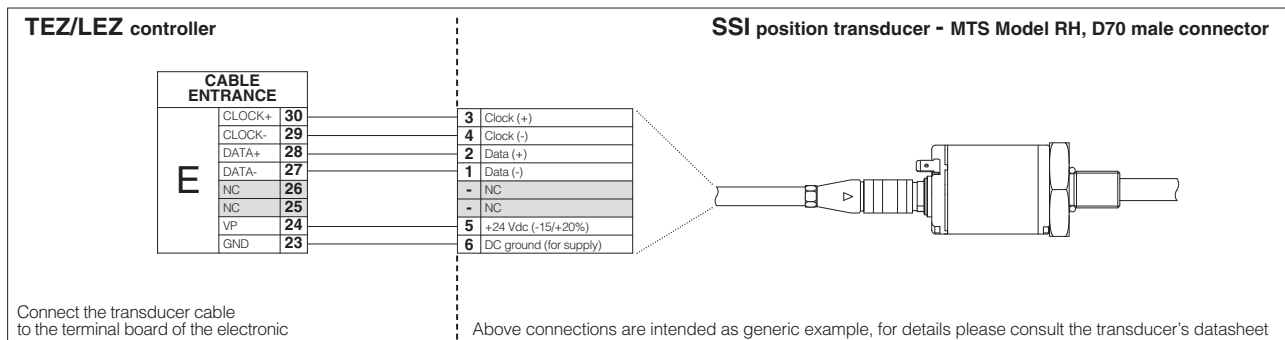


18.7 D execution - Digital position transducers connections

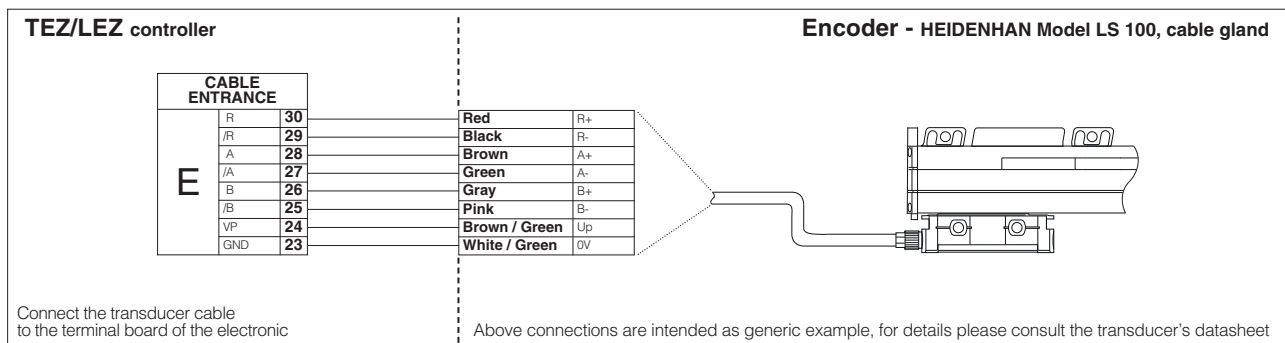
CABLE ENTRANCE	PIN	SSI - default transducer (1)			Encoder (1)		
		SIGNAL	TECHNICAL SPECIFICATION	NOTES	SIGNAL	TECHNICAL SPECIFICATION	NOTES
E	30	CLOCK+	Serial synchronous clock (+)	Input - digital signal	R	Input channel R	Input - digital signal
	29	CLOCK-	Serial synchronous clock (-)		/R	Input channel /R	
	28	DATA+	Serial position data (+)		A	Input channel A	
	27	DATA-	Serial position data (-)		/A	Input channel /A	
	26	NC	Not connect	Do not connect	B	Input channel B	
	25	NC			/B	Input channel /B	
	24	VP	Power supply: +24Vdc , +5Vdc or OFF (default OFF)	Output - power supply Software selectable	VP	Power supply: +24Vdc , +5Vdc or OFF (default OFF)	Output - power supply Software selectable
23	GND	Common gnd for transducer power and signals	Common gnd	GND	Common gnd for transducer power and signals	Common gnd	

(1) Digital position transducer type is software selectable: Encoder or SSI, see 15.9

SSI connection - example



Encoder connection - example



18.8 A execution - Analog position transducers connector

CABLE ENTRANCE	PIN	SIGNAL	TECHNICAL SPECIFICATION	NOTES
E	32	TR	Signal transducer	Input - analog signal
	24	VP	Power supply: +24Vdc or OFF (default OFF)	Output - power supply Software selectable
	23	GND	Common gnd for transducer power and signals	Common gnd

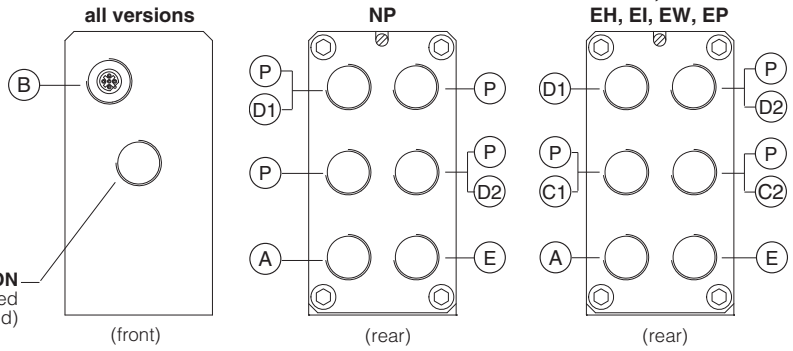
CABLE ENTRANCE OVERVIEW

Cables entrance description:

- (A) main connections
- (B) USB connector always present (factory plugged)
- (C1) fieldbus (input)
- (C2) fieldbus (output)
- (D1) pressure transducer 1
- (D2) pressure transducer 2
- (E) position transducer
- (P) threaded plug

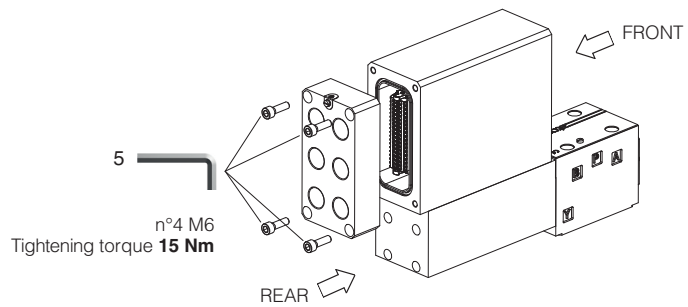
COIL CONNECTION

only for 05H version - factory wired
(for 01H version - factory plugged)



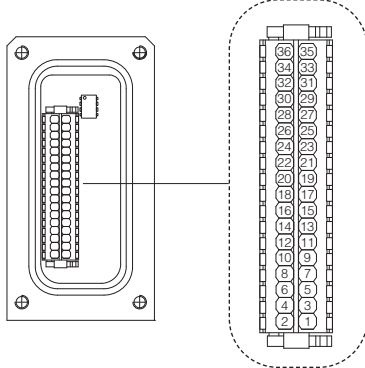
TERMINAL BOARD AND FIELDBUS TERMINATOR

Remove the 4 screws of driver's rear cover to access terminal board and fieldbus terminator

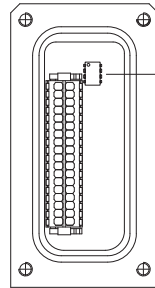


WARNING: the above operation must be performed in a safety area

Terminal board - see section 17



Fieldbus terminator only for BC and BP executions (1)



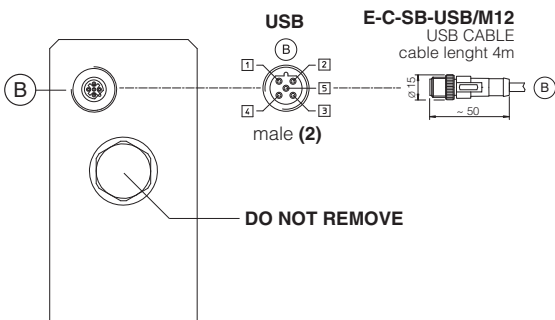
BC - CANopen setting:

Switch	Termination enabled
1	OFF
2	OFF
3	OFF
4	ON

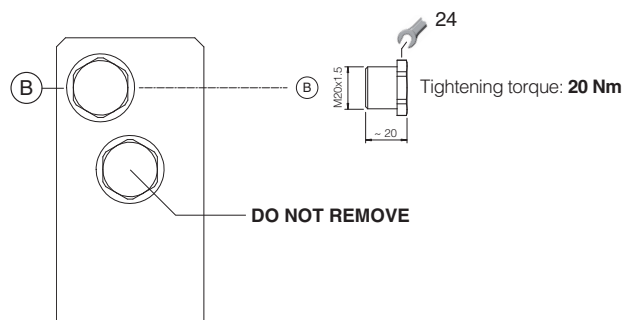
BP - PROFIBUS DP setting:

Switch	Termination enabled
1	ON
2	ON
3	OFF
4	OFF

USB CONNECTOR

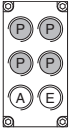
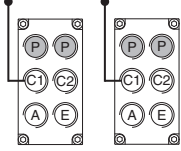
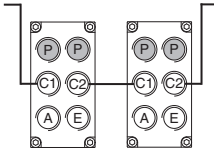


METALLIC PROTECTION CAP - supplied with the valves

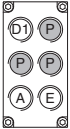
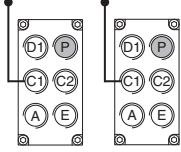
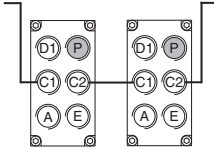


(1) Drivers with BC and BP fieldbus interface are delivered by default 'Not Terminated'. All switches are set OFF
(2) Pin layout always referred to driver's view

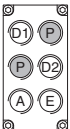
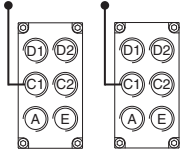
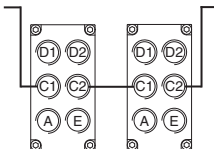
19.1 Cable glands and threaded plug for SN

Communication interfaces	To be ordered separately				Cable entrance overview	Notes
	Cable gland quantity	entrance	Threaded plug quantity	entrance		
NP	2	A - E	none	none		Cable entrance A, E are open for costumers Cable entrance P are factory plugged
BC, BP, EH, EW, EI, EP "via stub" connection	3	C1 A - E	1	C2		Cable entrance A, E, C1, C2 are open for costumers Cable entrance P are factory plugged
BC, BP, EH, EW, EI, EP "daisy chain" connection	4	C1 - C2 A - E	none	none		Cable entrance A, E, C1, C2 are open for costumers Cable entrance P are factory plugged

19.2 Cable glands and threaded plug for SP, SL - with one pressure transducer

Communication interfaces	To be ordered separately				Cable entrance overview	Notes
	Cable gland quantity	entrance	Threaded plug quantity	entrance		
NP	3	D1 A - E	none	none		Cable entrance A, E, D1 are open for costumers Cable entrance P are factory plugged
BC, BP, EH, EW, EI, EP "via stub" connection	4	D1 C1 A - E	1	C2		Cable entrance A, E, C1, C2, D1 are open for costumers Cable entrance P are factory plugged
BC, BP, EH, EW, EI, EP "daisy chain" connection	5	D1 C1 - C2 A - E	none	none		Cable entrance A, E, C1, C2, D1 are open for costumers Cable entrance P are factory plugged

19.3 Cable glands and threaded plug for SF - with double pressure transducers

Communication interfaces	To be ordered separately				Cable entrance overview	Notes
	Cable gland quantity	entrance	Threaded plug quantity	entrance		
NP	4	D1 D2 A - E	none	none		Cable entrance A, E, D1, D2 are open for costumers Cable entrance P are factory plugged
BC, BP, EH, EW, EI, EP "via stub" connection	5	D1 - D2 C1 A - E	1	C2		Cable entrance A, E, C1, C2, D1, D2 are open for costumers
BC, BP, EH, EW, EI, EP "daisy chain" connection	6	D1 - D2 C1 - C2 A - E	none	none		Cable entrance A, E, C1, C2, D1, D2 are open for costumers

20 MAIN SOFTWARE PARAMETER SETTINGS

For a detailed descriptions of the available settings, wirings and installation procedures, please refer to the user manuals included in the Z-SW programming software:

Z-MAN-RA-LEZ - user manual for **TEZ** and **LEZ** with **SN**

Z-MAN-RA-LEZ-S - user manual for **TEZ** and **LEZ** with **SP, SF, SL**

20.1 External reference and transducer parameters

Allow to configure the controller reference and transducer inputs, analog or digital, to match the specific application requirements:

- *Scaling parameters* define the correspondence of these signals with the specific actuator stroke or force to be controlled
- *Limit parameters* define maximum/minimum stroke and force to detect possible alarm conditions
- *Homing parameters* define the startup procedure to initialize incremental transducer (e.g. Encoder)

20.2 PID control dynamics parameters

Allow to optimize and adapt the controller closed loop to the wide range of hydraulic system characteristics:

- *PID parameters* each part of the closed loop algorithm (proportional, integral, derivative, feed forward, fine positioning, etc) can be modified to match the application requirements

20.3 Monitoring parameters

Allow to configure the controller monitoring function of the positioning error (difference between actual reference and feedback) and detects anomalous conditions:

- *Monitoring parameters* maximum allowed errors can be set for both static and dynamic positioning phases, and dedicated waiting times can be set to delay the activation of the alarm condition and relevant reaction (see 20.4)

20.4 Fault parameters

Allow to configure how the controller detect and react to alarm conditions:

- *Diagnostics parameters* define different conditions, threshold and delay time to detect alarm conditions
- *Reaction parameters* define different actions to be performed in case of alarm presence (stop at actual or preprogrammed position, emergency forward/backward, controller disabling, etc.)

20.5 Valve characteristics compensation

Allow to modify the valve regulation to match the actuator/system characteristics and to obtain the best overall performances:

- *Valve parameters* modify the standard valve regulation by means of deadband compensation, curve linearization and differentiated gain for positive and negative regulation

20.6 Motion phases parameters

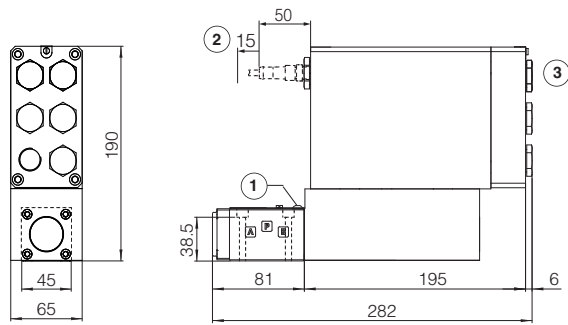
When the internal reference generation is active a pre-programmed cycle can be generated; start/stop/switch-over commands and reference generation types parameters can be set to design a customized sequence of motion phases adapted to the specific application requirements (see 2.2).

21 FASTENING BOLTS AND SEALS

Type	Size	Fastening bolts	Seals
DLHZA	06	4 socket head screws M5x50 class 12.9 Tightening torque = 8 Nm	4 OR 108; Diameter of ports A, B, P, T: Ø 7,5 mm (max) 1 OR 2025 Diameter of port Y: Ø = 3,2 mm (only for /Y option)
DLKZA	10	4 socket head screws M6x40 class 12.9 Tightening torque = 15 Nm	5 OR 2050; Diameter of ports A, B, P, T: Ø 11,2 mm (max) 1 OR 108 Diameter of port Y: Ø = 5 mm (only for /Y option)
DHZA	06	4 socket head screws M5x50 class 12.9 Tightening torque = 8 Nm	4 OR 108; Diameter of ports A, B, P, T: Ø 7,5 mm (max) 1 OR 2025 Diameter of port Y: Ø = 3,2 mm (only for /Y option)
DKZA	10	4 socket head screws M6x40 class 12.9 Tightening torque = 15 Nm	5 OR 2050; Diameter of ports A, B, P, T: Ø 11,2 mm (max) 1 OR 108 Diameter of port Y: Ø = 5 mm (only for /Y option)
DPZA	1 = 10	4 socket head screws M6x40 class 12.9 Tightening torque = 15 Nm	5 OR 2050; Diameter of ports A, B, P, T: Ø 11 mm (max) 2 OR 108 Diameter of ports X, Y: Ø = 5 mm (max)
	2 = 16	4 socket head screws M10x50 class 12.9 Tightening torque = 70 Nm 2 socket head screws M6x45 class 12.9 Tightening torque = 15 Nm	4 OR 130; Diameter of ports A, B, P, T: Ø 20 mm (max) 2 OR 2043 Diameter of ports X, Y: Ø = 7 mm (max)
	4 = 25	6 socket head screws M12x60 class 12.9 Tightening torque = 125 Nm	4 OR 4112; Diameter of ports A, B, P, T: Ø 24 mm (max) 2 OR 3056 Diameter of ports X, Y: Ø = 7 mm (max)
	4M = 27	6 socket head screws M12x60 class 12.9 Tightening torque = 125 Nm	4 OR 3137; Diameter of ports A, B, P, T: Ø 32 mm (max) 2 OR 3056 Diameter of ports X, Y: Ø = 7 mm (max)

22 INSTALLATION DIMENSIONS FOR DLHZA and DLKZA [mm]

DLHZA-TEZ-*



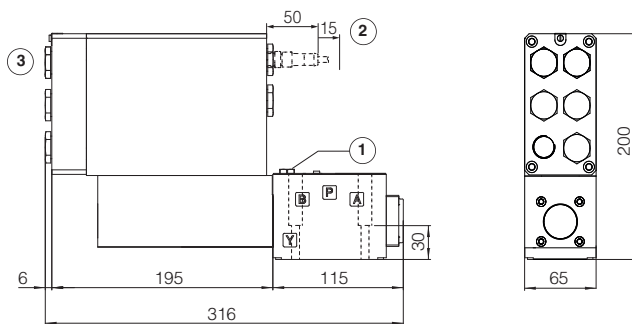
ISO 4401: 2005

Mounting surface: 4401-03-02-0-05
(see table P005)

Mass [kg]	
DLHZA	7,2

- ① = Air bleeding 3
- ② = Space to remove the connectors
- ③ = The dimensions of all connectors must be considered, see section 15.6

DLKZA-TEZ-*



ISO 4401: 2005

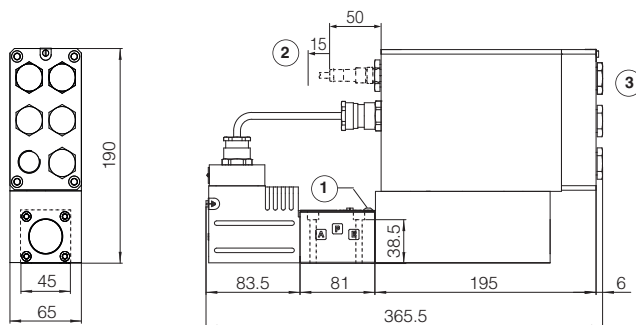
Mounting surface: 4401-05-04-0-05
(see table P005)

Mass [kg]	
DLKZA	9

- ① = Air bleeding 4
- ② = Space to remove the connectors 3
- ③ = The dimensions of all connectors must be considered, see section 15.6

23 INSTALLATION DIMENSIONS FOR DHZA and DKZA [mm]

DHZA-TEZ-*



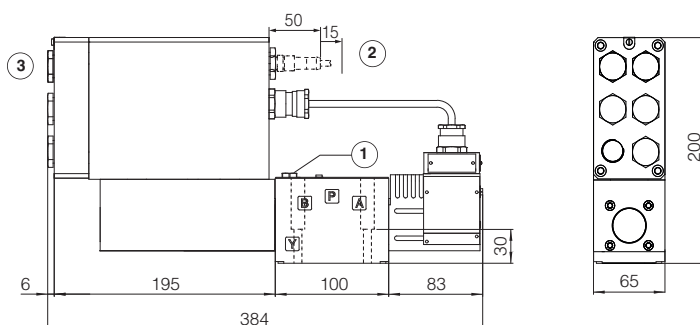
ISO 4401: 2005

Mounting surface: 4401-03-02-0-05
(see table P005)

Mass [kg]	
DHZA	8,9

- ① = Air bleeding 3
- ② = Space to remove the connectors
- ③ = The dimensions of all connectors must be considered, see section 15.6

DKZA-TEZ-*



ISO 4401: 2005

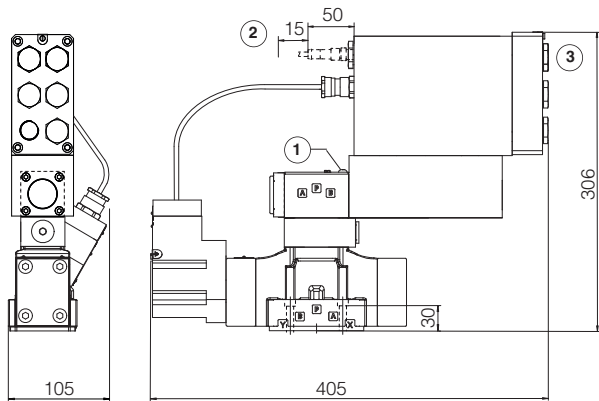
Mounting surface: 4401-05-04-0-05
(see table P005)

Mass [kg]	
DKZA	10,7

- ① = Air bleeding 4 13
- ② = Space to remove the connectors
- ③ = The dimensions of all connectors must be considered, see section 15.6

24 INSTALLATION DIMENSIONS FOR DPZA [mm]

DPZA-LEZ-1*

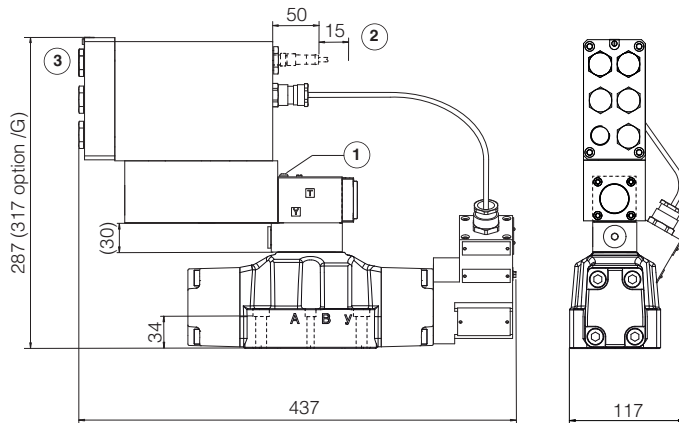


ISO 4401: 2005
Mounting surface: 4401-05-05-0-05
 (see table P005)

Mass [kg]	
DPZA-*-1	13.7

- ① = Air bleeding 3
- ② = Space to remove the connectors
- ③ = The dimensions of all connectors must be considered, see section 15.6

DPZA-LEZ-2*

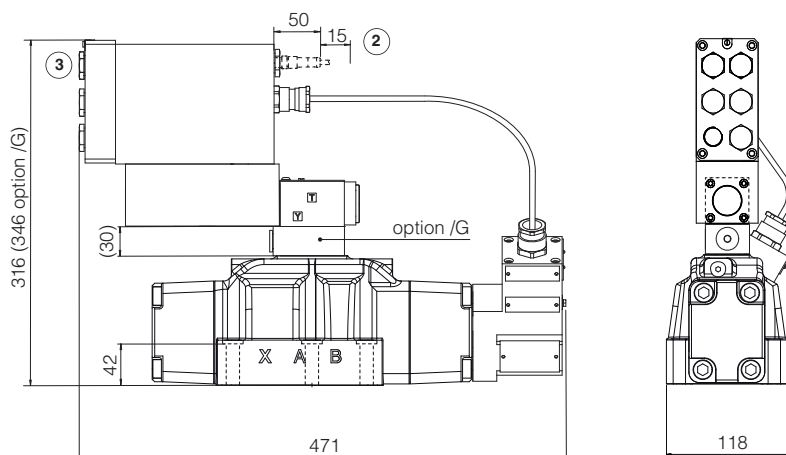


ISO 4401: 2005
Mounting surface: 4401-07-07-0-05
 (see table P005)

Mass [kg]	
DPZA-*-2	17.9

- ① = Air bleeding 3
- ② = Space to remove the connectors
- ③ = The dimensions of all connectors must be considered, see section 15.6

DPZA-LEZ-4*



ISO 4401: 2005
Mounting surface: 4401-08-08-0-05
 (see table P005)

Mass [kg]	
DPZA-*-4	23

- ① = Air bleeding 3
- ② = Space to remove the connectors
- ③ = The dimensions of all connectors must be considered, see section 15.6

25 RELATED DOCUMENTATION

- X010** Basics for digital electrohydraulics
- X020** Summary of Atos ex-proof components range certified to ATEX, IECEx, EAC, PESO
- X100** Operating and maintenance norms for ex-proof proportional valves
- FX135** Ex-proof direct operated servoproportionals
- FX150** Ex-proof direct operated servoproportional sleeve execution
- FX235** Ex-proof pilot operated servoproportionals