

Reference Sheet ASA56



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1 Document, audience, intended use

Nanotec's ASA56 and this document address to technically trained experts alone, such as developers, application /plant engineers, fitters, and service staff. Only experts may install, commission and run the product. Always required is the qualification for the product's assembly, commissioning and maintenance as part of an *overall* machine /system, as well as:

- Training and experience in working with motors, their control and electrostatically threatened components
- Reading and understanding of this and all applicable documents
- Observing all valid regulations

Place this PDF in valid version always to hand and accessible. Use ASA56 as intended only, within licit technical limits and ambients. For product combinations, please contact Nanotec Sales.

Disclaimer

Product modification /alteration is illicit. Nanotec is not liable for damage /malfunction from installation error, failure to observe this document, or undue repair; nor for product integration in the end system or interaction (= third-party ware). The audience alone is liable for selecting /running /using our products. Our risk analysis for partly completed machinery (if applicable) only rated the hazards of duly installed and networked *single* products. Risks in the *overall* system are exempt and to be rated by the *audience*. The general terms & conditions at www.nanotec.com apply (us.nanotec.com for clients of Nanotec USA).

2 Your product

ASA56 is a stepper motor in IP65 protection (save shaft outlet) with integrated incremental or multi-turn encoder for drive systems in a wide range of industrial scenarios.

2.1 Highlights

Typical ASA56 features are: size variance, holding force, and precision.

- UL certificate
- Protection class IP65 (shaft outlet: IP54)
- 2 motor sizes
- Optional brake integrated (on request)
- High encoder resolution

2.2 ASA56 variants

Find your product variant by its article number.

ASA5618X42-xxX	Motor length Medium Large
ASA5618x42-xxX	Encoder E3 : Incremental W1 : SSI

2.3 Product layout

Internalize the ASA56 product layout and technical data before installation so as to avert added hazards (say, abrupt motor run on defect / inhibition from your **overall** construct).

- ASA56 size sheet
- Torque tool to bolt the motor
- Flange *NEMA23*
- 4 *M5* screws 8.8 (ISO 4762/10642)

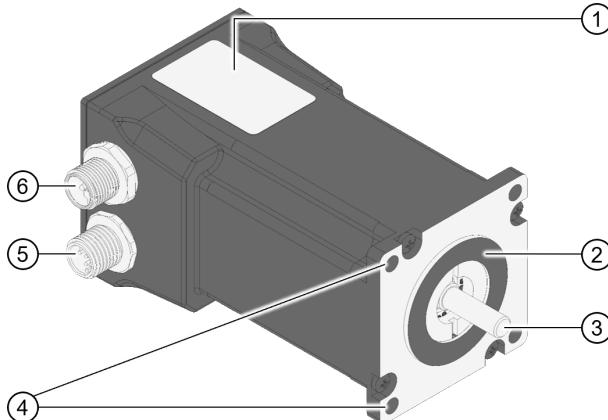


Fig. 1: ASA56 (here: size L).

1. Type label
2. IP54 ball bearing
3. Motor shaft
4. Four fixing bores M5
5. Encoder connector
6. Motor connector

3 Technical data

Use the product within its technical limits. The size sheet on our website applies. Select the exact ASA56 type there and download the needed CAD- / PDF file.

3.1 Ambient conditions

Except for the shaft / leadscrew outlet and the linear guide itself (= IP54), ASA56 is IP65-protected. For *overall* IP65, you must seal the outlet installation-ward, say, by O-ring or surface seal.

Protection class	IP65 (shaft outlet: IP54)
Air humidity (non-condensing)	0 to 85 %
Ambient °C (°F)	-10 to +50 °C (+14 to +122 °F)
Axial force F_a N $N^{max.}$	10
Radial force F_r (@ 10 mm) N $N^{max.}$	28

The following conditions apply to the motor, but not to encoder and connectors:

Max. Temperature Rise	80 °C (at standstill, 2 phases energized)
Insulation Class	B
Insulation Resistance	100 MΩ
Dielectric Strength	500 V AC (for 1 min, coil to housing)

3.2 Motor

There are two ASA56 lengths, each with a different holding torque.

ASA56 stepper	M size	L size
Current per winding A	4.2	4.2
Resistance per phase (@ 25 °C / 77 °F) Ω $±15\%$	0.45	0.55
Inductance per phase (@ 1kHz) mH $±20\%$	1.6	2.1
Rotor inertia kg·m ² (x10 ⁻⁶)	30	48
Holding torque Nm	1.4	2.3
Step angle ° $±5\%$	1.8	1.8
Axial play ($F_a = 4.0$ N) mm	0.08	0.08
Radial play ($F_r = 4.0$ N) mm	0.02	0.02

3.3 Encoder

ASA56 encoders work incremental or, in the SSI version, *multi-turn*.

	SSI	Incremental
Protective circuits	Reverse polarity, short circuit	Overvoltage
Energy harvesting	Wiegand effect	-/-
Operating voltage	4.75 to 15 VDC	5 VDC ^{±10%}
Consumption (typical)	≤ 0.3 W	≤ 30 mA (no-load @ 5 V)
Start-up time	100 ms	-/-
Clock input	RS 422	-/-
Sensor type	Magnetic	Magnetic
Incremental cpr /ppr ^{squared}	-/-	4096 /16384
SSI (<i>single-/multi-turn</i>) bit	17/16	-/-
Accuracy	±0.0878° (@ room temperature)	±0.2° (@ standstill / constant speed)
Axis rotation count ^{seen from front}	Clockwise	Clockwise
Maximum rpm	12,000	14,000

3.4 Pin assignment

NOTICE

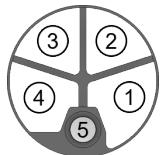


Electronic damage: from lack of reverse polarity guard!

- ▶ Assign pins correctly.
- ▶ Use correct connector types.

Motor and encoder

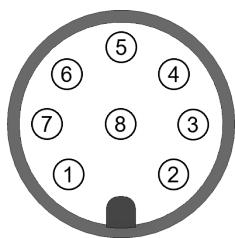
Fig. 2: Motor. L-coded M12 (m).



1: A\ 3: B
2: A 4: B\

5: n/a

Fig. 3: Encoder. A-coded M12 (m).



SSI:

1: Clk+
2: Clk-

3: Data+
4: Data-

5: Gnd
6: n/c

7: n/c
8: +Ub

Incremental:

1: A
2: A\

3: B
4: B\

5: Gnd
6: I\

7: I
8: +Ub

4 Sensor data format

Depending on type, the ASA56's encoder sends the motor position incrementally via two channels **A**, **B** plus index **I** or via **synchron-seriell-interface** (SSI) as a 33-bit packet (after 16 start bits).

Incremental output

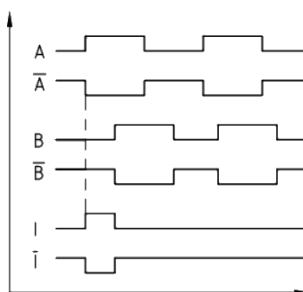


Fig. 4: The index signal I runs in sync with channel A's rising edge.

If the motor shaft rotates clockwise (seen from front), channel A's signal leads channel B by 90 degrees (electrical).

Ub = 5 V **Load** **High level** **Low level**
 A, A\, B, B\, I, I\ 35 mA ≥ 4.5 V ≤ 0.3 V

SSI-Output

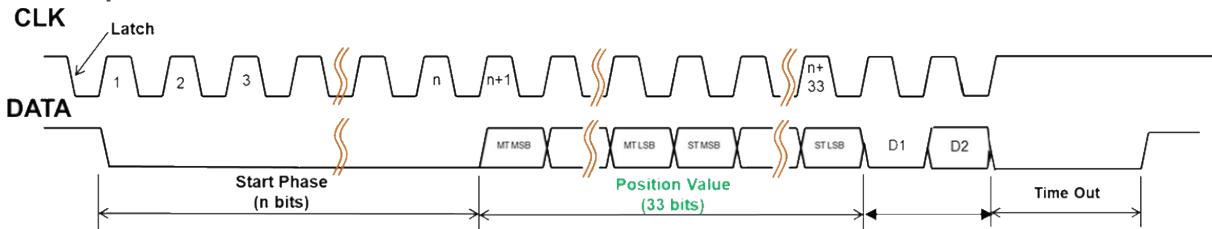


Fig. 5: By synchronous serial interface (SSI), the ASA56's encoder transfers the position values as 33-bit packets.

- **S303B**
- Cycle: ≥ 50 μ s
- Time-out: 7 μ s^{typ.}
- 16 Start bits (= 0) + multi-turn (16 bits) + single-turn (17 bits) + D1 + D2
- D1: Constant value = 0
- D2: Error-bit for displaying the sensor-internal status (1 = no error; 0 = error)

Prepare the SSI for Nanotec controllers

63	62	61	60	59	58	57	56	55	54	53	52	51	50	49	48
47	46	45	44	43	42	41	40	39	38	37	36	35	34	33	32
0	0	0	0	0	0	0	0	0	0	0	0	0	POS	POS	POS
31	30	29	28	27	26	25	24	23	22	21	20	19	18	17	16
POS															
15	14	13	12	11	10	9	8	7	6	5	4	3	2	1	0
POS	S	E													

Edit the 33B0_h **sub-inidices** below so that Nanotec controllers in *Autosetup* (see controller manual) duly process the encoder and its data:

1. Set 33B0_h:06_h to 2000000 (baud rate in Hz).
2. Set 33B0_h:05_h to 51 (number of bits plus start bits).
3. Set 33B0_h:07_h to FFFFFFFC_h (Position data: POS bits 2 to 31).
4. Set 33B0_h:08_h to 7 (Position data: POS bits 32 to 34).
5. Set 33B0_h:09_h to 3 (status and error bits 0 and 1).
6. Set 33B0_h:0B_h to 1 (error bit = 1, status bit = 0).
7. To store the object: Insert 65766173_h to 1010_h:06_h.
8. Restart the controller.

Fig. 6: ASA56 uses 51 status, start and position bits: 1 **S** for status (D1), 1 **E** for error (D2), 33 **POS** for position and 16 start bits (= 0).

- **Bit 0** (= error): value 1 if no error
- **Bit 1**: always value 0

5 Imprint, marking, versions

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Document + Added | > Changed | # Fixed

1.0.3^{2026.01} > Additional ambient conditions for motor added in Technical data.

1.0.2^{2025.07} # Correction of typo in :Technical data incremental encoder typical accuracy is $\pm 0.2^\circ$.

1.0.1^{2024.11} + Revision.

1.0.0^{2023.11} Release.

CE