

1. Incremental Optical Encoder (Hollow shaft- Blind hole)

1.1 Introduction:

K18 is a micro hollow shaft optical encoder with compact structure and high reliability, widely used in small equipment and industrial automation fields with space constraints.

1.2 Feature:

- Encoder external diameter Ø18mm、thickness 12.1mm、diameter of shaft Ø2.5mm;
- Adopt non-contact photoelectric principle;
- Multiple electrical interfaces available;
- Resolution per turn up to 16384PPR.

1.3 Application:

Bill counting machines, printers, micro motors, small instruments and other automation control fields.

1.4 Connection:

- Radial alignment (standard length 0.15M)
- Axial alignment (standard length 0.15M)

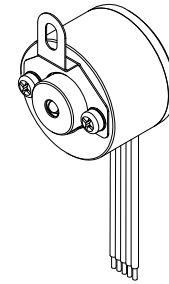
1.5 Protection:

IP40

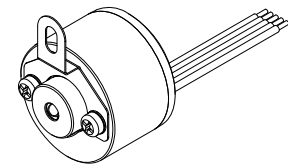
1.6 Weight:

about 25g

K18-J

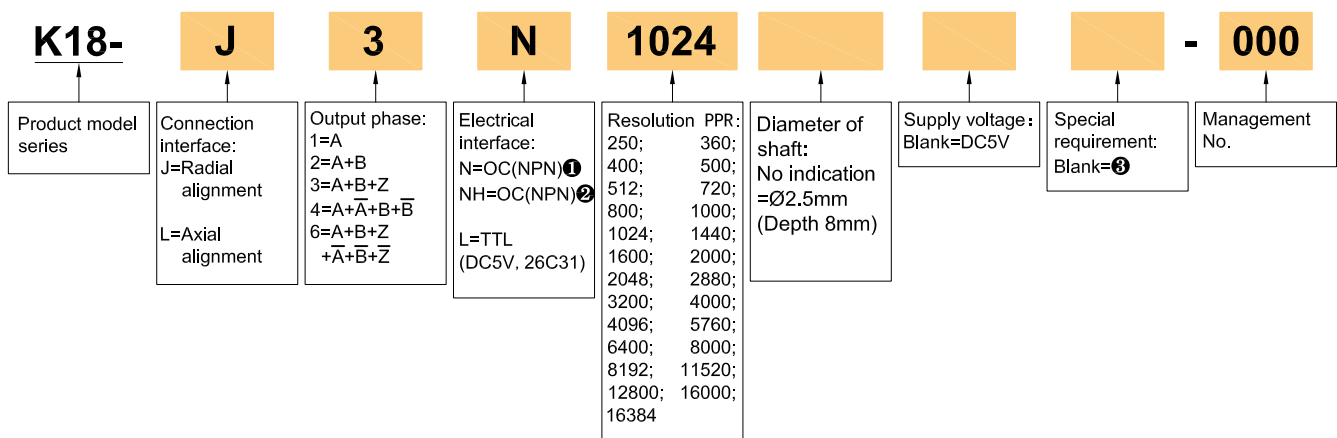


K18-L



2. Model Selection Guide

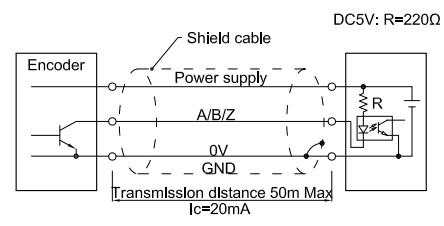
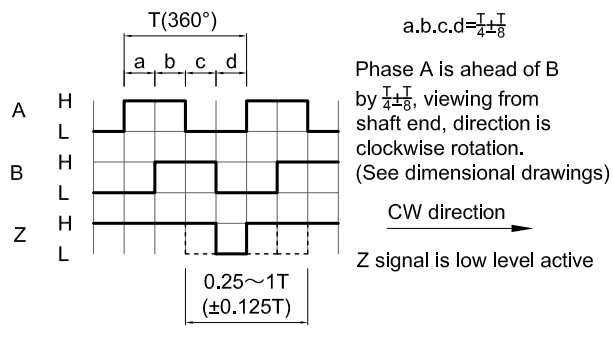
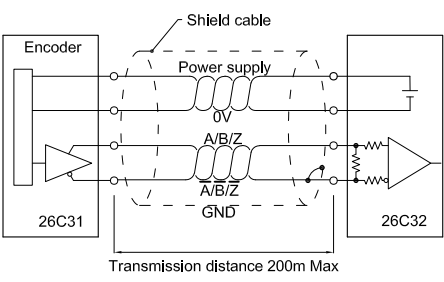
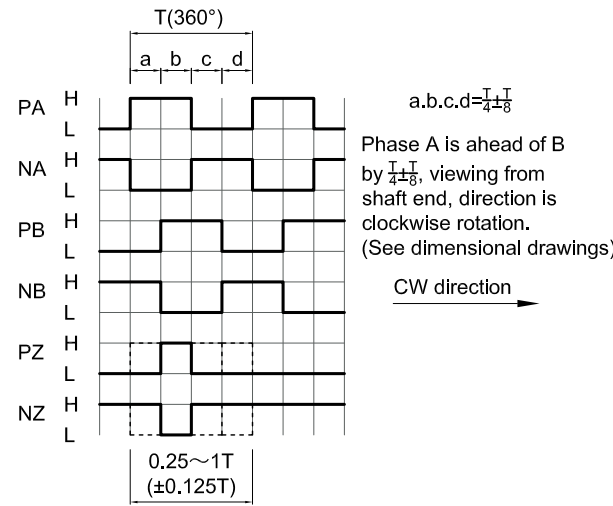
2.1 Model composition(select parameters)



2.2 Note

- ①. Z signal is low level active.
- ②. Z signal is high level active.
- ③. None indicated for IP40 and cable length of 0.15M, 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 2 of the provision of output circuit.

3. Output Mode

Electrical interface	Output circuit	Output wave form
OC NPN open collector circuit		 $T(360^\circ)$ $a \quad b \quad c \quad d$ $a.b.c.d = \frac{1}{4} \pm \frac{1}{8}$ Phase A is ahead of B by $\frac{1}{4} \pm \frac{1}{8}$, viewing from shaft end, direction is clockwise rotation. (See dimensional drawings) CW direction → Z signal is low level active $0.25 \sim 1T$ $(\pm 0.125T)$
TTL (DC5V)		 $T(360^\circ)$ $a \quad b \quad c \quad d$ $a.b.c.d = \frac{1}{4} \pm \frac{1}{8}$ Phase A is ahead of B by $\frac{1}{4} \pm \frac{1}{8}$, viewing from shaft end, direction is clockwise rotation. (See dimensional drawings) CW direction → $0.25 \sim 1T$ $(\pm 0.125T)$

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4. Electrical Parameters

Parameter \ Output type		OC		TTL	
		Item			
Supply voltage		DC+5V±5%			
Consumption current		100mA Max			
Allowable ripple		≤3%rms			
Top response frequency		100KHz		300KHz	
Output capacity	Output current	Input	≤30mA		≤±20mA
		Output	—		
	Output voltage	“H”	—		≥2.5V
		“L ”	≤0.4V		≤0.5V
	Load voltage		≤DC30V		—
Rise & Fall time		Less than 2us(cable length: 2m)		≤100ns Less than 1us(Cable length: 2m)	
Mark to space ratio		45% to 55%			
Phase shift between A & B		90°±10° (frequency in low speed)			
		90°±20° (frequency in high speed)			
GND		Not connect to encoder			

5. Mechanical Specifications

Diameter of shaft	Ø2.5mm Depth 8mm(Stainless steel material)
Starting torque	Less than $5 \times 10^{-4} \text{N} \cdot \text{m}$
Inertia moment	Less than $0.3 \times 10^{-6} \text{kg} \cdot \text{m}^2$
Shaft load	Radial 2N; Axial 2N
Slew speed	≤5000 rpm
Shell	Aluminium alloy
Weight	about 25g

6. Environmental Specifications

Environmental temperature	Operating: -10~+70°C; Storage: -15~+75°C
Environmental humidity	Operating and storage: 35~85%RH(noncondensing)
Vibration(Endurance)	Amplitude 0.75mm, 5~50Hz, 2h for X,Y,Z direction individually
Shock(Endurance)	49m/s ² 11ms three times for X,Y,Z direction individually
Protection	IP40

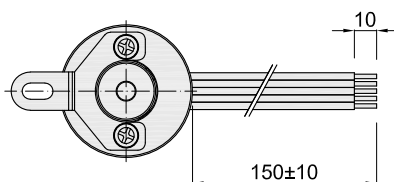
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7. Wiring Table

7.1 OC (Wiring table)

	Supply voltage		Incremental signal		
Wire color	Red	Black	White	Green	Yellow
Function	Up	0V	A	B	Z

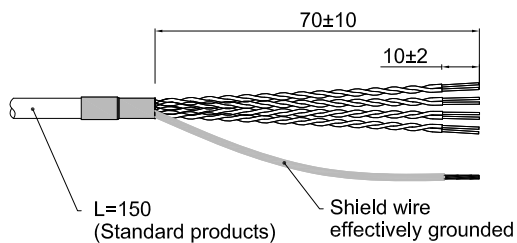


7.2 TTL (Wiring table)

	Supply voltage		Incremental signal					
Wire color	Red	Black	White	White/BK	Green	Green/BK	Yellow	Yellow/BK
Function	Up	0V	A+	A-	B+	B-	Z+	Z-
Twisted-paired cable								

Up=Supply voltage.

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



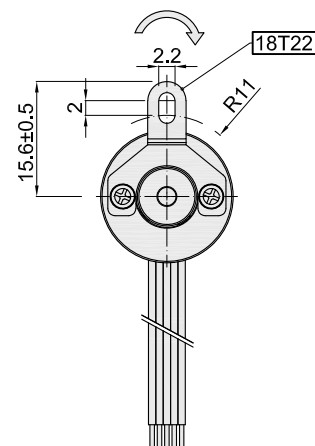
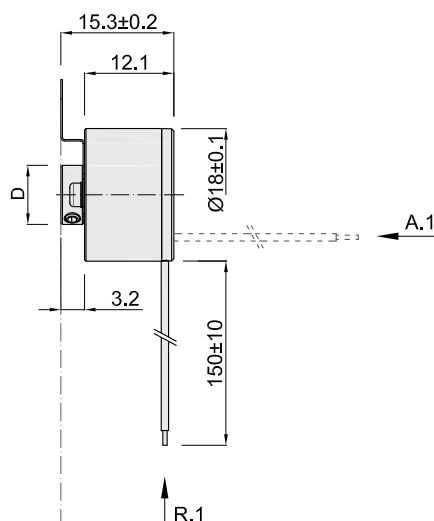
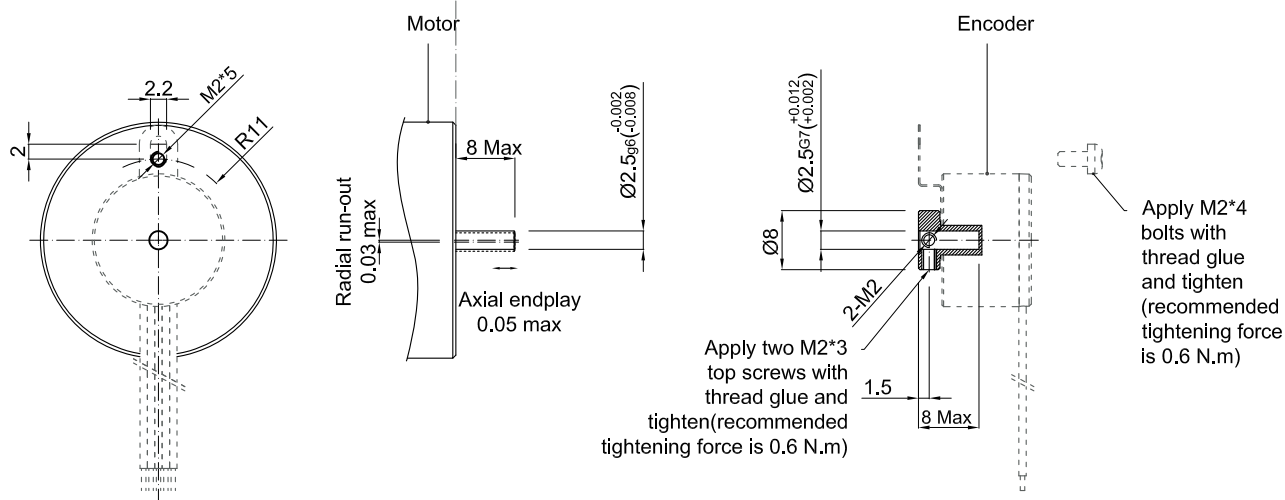
Unit: mm

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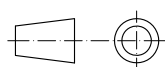
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8. Basic Dimensions**8.1 Dimensions**

B(Shaft)	D
$\varnothing 2.5^{G7}_{+0.012}_{+0.002}$	$\varnothing 8$

**8.2 Installation requirements**

Unit: mm



↻ = Shaft rotation direction of incremental signal output

R.1 = Radial alignment (standard length 150mm)

A.1 = Axial alignment (standard length 150mm)

18T22 = Mounting spring plate model

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.

9. Accessories

18T22

No: 03700144

