Lexium integrated drives
IL●2 for DeviceNet, EtherCAT, Modbus TCP, Ethernet Powerlink
ILA2 with AC synchronous servo motor

References												
Example:	**I**	**L**	**A**	**2**	**D**	**5**	**7**	**1**	**P**	**B**	**1**	**A**
Motor type **A** = AC synchronous servo motor	I	L	**A**	2	D	5	7	1	P	B	1	A
Supply voltage **2** = 24 ... 48 V	I	L	A	**2**	D	5	7	1	P	B	1	A
Communication interface **D** = DeviceNet **E** = EtherCAT **P** = Ethernet Powerlink **T** = Modbus TCP	I	L	A	2	**D**	5	7	1	P	B	1	A
Flange size **57** = 57 mm	I	L	A	2	D	**5**	**7**	1	P	B	1	A
Motor length ("L") *(1)* **1** = motor length ("L") **2** = motor length ("L")	I	L	A	2	D	5	7	**1**	P	B	1	A
Winding type **P** = medium speed of rotation, medium torque **T** = high speed of rotation, medium torque	I	L	A	2	D	5	7	1	**P**	B	1	A
Connection technology **B** = printed circuit board connector **C** = industrial connector	I	L	A	2	D	5	7	1	P	**B**	1	A
Measurement system **1** = singleturn encoder **2** = multiturn encoder *(2)*	I	L	A	2	D	5	7	1	P	B	**1**	A
Holding brake **A** = no holding brake **F** = with holding brake *(2)*	I	L	A	2	D	5	7	1	P	B	1	**A**

(1) The motor length "L" depends on the mechanical characteristics, see pages 4/51 and 4/53.
(2) Holding brake and multiturn encoder cannot be used in combination.

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