



AMC China JD Series Integrated
Servo Motor

» Overview

AMC China JD series integrated servo motor innovatively integrates control, drive, feedback and motor into a compact unit to form a complete servo control system. The servo system can be controlled through communication bus, analog and digital IO, or it can use the built-in motion engine to realize the control function without a motion controller, and the user only needs to provide a DC power supply to run it!

The integrated servo motor eliminates the connection cable between the motor and the drive, which can reduce the size of the control cabinet or even eliminate the need for a control cabinet! Reduced cumbersome connection cables will reduce the failure rate of the system (long motor cables cause annoying noise problems and poor cable and plug connections can cause many system failures) and shorten the project delivery time.

» Features

- Compact design. Drives, encoders, motors, and motion engines are integrated into one unit for easy installation, especially for multi-axis applications where installation space is limited.
- Various bus communication methods.including RS232/485&Modbus RTU, CANopen.
- Support a variety of working modes.Profile Modes mode (movement between points, trajectory planning is realized by the command limiter inside the motor), current (torque) mode, speed mode, position mode, Cyclic Synchronous Modes, PVT.
- Accepts a variety of command types. Such as $\pm 10V$ analog, 5V pulse + direction, PWM + direction, encoder follow, JOG, bus command, etc.
- Multiple highly programmable digital and analog I/O interfaces.
- Supply voltage 20-60VDC

» Recommended Applications

- Assembly automation: AGV, RGV, robot, tooling equipment;
- Measurement automation: The measurement of parts is in the fields of automobiles, airplanes, 3C, etc.;
- Testing equipment: ultrasonic flaw detection, airport security inspection;
- Semiconductor equipment: wafer transfer and pick and place;
- Communication field: signal conditioning, mobile antenna positioning;
- Medical field: CT scanner, blood analyzer, biochemical analyzer, X-ray machine;
- Intelligent equipment: airborne, shipborne, and vehicle-mounted automation equipment;
- laboratory automation;
- General automation;

» Appearance design with various protection grades

- ❖ Convenient and fast wiring method, this type of protection grade is IP20, as shown on the right.

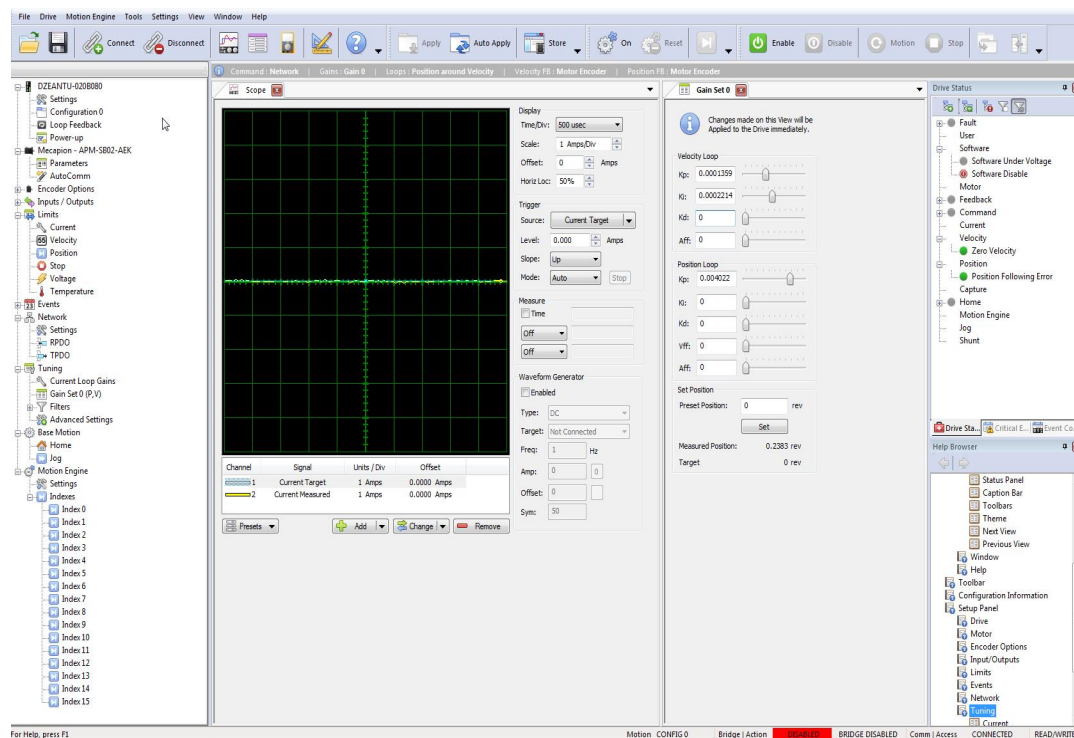


- ❖ The protection grade design of IP65 is suitable for occasions with high requirements for waterproof and dustproof, as shown in the figure on the right.



» Powerful debugging configuration software

- Simple and intuitive PID tuning method.
- Online monitoring of motor running status and alarm query, providing real-time information of motor events and actions.
- Provide flexible configuration of digital and analog IO ports.
- Events and alarms are highly configurable.



Advanced Event Configuration						
Group	Event	Delay [ms]	Action	Recovery [ms]	No Repeat [ms]	Recoveries
/	Fault					
/	User					
/	Software					
Δ	Motor					
	Motor Over Speed	0	Disable Power Bridge	0	100	Unlimited
	Motor Over Temp	0	Disable Power Bridge	0	0	Latch
/	Feedback		No Action			
/	Command		Disable Power Bridge			
/	Current		Disable Positive Direction			
/	Velocity		Dynamic Brake			
/	Position		Positive Stop			
	Shunt					
	Shunt Regulator Active	0	No Action	0	100	Unlimited

Debug configuration software download link: : <https://www.a-m-c.com/downloads/>
 > Software Downloads>DriveWare® 7 Software

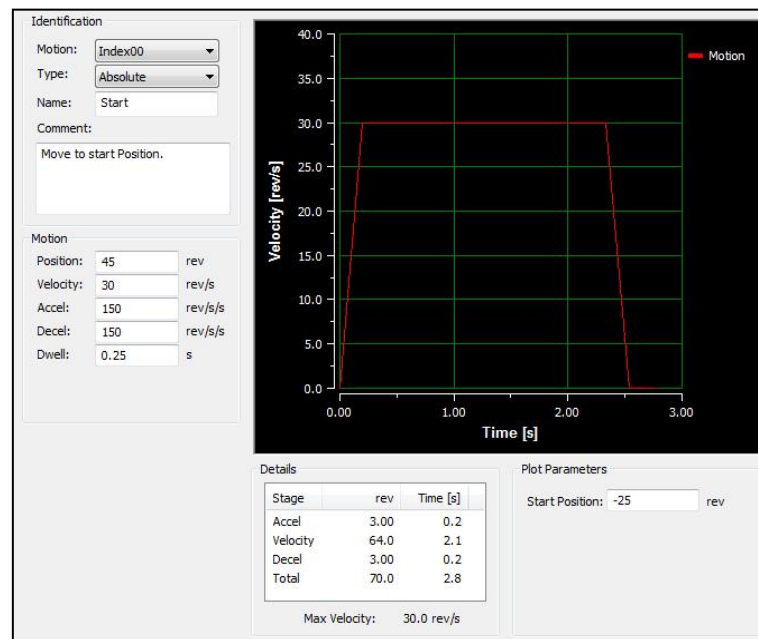
» Built-in motion engine

Motion engine – A motion engine refers to an internal motion controller that can be used in distributed motion applications.

The motion engine includes two operating modes:

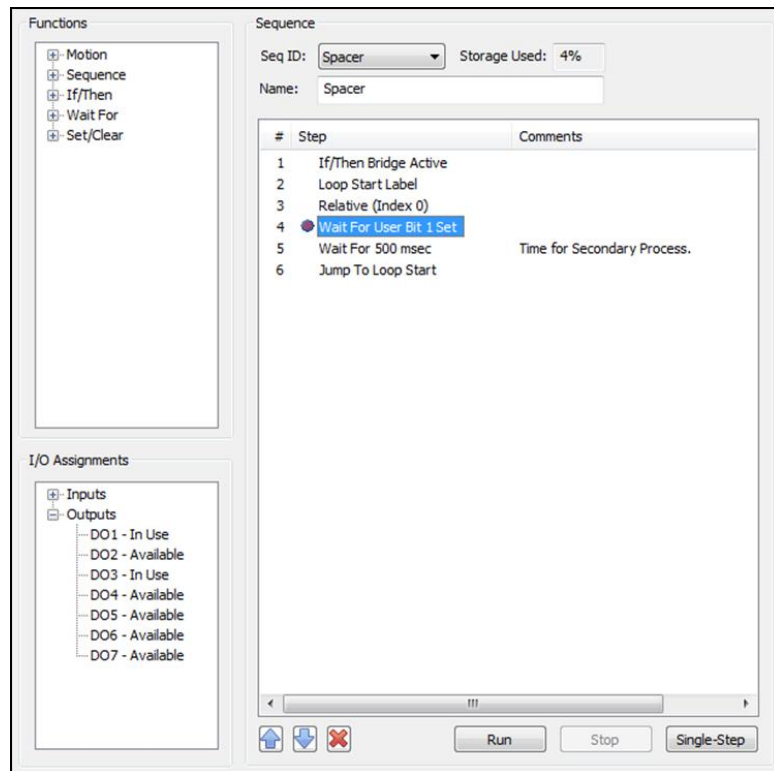
● Indexex

The motor responds to internal commands to perform predefined motion tasks. 16 Index tasks can be configured, and the movement can be set to absolute and relative two types. (each index task includes whether the movement is absolute or relative, the distance that the movement task needs to move, the running speed, the running speed of acceleration and deceleration, and the stop time, etc.).



● sequence

The motor responds to internal commands to execute pre-defined motion tasks (indexes) in a pre-defined sequence. The sequence includes functions that can call the configured homing mode and index, can set jump, If/Then type, wait (event, IO, user bit, time, value), can set breakpoint.



The screenshot shows the 'Sequence' configuration window. It includes a 'Functions' list on the left with options like Motion, Sequence, If/Then, Wait For, and Set/Clear. The 'I/O Assignments' section shows inputs and outputs for DO1 through DO7. The main 'Sequence' area displays a list of steps: 1. If/Then Bridge Active, 2. Loop Start Label, 3. Relative (Index 0), 4. Wait For User Bit 1 Set (highlighted), 5. Wait For 500 msec (commented 'Time for Secondary Process.'), and 6. Jump To Loop Start. The 'Seq ID' is 'Spacer' and 'Storage Used' is 4%. At the bottom, there are 'Run', 'Stop', and 'Single-Step' buttons.

» Industrial Fieldbus Communication

• CANopen

CANopen is a powerful and low-cost serial protocol and a fieldbus commonly used in industrial control, offering enhanced diagnostic and control capabilities with moderate bandwidth.



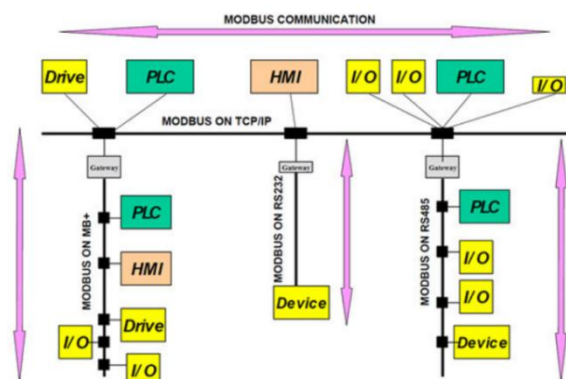
Messages are sent along the network lines of the CAN bus in packets called frames. CANopen frames have a Communication Object Identifier (COB-ID), which contains a 4-bit function code, a 7-bit node ID and control bits. The frame also has a 4-bit data length field and 0 to 8 bytes of data.

All nodes in a CANopen network have an object dictionary. The object dictionary contains the parameters of the node, such as its address (index location in the network), device name, object code, data type, read/write access, and an indication of optional and mandatory parameters. Essentially, this defines if, when and how nodes interpret and respond to data frames sent over the network. While all nodes see every message, only the node specified in the frame's node ID will respond to it.

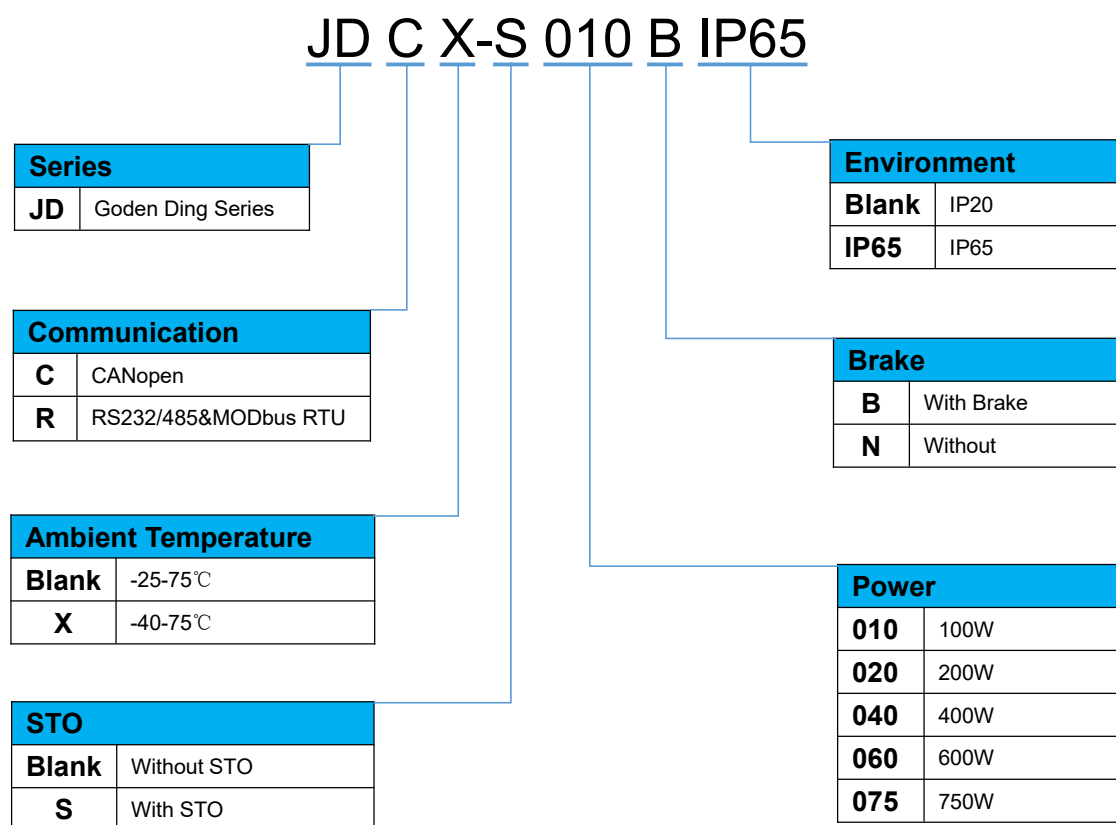
Feature	Description
Protocol	CiA301,CiA402
Communication Tate	12.5Kbps, 20Kbps, 50Kbps, 125Kbps, 250Kbps, 500Kbps, 800Kbps, 1Mbps
Message Type	SDO, PDO, SYNC, EMCY, NMT, Heartbeat
Control Mode	Profile Position, Profile Velocity, Profile Torque, Homing Mode
Number of PDOs	10RPDO,10TPDO

• Modbus

Modbus RTU is a field device network that uses serial communication. Sensors and devices can be daisy-chained into the network. Very popular in industrial control networks.



» Designation



1. integrated servo motor feedback part is Hall+4096PPR incremental encoder.
2. The shape of the shaft end of the integrated servo motor with a power of 100W is an optical shaft, and the shape of the shaft end of the integrated motor of other powers is a keyway.

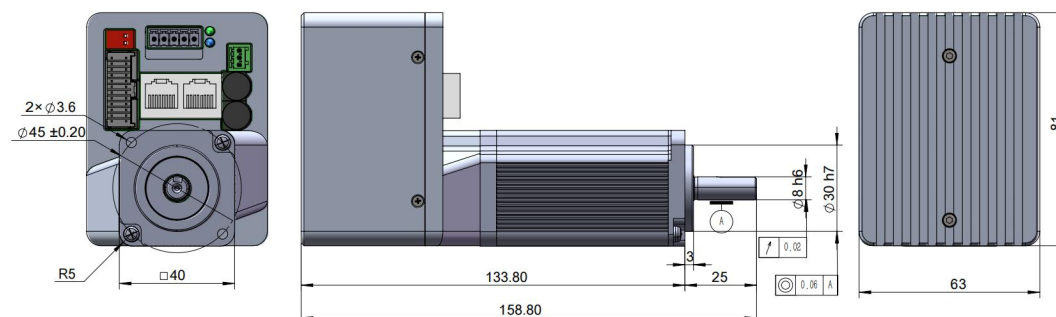
» Specification Parameter Description

Model	JD-S010	JD-S020	JD-S040	JD-S060	JD-S075
Communication Type	C:CANopen R:RS485/232, MODbus RTU				
Rated/Maximum Speed	3000/4000RPM				
Rated/Peak Torque	0.32/0.64NM	0.64/1.28NM	1.3/2.6NM	1.9/3.6NM	2.4/4.8NM
Rated Power	100W	200W	400W	600W	750W
Input Voltage	20-60VDC				
Rotor Inertia (kg·m²)	0.058×10 ⁻⁴	0.189×10 ⁻⁴	0.362×10 ⁻⁴	0.922×10 ⁻⁴	1.08×10 ⁻⁴
Feedback	Hall+4096PPR Incremental Encoder				
Programmable Digital Input (PDI)	5 programmable digital inputs (2 differential inputs, 3 single-ended inputs) ❖ The 3 single-ended inputs are configured as negative limit, positive limit, and home signal by default.If you need to change the default configuration can be changed in Driveware7. ❖ The 2 differential digital inputs can be configured as step and direction command, PWM and direction command, encoder input of load terminal (full closed loop), high-speed capture and other functions.				
Programmable Digital Output (PDO)	3 programmable digital outputs (can be configured as various alarm signal outputs of the motor, limit and in-position signal prompt outputs, event status outputs, etc.)				
Programmable Analog Input (PAI)	1 programmable analog input (12-bit resolution, configurable as ±10V analog command, ±10VDC position feedback, etc.)				
Operating Mode*	❖ Current ❖ Velocity ❖ Position ❖ Profile Modes ❖ Cyclic Synchronous Current Mode ,Cyclic Synchronous Velocity Mode ,Cyclic Synchronous Position Mode ❖ Interpolated Position Mode (PVT)				
Command Source	❖ Communication (CANopen,RS485/MODbus RTU) ❖ ±10 V Analog ❖ 5V Step and Direction(The integrated motor of CANope communication does not support this command) ❖ PWM and Direction (0-100%&Direction/0-50%&50%-100%) ❖ JOG ❖ Internal motion engine (index and sequence)				
Protection	40+ Configurable Functions, Over Current, Over Temperature , Over Voltage, Short Circuit (Phase-Phase & Phase-Ground), Under Voltage				
Operating TEMP	-20-75℃				
Store TEMP	-40-85℃				

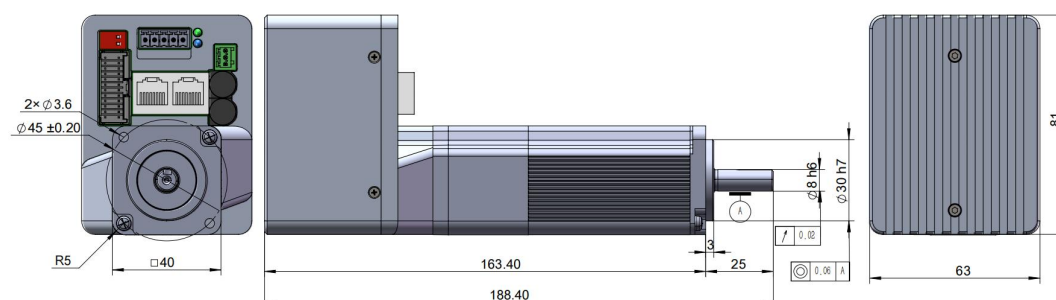
*Cyclic synchronous mode and PVT mode in Operating mode are only supported by integrated motors with CANopen communication.

» Mounting Dimensions-IP20

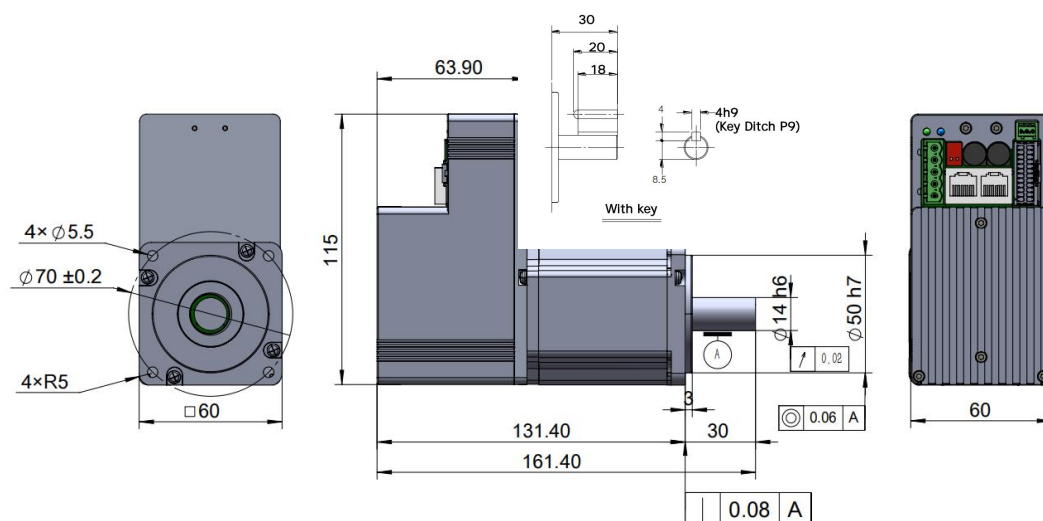
● JD□□-□010N(100W Without brake)



● JD□□-□010B(100W With brake)

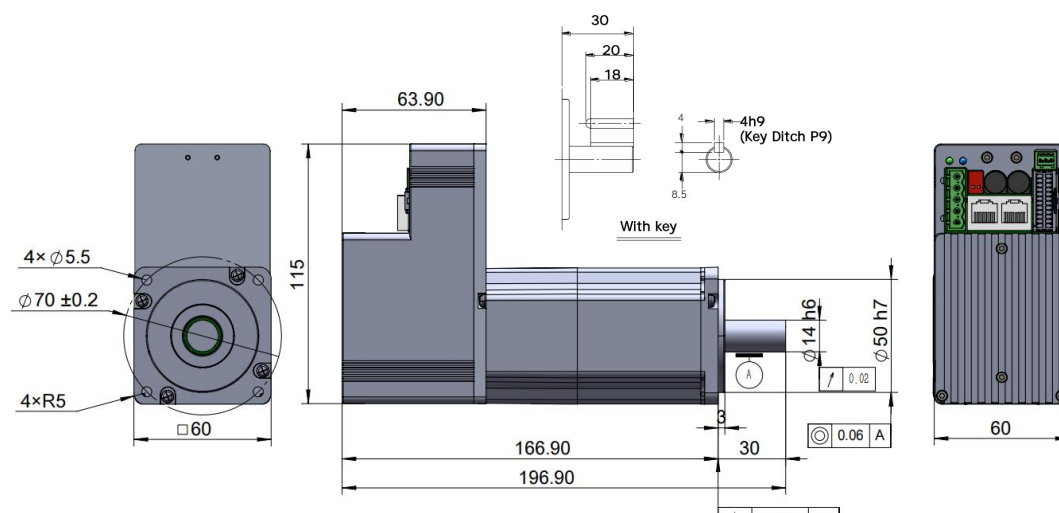


● JD□□-□020N(200W Without brake)

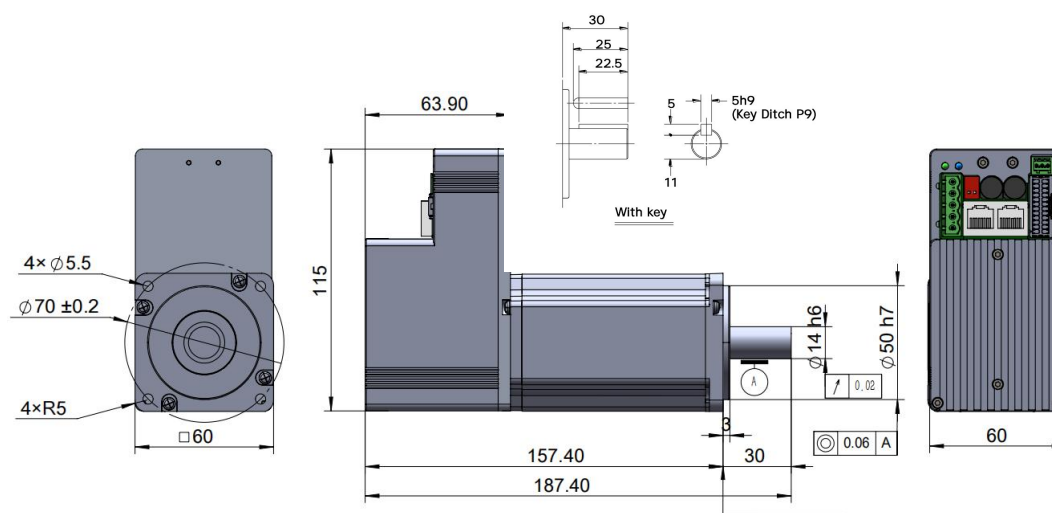


» Mounting Dimensions-IP20

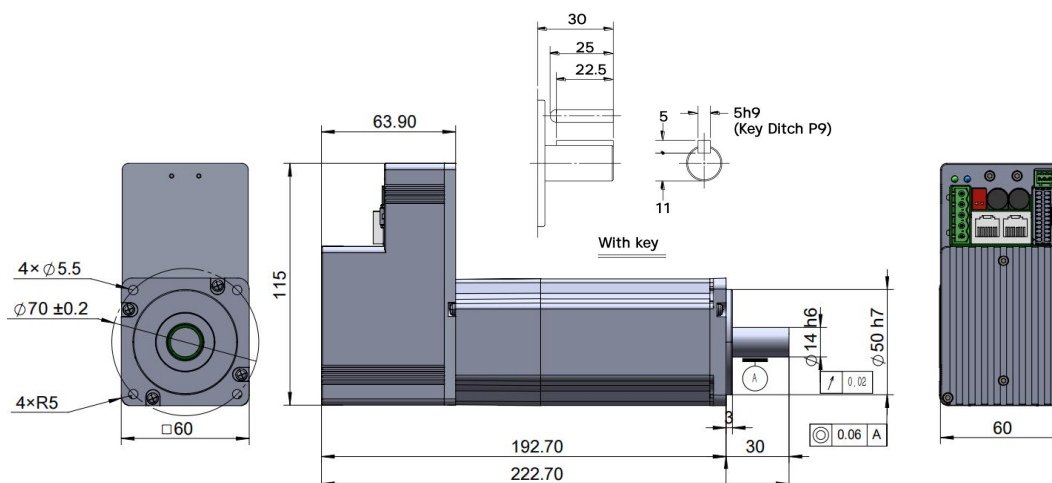
● JD□□-□020B(200W With brake)



● JD□□-□040N(400W Without brake)

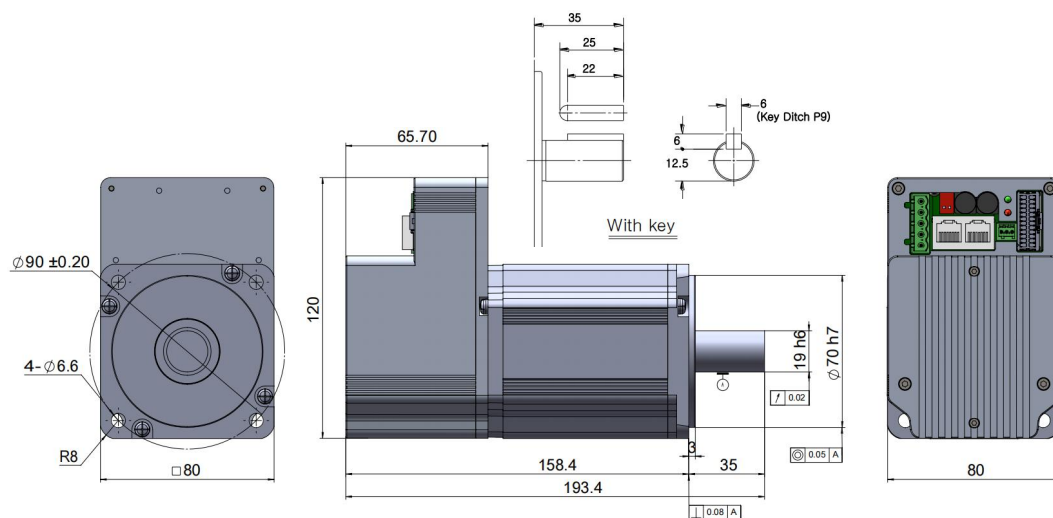


● JD□□-□040B(400W With brake)

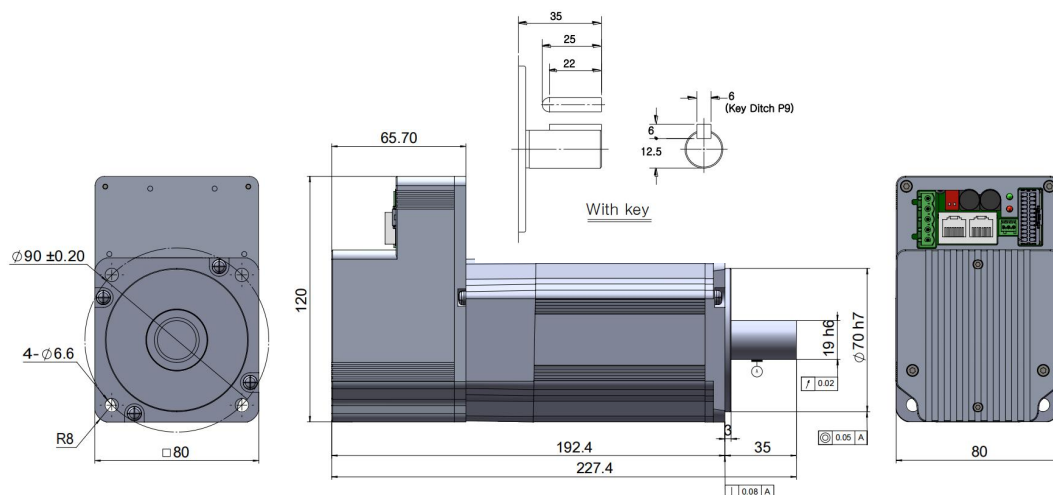


» Mounting Dimensions-IP20

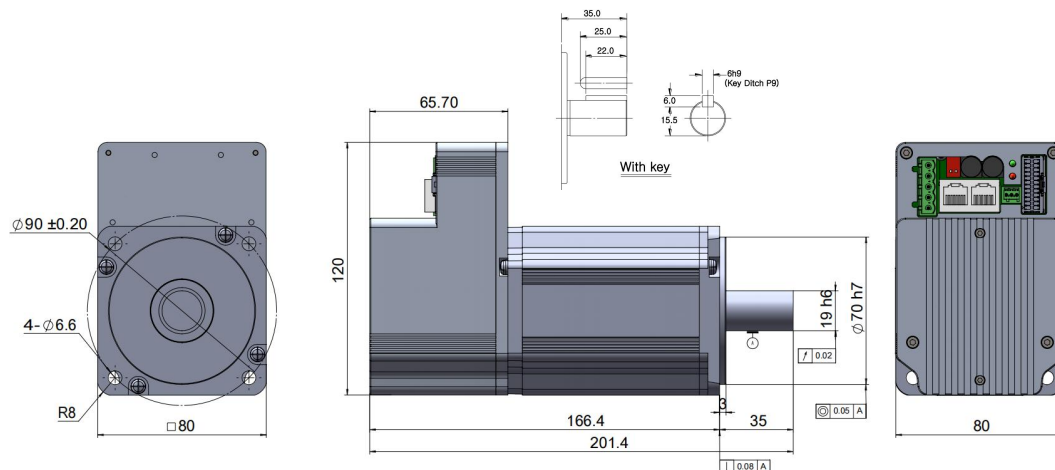
● JD□□-□060N(600W Without brake)



● JD□□-□060B(600W With brake)

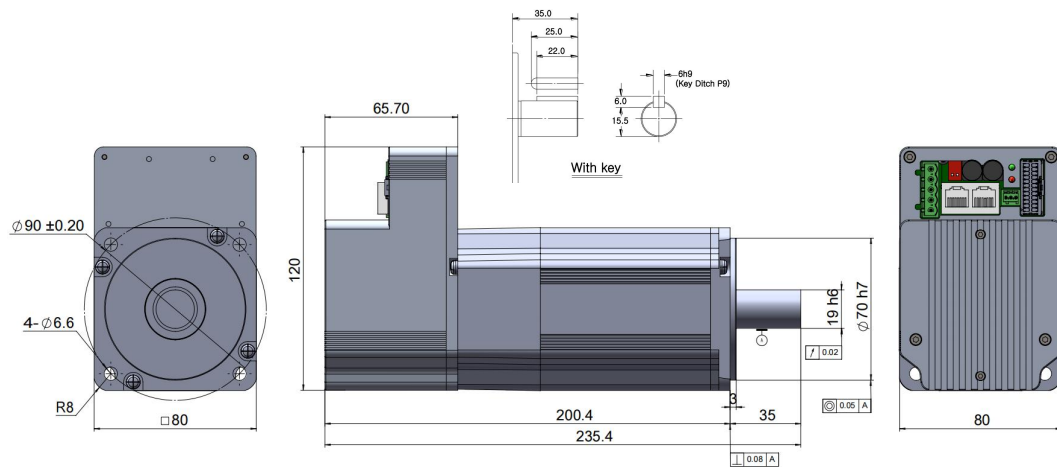


● JD□□-□075N(750W Without brake)



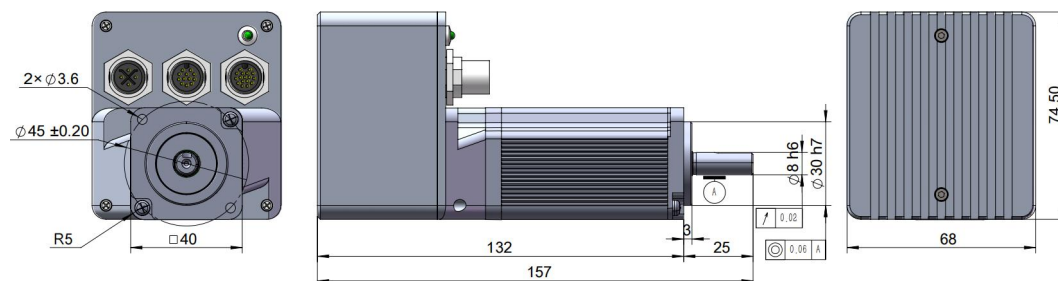
» Mounting Dimensions-IP20

● JD□□-□075B(750W With brake)

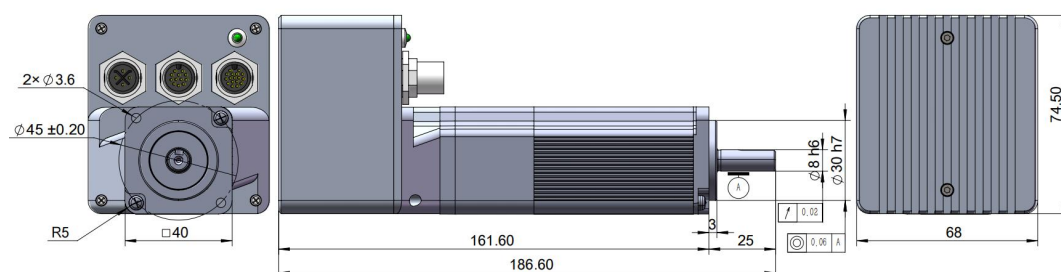


» Mounting Dimensions-IP65

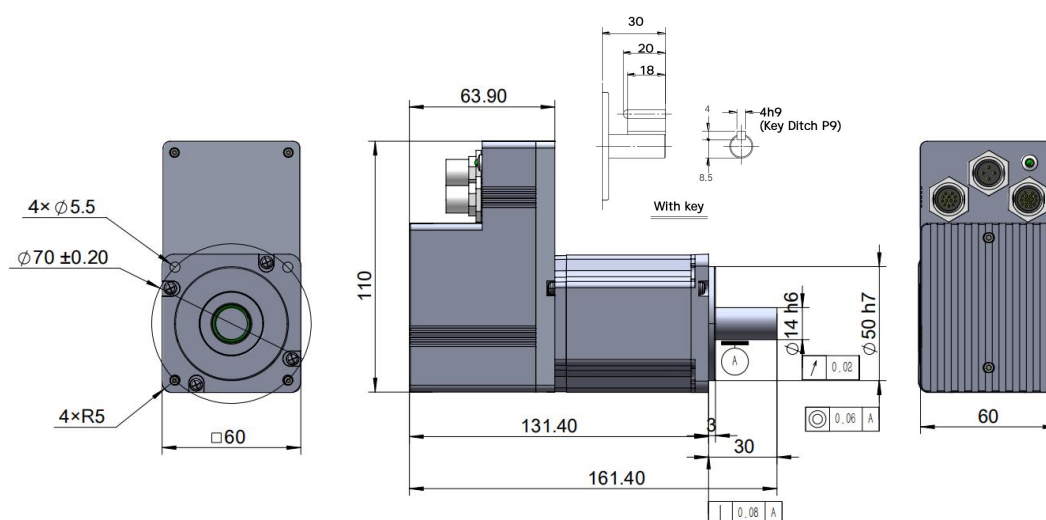
● JD□□-□010NIP65(100W Without brake)



● JD□□-□010BIP65(100W With brake)

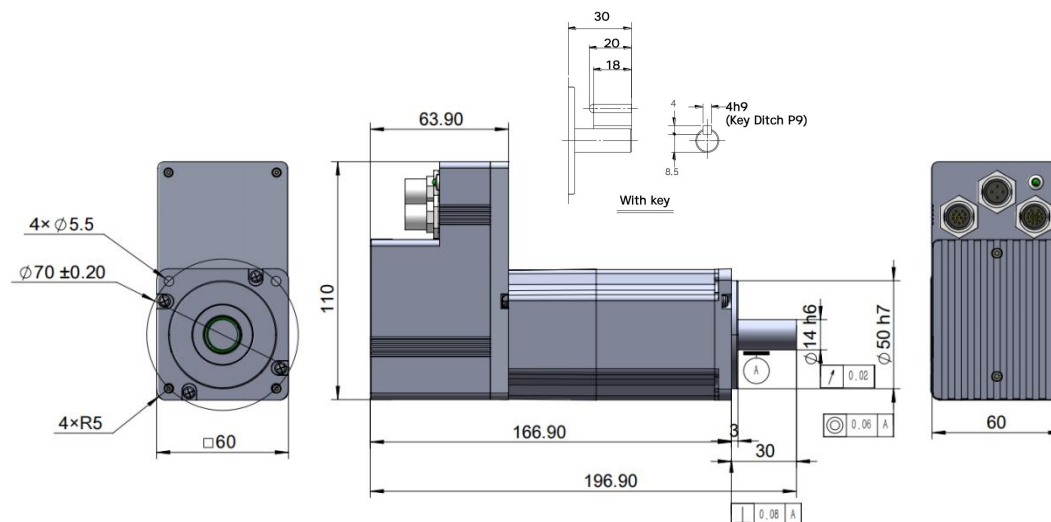


● JD□□-□020NIP65(200W Without brake)

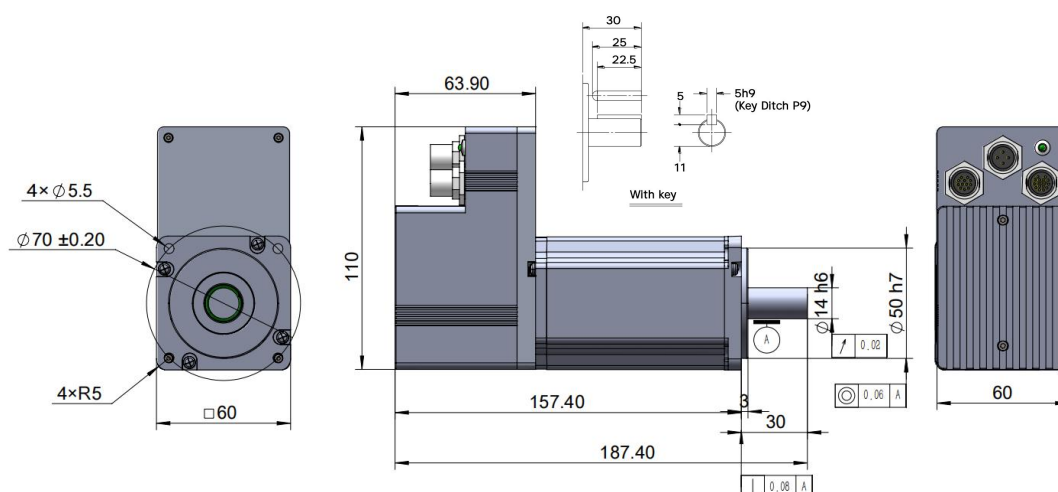


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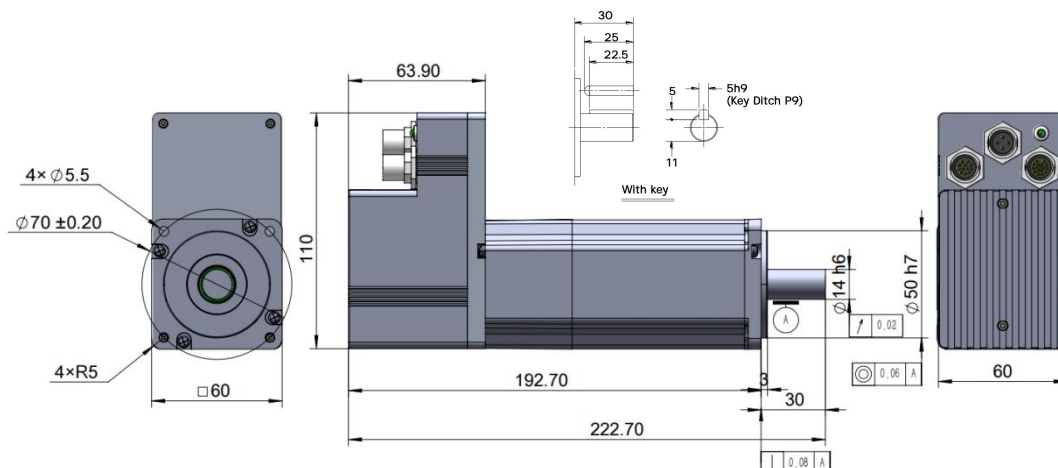
● JD□□-□020BIP65(200W Without brake)



● JD□□-□040NIP65(400W Without brake)

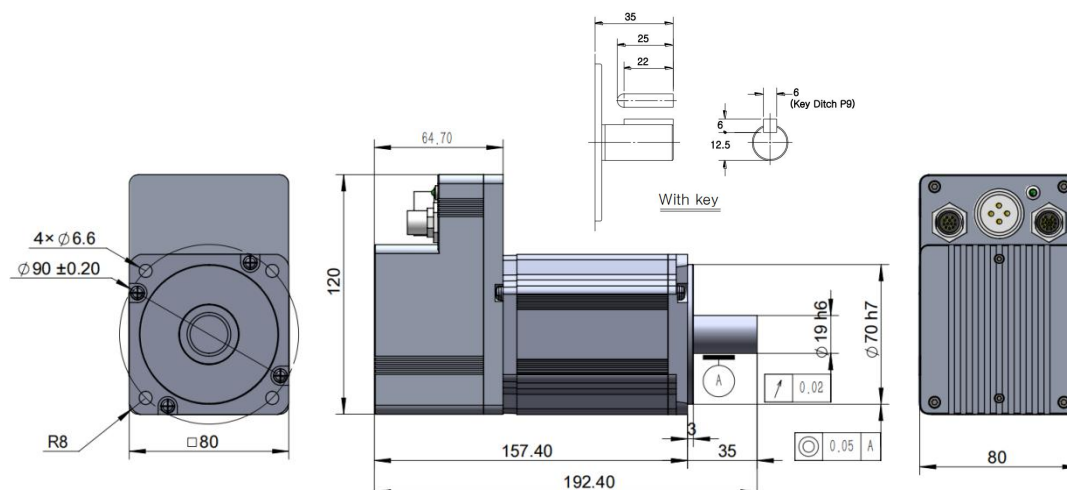


● JD□□-□040BIP65(400W Without brake)

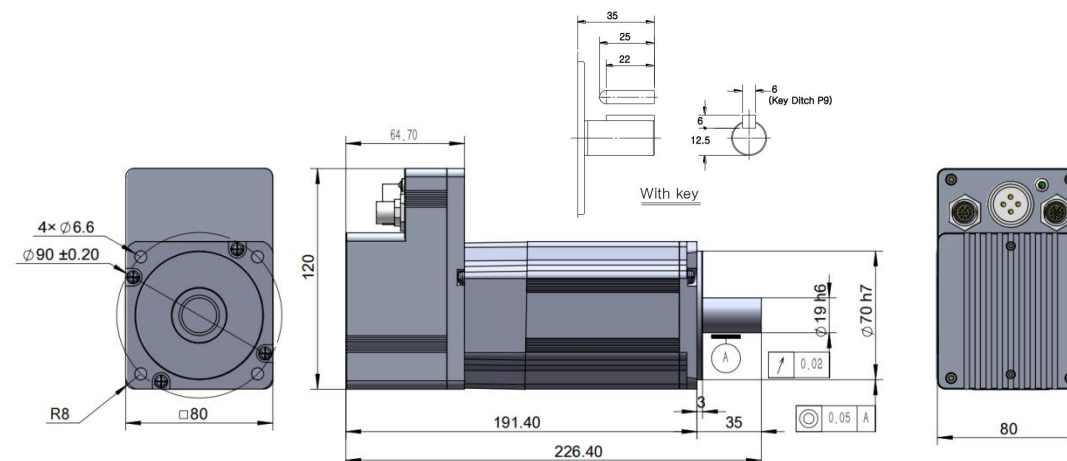


» Mounting Dimensions-IP65

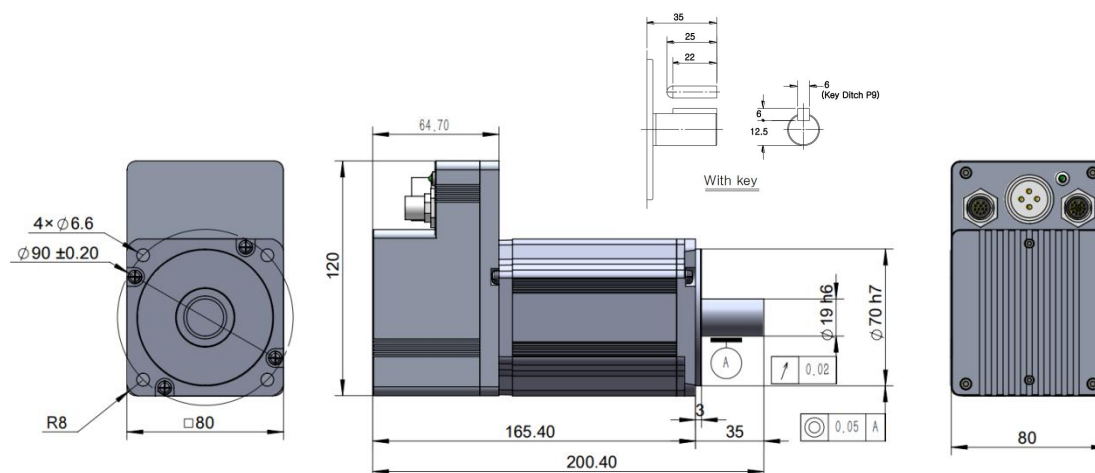
● JD□□-□060NIP65(600W Without brake)



● JD□□-□060IP65(600W Without brake)

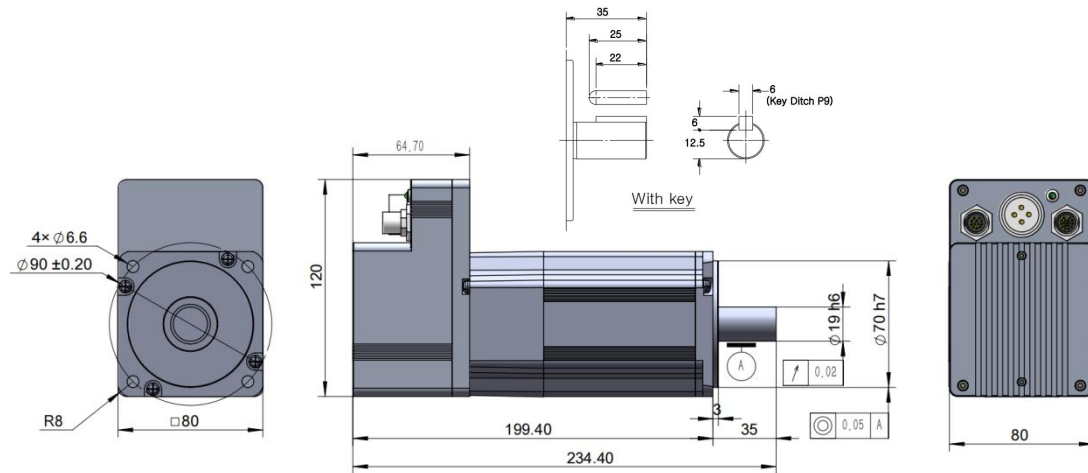


● JD□□-□075NIP65(750W Without brake)

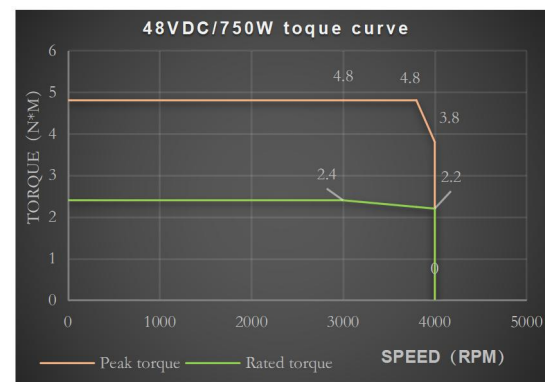
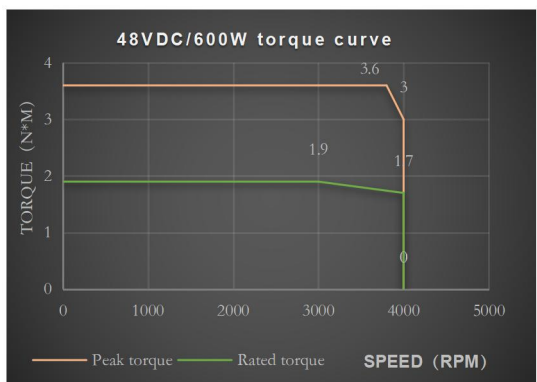
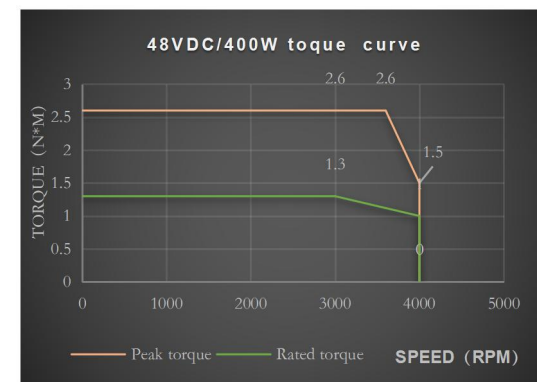
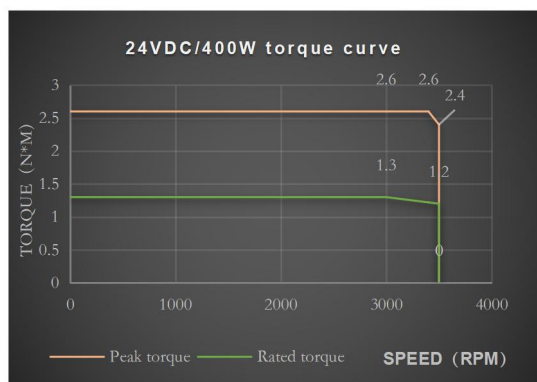
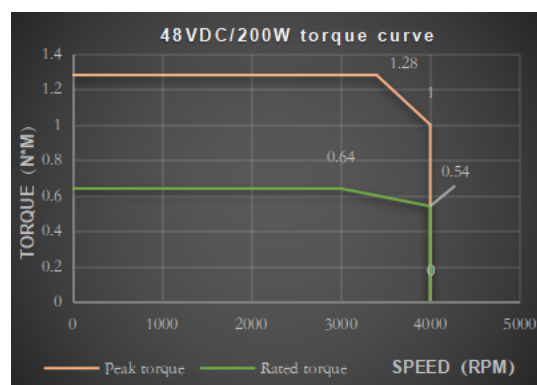
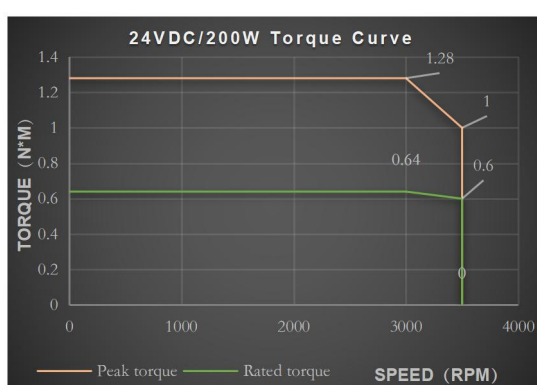
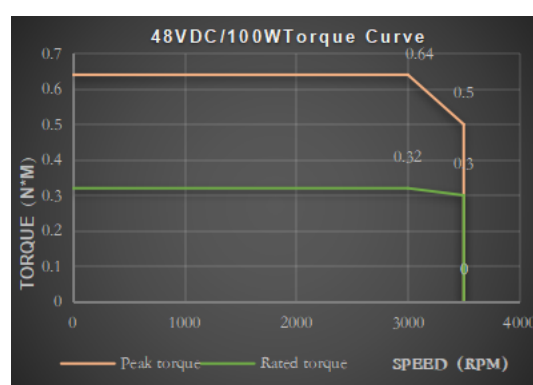
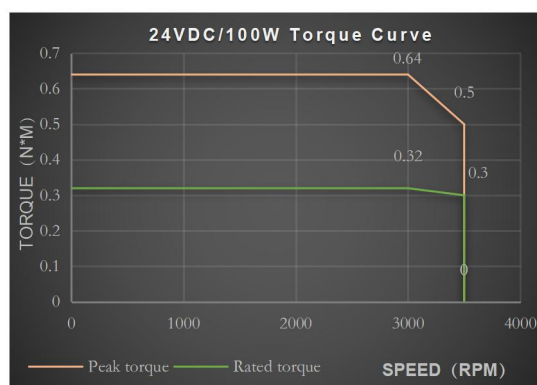


» Mounting Dimensions-IP65

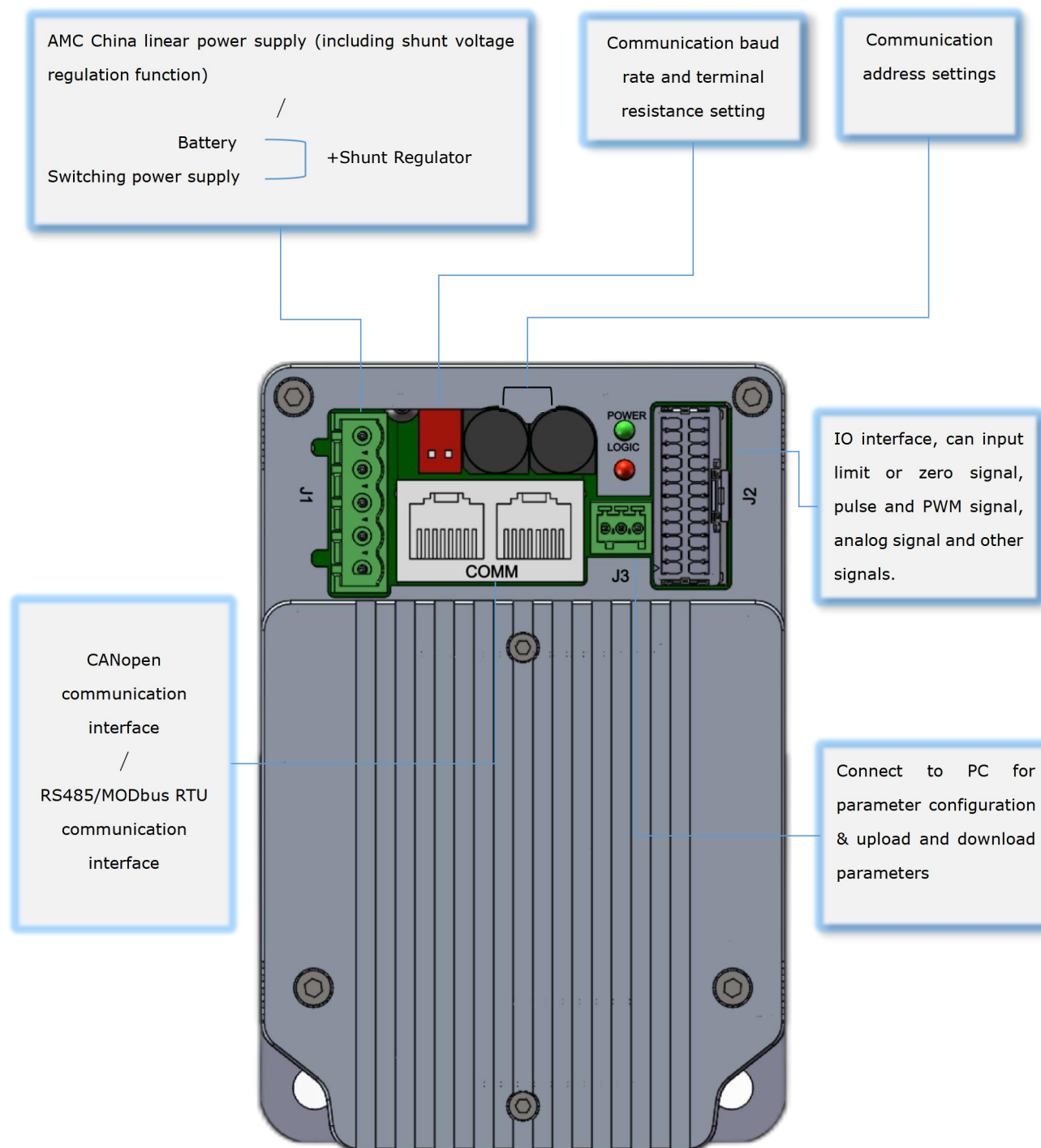
● JD□□-□075BIP65(750W Without brake)



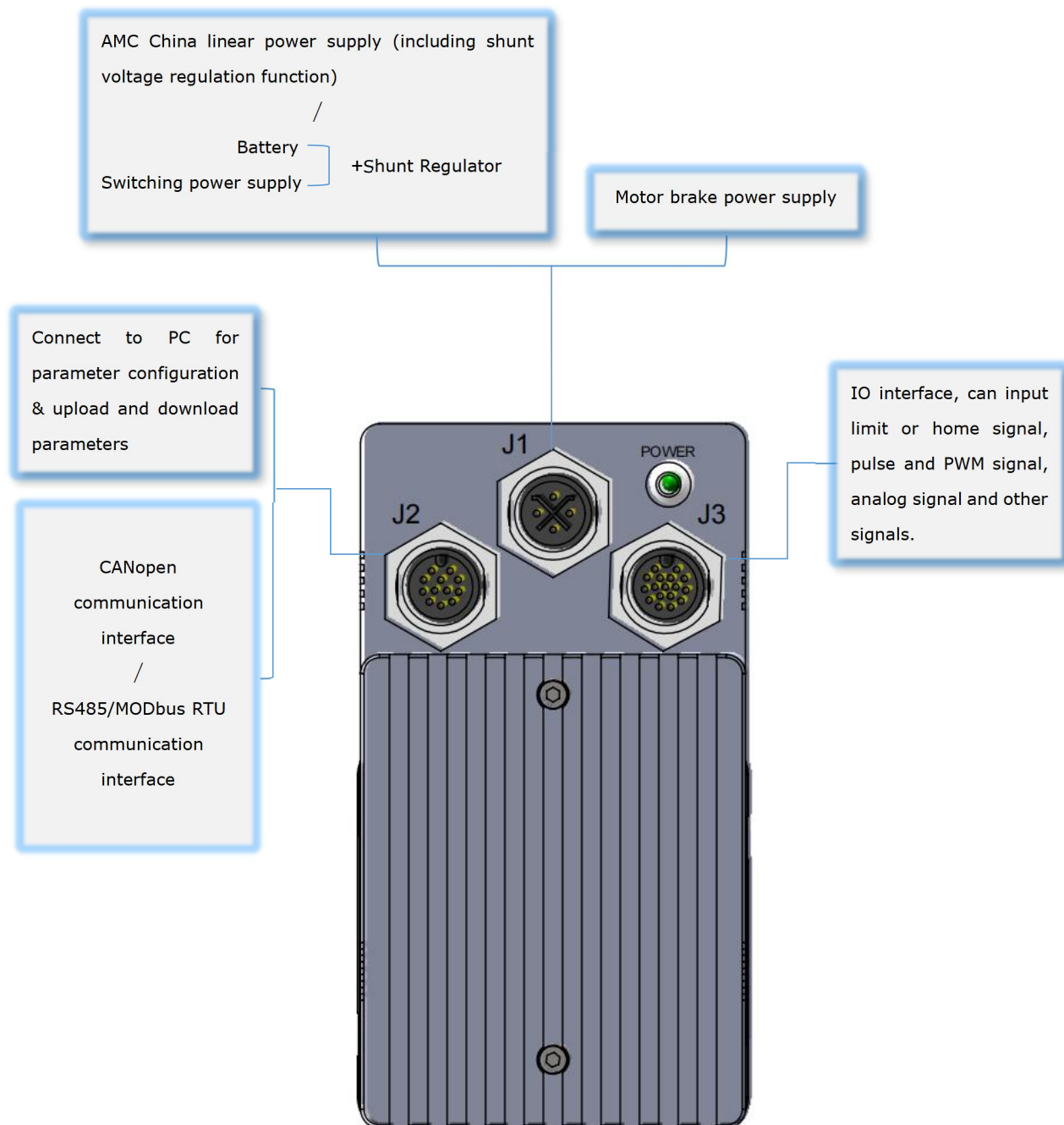
» Torque Curve



» System configuration instructions-IP20

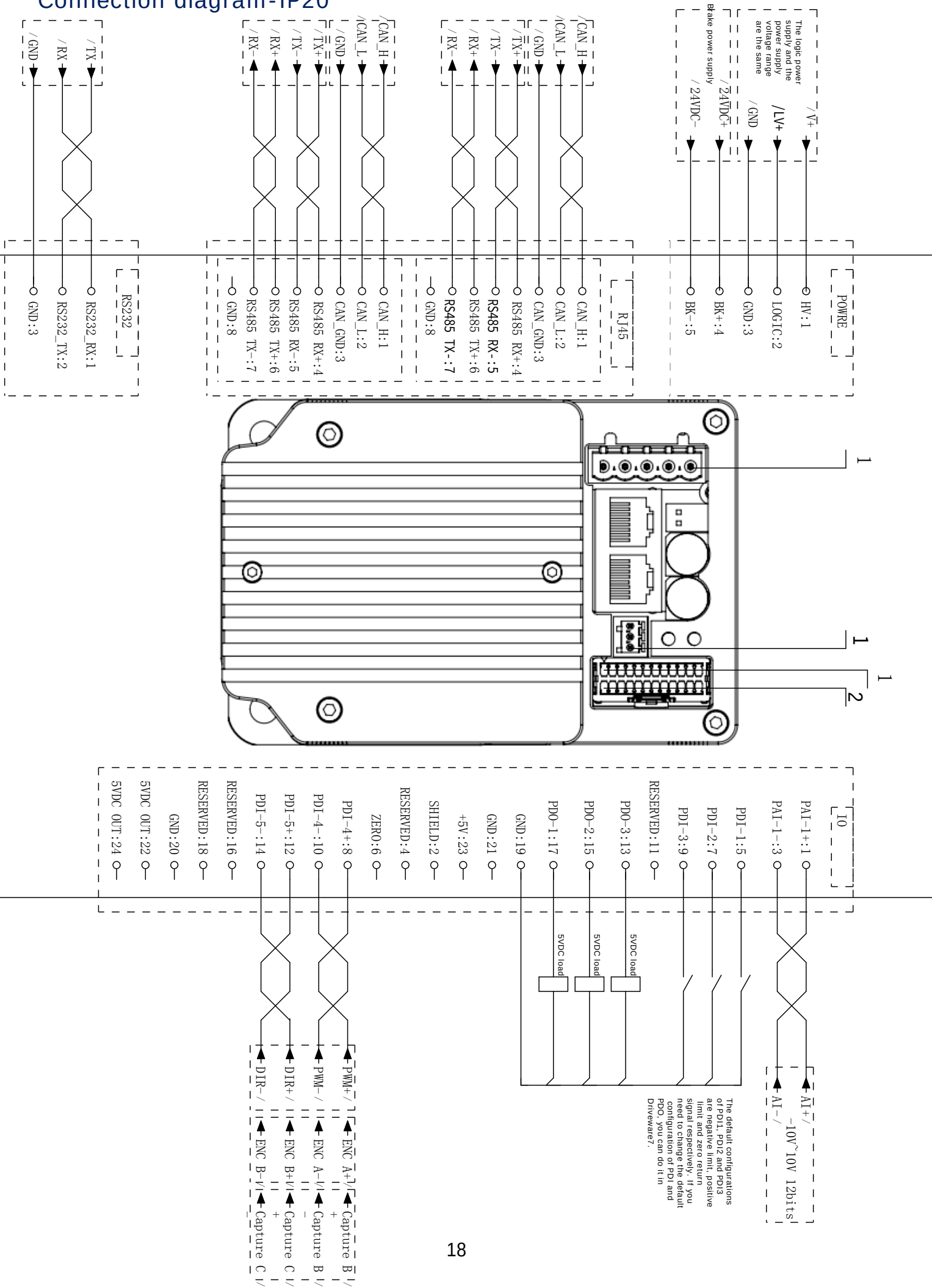


» System configuration instructions-IP





Connection diagram-IP20



Connection diagram

The diagram illustrates the connection points for the motor driver. It includes a power supply section with pins for V+, GND, 24VDC+, and 24VDC-. A CAN bus section shows CAN_H, CAN_L, and GND connections. An RS485 section shows TX+/- and RX+/- connections. A PDI (Pulse Width Modulation) section shows various pins for logic power, ground, and signal inputs/outputs. The diagram also shows the physical layout of the motor driver board with its internal components and wiring.

Power supply

- V+ → HV:1
- GND → GND:2
- 24VDC+ → BZ+:3
- 24VDC- → BZ-:4

CAN bus

- CAN_H → CAN_H:1
- CAN_L → CAN_L:2
- GND → CAN_GND:3

RS485

- RS485 TX+ → RS485 RX+:4
- RS485 TX- → RS485 RX-:5
- RS485 RX+ → RS485 TX+:6
- RS485 RX- → RS485 TX-:7

RS232

- RS232 TX → RS232 TX+:8
- RS232 RX → RS232 RX-:9

Logic power

- LOGIC POWER:1 → LV+
- GND:2 → GND
- PA11+:3 → AI+
- PA11-:4 → AI-

PDI (Pulse Width Modulation)

- PDI-1:5 → 5VDC load
- PDI-2:6 → 5VDC load
- PDI-3:7 → 5VDC load
- GND:8 → GND
- PDI-1:9 → PDI-1:9
- PDI-2:10 → PDI-2:10
- PDI-3:11 → PDI-3:11
- PDI-4:12 → PDI-4:12
- PDI-4:13 → PDI-4:13
- PDI-5:14 → PDI-5:14
- PDI-5:15 → PDI-5:15
- GND:16 → GND
- RESERVED:17 → RESERVED:17

Motor brake

- 24VDC+ → BZ+:3
- 24VDC- → BZ-:4

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- PDI-4:13 → PDI-4:13
- PDI-5:14 → PDI-5:14
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- GND:8 → GND
- PDI-1:9 → PDI-1:9
- PDI-2:10 → PDI-2:10
- PDI-3:11 → PDI-3:11
- PDI-4:12 → PDI-4:12
- PDI-4:13 → PDI-4:13
- PDI-5:14 → PDI-5:14
- PDI-5:15 → PDI-5:15
- GND:16 → GND
- RESERVED:17 → RESERVED:17

Motor brake

- 24VDC+ → BZ+:3
- 24VDC- → BZ-:4

Logic power

- LOGIC POWER:1 → LV+
- GND:2 → GND
- PA11+:3 → AI+
- PA11-:4 → AI-

PDI (Pulse Width Modulation)

- PDI-1:5 → 5VDC load
- PDI-2:6 → 5VDC load
- PDI-3:7 → 5VDC load
- GND:8 → GND
- PDI-1:9 → PDI-1:9
- PDI-2:10 → PDI-2:10
- PDI-3:11 → PDI-3:11
- PDI-4:12 → PDI-4:12
- PDI-4:13 → PDI-4:13
- PDI-5:14 → PDI-5:14
- PDI-5:15 → PDI-5:15
- GND:16 → GND
- RESERVED:17 → RESERVED:17

Motor brake

- 24VDC+ → BZ+:3
- 24VDC- → BZ-:4

Logic power

- LOGIC POWER:1 → LV+
- GND:2 → GND
- PA11+:3 → AI+
- PA11-:4 → AI-

PDI (Pulse Width Modulation)

- PDI-1:5 → 5VDC load
- PDI-2:6 → 5VDC load
- PDI-3:7 → 5VDC load
- GND:8 → GND
- PDI-1:9 → PDI-1:9
- PDI-2:10 → PDI-2:1

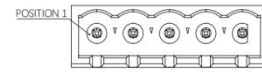
» Cable and Interface Description-IP20

• Power cord and power interface(J1)

Model	length
PJDB-1000	1M
PJDB-2000	2M
PJDB-5000	5M
PJDN-1000	1M
PJDN-2000	2M
PJDN-5000	5M



J1	definition
1	Power supply+ (HV)
2	Logic Power+(LOGIC)
3	GND
4	Brake+ (BK+)
5	Brake- (BK-)



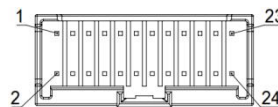
Mating connector	1911994 (Phoenix)
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• IO cable and IO interface(J2)

Model	length
SJD-1000	1M
SJD-2000	2M
SJD-5000	5M



J2	Signal	J2	Signal
1	PAI+	2	SHIELD
3	PAI-	4	/
5	PDI1 (Negative limit)	6	ZERO
7	PDI2 (Positive limit)	8	PDI4+
9	PDI3 (Home)	10	PDI4-
11	/	12	PDI5+
13	PDO3	14	PDI5-
15	PDO2	16	/
17	PDO1	18	/
19	GND	20	+5V
21	GND	22	+5V
23	GND	24	+5V



Mating connector	0513532400 (Molex)
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• Debug configuration cable (J3)

Model	length
TJD-1500	1.5M



J3	Signal
1	RS232 RX
2	RS232 TX
3	GND



Mating connector	188133 (Phoenix)
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• Communication cable (J4)

Model	length
TJD-1000	1M
TJD-2000	2M
TJD-5000	5M



J3-COM1	J3-COM2
1	CAN_H
2	CAN_L
3	CAN_GND(ISO)
4	RS485 RX+
5	RS232 RX / RS485 RX-
6	RS485 TX+
7	RS232 TX / RS485 TX-
8	GND

Note: Fixed model drives only support one of CANopen or RS485 communication modes.

» Cable and Interface Description-IP65

• Power cord and power interface(J1)

Model	length	Motor flange
PJDH-1000	1M	40/60mm
PJDH-3000	3M	
PJDH-5000	5M	
PJDH-81000	1M	80mm
PJDH-83000	3M	
PJDH-85000	5M	



J1	definition
1	Power supply+ (HV)
2	GND
3	Brake+ (BK+)
4	Brake- (BK-)



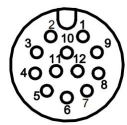
• Communication configuration cable and interface (J2)

Model	length
TJDH-1000	1M
TJDH-3000	3M
TJDH-5000	5M



J2			
1	CAN_H	7	RS485 TX- /232 TX
2	CAN_L	8	GND
3	CAN_GND	9	JUMPER1
4	RS485 RX+	10	JUMPER2
5	RS485 RX- /232RX	11	NC
6	RS485 TX+	12	NC

NOTE:Shorting pins 9 and 10 enables RS232 communication.

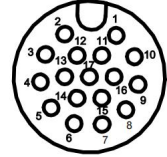


• IO cable and IO interface(J3)

Model	length
SJDH-1000	1M
SJDH-3000	3M
SJDH-5000	5M

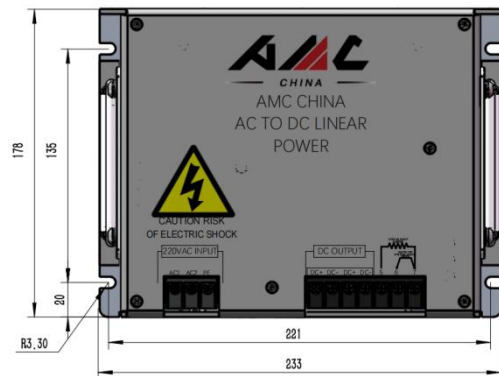


J3			
1	LV+	10	PDI2
2	GND	11	PDI3
3	PAI+	12	PDI4+
4	PAI-	13	PDI4-
5	PDO1	14	PDI5+
6	PDO2	15	PDI5-
7	PDO3	16	GND
8	GND	17	NC
9	PDI1	/	

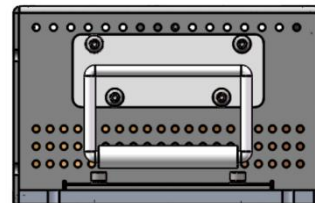
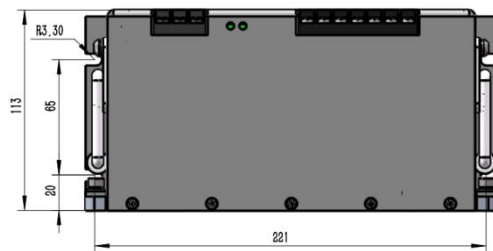


» Linear unregulated power supply

- In order to match the power requirements of various analog circuits, high-precision instruments, aerospace, measurement and control, scientific research experiments and other high-precision applications, Emerson (AMC China) has launched a linear power supply.



Specifications	
Input voltage	220VAC
The output voltage	48VDC±5%
Output current	20A
Whether to isolate	YES
Output interface group	2
Shunt voltage regulator	YES
Clamping voltage	55±2VDC



» Shunt Regulator

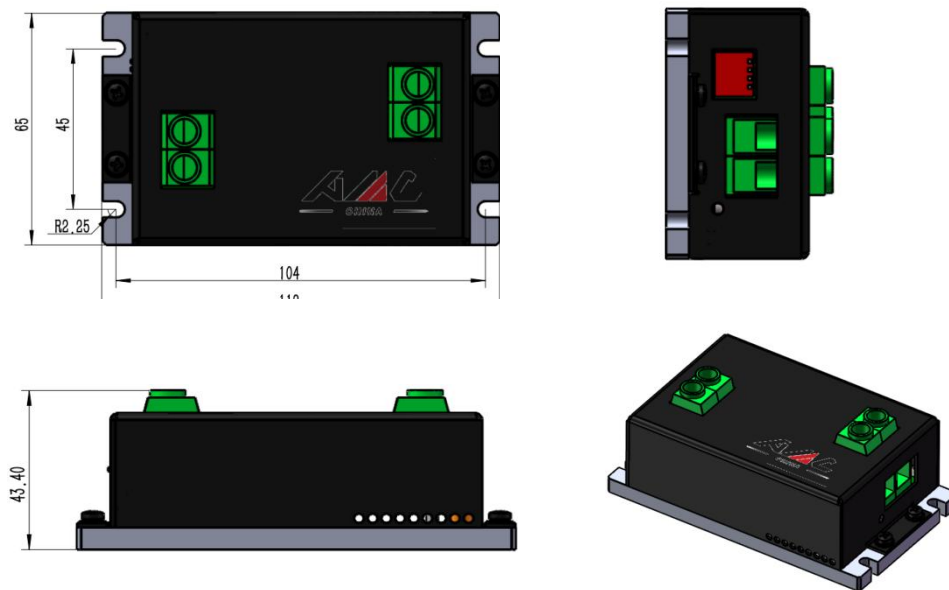
» SR060/080

The SR060/080 series shunt regulators are designed for applications where the actuator in the servo system feeds back energy during the deceleration process, causing the bus voltage to rise. During deceleration braking, most of the mechanical energy is converted into electrical energy back to the power supply, which charges the output capacitor to a higher voltage. If charging reaches the system overvoltage protection point (controller, amplifier, sensor, etc.), the system will fail. To ensure smooth braking of high inertia loads, a shunt regulator is recommended. The need for a shunt regulator is determined by observing the change in the DC bus voltage by braking under the worst conditions.

Clamping voltage can be set: 30VDC (for 24VDC power supply system), 42VDC (for 36VDC power supply system), 55VDC (for 48VDC power supply system), 78VDC (for 72VDC power supply system).

Recommended external resistor: 5Ω, power ≥ 50W (The power is matched according to the energy that needs to be released).

MOUNTING DIMENSIONS





Golden Ding Series Integrated Servo Motor Model and data List

	Rated Power (W)	Rated Torque (Nm)	Rated Speed @48VDC (RPM)	Flange Size (mm)	Power Supply Range		20-80VDC, with Hall and 4096 incremental magnet encoder						Shaft
					Operation Temperature	-25-75 °C				-40-65 °C			
					IP Level	IP20		IP65		IP20	IP65		
CANopen	100	0.32	3000	40	Without Brake	JDC-010N	JDC-S010N	JDC-010NIP65	JDCX-010N	JDCX-010NIP65	Round		
		With Brake		JDC-010B	JDC-S010B	JDC-010BIP65	JDCX-010B	JDCX-010BIP65					
	200	0.64		60	Without Brake	JDC-020N	JDC-S020N	JDC-020NIP65	JDCX-020N	JDCX-020NIP65			
		With Brake		JDC-020B	JDC-S020B	JDC-020BIP65	JDCX-020B	JDCX-020BIP65	With Key				
	400	1.30		60	Without Brake	JDC-040N	JDC-S040N	JDC-040NIP65		JDCX-040N	JDCX-040NIP65		
		With Brake		JDC-040B	JDC-S040B	JDC-040BIP65	JDCX-040B	JDCX-040BIP65					
	600	1.90		80	Without Brake	JDC-060N	JDC-S060N	JDC-060NIP65		JDCX-060N	JDCX-060NIP65		
		With Brake		JDC-060B	JDC-S060B	JDC-060BIP65	JDCX-060B	JDCX-060BIP65					
	750	2.40		80	Without Brake	JDC-075N	JDC-S075N	JDC-075NIP65		JDCX-075N	JDCX-075NIP65		
		With Brake		JDC-075B	JDC-S075B	JDC-075BIP65	JDCX-075B	JDCX-075BIP65					
RS485	100	0.32	3000	40	Without Brake	JDR-010N		JDR-010NIP65	JDRX-010N	JDRX-010NIP65	Round		
		With Brake		JDR-010B		JDR-010BIP65	JDRX-010B	JDRX-010BIP65					
	200	0.64		60	Without Brake	JDR-020N		JDR-020NIP65	JDRX-020N	JDRX-020NIP65			
		With Brake		JDR-020B		JDR-020BIP65	JDRX-020B	JDRX-020BIP65	With Key				
	400	1.30		60	Without Brake	JDR-040N		JDR-040NIP65		JDRX-040N	JDRX-040NIP65		
		With Brake		JDR-040B		JDR-040BIP65	JDRX-040B	JDRX-040BIP65					
	600	1.90		80	Without Brake	JDR-060N		JDR-060NIP65		JDRX-060N	JDRX-060NIP65		
		With Brake		JDR-060B		JDR-060BIP65	JDRX-060B	JDRX-060BIP65					
	750	2.40		80	Without Brake	JDR-075N		JDR-075NIP65		JDRX-075N	JDRX-075NIP65		
		With Brake		JDR-075B		JDR-075BIP65	JDRX-075B	JDRX-075BIP65					

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