

## Kinetix 300 EtherNet/IP Indexing Servo Drives



The Kinetix 300 EtherNet/IP indexing drive provides a cost-effective single-axis solution for low axis count motion control applications. Using one standard Ethernet/IP network for an entire machine - including Motion, Control, I/O, and HMI simplifies wiring, reduces panel layout costs, and allows easy integration into manufacturing and enterprise systems. In addition, safe torque-off functionality helps protect personnel while increasing machine productivity.

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### Kinetix 300 Servo Drive Components

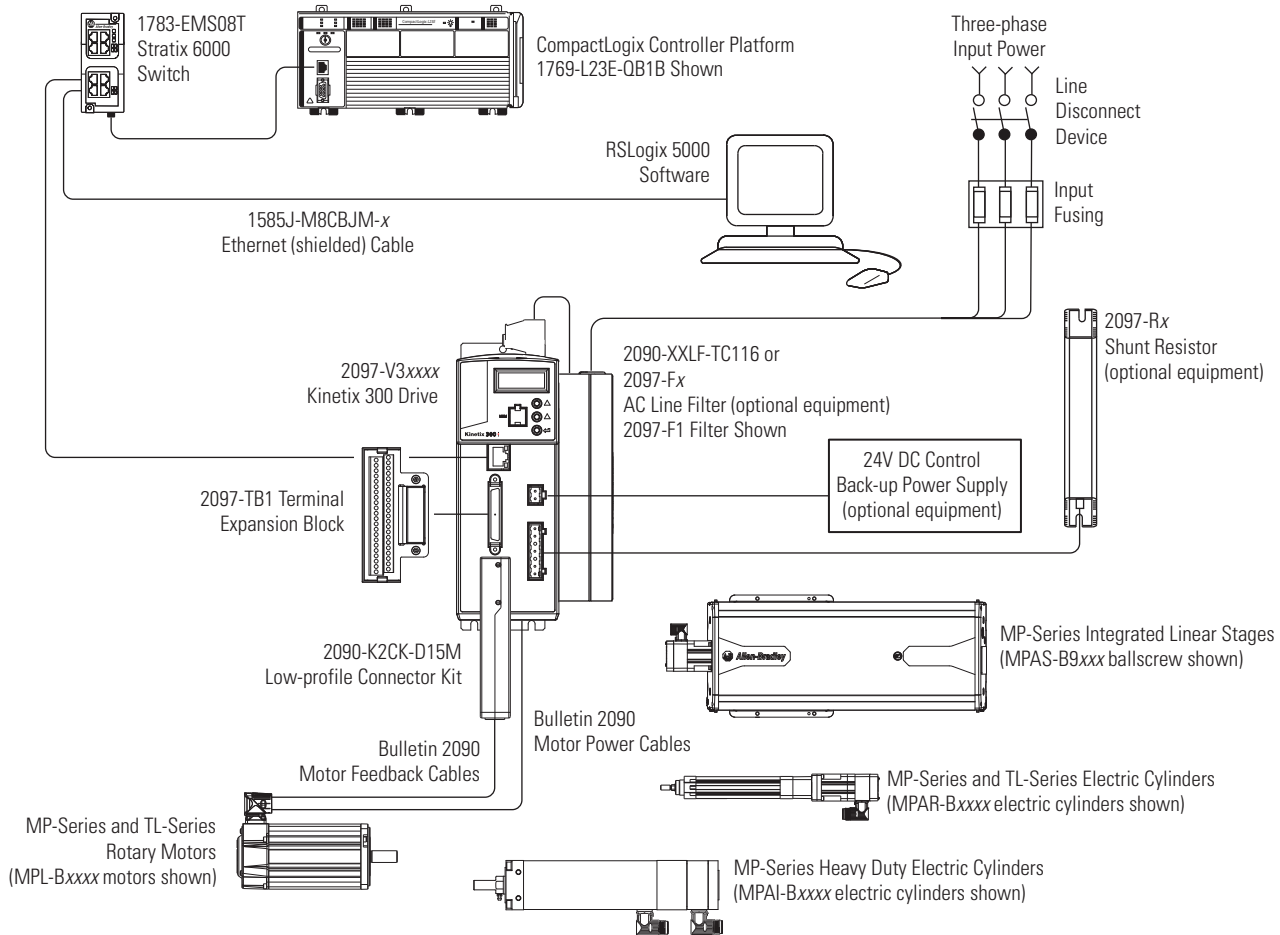
Kinetix 300 servo drive systems consist of these required components:

- One 2097-V3xxxx indexing drive
- One MP-Series or TL-Series servo motor or linear actuator
- One motor power and motor feedback cable
- One 2090-K2CK-D15M low-profile connector kit for motor feedback
- One 2097-TB1 I/O terminal expansion block
- 1585J-M8CBJM-x (shielded) Ethernet cable

Kinetix 300 servo drive systems may also include any of these optional components:

- One 2097-Fx or 2090-XXLF-TC116 AC line filter
- One 2097-Rx shunt resistor

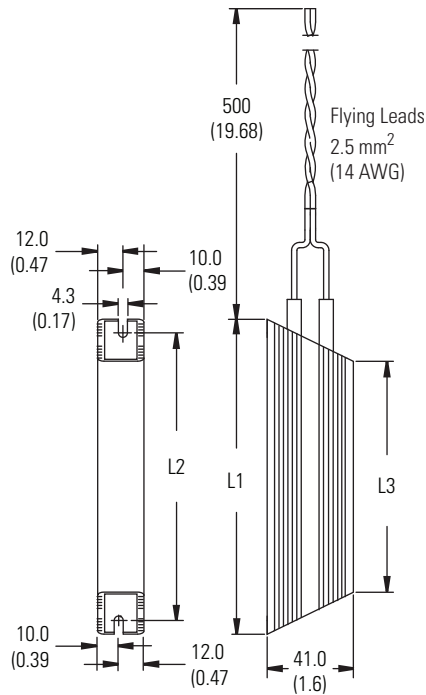
**Typical Configuration - Kinetix 300 Drive System**



## Shunt Resistor Specifications

The Bulletin 2097 passive shunt resistor wires directly to the Kinetix 300 drive.

### Shunt Resistor Dimensions



Dimensions are in mm (in.)

| Shunt Resistor Cat. No. | L1        | L2        | L3        |
|-------------------------|-----------|-----------|-----------|
| 2097-R2                 | 210 (8.3) | 197 (7.7) | 170 (6.7) |
| 2097-R3                 | 210 (8.3) | 197 (7.7) | 170 (6.7) |
| 2097-R4                 | 150 (5.9) | 137 (5.4) | 110 (4.3) |
| 2097-R6                 | 210 (8.3) | 197 (7.7) | 170 (6.7) |
| 2097-R7                 | 150 (5.9) | 137 (5.4) | 110 (4.3) |

### Shunt Resistor Power Specifications

| Shunt Module Cat. No. | Specifications      |                    |               |                |   |                | Kinetix 300 Drive Cat. No.   |
|-----------------------|---------------------|--------------------|---------------|----------------|---|----------------|--|
|                       | Resistance $\Omega$ | Continuous Power W | Peak Power kW | Peak Current A | D <sub>Application</sub> , Max <sup>(1)</sup> % | Weight kg (lb) |  |
| 2097-R2               | 20                  | 150                | 7.6           | 19.5           | 1.97  | 0.3 (0.7)      | 2097-V32PR4<br>2097-V33PR5   |
| 2097-R3               | 30                  |                    | 5.1           | 13.0           | 2.96  |                | 2097-V33PR6  |
| 2097-R4               | 40                  | 80                 | 3.8           | 9.8            | 2.10  | 0.2 (0.4)      | 2097-V31PRO<br>2097-V31PR2<br>2097-V32PRO<br>2097-V32PR2<br>2097-V33PR1<br>2097-V33PR3 |
| 2097-R6               | 75                  | 150                | 7.9           | 10.3           | 1.90  | 0.3 (0.7)      | 2097-V34PR5<br>2097-V34PR6   |
| 2097-R7               | 150                 | 80                 | 4.0           | 5.1            | 2.02  | 0.2 (0.4)      | 2097-V34PR3  |

(1) D<sub>Application</sub> is the application duty cycle in percent. For the intermittent regeneration applications, use  $D_{Application} = t/T$ , where t is the duration when regeneration is needed and T is the time interval between two regenerations. Both t and T must use the same time units, for example, seconds.