## Automatización Eléctrica

Especialistas en Automatizacion

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## Safety guard switchting unit

The safety controller to support maintenance mode of machinery in the safe way.

- Two operation modes to support:
- Auto switching for applications where machine and worker co-operate.
- Manual switching for applications with limitation in operation like maintenance.
- Clear and transparent segmentation of safety functions by use of unique "AND"connection
- Clear LED diagnosis of all in- and output signals for easy maintenance
- PLe according to EN ISO 13849-1 and SIL 3 according to EN 61508.


## Ordering information

Enabling grip switches


## Specifications

| Ratings of guard switching unit Power input |  |  |
| :---: | :---: | :---: |
| Item | G9SX-GS226-T15-_ | G9SX-EX- |
| Rated supply voltage | 24 VDC |  |
| Inputs |  |  |
| Item | G9SX-GS226-T15-_ |  |
| Safety input | Operating voltage: 20.4 VDC to 26.4 VDC , internal impedance: approx. $2.8 \mathrm{k} \Omega$ |  |
| Feedback/reset input |  |  |
| Mode selector input |  |  |
| Outputs |  |  |
| Item | G9SX-G9SX-GS226-T15-_ |  |
| Instantaneous safety output OFF-delayed safety output | P channel MOS FET transistor output Load current: 0.8 A DC max. |  |
| Auxiliary output | PNP transistor output Load current: 100 mA max. |  |
| External indicator outputs | P channel MOS FET transistor outputs <br> Connectable indicators <br> - Incandescent lamp: 24 VDC, 3 W to 7 W <br> - LED lamp: <br> 10 to 300 mA DC |  |

## Application example

## Automatic switching mode

Worker is loading and unloading the machine manually. When loading is finished, robot cycle is started manually by the worker. When robots return to their home position, loading cycle is selected automatically.
Loading condition: Safety sensor $B$ is not active, safety sensor $A$ is active because the robots are not allowed to move to the loading area while the worker loads the machine. So the worker is safe because safety sensor $A$ is active.
Robot work condition: Safety sensor $B$ is active, safety sensor $A$ is not active because the worker is not allowed to move to the loading area when the robots work. So the worker is safe because safety sensor B stops the machine if he moves to the loading area.


## Manual switching mode

Worker has to do maintenance in this machine. While maintenance, it is necessary to move the machine in a limited way. The worker has to select automatic mode or manual mode manually by using the mode selector switch.

## Operation steps:

1) Select maintenance mode by using the mode selector
2) Open the door to do the maintenance while the machine still is able to operate in a limited way (monitoring of limited movement by using the safety limit switch).
3) Close the cover after finishing maintenance
4) Select automatic mode by using the mode selector

E-Stop conditions:
a) open the door while not in maintenance mode
b) the machine actuates the limit switch (breaks the limit).
c) the Enabling grip switch A4EG is actuated to stop the machine in emergency condition.


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