Technical Explanation for Temperature Controllers

CSM_Temperature_TG_E_6_5

Introduction

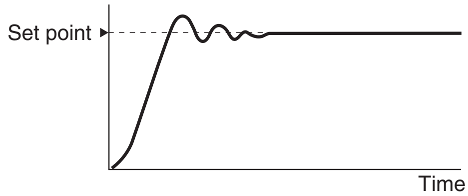
What Is a Temperature Controller?

A Temperature Controller is a device that is used to control a heater or other equipment by comparing a sensor signal with a set point and performing calculations according to the deviation between those values. Devices that can handle sensor signals other than for temperature, such as humidity, pressure, and flow rate, are called Controllers. Electronic controllers are specifically called Digital Controllers.

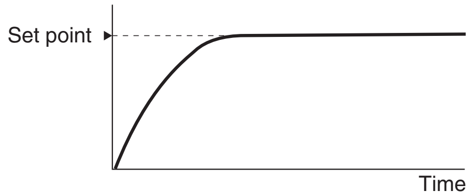
Temperature Control

Temperature Controllers control temperature so that the process value will be the same as the set point, but the response will differ due to the characteristics of the controlled object and the control method of the Temperature Controller. Typically, a response shown in Figure (2), where the set point is reached as quick as possible without overshooting, is required in a Temperature Controller. There are also cases such as the one shown in Figure (1), where a response quickly increases the temperature even if it overshoots is required, and the one shown in Figure (3), where a response slowly increases the temperature is required.

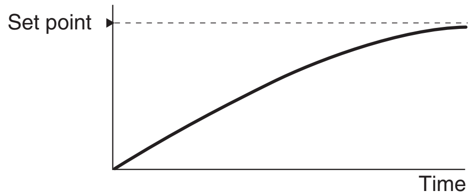
(1) Response where the process value settles on the set point while repeatedly overshooting and undershooting



(2) Proper response

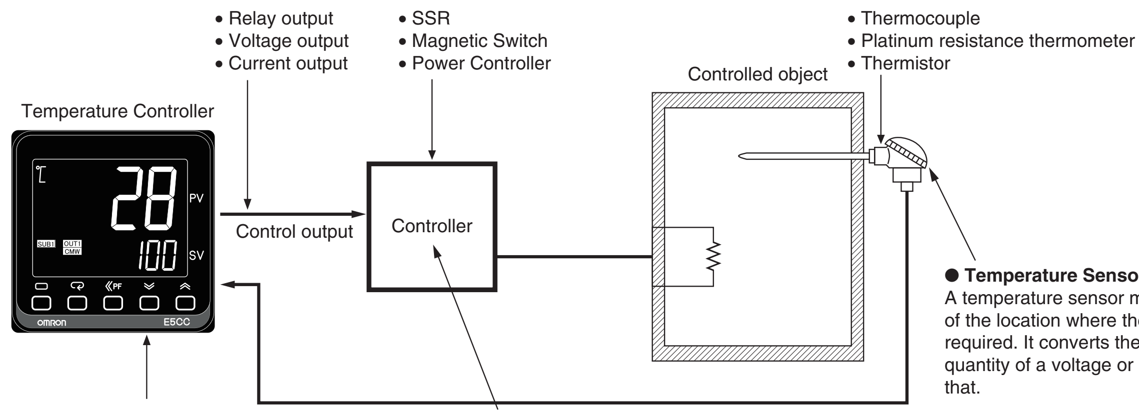


(3) Response where the process value slowly reaches the set point



Temperature Control Configuration Example

The following example describes the basic configuration for temperature control.



● **Temperature Sensor**
A temperature sensor measures the temperature of the location where the temperature control is required. It converts the temperature to a physical quantity of a voltage or resistance and outputs that.

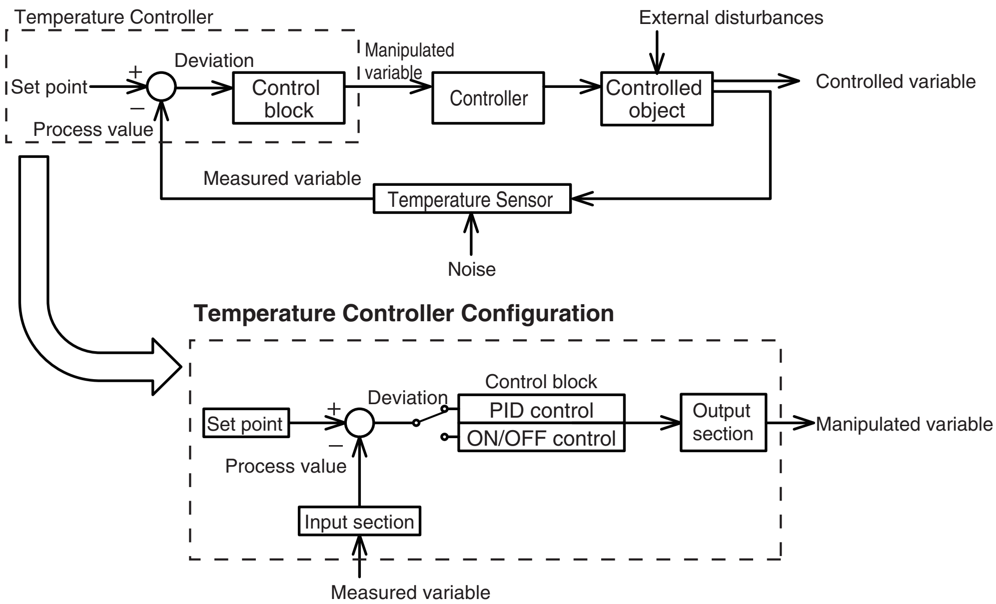
● **Temperature Controller**
A Temperature Controller converts the output from a temperature sensor to the process value and outputs the control output to the controller so the process value will approach the set point.

● **Controller**
A controller is a magnetic switch that turns the current to a heater ON and OFF, a valve that supplies fuel, or some other type of device that is used to heat or cool a furnace, tank, or other controlled object. If the output of the Temperature Controller is a relay output, a relay may also function as the controller.

Temperature Controller Principle

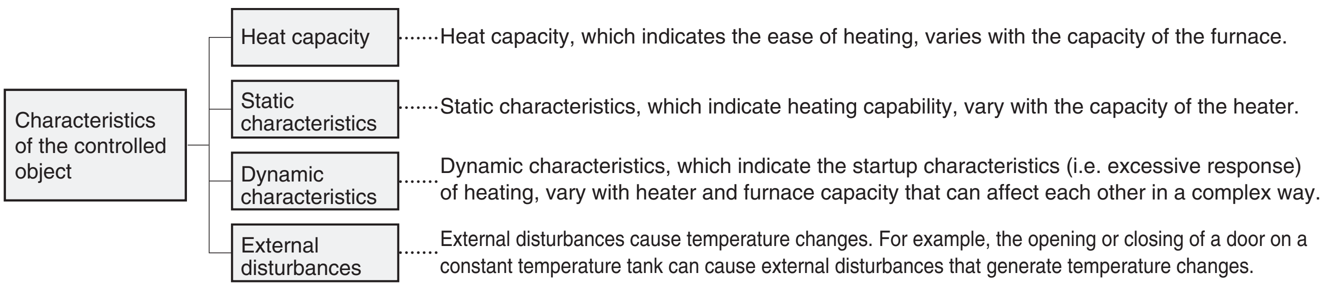
The following figure shows an example of a feedback control system used for temperature control.
The major parts of the feedback control system are built into the Temperature Controller. A feedback control system can be built and temperature can be controlled by combining a Temperature Controller with a controller and temperature sensor that are suitable for the controlled object.

Configuration of a Feedback Control System



Characteristics of the Controlled Object

Before selecting a Temperature Controller or temperature sensor, it is necessary to understand the thermal characteristics of the controlled object for proper temperature control.



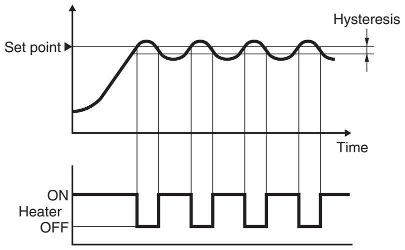
Sensors
Switches
Safety Components
Relays
Control Components
Automation Systems
Motion / Drives
Energy Conservation Support / Environment Measure Equipment
Power Supplies / In Addition
Others
Common

Control Methods

ON/OFF Control Action

As shown in the graph below, if the process value is lower than the set point, the output will be turned ON and power will be supplied to the heater. If the process value is higher than the set point, the output will be turned OFF and power to the heater will be shut off. This control method, in which the output is turned ON and OFF based on the set point in order to keep the temperature constant, is called ON/OFF control action. With this action, the temperature is controlled using two values (i.e., 0% and 100% of the set point). Therefore, the operation is also called two-position control action.

Characteristics of ON/OFF control action

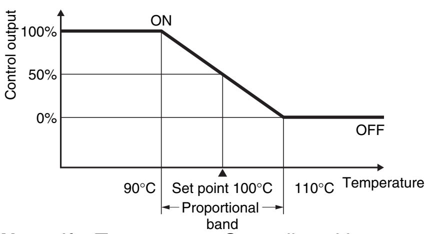


P Action (Proportional Control Action)

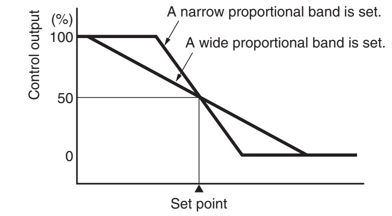
P action (or proportional control action) is used to output a manipulated variable (control output variable) that is proportional to the deviation in order to decrease the deviation between the process value and set point. A proportional band is set centering on the set point, and the output is determined with the following rules.

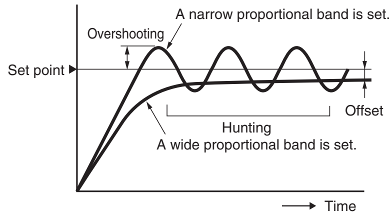
- A manipulated variable that is proportional to the deviation is output when the process value is within the proportional band.
- A 100% manipulated variable is output when the process value is lower than the proportional band.
- A 0% manipulated variable is output when the process value is higher than the proportional band.

Smoother control than the ON/OFF control action is possible because the output is gradually changed near the set point according to deviation. However, if the temperature is controlled with the proportional action alone, it will stabilize at a temperature that is off from the set point (offset).



Note: If a Temperature Controller with a temperature range of 0°C to 400°C has a 5% proportional band, the width of the proportional band will be converted into a temperature range of 20°C. In this case, a full output is kept turned ON until the process value reaches 90°C, and the output is OFF periodically when the process value exceeds 90°C, provided the set point is 100°C. When the process value is 100°C, there will be no difference in time between the ON period and the OFF period (i.e. the output is turned ON and OFF 50% of the time.)

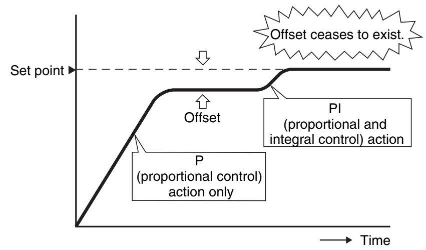


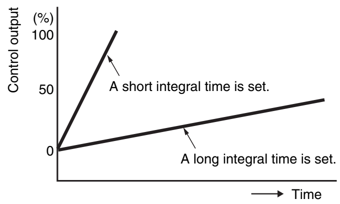


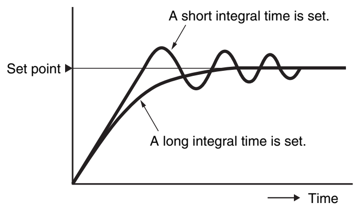
I Action (Integral Control Action)

I action (or integral action) increases or decreases the manipulated variable according to the size and duration of the deviation.

The temperature will stabilize at a temperature off from the set point (offset) with only the proportional action, but the deviation with the passage of time will be decreased and the process value will be the same as the set point by combining the proportional and integral actions.

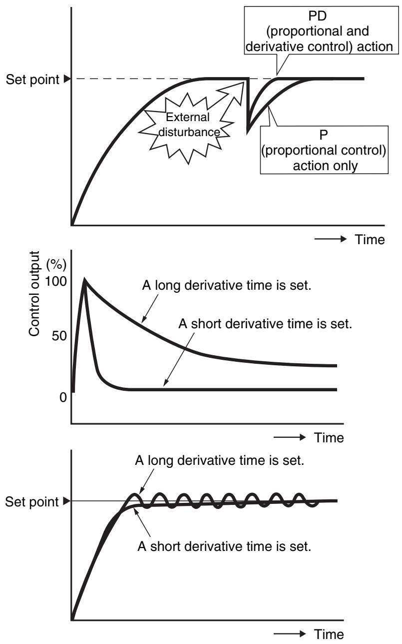






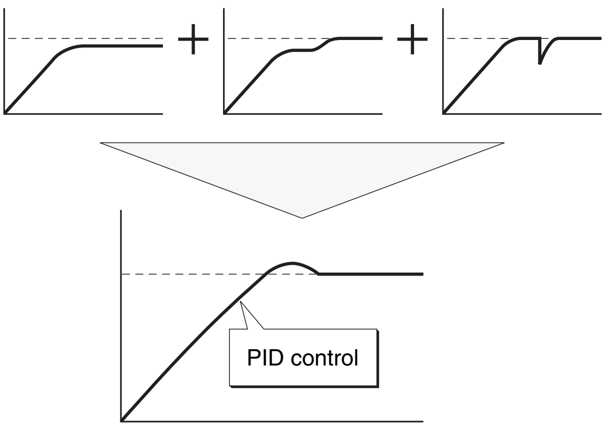
D Action (Derivative Control Action)

D action (or derivative action) provides a manipulated variable in response to abrupt changes in the process value, due to factors such as an external disturbance, so that control will quickly return to the original status.The proportional and integral actions both corrects the control results, so the response to abrupt changes is delayed. The derivative action compensates for that drawback and provides a large manipulated variable for rapid external disturbances.



PID Control

PID control is a combination of proportional, integral, and derivative control actions. The temperature is controlled smoothly here by proportional control action without hunting, automatic offset adjustment is made by integral control action, and quick response to an external disturbance is made possible by derivative control action.

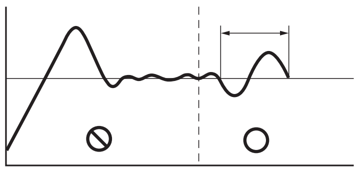


Two PID Control

Conventional PID control uses a single control block to control the responses of the Temperature Controller to a set point and to external disturbances. Therefore, the response to the set point will oscillate due to overshooting if importance is placed on responding to external disturbances with the P and I parameters set to small values and the D parameter set to a large value in the control block. On the other hand, the Temperature Controller will not be able to respond to external disturbances quickly if importance is placed on responding to the set point (i.e., the P and I parameters are set to large values). This makes it impossible to satisfy both the types of response in this case.
Two PID control provides good response for both response to the set point and an external disturbance.

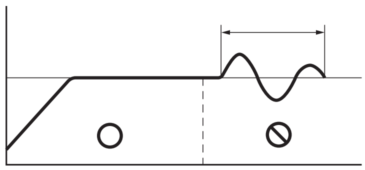
PID Control

(1)



Response to the set point will be slow if response to the external disturbance is improved.

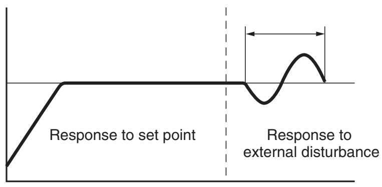
(2)



Response to the external disturbance will be slow if response to the set point is improved.

Two PID Control

(3)



Controls both the set point and the external disturbance response.

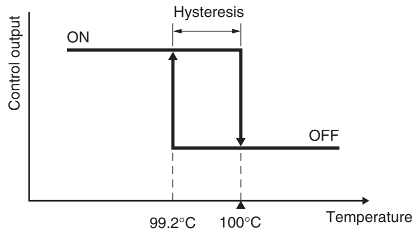
Explanation of Terms

Control Terminology

Hysteresis

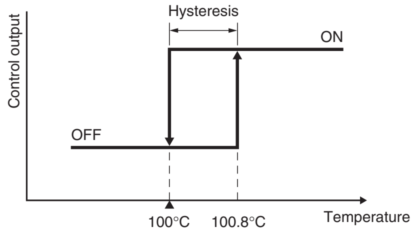
ON/OFF control turns the control output ON and OFF at the set point, so if there are small amounts of noise near the set point, the output will turn ON and OFF frequently (which is called chattering). This will shorten the life of the output relay or unfavorably affects some devices connected to the Temperature Controller. To prevent this from happening, a temperature band (hysteresis) is created between the ON and OFF operations. This gap is called hysteresis.

Hysteresis (Reverse Operation)



Note: Hysteresis indicates 0.8°C.

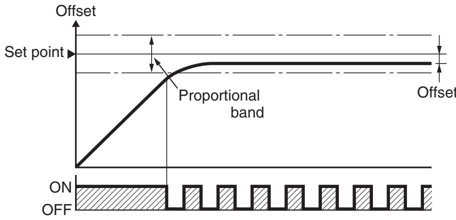
Hysteresis (Direct Operation)



Note: Hysteresis indicates 0.8°C.

Offset

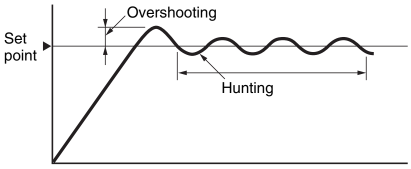
Proportional control action causes an error in the process value due to the heat capacity of the controlled object and the capacity of the heater. The result is a small discrepancy between the process value and the set point in stable operation. This error is called offset. Offset is the difference in temperature between the set point and the actual process temperature. It may exist above or below the set point.



Hunting and Overshooting

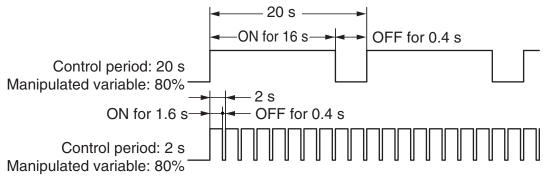
ON/OFF control action often involves the waveform shown in the following diagram. A temperature rise that exceeds the set point after temperature control starts is called overshooting. Temperature oscillation near the set point is called hunting. Improved temperature control is to be expected if the degree of overshooting and hunting are low.

Hunting and Overshooting in ON/OFF Control Action



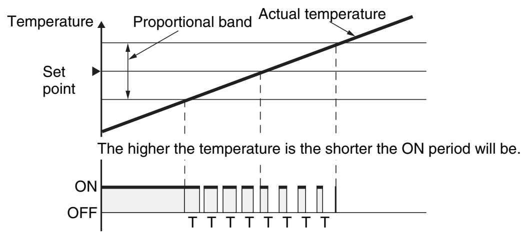
Time-proportioning Control Action

Relays and SSRs can output only ON (100%) and OFF (0%). PID control, however, outputs the manipulated variable between 0% and 100%. Time-proportioning control action is an output method that adds a time parameter (control period) to the manipulated variable, which allows for a 0% to 100% output when using an ON/OFF output. A manipulated variable between 0% and 100% can be output by turning the output ON for the control period (seconds) multiplied by the manipulated variable (%), and then turning the output OFF for the remainder of the control period. Because the output turns ON and OFF only once during the control period, a long control period delays the control response, and a short control period speeds up the control response. If the control period is short, the life expectancy of output devices with contacts such as relays will decrease. As a general rule, set the control period for relay outputs to 20 seconds, and set the control period for SSR outputs to 2 seconds.



Proportional Band

The proportional band is a parameter that sets the range in which control performs the proportional action. When the process value enters the proportional band, the proportional action outputs a manipulated variable between 0% and 100% that is proportional to the deviation between the set point and the process value. When the process value is outside the proportional band in heating control, the manipulated variable is output at 100% when the process value is lower and 0% when higher than the band.



$$MV = \frac{T_{ON}}{T_{ON} + T_{OFF}} \times 100(\%)$$

Example:
If the control cycle is 10 s with an 80% control output, the ON and OFF periods will be as follows.

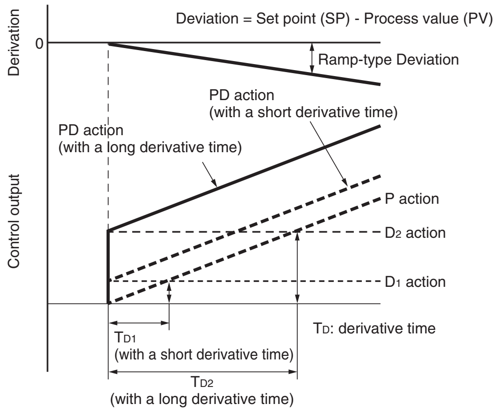
T_{ON}: 8 s

T_{OFF}: 2 s

Derivative Time

The derivative action are not used alone for control. It is used for control together with the proportional action. The control method that combines the proportional action and the derivative action is called the PD actions. When a ramp-type deviation (i.e., a deviation with a constant slope) is provided in the PD actions as shown in the figure, the time until the derivative manipulated variable reaches the same manipulated variable as the proportional action is called the derivative time. Therefore, this shows that the longer the derivative time is, the stronger the correction by the derivative action will be.

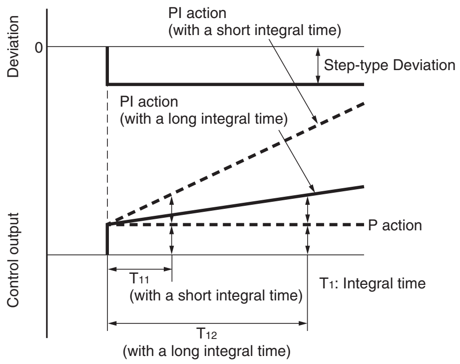
PD Action and Derivative Time



Integral Time

When a step-type deviation is added in the PI actions that combine the proportional and derivative actions or the PID actions that combine the proportional, integral, and derivative actions, the time until the integral manipulated variable reaches the same manipulated variable as the proportional action is called the integral time. Therefore, the shorter the integral time is, the stronger the integral action will be. But if the integral time is too short, the correction will be too strong and hunting may occur.

PI Action and Integral Time



Constant Value Control

For constant value control, control is preformed at a specific set point.

Program Control

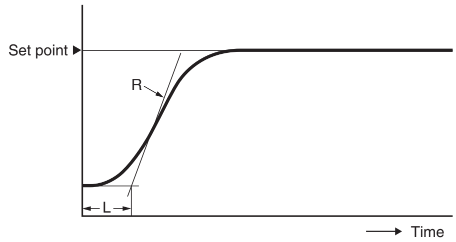
Program control is used to control temperature for a set point that will change at predetermined time interval according to a program.

Autotuning

The PID constants that can be used for good temperature control depend on the characteristics of the controlled object. The method to derive suitable PID constants for the differing characteristics of controlled objects is called autotuning. Typical methods are the step response method and limit cycle method.

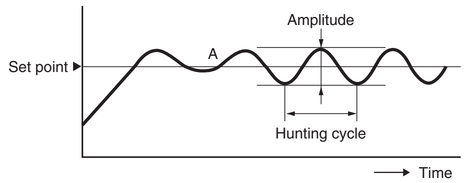
Step Response Method

A manipulated variable of 100% is output in steps, the maximum temperature ramp R and dead time L are measured from the response of the controlled object, and the PID constants are calculated from the values of R and L.



Limit Cycle Method

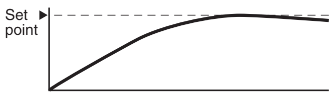
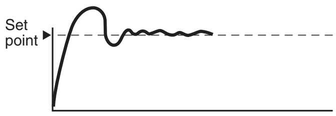
Outputs a manipulated variable at 100% and 0% alternately, and the PID constants are calculated from the hunting cycle and amplitude values that occur in the controlled object. Autotuning typically refers to the limit cycle method.



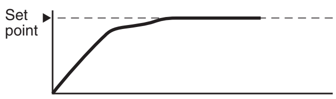
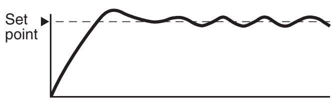
Readjusting PID Constants

Control can usually be performed without problems using the PID constants that are calculated with autotuning. Depending on the application, the priorities of overshooting suppression, response speed improvement, and stability improvement may be different. In those cases, the individual values of the PID constants can be adjusted by referring to the following examples to make the response behave closer to the anticipated response.

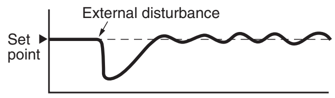
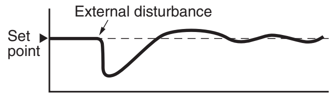
Response to Change in the Proportional Band

Wider		It is possible to suppress overshooting although a comparatively long startup time and set time will be required.
Nar-rower		The process value reaches the set point within a comparatively short time and keeps the temperature stable although overshooting and hunting will result until the temperature becomes stable.

Response to Change in Integral Time

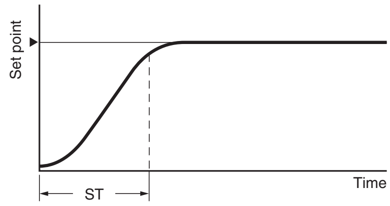
Wider		The set point takes longer to reach. It is possible to reduce hunting, overshooting, and undershooting although a comparatively long startup time and set time will be required.
Nar-rower		The process temperature reaches the set point within a comparatively short time although overshooting, undershooting, and hunting will result.

Response to Change in Derivative Time

Wider		The process value reaches the set point within a comparatively short time with comparatively small amounts of overshooting and undershooting. Fine-cycle hunting will result due to the change in process value.
Nar-rower		The process value will take a relatively long time to reach the set point with heavy overshooting and undershooting.

Self-tuning

The PID constants are calculated with the step response tuning when the Temperature Controller operation begins and when the set point is changed. Once the PID constants have been calculated, self-tuning is not executed when the next control operation is started as long as the set point remains unchanged.

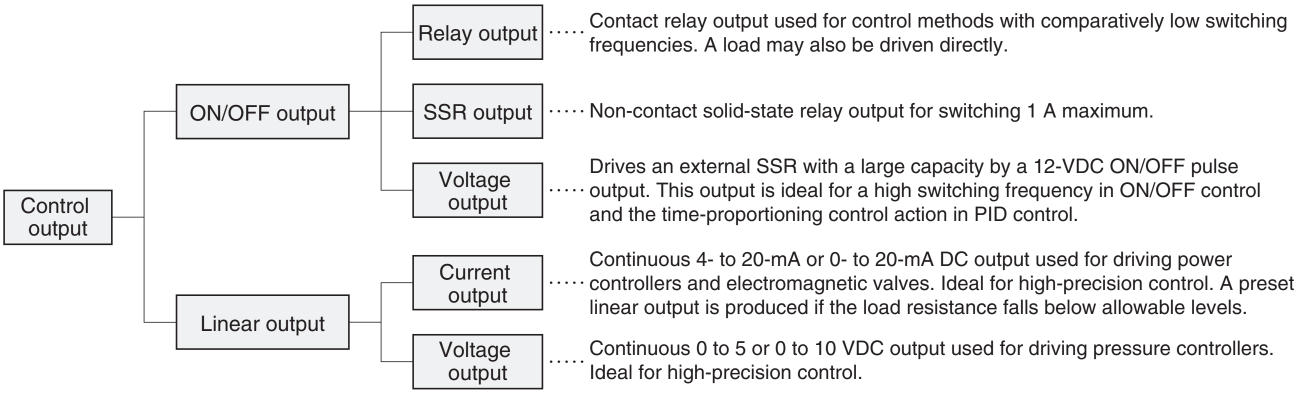


Models and Tuning Methods

Model	Tuning Methods
E5☐C	AT, ST
E5☐N *	AT, ST
E5☐R	AT
E5CS-U/E5CSV	AT, ST
E5CB	AT
EJ1	AT
E5ZN	AT
C200H-TC	AT
C200H-TV	AT
C200H-PID	AT

ST: Self-tuning
AT: Autotuning
Note: Not including the E5ZN

Control Outputs



Alarm Terminology

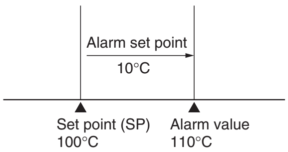
Alarm Output
Some Temperature Controllers output an alarm signal to the alarm output, while others allow you to assign an auxiliary output or control output as the output destination.

Alarm Operation
The process value, alarm value, and set point are compared, and a signal is output according to the operating mode specified by the alarm type. The main operating modes are a deviation alarm, absolute-value alarm, standby sequence alarm, heater burnout alarm, SSR failure alarm, and loop burnout alarm. These alarms may also be combined.

Deviation Alarm
The deviation alarm turns ON according to the deviation from the set point in the Temperature Controller.

Setting Example

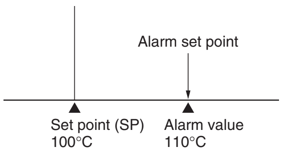
Alarm temperature is set to 110°C.
The alarm set point is set to 10°C.



Absolute-value Alarm
The absolute-value alarm turns ON according to the alarm temperature regardless of the set point in the Temperature Controller.

Setting Example

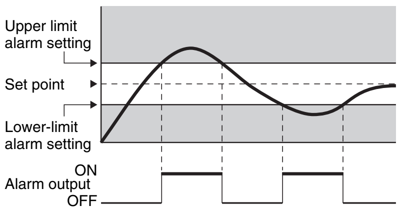
Alarm temperature is set to 110°C.
The alarm set point is set to 110°C.



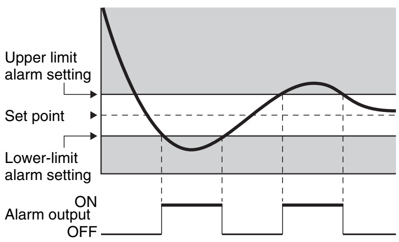
Standby Sequence Alarm
It may be difficult to keep the process value outside the specified alarm range in some cases (e.g., when starting up the Temperature Controller), and the alarm turns ON abruptly as a result. This can be prevented with the standby sequential function of the Temperature Controller. This function makes it possible to ignore the process value right after the Temperature Controller is turned ON or right after the Temperature Controller starts temperature control. In this case, the alarm will turn ON if the process value enters the alarm range after the process value has been once stabilized.

Example of Alarm Output with Standby Sequence Set

Temperature rise



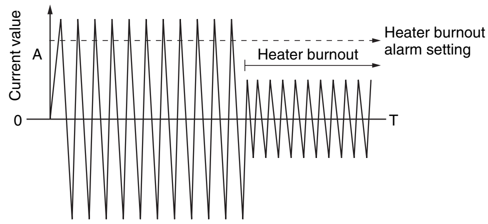
Temperature drop



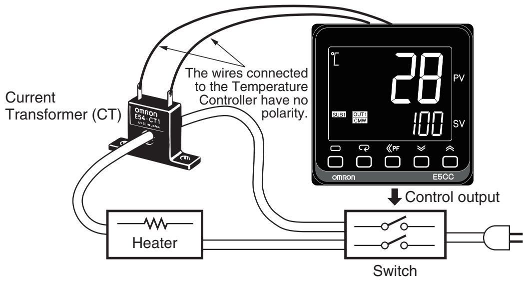
SSR Failure Alarm
SSRs often fail structurally in a short-circuit mode, and if there is a short-circuit failure, there is a risk of a hazardous situation where the temperature of the heater may continue to increase. The SSR failure alarm detects an SSR short-circuit failure and outputs an alarm. The heater current is detected using a current transformer (CT), and the SSR failure alarm is output if the current continues flowing to the heater even though the output from the Temperature Controller that drives the SSR is OFF.

Heater Burnout Alarm
If equipment continues to operate when people are not aware that the heater has burned out, products may become faulty, and in the worst case, the equipment may be damaged. The heater burnout alarm detects burnouts in heaters and disconnected heater cables. The heater current is detected using a current transformer (CT), and the heater burnout alarm is output if the current does not flow to the heater even though the output of the Temperature Controller that drives the heater is ON. A heater burnout in a three-phase heater can also be detected if the type of Temperature Controller that can be connected to two current transformers (CTs) is used.

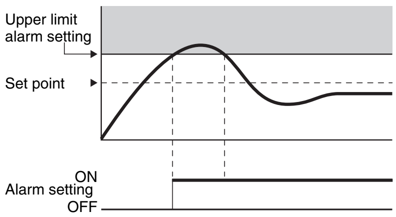
* When the Temperature Controller output is a current output, the heater burnout alarm cannot be used.



Heater current waveform (CT waveform)



Alarm Latch
An alarm latch can be used to keep the alarm ON until the latch is canceled regardless of the temperature after the alarm output has turned ON.

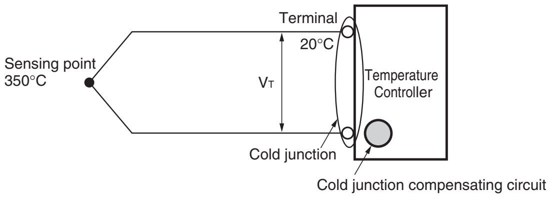


LBA (Loop Burnout Alarm)
An alarm is output by assuming the occurrence of control loop failure when deviation is a certain value or higher and the input does not change in the direction that reduces the deviation, even though control is being performed. This alarm can be used when operation is started but the sensor has not been installed after replacing the heater and as a method for detecting missing sensors.

Temperature Sensor Terminology

Cold Junction Compensation

A thermocouple produces a voltage (i.e., a thermoelectromotive force) from the temperature difference between the hot junction and the cold junction on the opposite side. For this reason, a thermocouple outputs a relative temperature, not an absolute temperature. In order for the Temperature Controller to calculate the absolute temperature from the relative temperature that is output by the thermocouple, the effect of the cold junction temperature is compensated for, or canceled out, by detecting the temperature of the cold junction and adding a thermoelectromotive force that corresponds to that temperature to the thermoelectromotive force of the thermocouple. The method of calculating the absolute temperature of the hot junction by adding a voltage is called cold junction compensation.



In the above diagram, the thermo-electromotive force (1) V_T that is measured at the input terminal of the Temperature Controller is equal to V (350, 20).

Here, V (A, B) gives the thermo-electromotive force when the cold junction is A °C and the cold junction is B °C.

Based on the law of intermediate temperatures, a basic behavior of thermocouples, (2) V (A, B) = V (A, C) - V(B, C).

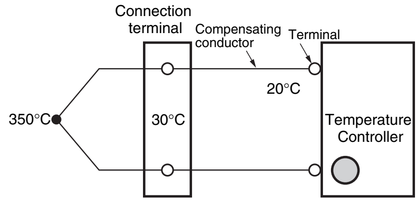
> When the ambient (terminal section) temperature is 20°C, the temperature sensor inside the Temperature Controller detects 20°C. If we add the voltage V(20, 0) that corresponds to 20°C in the standard electromotive force table to the right side, we get the following:
>
> V(350, 20) + V(20, 0)
>
> V(350, 20) ↓ Thermo-electromotive force from thermocouple
>
> V(20, 0) ↓ Electromotive force generated by the cold junction compensation circuit
>
> If we expand the first part of formula (2) with A = 350, B = 20, and C = 0, we get the following:
> = V{(350, 0) – V(20, 0)} + V(20, 0) = V(350, 0).
>
> V(350, 0) is the thermo-electromotive force for a cold junction temperature of 0°C. This is the value that is defined as the standard thermo-electromotive force by JIS, so if we check the voltage, we can find the temperature of the hot junction (here, 350°C).

Compensating Conductor

If the thermocouple temperature sensor cable does not reach the Temperature Controller and the cable between the sensor and the Temperature Controller is extended with copper wire, a large temperature error will occur.

A compensating conductor must be used to extend the thermocouple temperature sensor cable. A compensating conductor is a cable that produces nearly the same thermoelectromotive force as the thermocouple around room temperature, and a compensating conductor that is suitable for the thermocouple must be used. Compared to a thermocouple cable, a compensating conductor is generally inexpensive. Compensating conductors suitable for various thermocouples are available commercially.

Example of Compensating Conductor Use



V (350, 30) + V (30, 20) + V (20, 0)

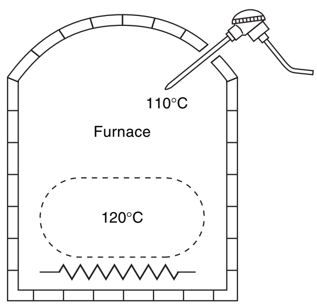
- V (350, 30): Thermo-electromotive force from thermocouple
- V (30, 20): Thermo-electromotive force from compensating conductors
- V (20, 0): Voltage from cold junction compensation

= {V (350, 30) - V (30, 0)} + {V(30, 0) - V (20, 0)} + V (20, 0)
= V (350, 0)

If you extend the cable of a platinum resistance thermometer or thermistor temperature sensor, using a compensating conductor will actually cause a large temperature error. Extend the cable using a cable with sufficiently low conductor resistance.

Input Shift

As the process value, the Temperature Controller displays the result of adding an input shift to or subtracting it from the temperature measured by the temperature sensor. You can use the input shift to compensate the Temperature Controller display when the temperature sensor measurement point and the point at which you intend to measure temperature are different and the temperature difference is already known.

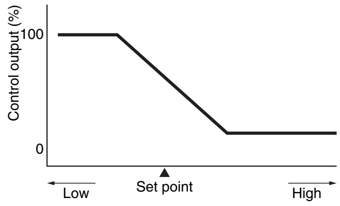


Input compensation value: 10°C (Displayed value is 120°C.)
(120 – 110 = 10)

Output Terminology

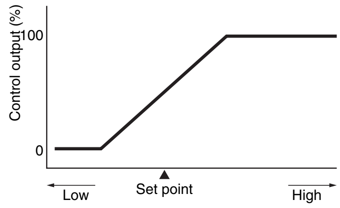
Reverse Operation (Heating)

Reverse operation is used to increase the manipulated variable when the temperature is lower than the set point. Heating control is reverse operation.



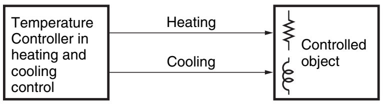
Direct Operation (Cooling)

Direct operation is used to increase the manipulated variable when the temperature is higher than the set point.
Cooling control is direct operation.

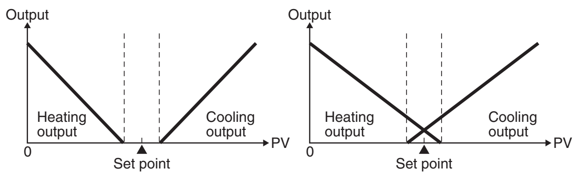


Heating and Cooling Control

Temperature control over a controlled object would be difficult if heating was the only type of control available, so cooling control was also added. Two control outputs (one for heating and one for cooling) can be provided by one Temperature Controller.

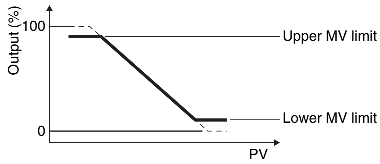


Heating and Cooling Outputs

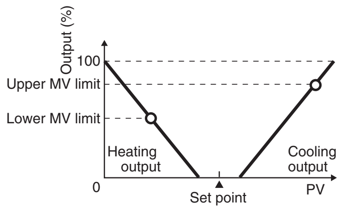


MV (Manipulated Variable) Limiter

The MV upper limit and MV lower limit are used to set the upper and lower limits of the manipulated variable that will be output. When the manipulated variable calculated by the Temperature Controller is outside the range of the MV limiter, the actual output will be the upper limit or the lower limit.

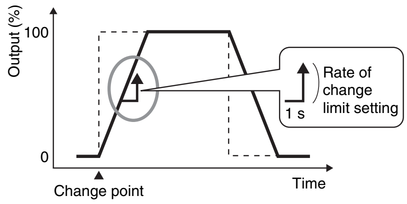


With heating and cooling control, the cooling MV is treated as a negative value. Generally speaking then, the upper limit (positive value) is set to the heating output and the lower limit (negative value) is set to the cooling output as shown in the following diagram.



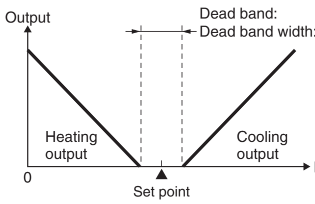
Rate of Change Limit

The rate of change limit for the MV sets the amount of change that occurs per second in the MV. If the MV calculated by the Temperature Controller changes significantly, the actual output follows the rate of change limiter setting for MV until it approaches the calculated value.

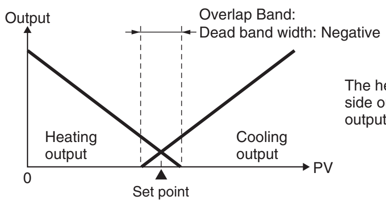


Dead Band

The overlap band and dead band are set for the cooling output. A negative value here produces an overlap band and a positive value produces a dead band.



The heating side output and cooling side output will not be simultaneously output.



The heating side output and cooling side output will be simultaneously output near the set point.

Cooling Coefficient

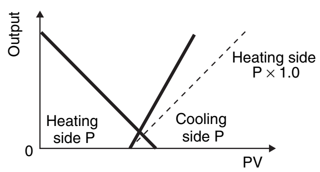
For Temperature Controllers capable of heating/cooling control that do not have separate PID constants for the heating and cooling, it may not be possible to obtain good control performance with the same PID constants when the heating and cooling characteristics of the controlled object differ greatly. In this case, adjust the proportional band on the cooling side (cooling side P) with the cooling coefficient until heating and cooling side control are balanced. The P for heating and cooling side can be calculated using the following formulas.

Heating side P = P

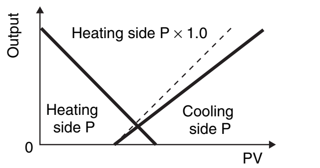
Cooling side P = Heating side P x cooling coefficient

For cooling side P control when heating side characteristics are different, multiply the heating side P by the cooling coefficient.

Heating Side P × 0.8



Heating Side P × 1.5



Heating/Cooling PID Control

For Temperature Controllers that can set PID control separately for heating and cooling, the PID constants for these will be automatically set by selecting an adjustment method with the heating/cooling tuning method according to the control characteristics of the cooling side, and then executing autotuning.

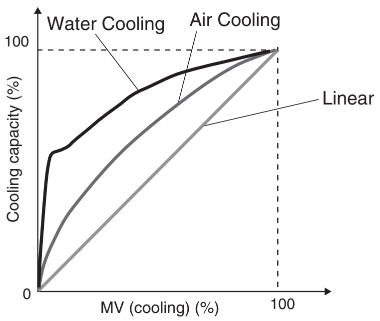
Parameter	Setting
Heating/Cooling Tuning Method	Same as heating control
	Linear
	Air cooling
	Water cooling

Linear Tuning

Control that is suitable for an application that has linear cooling characteristics is performed.

Air Cooling/Water Cooling Tuning

Control that is suitable for an application that does not have linear cooling characteristics (such as plastic molding machines) is performed. The response is fast and the response characteristics are stable.

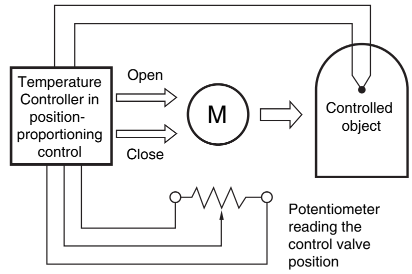


Cooling Characteristic

Positioning-Proportional Control

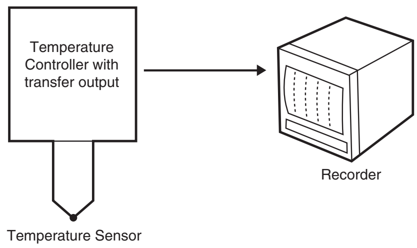
This is also called ON/OFF servo control. When a Control Motor or Modutrol Motor with a valve is used in this control system, a potentiometer for open/close control reads the degree of opening (position) of the control valve, outputs an open and close signal, and transmits the control output to Temperature Controller. The Temperature Controller outputs two signals: an open and close signal.

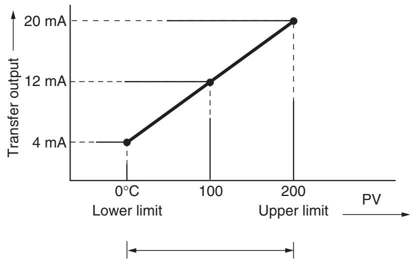
Floating control (feedback of the valve position is not provided with a potentiometer; control is possible even without a potentiometer) can also be selected.



Transfer Output

There may be situations where you want to send the process value and set point to a recorder, another Temperature Controller, or a PLC using a method other than communications. The transfer output converts one value out of process value, set point, or other value to a current between 4 and 20 mA and outputs it. The device that receives the transfer output must support a current input between 4 and 20 mA.

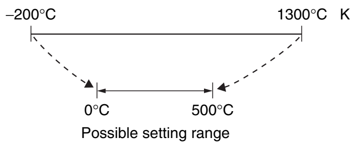




Setting Terminology

Set Limit

The range in which the set point can be set is determined by the type of temperature sensor, so a large value can be set. The set limit can restrict the temperature range that can be set in cases where the equipment will be damaged if a temperature is set that is higher than the temperature that will actually be used.

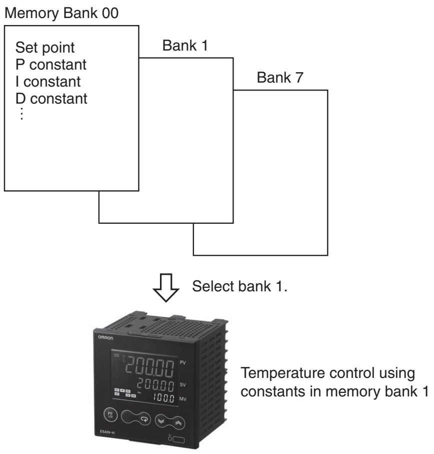


Multiple Set Points

Multiple set points can be preset and then switched using the front keys or event inputs.

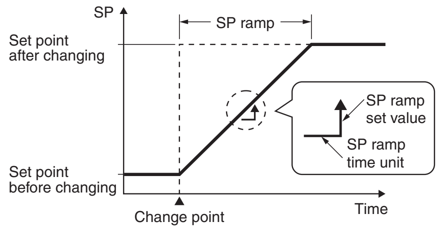
Setting Memory Banks

Temperature Controllers that have multiple set points, PID constants, and alarm values save these parameters in groups called banks. The parameters registered in a bank can be changed at once by switching banks during control.



Set Point (SP) Ramp

Use this function to increase the temperature at a predetermined rate or to increase the temperature to the target temperature in a predetermined time. When the SP ramp is enabled, the set point will be set and the temperature will be controlled until it reaches the set point as shown in the following figure.



Remote Set Point (SP) Input

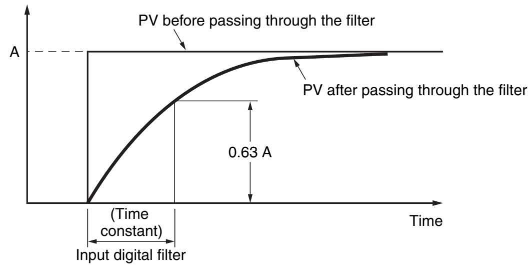
The remote SP is used to set and change the set point with an external analog signal (4 to 20 mA). Enable the remote SP to control the temperature using the remote SP as the set point.

Event Input

The event input is used to input an ON/OFF signal to the Temperature Controller. A function can be assigned to the input, such as switching multi-SPs or RUN/STOP, and this allows the Temperature Controller to be externally controlled.

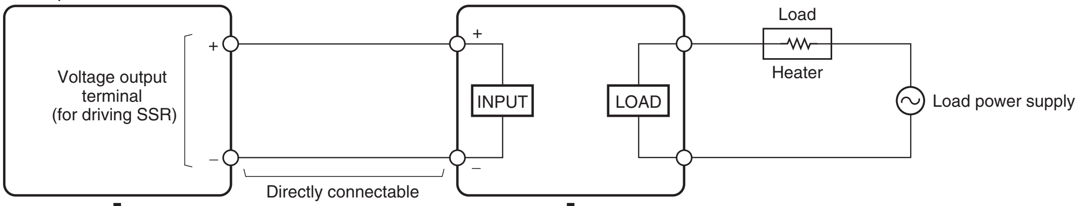
Input Digital Filter

The input digital filter is used when the external noise in the sensor input signal is large and control or measurements are unstable. The process value that will be used for control is a value that has passed through the input digital filter. The input digital filter setting value is the time constant of the digital filter. The following figure shows the relationship between the time constant and the process value (PV) after passing through the filter.



Further Information

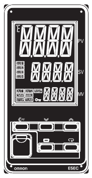
Connection Examples between Temperature Controllers and SSRs



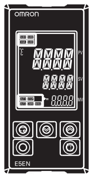
Number of Connectable SSRs in parallel

Temperature Controllers with voltage output of 40 mA at 12 VDC

E5EC/E5AC
E5EC-T/E5AC-T

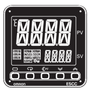


E5AN-H/E5EN-H



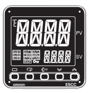
Temperature Controllers with voltage output of 21 mA at 12 VDC

E5CC/-T

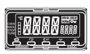


E5CN-H

E5CC-U



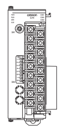
E5GC



E5CB

E5CS Series

EJ1

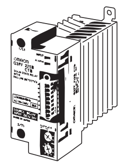


E5DC

G3PF (SSR with built-in Current Transformer)
25 A or 35 A at 240/480 VAC
Number of connectable SSRs: 8 (40 mA models), 4 (21 mA models)

Rated input voltage: 12 to 24 VDC

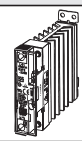
With built-in CT. Detects heater burnout and SSR short-circuit failures.



G3PE (Single-phase)
15 A, 25 A, 35 A, or 45 A at 240/480 VAC
Number of connectable SSRs: 5 *1 (40 mA models), 3 *2 (21 mA models)

Rated input voltage: 12 to 24 VDC

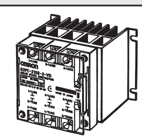
Extremely thin Relays integrated with heat sinks.



G3PE (Three-phase)
15 A, 25 A, 35 A, or 45 A at 240/480 VAC
Number of connectable SSRs: 4 (40 mA models), 2 (21 mA models)

Rated input voltage: 12 to 24 VDC

Slim design with 3-phase output and built-in heat sinks.

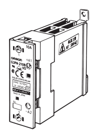


Note: Refer to your OMRON website for details.

G3PA
10 A, 20 A, 40 A, or 60 A at 240 VAC
20 A, 30 A, or 50 A at 480 VAC
Number of connectable SSRs: 5 *3 (40 mA models), 3 *4 (21 mA models)

Rated input voltage: 5 to 24 VDC or 12 to 24 VDC

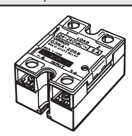
Thin Relays integrated with heat sinks.



G3NA
5 A, 10 A, 20 A, 25 A, 40 A, 50 A, 75 A, or 90 A at 240 VAC
10 A, 20 A, 25 A, 40 A, 50 A, 75 A, or 90 A at 480 VAC
Number of connectable SSRs: 5 *5 (40 mA models), 3 *6 (21 mA models)

Rated input voltage: 5 to 24 VDC

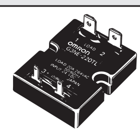
Standard model with screw terminals.



G3NE
5 A, 10 A, or 20 A at 240 VAC
Number of connectable SSRs: 2 (40 mA models), 1 (21 mA models)

Rated input voltage: 12 VDC

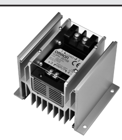
Compact, low-cost model with faston terminals.



G3PH
75 A or 150 A at 240/480 VAC
Number of connectable SSRs: 8 (40 mA models), 4 (21 mA models)

Rated input voltage: 5 to 24 VDC

For high-power heater control.



● Calculating the Number of Connectable SSRs in Parallel

(A): The maximum load current for the voltage output (for driving SSR) of each Temperature Controller.
(B): SSR input current
(A) ÷ (B) = Number of connectable SSRs

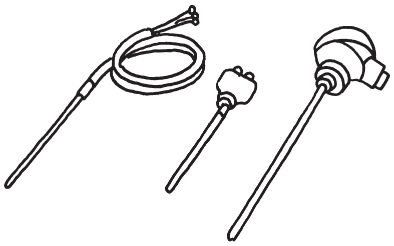
*1. Two G3PE-BL SSRs can be connected.
*2. One G3PE-BL SSR can be connected.
*3. Two G3PA-BL SSRs can be connected.
*4. One G3PA-BL SSR can be connected.
*5. Two of the -UTU models of the G3NA SSRs can be connected.
*6. One of the -UTU model of the G3NA SSRs can be connected. Four of the 480-VAC models of the G3NA SSRs can be connected.

FAQs

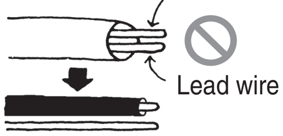
The temperature error of the Temperature Controller seems large. What is the cause of this?

The following are possible causes.

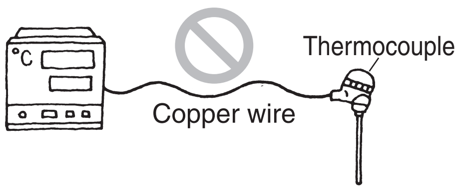
- The input type of the temperature sensor is incorrect (temperature sensor type setting).



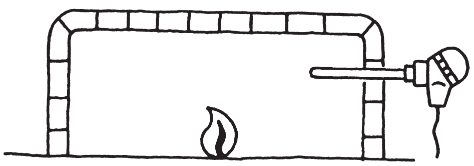
- Temperature sensor lead wires and power lines are in the same conduit, causing noise from the power lines (generally, display values will be unstable).
  Countermeasures
  Wire the lead wires and power lines in separate conduits, or wire them using a more direct path.



- Connection between the Temperature Controller and thermocouple is using copper wires.
  Countermeasures
  Connect the thermocouple's lead wires directly, or connect a compensating conductor that is suitable for the thermocouple.



- The measurement location of the temperature sensor is not suitable.



- The incorrect input shift value has been set.

Why does overshooting or undershooting occur?

The following are possible causes.
- Narrow proportional band or small P constant
- Short integral time or small I constant
- Long derivative time or large D constant
- ON/OFF control is enabled.
- Control period is long for a control system with a fast thermal response.
- Setting the overlap band in the heating and cooling control to a dead band by mistake.

Why are process values not being displayed correctly? And why is *S.Err* displayed?

The following are possible causes.
- The input type in the Initial Setting Level is set incorrectly.
- The temperature unit in the Initial Setting Level is set incorrectly.
- The input shift value in the Adjustment Level is set incorrectly.
- The data setting unit is incorrect.
- The temperature sensor polarity or connected terminals are incorrect.
- A temperature sensor has been connected that cannot be used with the installed Temperature Controller.
- The temperature sensor has burnt out, short-circuited, or deteriorated.
- The temperature sensor has not been connected.
- The thermocouple and compensating conductor types are incorrect.
- A device using metal other than a thermocouple or compensating conductor has been connected between the thermocouple and Temperature Controller.
- The connection terminal screws are loose and a contact failure occurs.
- The thermocouple lead wires or compensating conductors are too long and the conductor resistance is affecting the Temperature Controller.
- The resistance of the three conductors connected between the platinum resistance thermometer and the Temperature Controller terminals is different.
- Noise emitted by devices around the Temperature Controller is affecting the Temperature Controller.
- The temperature sensor lead wires and power lines are close, causing inductive noise from the power lines.
- The thermal response is slow because the installation location of the temperature sensor is far from the control point.
- The ambient operating temperature of the Temperature Controller exceeds the rating.
- A wireless device is used around the Temperature Controller.
- The temperature of the thermocouple-input-type terminal block varies due to heat radiated from peripheral devices.
- Wind is blowing on the thermocouple-input-type terminal block.

Why does the process value exceeds the set point?

The following are possible causes.

- The contacts for the relay driven by control outputs are welded.
- The SSR has a short-circuit fault.
- The PID constants are not suitable.
- Restricted MV limit values are set.
- The controlled object is heating by itself.

Why does the process value oscillate around the set point and not stabilize at the set point?

The following are possible causes.

- Narrow proportional band or small P constant
- Short integral time or small I constant
- Long derivative time or large D constant
- ON/OFF control is enabled.
- Control period is long for a control system with a fast thermal response.
- Setting the overlap band in the heating and cooling control to a dead band by mistake.
- The heating capacity of the heater is too large for the heating capacity of the controlled object.
- There is periodic external disturbance, which changes the heating capacity of the controlled object.
- AT execution is in progress.

Why are communications not possible or why are there communications errors?

The following are possible causes.

- The communications wiring is not correct.
- The communications line has become disconnected.
- The communications cable is broken.
- The communications cable is too long.
- The wrong communications cable has been used.
- More than the specified number of communications devices are connected to the same communications path. (RS-422/RS-485 only)
- Terminating resistance has not been connected at each end of the communications line. (RS-422/RS-485 only)
- The specified power supply voltage is not being supplied to the Temperature Controller.
- The specified power supply voltage is not being supplied to an Interface Converter.
- The same baud rate and communications method are not being used by all of the Temperature Controllers, host devices, and other devices on the same communications line.
- The unit number specified in the command frame is different from the unit number set by the Temperature Controller.
- The same unit number as the Temperature Controller is being used for another node on the same communications line. (RS-422/RS-485 only)
- There is a mistake in programming the host device.
- The host device detects an error before it receives a response from the Temperature Controller.
- The host device detects the absence of a response as an error after a broadcast command or a software reset command (except for SYSWAY).
- The host device sent another command before receiving a response from the Temperature Controller.
- The host device sent the next command too soon after receiving a response from the Temperature Controller.
- The communications line became unstable when the Temperature Controller power was turned ON or interrupted, and the host device read the unstable status as data.
- The communications data was corrupted by noise from the environment.