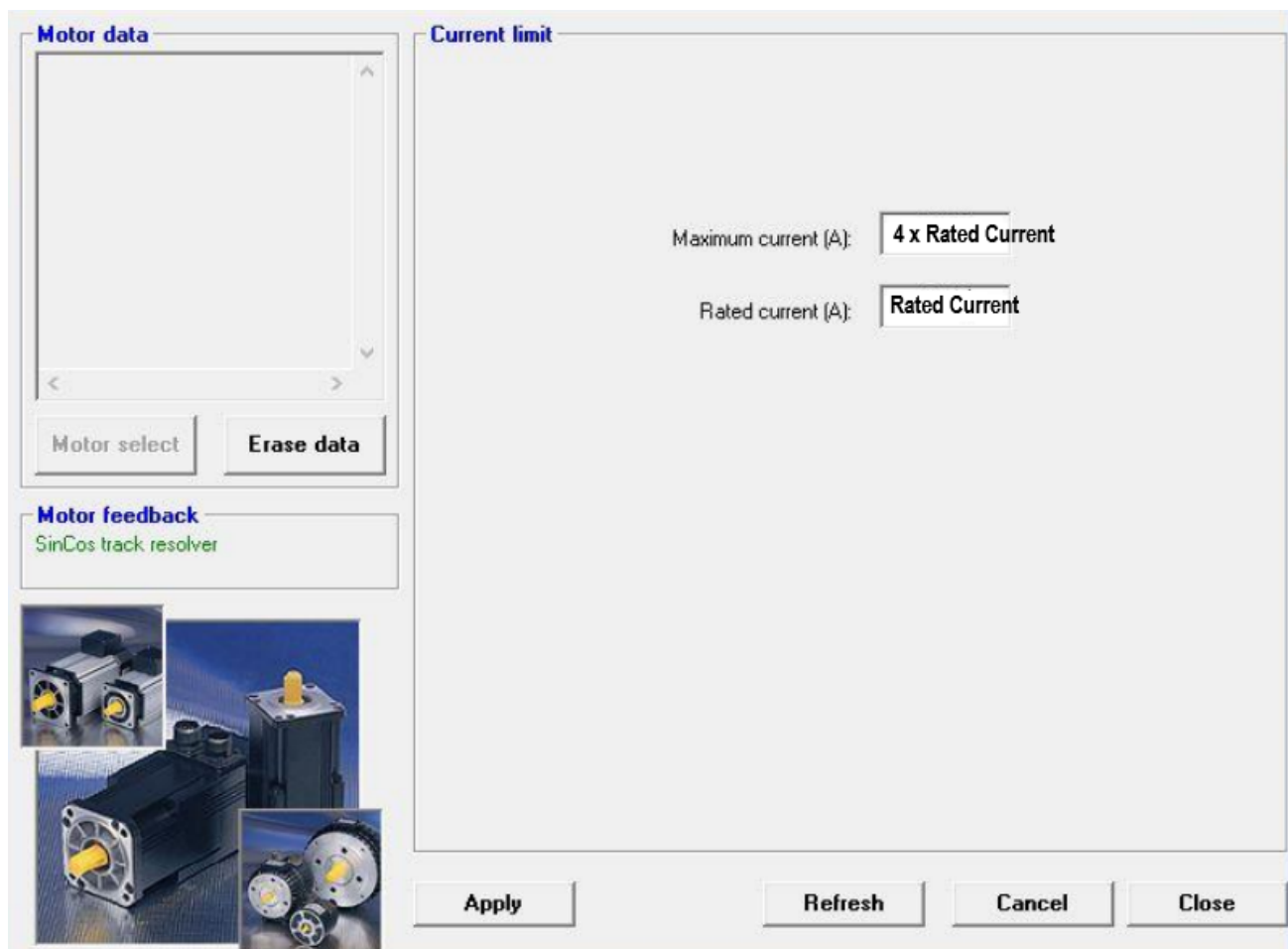


Xtrapulspack Servo drive TTL Incremental Encoder

for the configuration of the Xtrapulspack Gem Drive Studio software is used.

Please use our [Datasheet engine](#) to see the motor parameters.

Step 1) ⇒ Motor config ⇒ Current limit



The screenshot displays the 'Current limit' configuration window in the Gem Drive Studio software. The window is divided into two main sections: 'Motor data' and 'Current limit'.

Motor data: This section contains a large empty text area for motor information. Below it are two buttons: 'Motor select' and 'Erase data'.

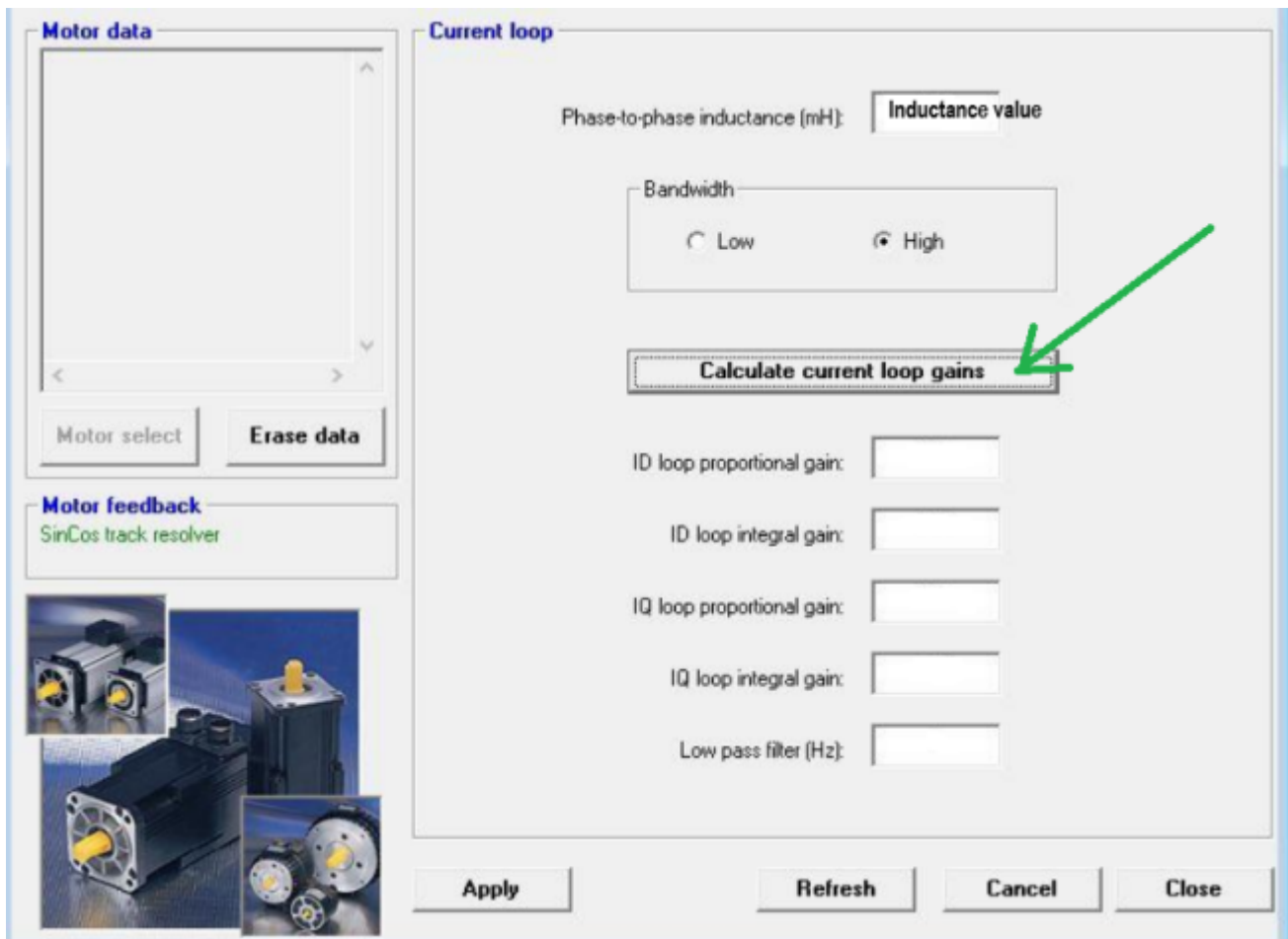
Motor feedback: This section shows 'SinCos track resolver' as the selected feedback type.

Current limit: This section contains two input fields for current values:

- Maximum current (A):
- Rated current (A):

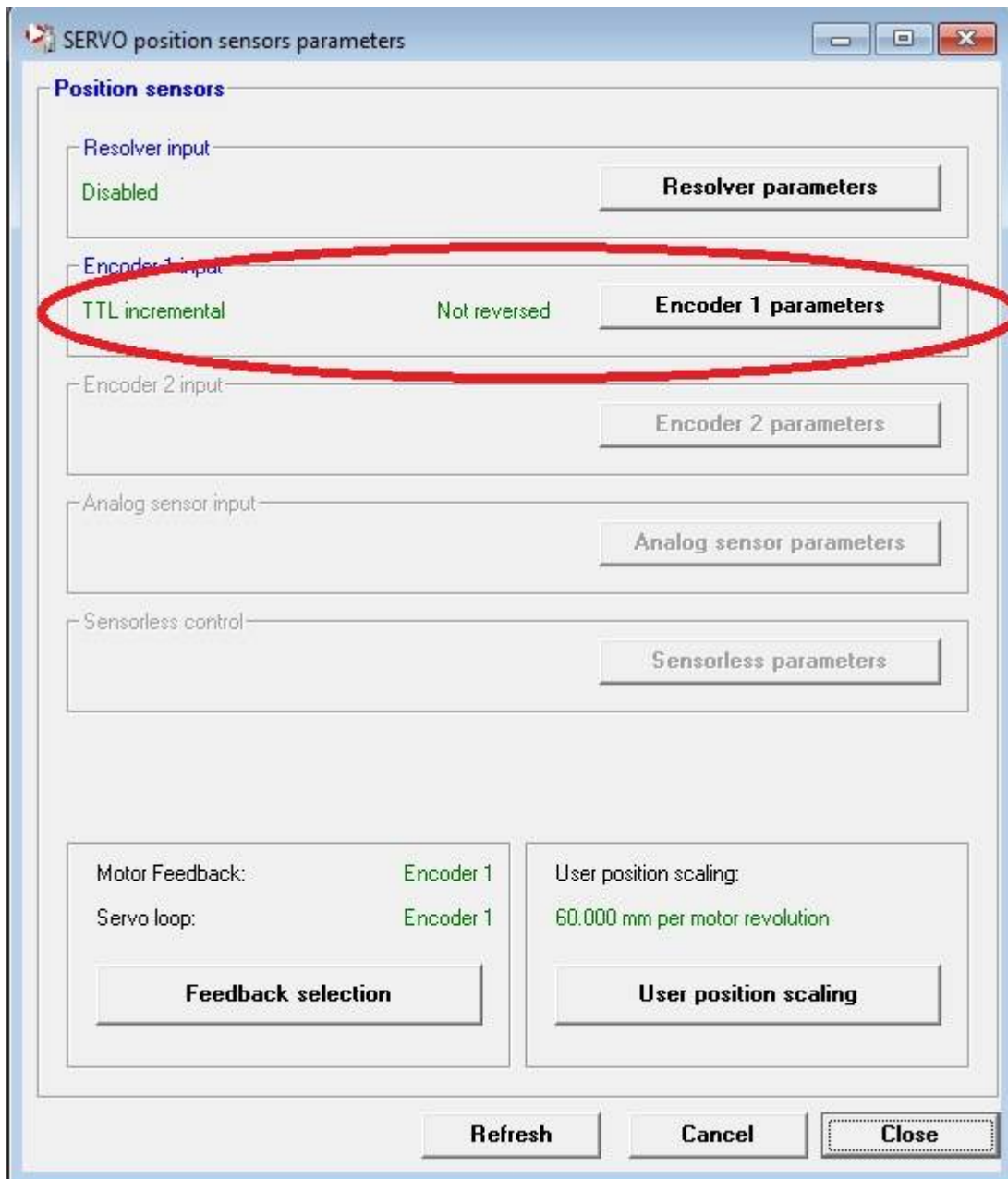
At the bottom of the window, there are four buttons: 'Apply', 'Refresh', 'Cancel', and 'Close'.

Step 2) => Motor config => Current Loop

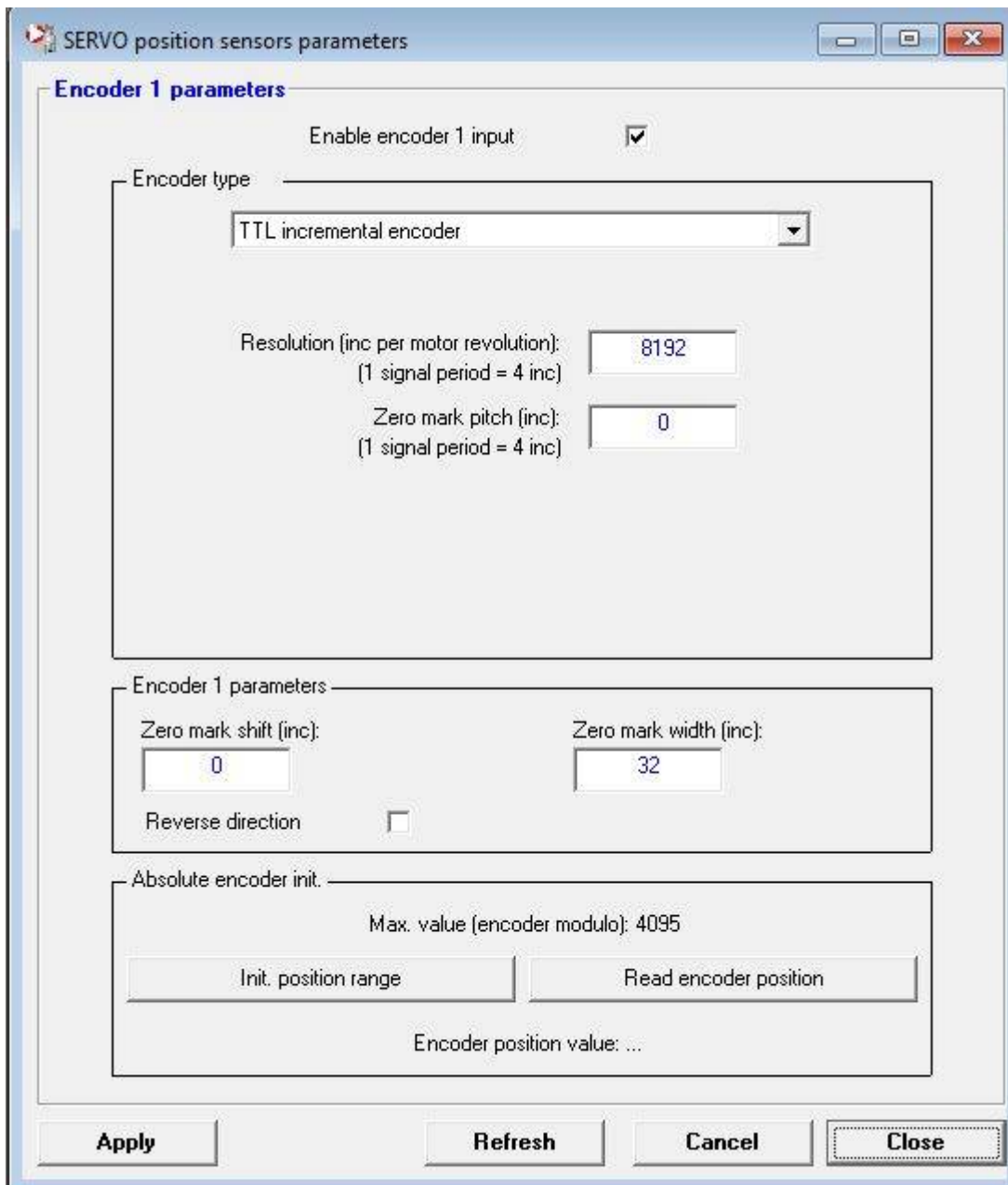


Step 3) Position sensors

In order to use the digital output incremental encoder as motor feedback please disable Resolver input and select TTL incremental.



As a default use the resolution of 8192 pulses/cycle. If the motor as different resolution please use the right one here.



Step 4) Position sensors ⇒ User position scaling

User position scaling

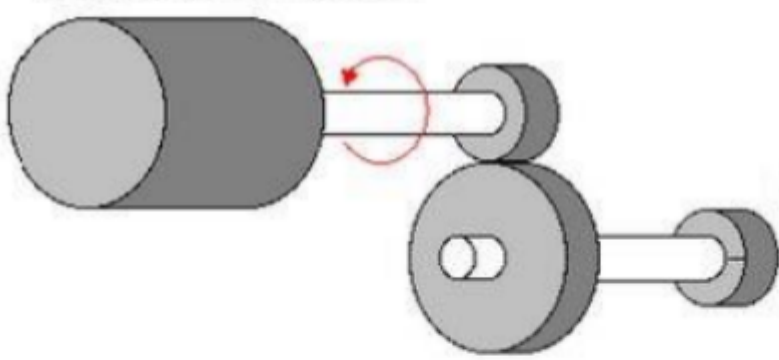
Position unit

- Revolution
- Increment
- Millimeter
- Meter
- Degree
- Other unit:

Display factor

- 1
- 0.1
- 0.01
- 0.001

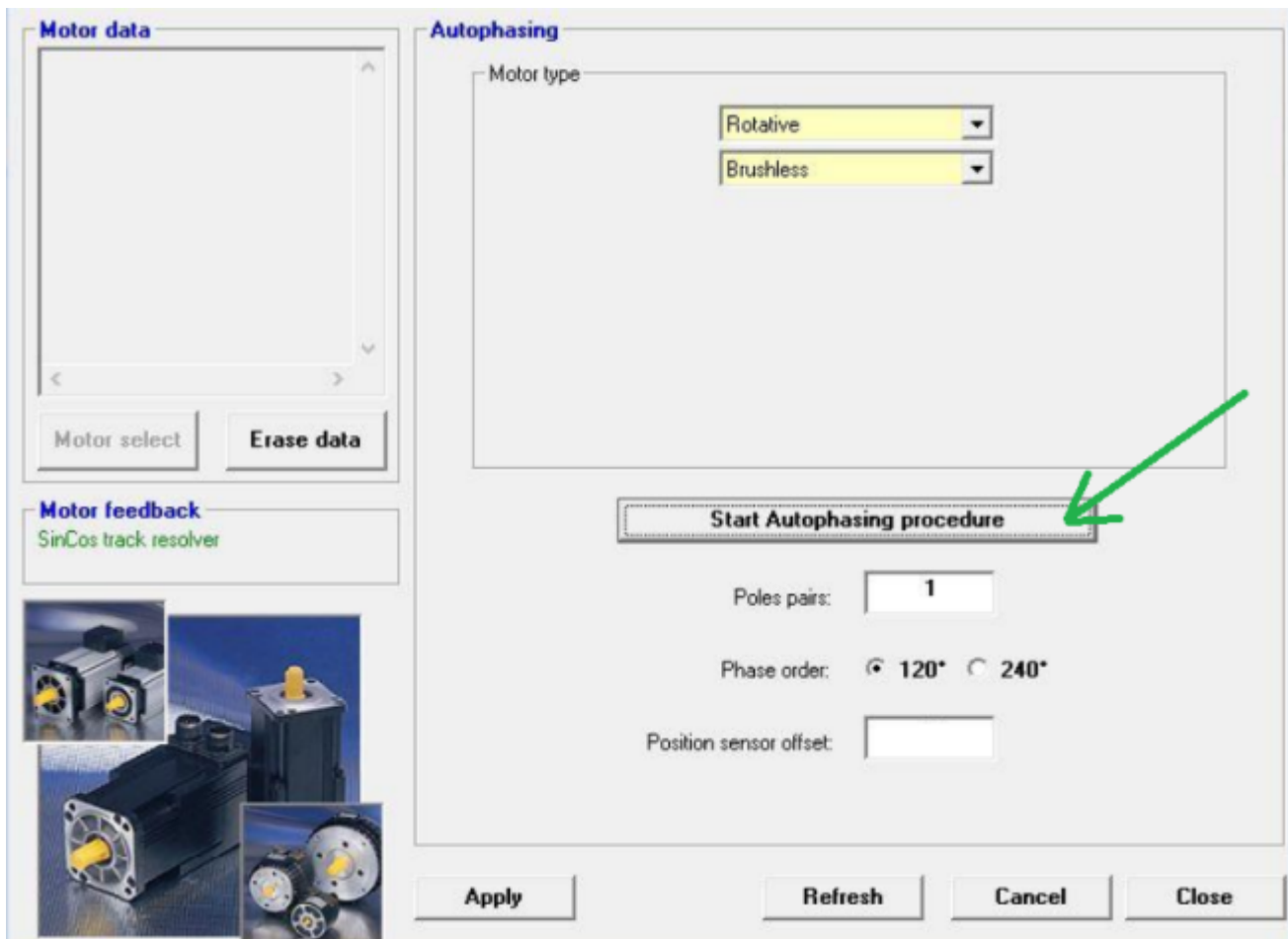
Motor displacement: 1 revolution



Load displacement in mm:

Apply Refresh Cancel Close

Step 5) Motor config ⇒ Autophasing



Step 6) Specify the motion profile requirements

Use Profile modes to specified using **Position profile mode** the speed and acceleration requirements for your application.

Step 7) Perform an Autotune

Use Controller ⇒ Autotuning to tune the motor following the position profile mode specifications.

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