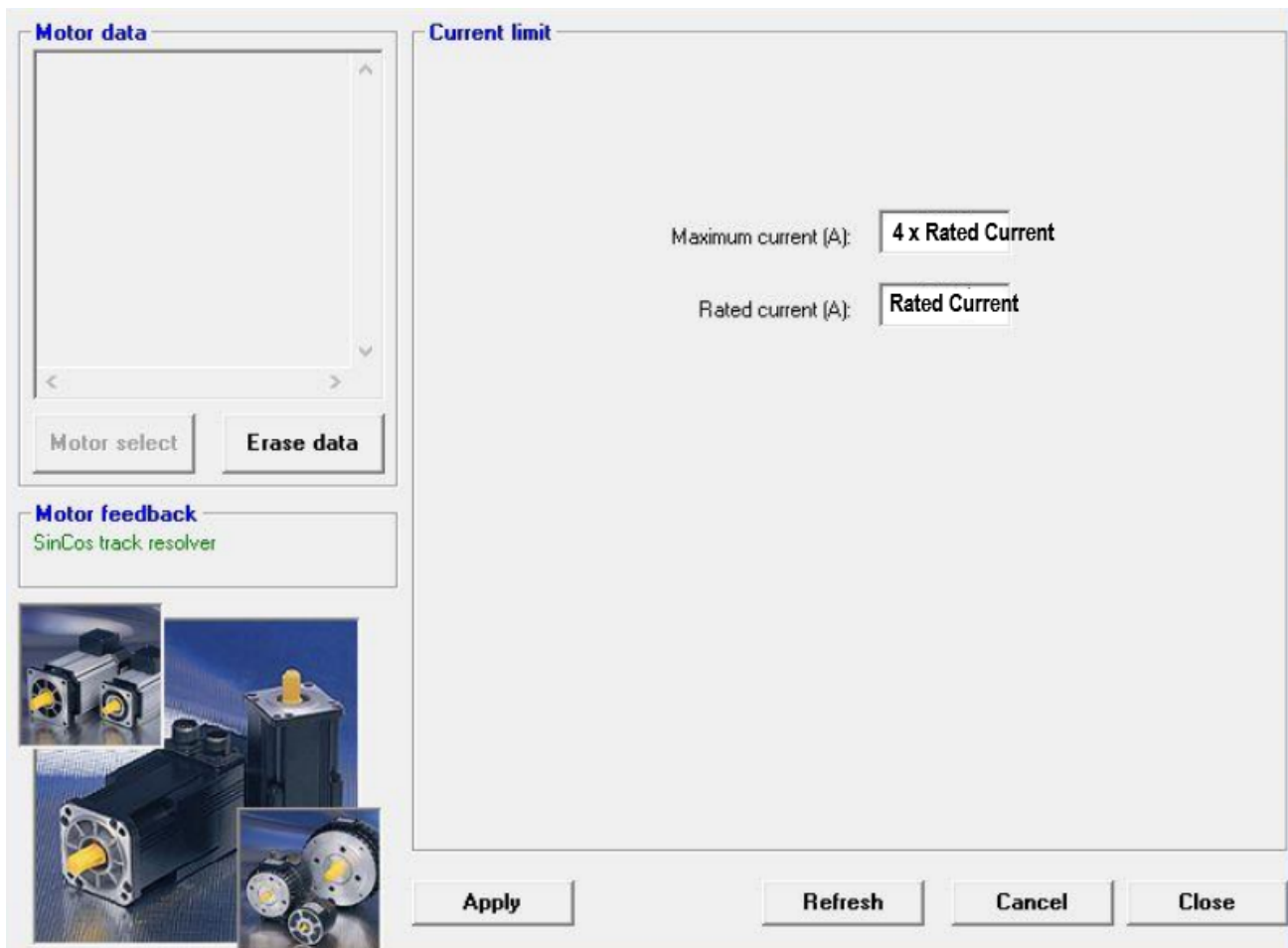


# Xtrapulspack Servo drive TTL Incremental Encoder

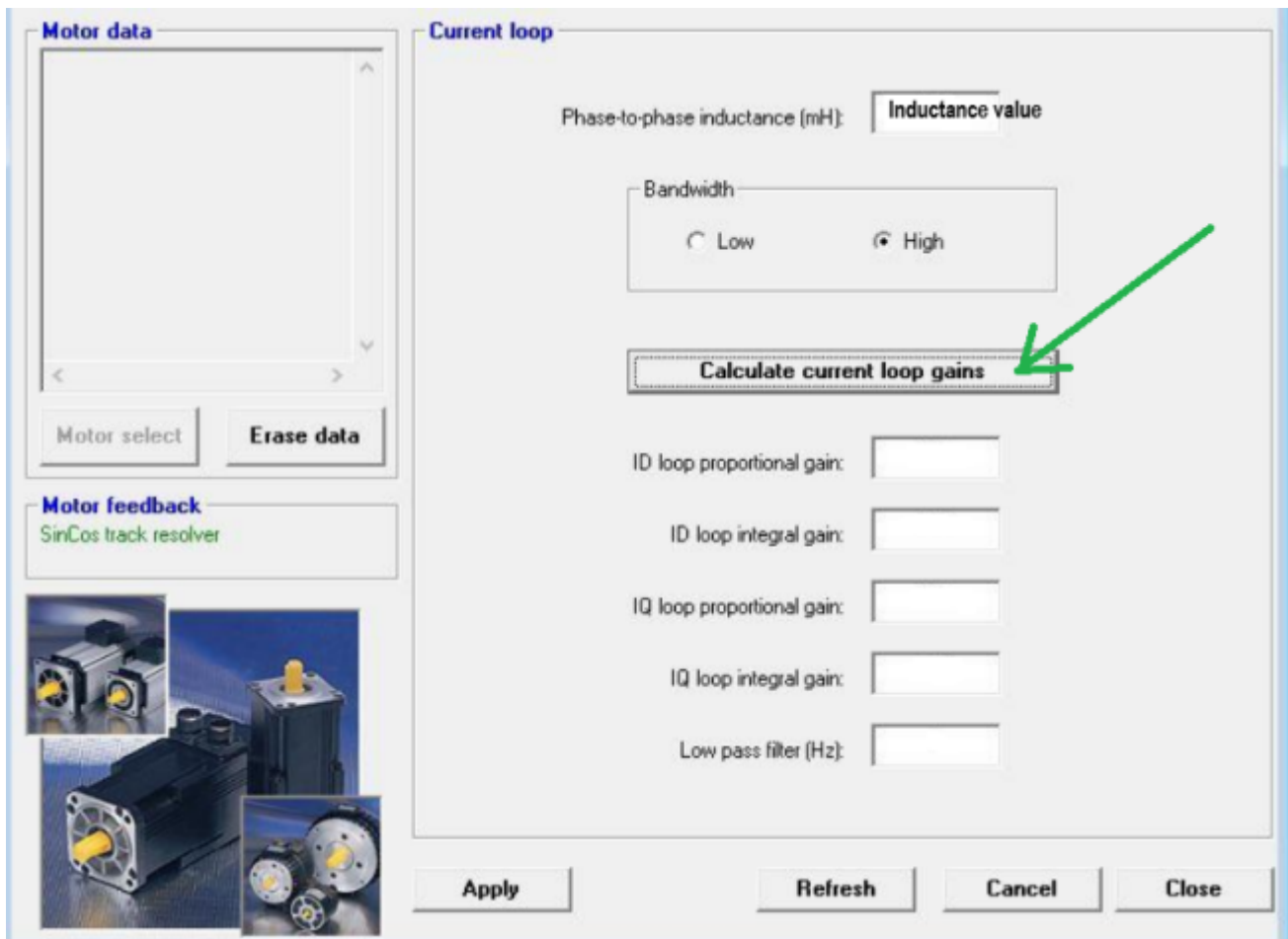
for the configuration of the Xtrapulspack Gem Drive Studio software is used.

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

## Step 1) ⇒ Motor config ⇒ Current limit

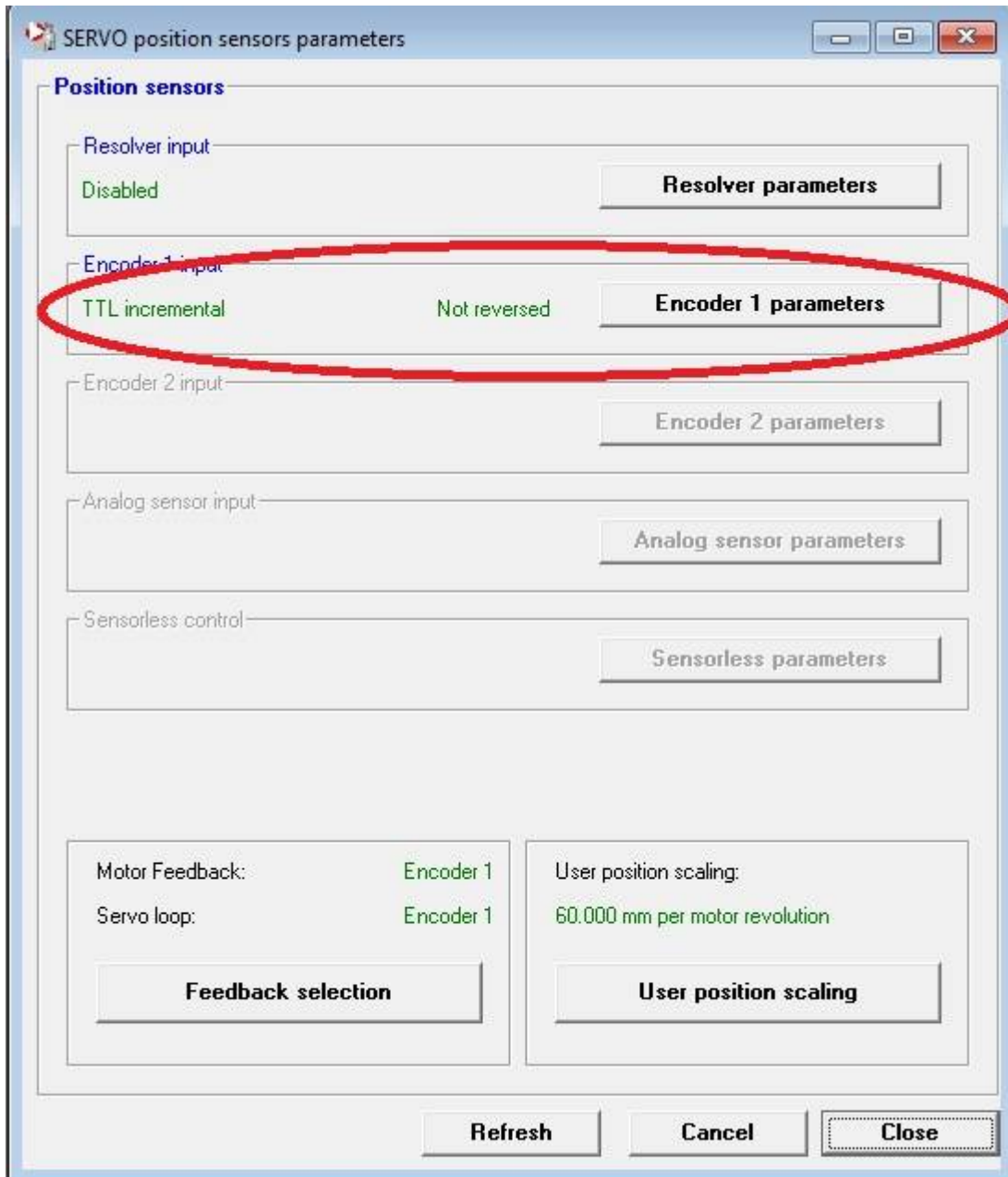


## Step 2) => Motor config => Current Loop

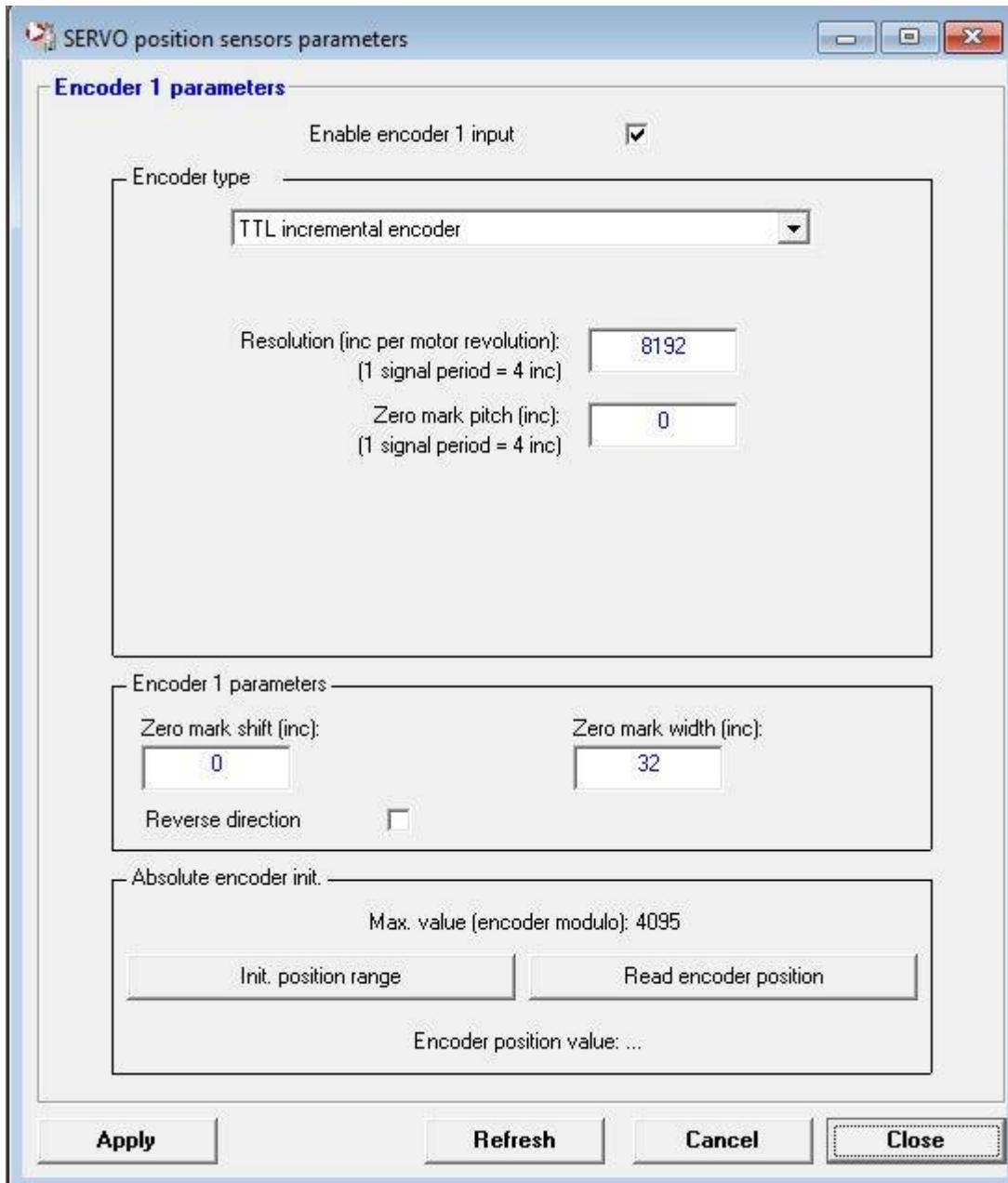


### Step 3) Position sensors

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**

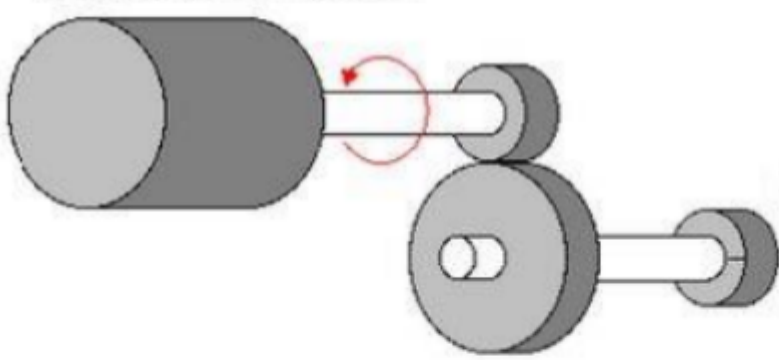
Position unit

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

Display factor

- 1
- 0.1
- 0.01
- 0.001

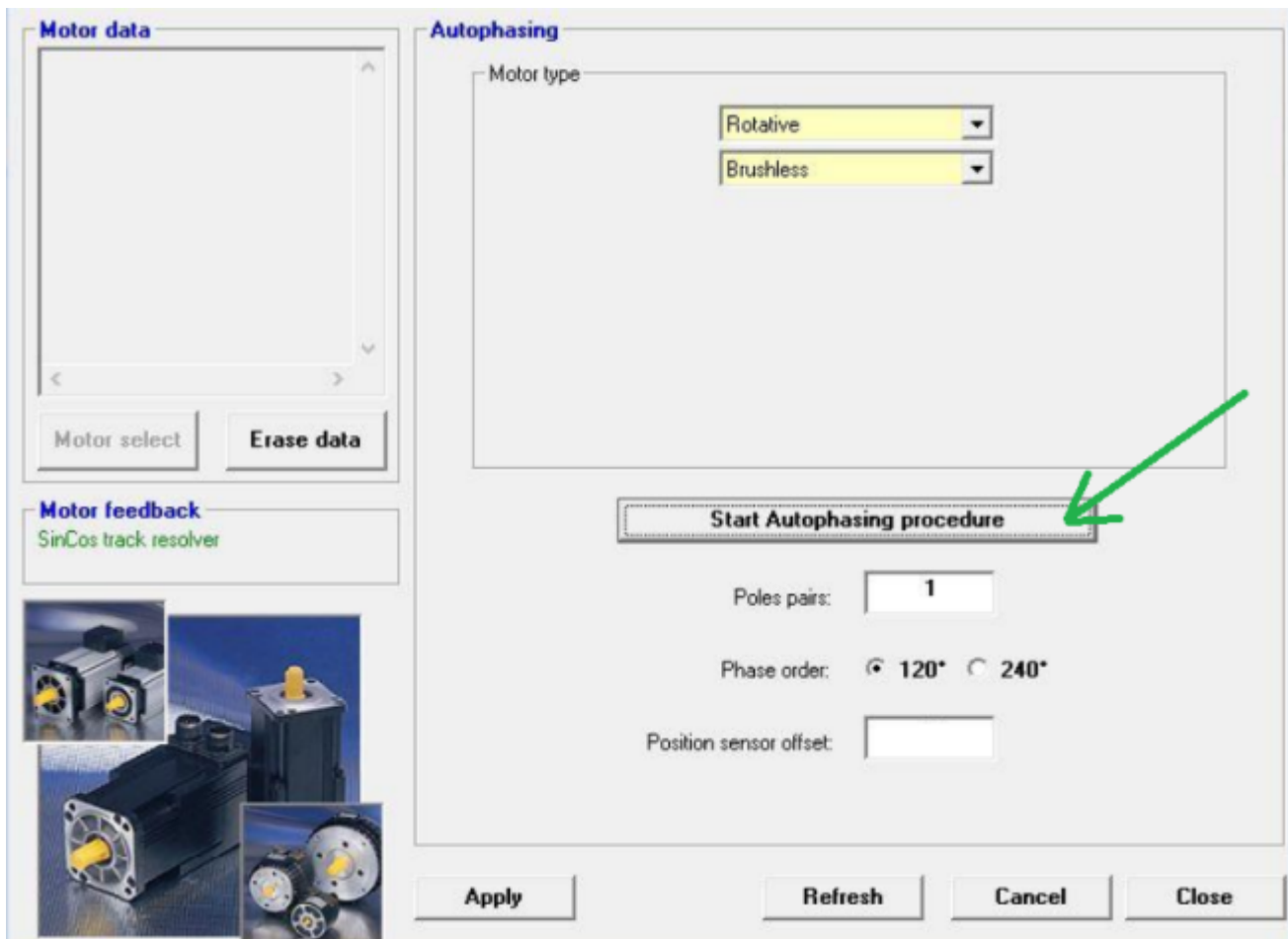
Motor displacement: 1 revolution



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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