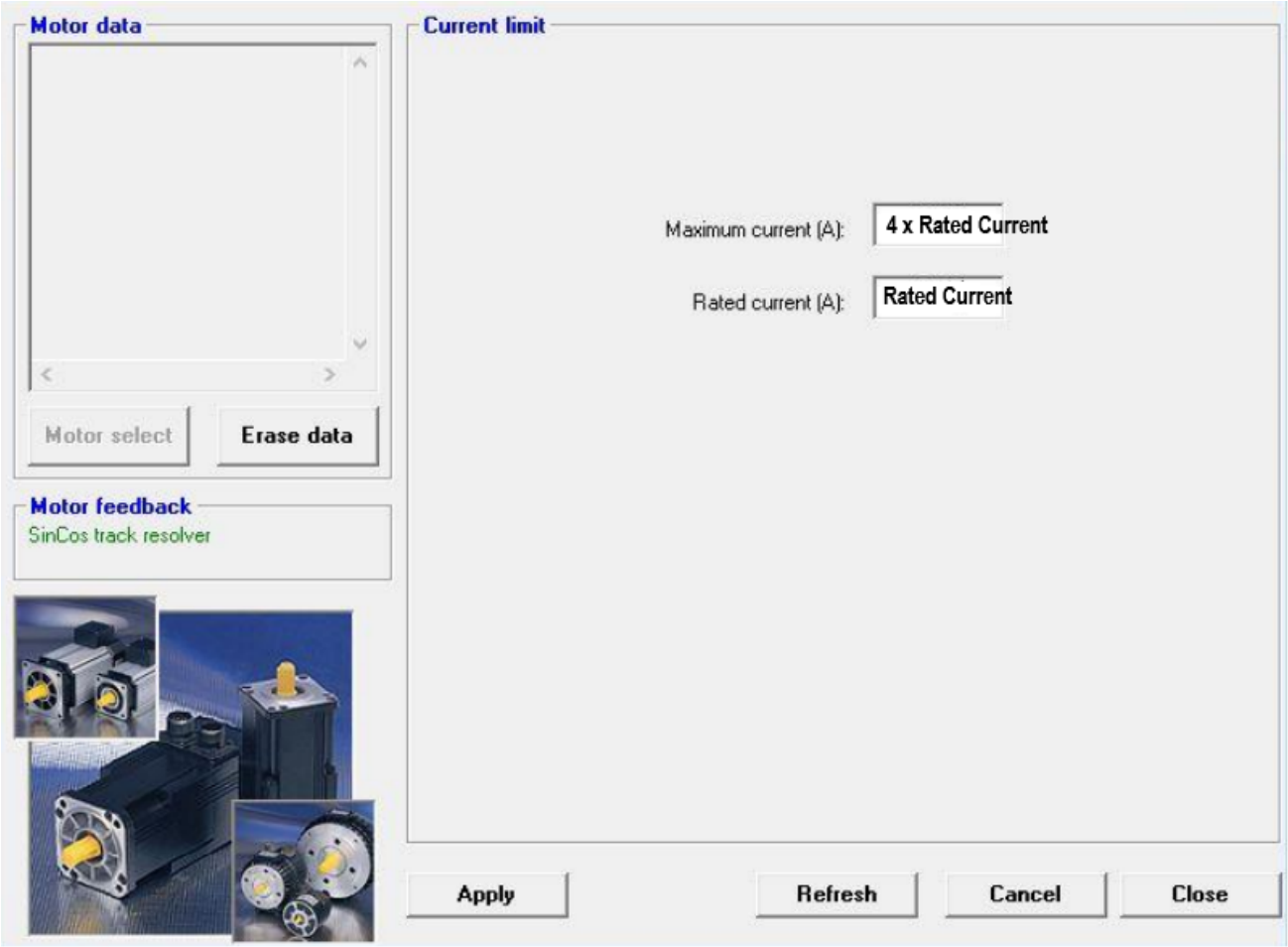
Xtrapulspack Servo drive TTL Incremental Encoder

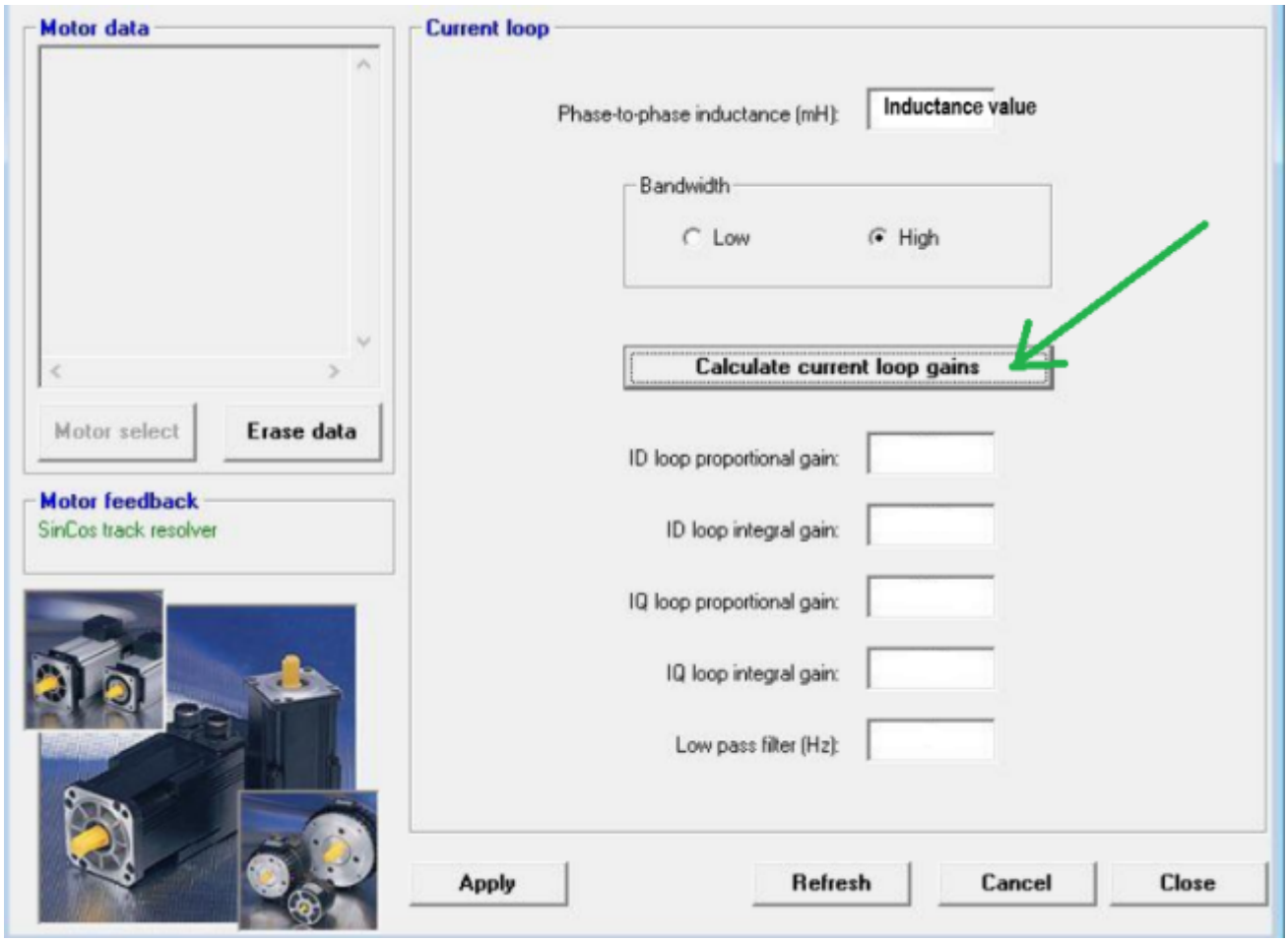
for the configuration of the Xtrapulspack Gem Drive Studio software is used.

Please use our Datasheet engine to see the motor parameters.

Step 1) ⇒ Motor config ⇒ Current limit

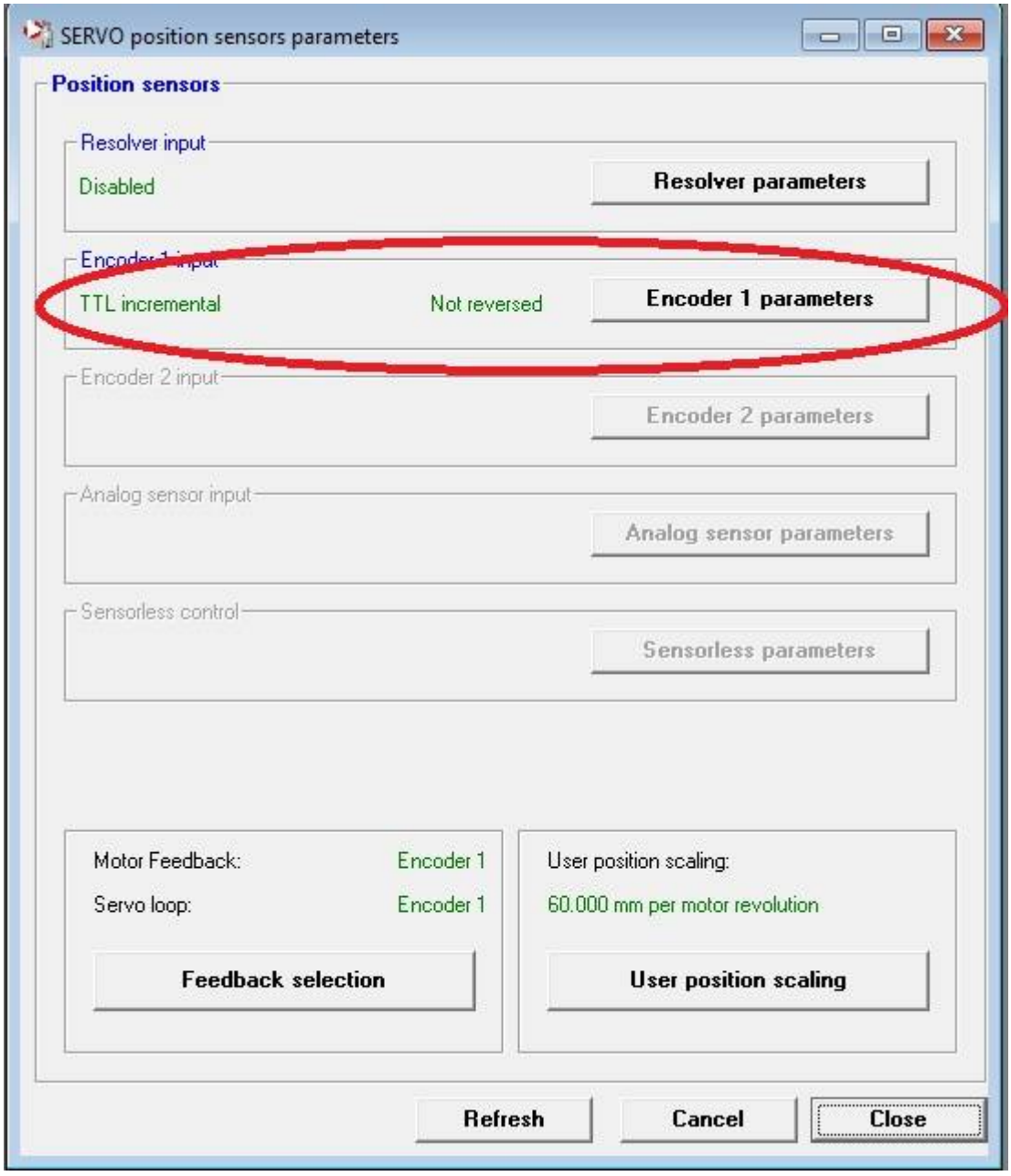


Step 2) => Motor config => Current Loop

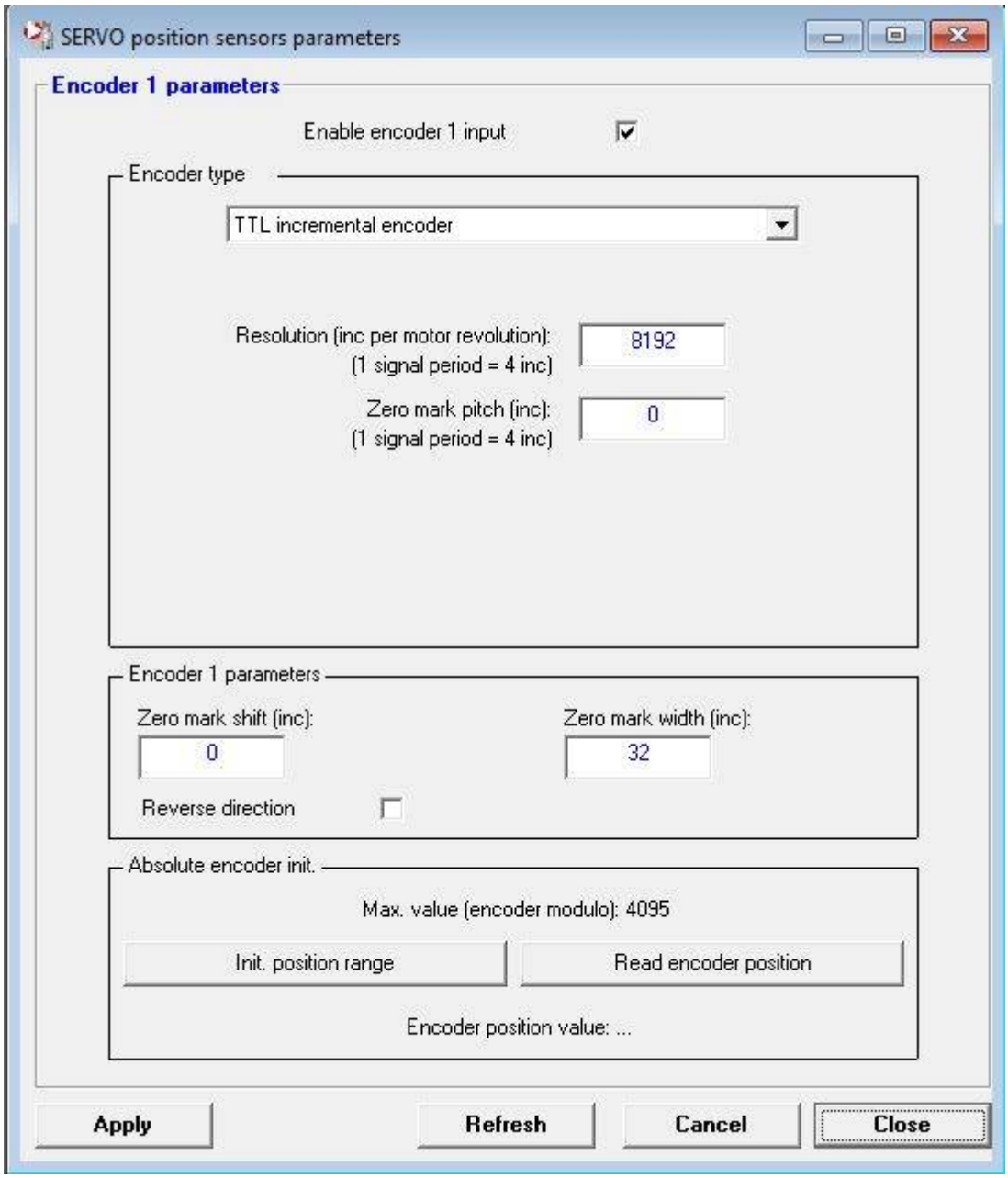


Step 3) Position sensors

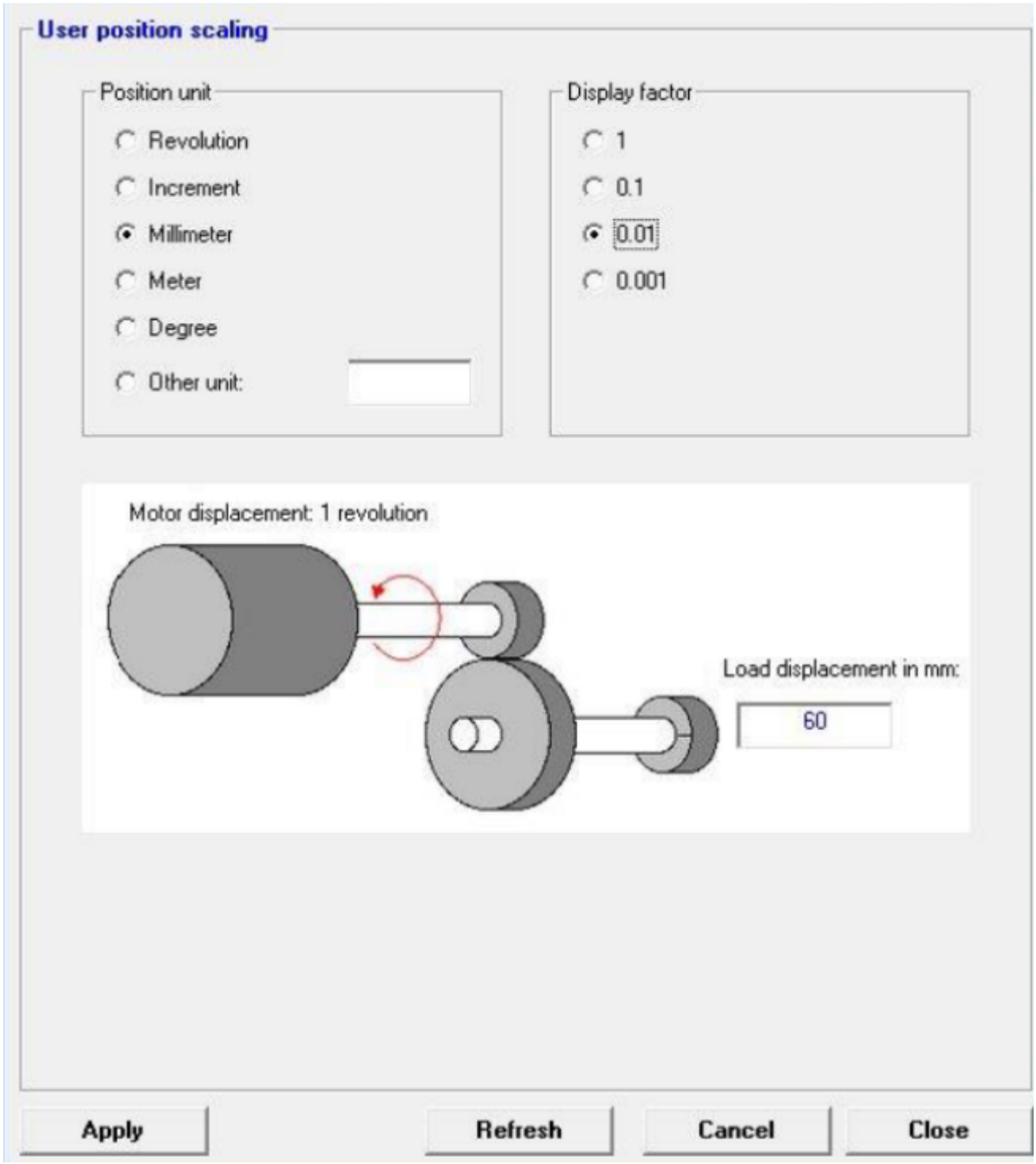
In order to use the digital output incremental encoder as motor feedback please disable Resolver input and select TTL incremental.



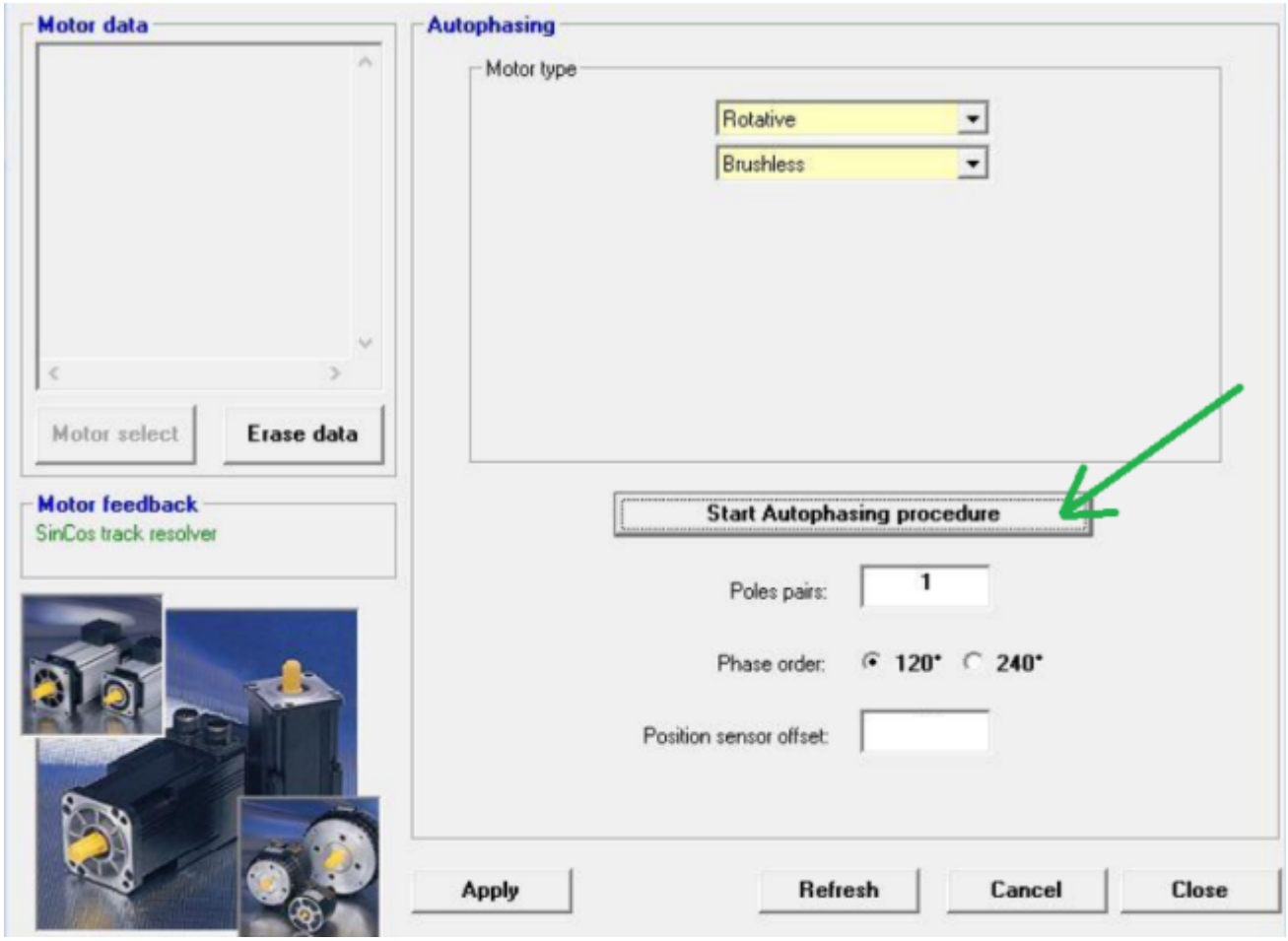
As a default use the resolution of 8192 pulses/cycle. If the motor as different resolution please use the right one here.



Step 4) Position sensors ⇒ User position scaling



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.