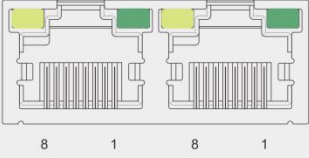


Step 1: Definition of debugging cable and network port

RJ45 wiring definition



Double RS-485 interface

No.	Definition	Color	No.	Definition	Color
1	RS485-A	Orange white	5	—	Blue white
2	RS485-B	Orange	6	—	Green
3	GND	Green white	7	—	Brown white
4	—	Blue	8	—	Brown

Please prepare the USB to 485 debugging cable by yourself and install the driver

Network cable pin 1 connects to adapter pin 1, network cable pin 2 connects to adapter pin 2,

GND may not be connected.

Step 2: Set the slave address of the driver and baud rate. (The baud rate can be set according to the driver panel)



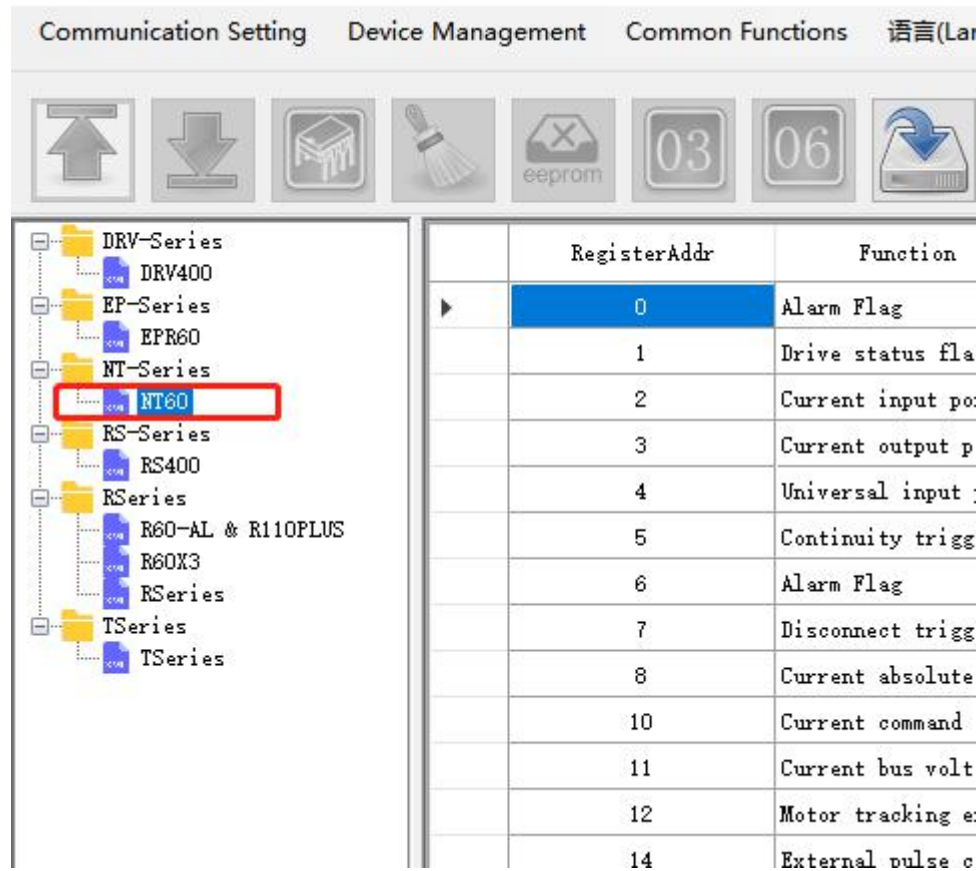
Eg: Slave 1, 115200 baud rate

SW1=OFF、SW2=ON、SW3=ON、SW4=ON、SW5=ON、SW6=OFF、SW7=OFF

SW8 is the effective terminal resistance, which can be ignored

The dialing code needs to be powered off and restarted to take effect

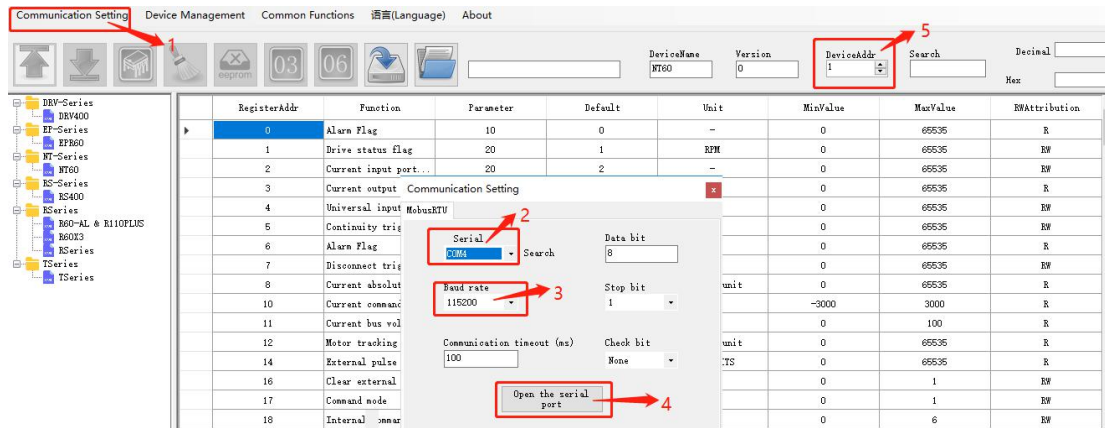
Step 3: select the corresponding driver model on the debugging software



The screenshot shows a software interface with a menu bar at the top containing "Communication Setting", "Device Management", "Common Functions", and "语言(La)". Below the menu bar is a toolbar with icons for navigation and device management, including an "EEPROM" icon. The main area is divided into two panes. The left pane shows a tree view of driver models, with "NT60" selected and highlighted by a red rectangle. The right pane displays a table with two columns: "RegisterAddr" and "Function".

RegisterAddr	Function
0	Alarm Flag
1	Drive status fla
2	Current input po:
3	Current output p
4	Universal input :
5	Continuity trigg
6	Alarm Flag
7	Disconnect trigg
8	Current absolute
10	Current command
11	Current bus volt
12	Motor tracking e
14	External pulse c

Step 4: Connection to the debugging software



Port settings can be viewed in the computer's device manager



Step 6: Motion test

Communication Setting Device Management **Common Functions** 语言(Language) About

MotionTest

Pulse command source: 0-Internal pulse gen
 Motor type: 0-2 phase
 Internal pulse application mode: 3-IO control: forward

Motor operation mode: 0-Open loop
 Running direction: 0-Normal
 Operation mode: 0-Incremental

Acc: 200
 Deceleration (r/s²): 200
 Speed: 600
 Position: 2000
 Fixed length forward
 Fixed length inversion

JOG acceleration: 100
 JOG deceleration: 100
 JOG speed: 429
 Emergency stop decel: 500
 Continuous forward
 Continuous reverse

IO input and output | General parameters | Servo mode setting | Current loop parameters | Homing mode setting

Frequent on Frequent off

Input	Function	Polarity	Output	Function	Polarity
IN1: 0-Pulse input	<input checked="" type="checkbox"/>		OUT1: 1-Error alarm	<input checked="" type="checkbox"/>	
IN2: 1-Direction input	<input checked="" type="checkbox"/>		OUT2: 4-Speed reached	<input checked="" type="checkbox"/>	
IN3: 7-Jog forward / stop	<input type="checkbox"/>		OUT3: 2-Brake output	<input checked="" type="checkbox"/>	
IN4: 8-Jog reverse / di	<input checked="" type="checkbox"/>		OUT4: 3-Positioning is c	<input checked="" type="checkbox"/>	
IN5: 12-Start to homing	<input checked="" type="checkbox"/>		OUT5: 0-Normal output	<input type="checkbox"/>	
IN6: 11-Homing signal i	<input checked="" type="checkbox"/>		OUT6: 0-Normal output	<input type="checkbox"/>	

Clean

```

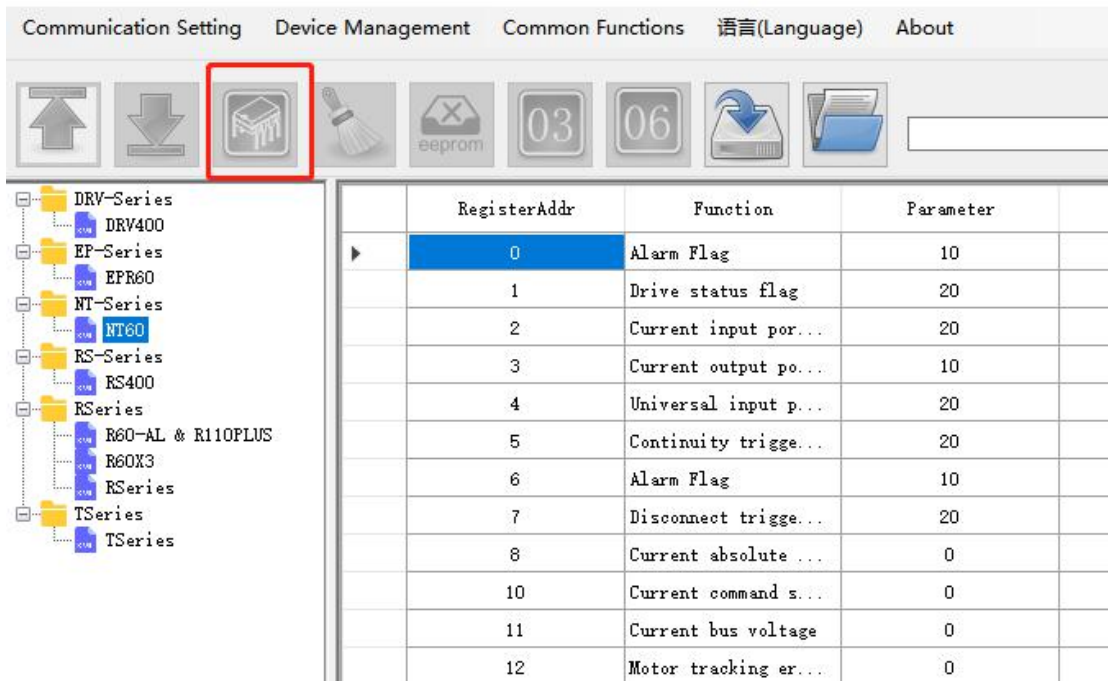
(2020/9/5 11:19:09739)Rs:01 03 00 84
(2020/9/5 11:19:09864)Rs:01 03 03 00
00 00 00 00 00 00 00 00 00 00 00 00
00 00 00 00 00 00 00 00 00 00 00 00
(2020/9/5 11:19:09877)Rs:01 03 00 08
(2020/9/5 11:19:105)Rs:01 03 05 00 04
00 84 00 84 00 84 00 84 00 84 00 84
  
```

Step 7: Save parameters

Please keep the motor inactive when saving the parameters

RUI TECH CONFIGURATOR 1.0.0.3

Communication Setting Device Management Common Functions 语言(Language) About



RegisterAddr	Function	Parameter
0	Alarm Flag	10
1	Drive status flag	20
2	Current input por...	20
3	Current output po...	10
4	Universal input p...	20
5	Continuity trigge...	20
6	Alarm Flag	10
7	Disconnect trigge...	20
8	Current absolute ...	0
10	Current command s...	0
11	Current bus voltage	0
12	Motor tracking er...	0