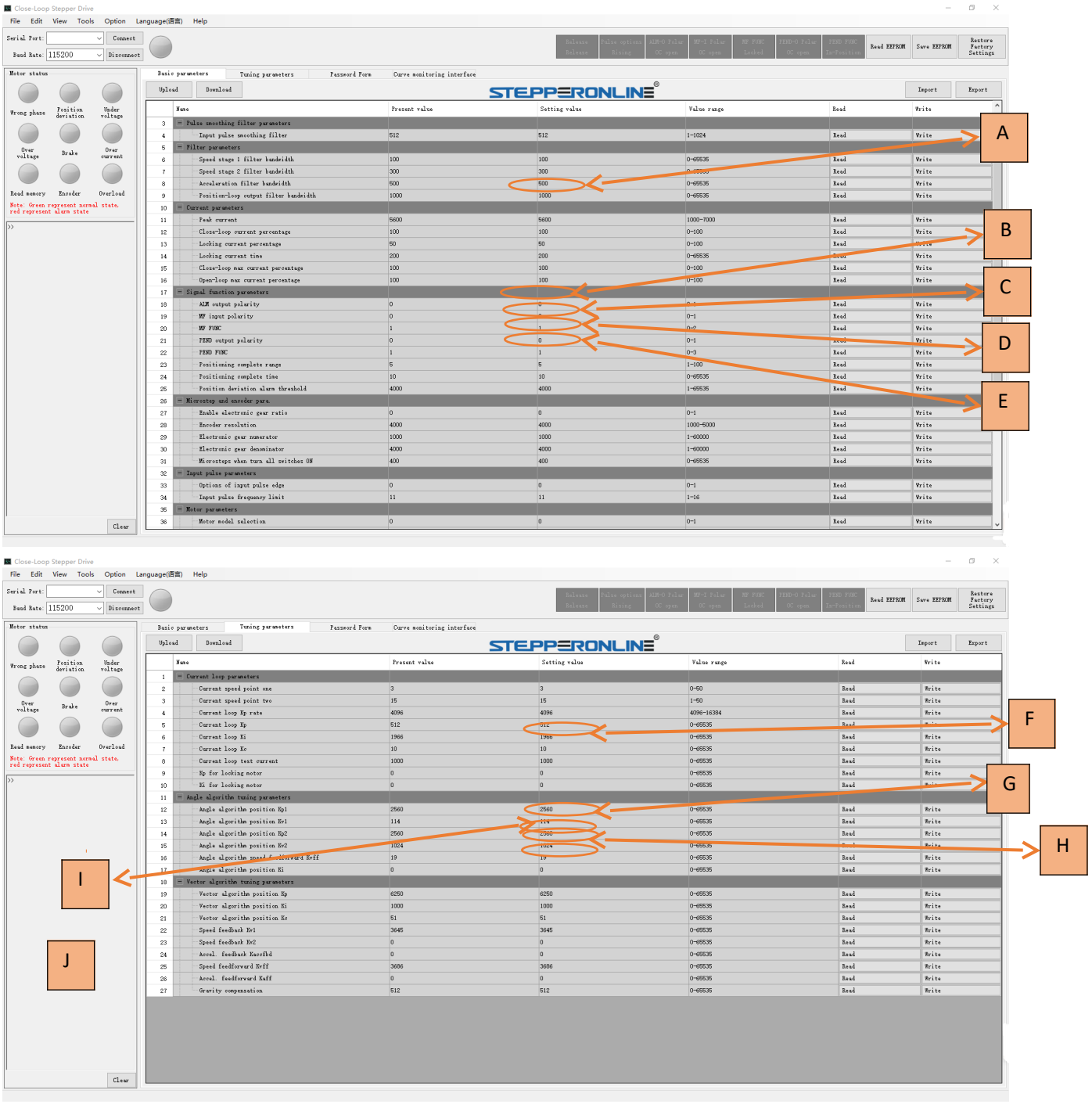

A Input pulse smoothing filter： Filter time= （x）*50us When the load is heavier and there are higher requirements for speed and acceleration, increase this value. Increasing the response of this parameter will reduce the response, but the load acceleration and deceleration will be longer. When you need to draw a circle, the number of X and Y axis should be the same.

B Peak current: Driver output maximum current

C Percentage of closed-loop base current: The base of the current loop proportional gain section adjustment

D Locking current percentage: The motor locks current when the motor is stopped, and the magnitude of this current is related to the output and heat of the

motor when the motor is locked.

E Locking current time： The motor enters the lock current time when it stops (ms)

F Current loop KP: The current loop proportional gain, when the load is heavier, and the speed requirement is high, increase by 100 each time on the original basis. When the load is lighter and the sound requirement is higher, the original basis is reduced by 100 each time.

G Position loop proportional gain KP1: Increasing this value can increase the rigidity. This parameter can be increased when the response and positioning are required to be faster.

Suggest 2560-5560 adjustment.

H Position loop proportional gain KP2： Increasing this value can increase the rigidity. This parameter can be increased when the response and positioning are required to be faster.

It is recommended to adjust 2560-5560. (Note: G and H need to be debugged together, the parameters can be the same, or H can be 5% larger than G)

I Speed loop proportional gain KV1 : Suggested range: 114-2000, I and J are recommended to be adjusted at the same time. Increasing this value can increase the rigidity, increasing by 100 each time.

JSpeed loop proportional gain KV2: Suggested range: 1024-8000, I and J are recommended to be adjusted at the same time. Increasing this value can increase the rigidity, increasing by 500 each time.