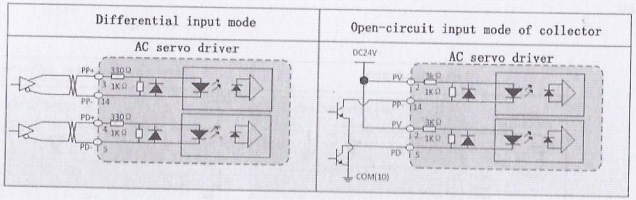
3. Position pulse instruction interface

There are two ways to drive differential drive and one end drive. Differential drive connection is recommended. Twisted pair should be used for wiring.

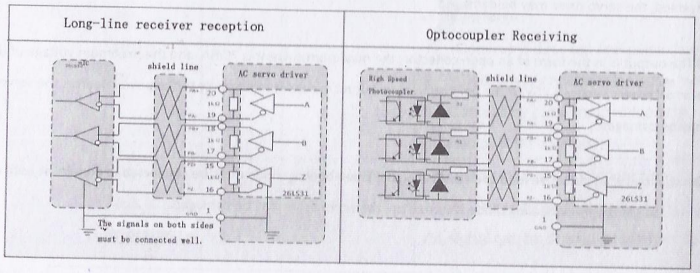


● In the differential input mode, the proposed use of AM26LS31 similar line driving chip; in order to make the pulse data transmission have very good anti-interference ability, recommend the use of differential drive mode; the maximum input pulse frequency 550kHz (kpps).

● Under the open collector input mode, the maximum input pulse frequency is 200kHz (kpps).

4. Encoder signal differential drive output

After the encoder signal is divided into frequency, it is output to the upper controller through line driver (26LS31).

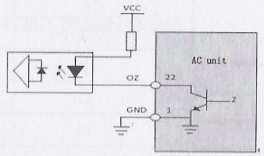


● When the long line receiver is received, the driver encoder signal (GND) must be connected to the upper controller signal.

● When the optocoupler is received, the upper controller uses a high-speed optocoupler (for example, 6N137), and the current limiting resistor R1 has a value of about 220.

5. Encoder ABZ signal open collector output

The servo drives the ABZ signal of the encoder in an open collector mode. Since the Z pulse width is narrow, the upper computer should be received by high-speed optocoupler.



● VCC maximum voltage 30V, output current maximum 50mA.

● Only the advanced servo unit supports the open collector output function of the A and B signals.