

Closed-Loop Stepper Driver HBS57



Changzhou ACT Motor Co., Ltd

HBS	Hybrid Step Servo Motor Driver	
	HBS57	
	MicroSteps Setting:200~51200	DC : 24~60V

Products Image



Overview

- Without losing step, High accuracy in positioning.
- Accelerate and decelerate control inside. Great improvement in smoothness of starting or stopping the motor.
- Small vibration, Smooth and reliable moving at low speed.
- The optocoupler isolates the differential signal input.
- Over current, over voltage and over position error protection.
- The impulse response frequency can reach up to 200KHz.
- Subdivision Settings (within 200~ 51200).

Features

Input voltage	24~60VDC
Output current	4.5A
Pulse frequency	0~200KHz
MicroSteps	16 MicroSteps
Signal current	7~20mA
Using environment	0 ~ 70 °C, avoid dust and corrosive gas
Storage environment	-20~+80°C , avoid direct sunlight
Heavy volume	280g (Does not contain the packaging)

Generally speaking, the power supply voltage is a little higher, and the motor's high-speed performance will be relatively low when the power supply voltage is good. It is suggested that the normal operating speed range is 36V above power supply for high-speed operation.

Encoder signal

Symbol	Name	Wiring color
PB+	Encoder phase B +	Green
PB-	Encoder phase B -	Yellow
PA+	Encoder phase A +	Blue
PA-	Encoder phase A -	BLACK
+5V	Encoder power	Red (+5V)
GND	Encoder power ground	White (0V)

Motor and power

Symbol	Name	Remark
A+	Phase A+	Black
A-	Phase A-	Red
B+	Phase B+	Yellow
B-	Phase B-	Blue
+V	Input Power +	+24V~60V
GND	Input Power-	0V

Control Signal

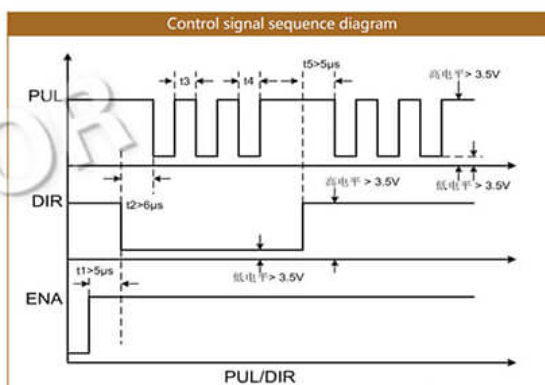
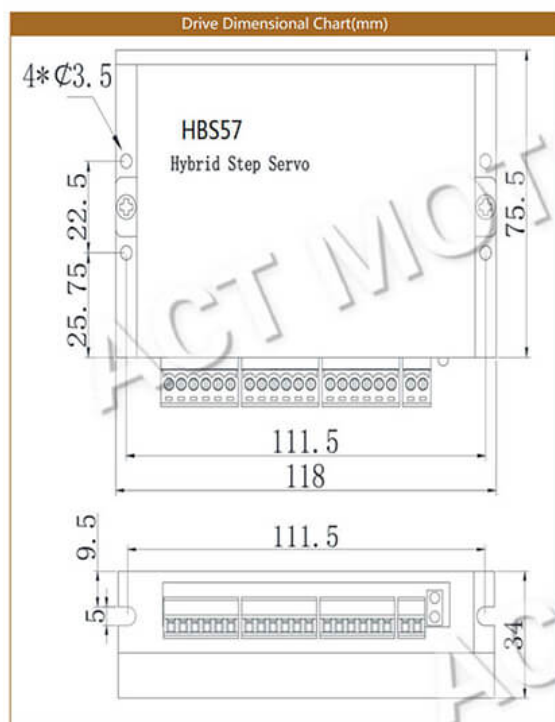
Symbol	Name	Remark
PUL+	Pulse signal +	/
PUL-	Pulse signal -	/
DIR+	Direction signal +	/
DIR-	Direction signal -	/
ENA+	Enable signal +	Only connected when used
ENA-	Enable signal -	Only connected when used

ALM Signal

Symbol	Name	Remark
ALM+	Positive alarm signal	Only connected when used
ALM-	Negative alarm signal	Only connected when used

Tel: 0519-81189628/81189728 Fax: 0519-81189528 Address: No. 1 Zhengda Road, Jingkai District, Changzhou City, Jiangsu Province Post Code: 213025
Web: <http://www.act-motor.com>

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Remark :

- ENA must be ahead of DIR by at least 5 μ s. Usually, ENA+ and ENA- are NC (not connected);
- DIR must be ahead of PUL active edge by 6 μ s to ensure correct direction;
- Pulse width not less than 2.5 μ s;
- Low level width not less than 2.5 μ s.

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