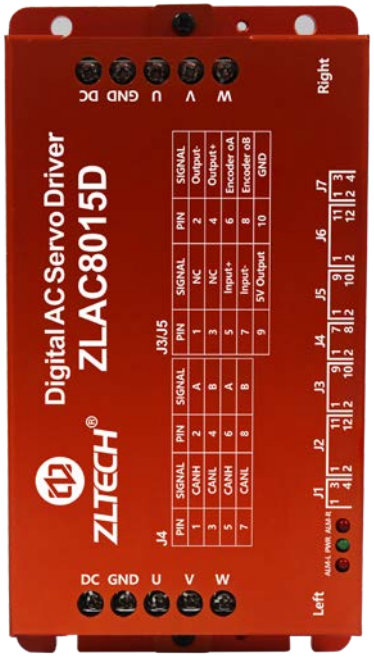
ZLAC8015D

Servo Driver Manual (Special for Hub Servo Motor)

【Please read the manual in detail before use, to avoid damage to the driver】



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RELEASE NOTES

Version	Update Time	Update Content	Updater
V1.0	2019-12-28	First Edition	LHY

PREFACE

Thanks for choosing ZLAC8015D, the servo driver for hub servo motor.

This manual describes the installation, debugging, maintenance, operation and other aspects of the servo driver ZLAC8015D. Please read this manual in detail before use, and be familiar with the safety precautions.

This manual may be revised timely when product is improved, specification and version are changed or for some other reasons, which will not be notified particularly.

Any questions when using our products, please read the relevant manual or call our technical service department, we will meet your requirements in the shortest possible time.

Marks and warning signal:

Danger: Indicates that this operation error may endanger personal safety!

Attention: Indicates that this operation error may result in equipment damage!

SAFETY PRECAUTIONS

Open Box and Check

Do not install integrated step-servo motor which is damaged or with missing parts.

Installation

Installed on a non-flammable metal frame, prevent the intrusion of dust, corrosive gases, conductive objects, liquids and flammable materials, and maintain good heat dissipation conditions.

During installation, be sure to tighten the mounting screws of the integrated step-servo motor. It should be protected from vibration and shock.

Wiring

Please perform the wiring work by professional electrical engineer;

Before wiring, please confirm that the input power is off. Wiring and inspection must be performed after the power is turned off and the integrated step-servo motor indicator is off to prevent electric shock;

When plugging and unplugging the integrated step-servo motor terminals, make sure that its indicator is off before proceeding;

Please set the emergent stop circuit outside the controller;

Please tighten the output terminal with a suitable torque.

Electrify

Please confirm whether the main circuit input power is consistent with the rated working voltage of the integrated step-servo motor;

Do not test the integrated step-servo motor for high voltage and insulation resistance at will;

Do not connect the electromagnetic contactor or electromagnetic switch to the output circuit.

Operation

Do not directly touch the output terminals after the integrated step-servo motor is powered on;

When the system is running, the integrated step-servo motor may

have a high temperature rise, do not touch it;

Please confirm the input and output signals to ensure safe operation;

The alarm can be reset only after the operation signal is cut off. Alarm resetting in the running signal state will cause the integrated step-servo motor to restart suddenly;

Do not change the parameter settings of the integrated step-servo motor at will. The parameter modification needs to be performed under standby condition.

Maintenance and Inspection

Do not touch the integrated step-servo motor terminals directly, and some have high voltage, very dangerous;

Before powering up, be sure to install the cover; when removing the cover, be sure to cut off the power supply first;

Before wiring, please confirm whether the input power is off;

After cutting off the main circuit input power and confirming the integrated step-servo motor indicator light has completely extinguished, it can be inspected and maintained;

Do the inspection and maintenance by professional electrical engineer;

Do not do wiring, disassembling or other operation on the terminals during power on.

There is an integrated circuit on the main control board of the servo driver. Please pay full attention when checking to avoid damage caused by static induction.

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1. PRODUCT INTRODUCTION

1.1. OUTLINE

ZLAC8015D is a high-performance digital servo driver for hub servo motor. It has a simple structure and high integration, and adds bus communication and single-axis controller function.

1.2. FEATURES

■ Adopt CAN bus communication, support CiA301 and CiA402 sub-protocol of CANopen protocol, could mount up to 127 devices. CAN bus communication baud rate range 25-1000kbps, default 500Kbps.

■ Adopt RS485 bus communication, support modbus-RTU protocol, could mount up to 127 devices. RS485 bus communication baud rate range 9600-25600Bps, default 115200bps.

■ Support operation modes such as position control, velocity control and torque control.

■ User can control the start and stop of the motor through bus communication and query the real-time status of the motor.

■ Input voltage: 24V-48VDC.

■ 2 isolated signal input ports, programmable, implement the driver's functions such as enable, start stop, emergency stop and limit.

■ With protect function such as over-voltage, over-current.

1.3. APPLICATION

Suitable for AGV, delivery robot, service robot, automated handling machine, etc.

2. ELECTRICAL, ENVIRONMENTAL INDEX

2.1. ELECTRICIAL INDEX

Driver Parameter	Min value	Typical value	Max value	Unit
Input voltage	20 VDC	36VDC	48VDC	V
Output current(peak)	0	15	30	A
Control signal input current	7	10	16	mA
Over-voltage protection	-	60	-	VDC
Under-voltage protection	-	16	-	VDC
Input signal voltage	-	5	-	VDC
Insulation resistance	100			MΩ

2.2. ENVIROMENTAL INDEX

Cooling Type		Natural cooling or forced cooling
Working environment	Application occasion	Avoid dust, oil mist and corrosive gases
	Working temperature	0~50℃
	Max. ambient humidity	90% RH(no condensation)
	Storage temperature	-10~70℃
	Vibration	10~55Hz/0.15mm

2.3. INSTALLATION DIMENSION

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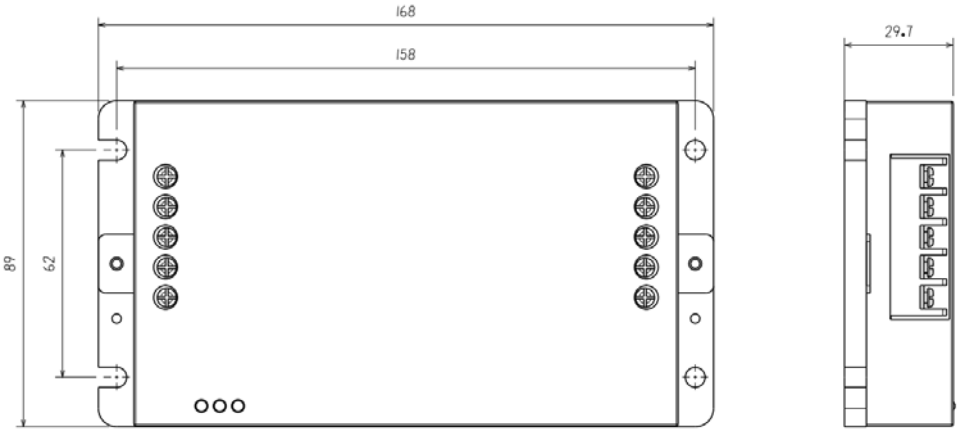


Fig.1 Installation dimension diagram (unit: cm)

2.4. INSTALLATION

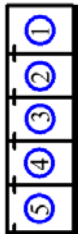
User can use the wide or narrow side of the driver cooled radiator for installation. If installing with wide side, use M3 screws to install through the holes on four corners. If installing with narrow side, use M3 screws to install through the holes on both sides. In order to achieve good heat dissipation, it is recommended to use narrow-side installation.

The power device of the driver will generate heat. If it works continuously under the condition of high input voltage and high power, the effective heat dissipation area should be enlarged or forced cooling. Do not use it in a place where there is no air circulation or where the ambient temperature exceeds 60 ° C. Do not install the driver in a humid or metal debris place.

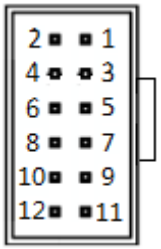
3. DRIVER INTERFACE AND WIRING

3.1. INTERFACE DEFINITION

3.1.1 Power input port

Port	Pin	Mark	Name	Function
	1	DC	Power supply interface	Power supply 24V-48V
	2	GND		
	3	U	Motor power interface	Wire connected to motor
	4	V		
	5	W		

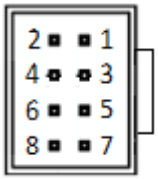
3.1.2 J2/J6(Feedback port)

Port	Pin	Mark	Name	Function
	1	iA+	Encoder	
	2	iA-		
	3	iB+		
	4	iB-		
	5	RTC+	temperature sensor	
	6	RTC-		
	7	V	Hall sensor	
	8	W		
	9	U		
	10	GND	Power ground	
	11	VCC	Power positive	Output to encoder and HALL
	12	GND	Power ground	

3.1.3 J3/J5(Control signal port)

Port	Pin	Mark	Name	Function
	1	B-	Brake-	Brake control (5-24V)
	2	BGND	External power ground	
	3	BDC	Brake+, External power positive	
	4			
	5	IN1+	Input 1	Could be configured via CAN or 485
	7	IN1-		
	6	oA+	Encoder output	
	8	oB+		
	9	5V	5V OUT	Could be used to supply power for IN ,output current cannot exceed 100mA
	10	GND	GND	

3.1.4 J4(Communication port)

Port	Pin	Mark	Name	Function
	1	CANH	CANOPEN	
	3	CANL		
	2	A	RS485	
	4	B		
	5	CANH	CANOPEN	
	7	CANL		
	6	A	RS485	
	8	B		

3.2 CONTROL SIGNAL WIRING

ZLAC8015D series driver provides 2 photoelectric isolation programmable input interfaces, compatible with NPN wiring and PNP wiring.

2-channel (IN1-IN2) programmable input signal is isolated from the external control interface by an optocoupler. The driver is compatible with common cathode and common anode connections, as shown in the following Figure 2. In order to ensure the reliable conduction of the optocoupler inside the driver, the drive current provided by the controller must be at least 10mA.

The level pulse width of IN1-IN2 input needs to be bigger than 10ms, otherwise the driver may not respond normally. The IN1-IN2 timing diagram is shown in Figure 3.

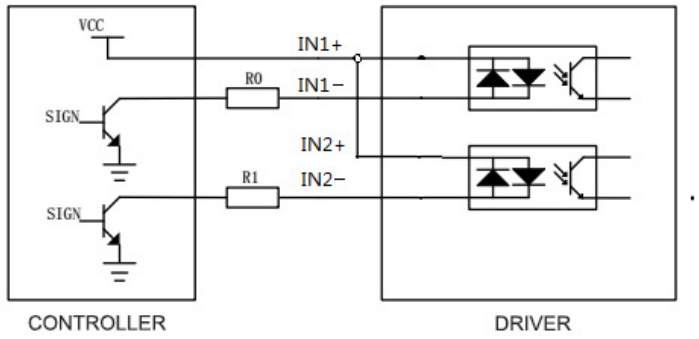


Fig.2 Input interface circuit

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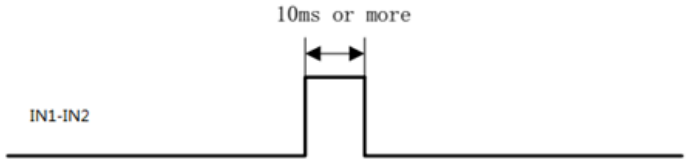

Fig.3 Control signal interface wiring diagram

Note: The default input voltage of the control signal is 5V. For other voltages, current limiting resistors must be added, for example: 12V, external 1K 1 / 2W resistor; 24V, external 2K 1 / 2W resistor.

After the driver is powered on, digital Inputs defaults to the unspecified state. At this time, the input signal is invalid. User could configure input functions through communication.

3.3. CANOPEN COMMUNICATION PORT DESCRIPTION

ZLAC8015D series driver provides 4PIN communication port. For pin definition, please refer to 3.1.4 Communication Port, which includes CANH, CANL, CANH and CANL.

Note: Please use shielded twisted-pair cables for communication cable and make ground connection to ensure stable communication.

3.4. RS485 COMMUNICATION PORT DESCRIPTION

ZLAC8015D series driver provides 4PIN communication port. For pin definition, please refer to 3.1.4 Communication Port, which includes A, B, and A, B.

Note: Please use shielded twisted-pair cables for communication cable and make ground connection to ensure stable communication.

3.5. STATUS INDICATOR LED

The green LED is power indicator, which is always on when the driver is powered on;. It is off when the driver is powered off. The red LED is fault indicator. When the driver fails, the driver will stop and prompt the corresponding fault code. The fault can be cleared

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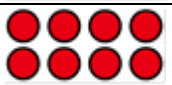
when the user powers off and restarts the power. The status indicator LED represents different operation and fault information, as shown in the following table:

Status	Situation	Status indicator LED description	
Over-Voltage	The power supply voltage exceeds the maximum rated voltage.	1 Red	
Under-Voltage	The power supply voltage is lower than the minimum working voltage.	2 Red	
Over-Current	Phase current through the motor exceeds short-circuit between phases	3 Red	
Over-Load	The phase current through the motor exceeds the set overload current	4 Red	
Current out-of-tolerance	Control current and output current are out of tolerance	5 Red	
Position out-of-tolerance	The given position is out of tolerance with the output position	6 Red	
Speed out-of-tolerance	The given speed and output speed are out of tolerance	7 Red	
Internal reference error	Internal fault of the driver	8 Red	
Parameter reading error	EEPROM parameters read error	9 Red	
HALL fault	The HALL cable is not plugged in or the signal is incorrect	10 Red	
High motor temperature	Motor temperature is too high	11 Red	

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