

ZLAC8030L V2.0 SERVO DRIVER

RS485 COMMUNICATION QUICK START GUIDE

Version	Description	Date
V1.00	First Edition	2023-9-11

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一、RS485 SERIAL PORT SETTINGS

RS485 communication of ZLAC8030L supports Modbus RTU protocol.

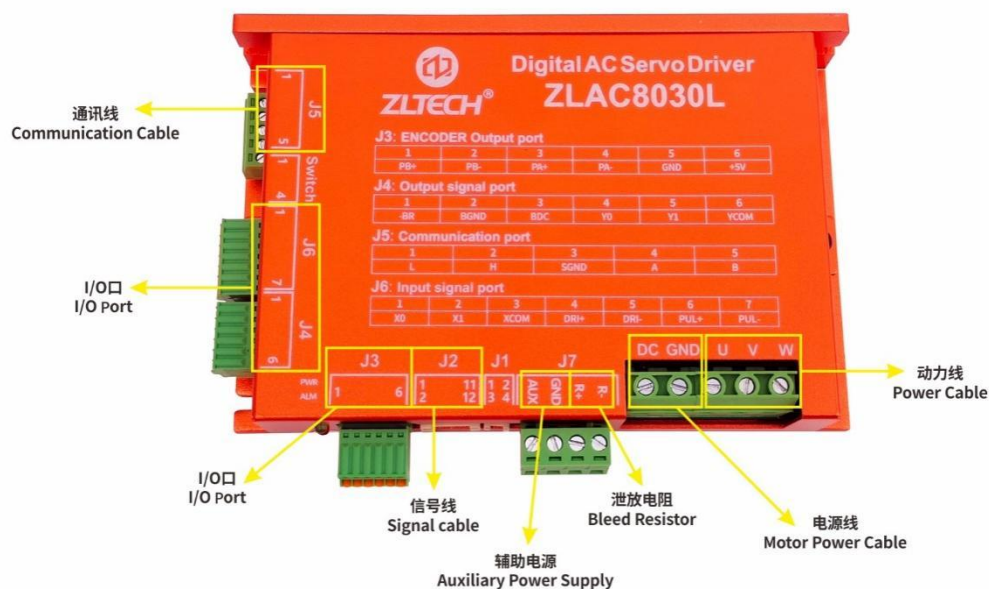
The driver address can be set to 0-127. The default address is 4.

For RS485 communication, ZLAC8030L has 6 optional baud rates: 9600, 19200, 38400, 57600, 115200, 128000. Baud rate could be set through software, its default value is 115200.

二、WIRING CONNECTION

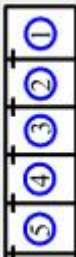
2.1 Basic Wiring Diagram

Note: Motor power cable sequence is U (Yellow), V (Green), W (Blue).



2.2 RS485 Port

Note: 485 interface only one group, if the user needs to connect multiple drives please connect A (pin4), B (pin5) and SGND (pin3), this drive communication is with isolation, the user needs to connect the ground signal SGND

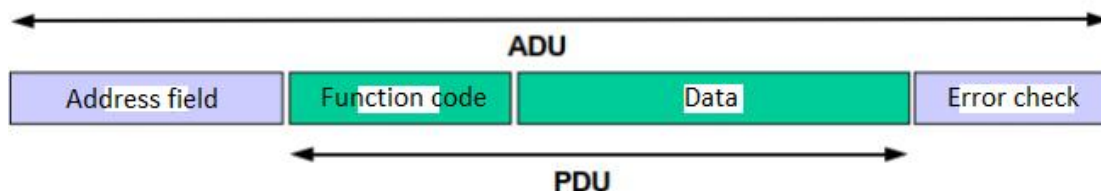
Port	Pin	Symbol	Name	Function
	1	CANL	CAN	CAN/RS485 is an isolated output and is recommended when used while connecting to a common ground
	2	CANH		
	3	SGND	Communication ground	
	4	A	RS485	
	5	B		

三、PROTOCOL FORMAT

3.1 Communication Setting

Baud rate: 115200, ID: 4 (default)

3.2 RS485 Basic Format



The function codes supported by ZLAC8030L are as below:

Function description	Function code	Error function code
Read multiple registers	0x03	0x83
Write single register	0x06	0x86
Writer multiple registers	0x10	0x90

3.3 Write Single Register Function Code 0x06

Send command format: Driver address + Function code + Register address + data + CRC check code.

Command	Content Description
04	Driver Address
06	Function Code
20	High 8 bits of register start address
3A	Low 8 bits of register start address
00	High 8 bits of register data
64	Low 8 bits of register data
A3	High 8 bits of CRC check
B9	Low 8 bits of CRC check

Return command format: Driver address + Function code + Register address + data + CRC check code.

Command	Content Description
04	Driver Address
06	Function Code
20	High 8 bits of register start address
3A	Low 8 bits of register start address
00	High 8 bits of register number
64	Low 8 bits of register number
A3	High 8 bits of CRC check
B9	Low 8 bits of CRC check

3.4 Write Multiple Register Function Code 0x10

Send command format: Driver address + Function code + Register address + Register number+ Number of bytes + data + CRC check code.

Command	Content Description
04	Driver Address
10	Function Code
20	High 8 bits of register start address
0B	Low 8 bits of register start address
00	High 8 bits of register number
02	Low 8 bits of register number
04	Number of bytes
04	High 8 bits of data 0
00	Low 8 bits of data 0
00	High 8 bits of data 1
0F	Low 8 bits of data 1
7B	High 8 bits of CRC check
25	Low 8 bits of CRC check

Return command format: Driver address + Function code + Register Register number + CRC check code.

Command	Content Description
04	Driver Address
10	Function Code
20	High 8 bits of register start address
0B	Low 8 bits of register start address
00	High 8 bits of register number
02	Low 8 bits of register number
3B	High 8 bits of CRC check
9F	Low 8 bits of CRC check

3.5 Read Register Function Code 0x03

Eg: Send command “Read the actual speed of motor”, return “The actual speed of motor is 10RPM”

Send:

Command	Content Description
04	Driver Address
03	Function Code
20	High 8 bits of register start address
2C	Low 8 bits of register start address
00	High 8 bits of register number
01	Low 8 bits of register number
4E	High 8 bits of CRC check
56	Low 8 bits of CRC check

Return data:

Command	Content Description
04	Driver Address
03	Function Code
02	Number of bytes read
00	High 8 bits of data
64	Low 8 bits of data
75	High 8 bits of CRC check
AF	Low 8 bits of CRC check

四、CONTROL MODE

4.1 Profile Velocity Mode

Description	Send	Return
Set Profile Velocity Mode	04 06 20 32 00 03 63 91	04 06 20 32 00 03 63 91
Motor enable	04 06 20 31 00 08 D2 56	04 06 20 31 00 08 D2 56
Set target speed 100RPM	04 06 20 3A 00 64 A3 B9	04 06 20 3A 00 64 A3 B9
Set target speed-100RPM	04 06 20 3A FF 9C E3 CB	04 06 20 3A FF 9C E3 CB

4.2 Profile Position Mode (Relative Position)

Description	Send	Return
Set relative Profile Position Mode	04 06 20 32 00 01 E2 50	04 06 20 32 00 01 E2 50
Set max speed of 50RPM	04 06 20 36 00 32 E3 84	04 06 20 36 00 32 E3 84
Set S-type acceleration time 200ms	04 06 20 37 00 C8 32 07	04 06 20 37 00 C8 32 07
Set S-type deceleration time 200ms	04 06 20 38 00 C8 02 04	04 06 20 38 00 C8 02 04
Motor enable	04 06 20 31 00 08 D2 56	04 06 20 31 00 08 D2 56
Set target position 20480 pulses	04 10 20 34 00 02 04 00 00 50 00 45 45	04 10 20 34 00 02 0B 93
Start up	04 06 20 31 00 10 D2 5C	04 06 20 31 00 10 D2 5C
Set target position -20480 pulses	04 10 20 34 00 02 04 FF FF B0 00 0C A1	04 10 20 34 00 02 0B 93
Start up	04 06 20 31 00 10 D2 5C	04 06 20 31 00 10 D2 5C

4.3 Profile Position Mode (Absolute Position)

Description	Send	Return
Set absolute Profile Position Mode	04 06 20 32 00 02 A2 51	04 06 20 32 00 02 A2 51
Set max speed of 150RPM	04 06 20 36 00 32 E3 84	04 06 20 36 00 32 E3 84
Set S-type acceleration time 100ms	04 06 20 37 00 C8 32 07	04 06 20 37 00 C8 32 07
Set S-type deceleration time 100ms	04 06 20 38 00 C8 02 04	04 06 20 38 00 C8 02 04
Motor enable	04 06 20 31 00 08 D2 56	04 06 20 31 00 08 D2 56
Set target position 20480 pulses	04 10 20 34 00 02 04 00 00 50 00 45 45	04 10 20 34 00 02 0B 93
Start up	04 06 20 31 00 10 D2 5C	04 06 20 31 00 10 D2 5C
Set target position -20480 pulses	04 10 20 34 00 02 04 FF FF B0 00 0C A1	04 10 20 34 00 02 0B 93
Start up	04 06 20 31 00 10 D2 5C	04 06 20 31 00 10 D2 5C

4.4 Profile Torque Mode

Description	Send	Return
Set Profile Torque Mode	04 06 20 32 00 04 22 53	04 06 20 32 00 04 22 53
Motor enable	04 06 20 31 00 08 D2 56	04 06 20 31 00 08 D2 56
Set target torque 2000mA	04 06 20 33 07 D0 71 FC	04 06 20 33 07 D0 71 FC
Set target torque-2000mA	04 06 20 33 F8 30 31 84	04 06 20 33 F8 30 31 84

4.5 General Command

Send	Description
04 06 20 31 00 07 92 52	Stop
04 06 20 31 00 06 53 92	Clear fault
04 03 20 2A 00 02 EE 56	Read motor encoder value
04 03 20 2C 00 01 4E 56	Read motor actual speed (unit: 0.1RPM)
04 03 20 2E 00 01 EF 96	Read fault code
04 03 20 25 00 01 9E 54	Read software version
04 03 20 26 00 01 6E 54	Read motor temperature (unit: 1°C)

4.6 Emergency Stop Command

Send	Receive	Description
04 06 20 31 00 05 13 93	04 06 20 31 00 05 13 93	Mtor stops and keep enabled status
04 06 20 31 00 08 D2 56	04 06 20 31 00 08 D2 56	Motor Enable (Release Emergency Stop)

※ Attention: After sending emergency stop command, user needs to send enable command to release the emergency stop status.

五、FUNCTION SETTING

5.1 Alarm PWM Processing Method

Open Command: 04 06 20 54 00 01 02 4F

Close Command: 04 06 20 54 00 00 C3 8F

Save Instruction: 04 06 20 09 00 02 D3 9C

Trigger Mechanism: When enabling this function, driver will enter an alarm and short-circuit the motor's power UVW (after the motor power cable UVW short-circuit, it will generate resistance during motor's rotation)

Function: To prevent the robot from sliding instantly after motor alarms

5.2 Parking Mode

Open Command: 04 06 20 57 00 01 F2 4F

Close Command: 04 06 20 57 00 00 33 8F

Trigger Mechanism: When enabling this function, the motor output current will not exceed 3A

Function: When the robot is charging or standby, enter this function to prevent the motor from over temperature problem

5.3 Speed Resolution

Setting Instruction: 04 06 20 58 00 0A 83 8B (setting range: 0-10) 10 is hexadecimal A

Save Instruction: 04 06 20 09 00 02 D3 9C

Rule: Set to A, output speed unit: $1/10=0.1$ RPM. Eg: target speed is 100 RPM, and the actual output is 10 RPM

Set to 5, output speed units: $1/5=0.2$ RPM. Eg: target speed is 100 RPM, and the actual output is 20 RPM

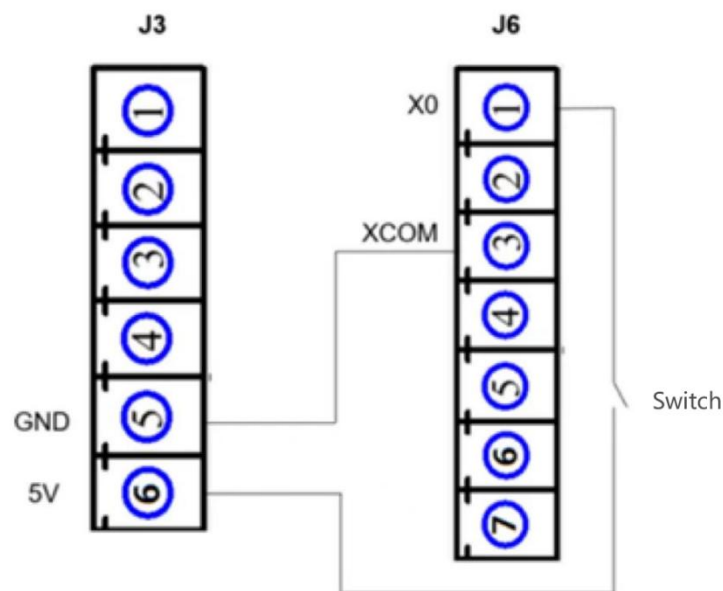
Set to 1, output speed unit: $1/1=1$ RPM. Eg: target speed is 100 RPM, and the actual output is 100 RPM

Trigger Mechanism: After enabling the testing function, it must be saved and restarted to be effective

Function: User could use more precise target speed control

5.4 I/O Emergency Stop Processing Method

5.4.1 Wiring Diagram J3,J6



5.4.2 RS485 Command Setting

Enable input interface INPUT1 emergency stop function: 04 06 20 42 00 09 E2 4D

Enable input interface INPUT2 emergency stop function: 04 06 20 43 00 09 B3 8D

Save instruction: 04 06 20 09 00 02 D3 9C

Turn on I0 emergency stop and release the shaft function command: 04 06 20 56 00 01 A3 8F

Turn off I0 emergency stop and release the shaft function instruction: 04 06 20 56 00 00 62 4F

Save instruction: 04 06 20 09 00 02 D3 9C

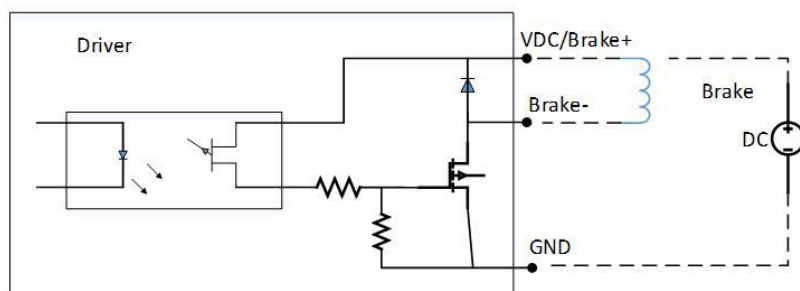
Trigger mechanism: After activating this function, and triggering an external emergency stop, the motor will be in an enabled state (0 speed)

Function: When the robot is in an abnormal state, it will trigger an external emergency stop

5.5 Brake Function

5.5.1 Wiring Diagram

Note: 20V-24V DC, brake doesn't have positive or negative poles, and could be wired freely.



5.5.2 Brake Command Setting

Release brake command: 04 06 20 46 00 00 63 8A

Close brake command: 04 06 20 46 00 01 A2 4A

Function: If user's motor is equipped with an external electromagnetic brake, this command can be used to release and close the brake.

六、RS485 STATUS WORD

Index	Bit definition	Status word	Status Description
2027h	R-bit7, bit6 L-bit14, bit14	00 00	Release shaft
		40 40	Lock shaft
		80 80	Emergency stop
		C0 C0	Alarm
	R-bit0 L-bit8	0	Stop
		1	Running

七、FAULT CODE

Index	Fault code	Description	Troubleshooting
	0000h	No error	Driver is normal.
	0001h	Over-voltage	1. Power supply voltage is too high 2. Excessive back electromotive force (it is recommended to add a bleeder circuit)

20A5h	0002h	Under-voltage	1. Power supply voltage is too low 2. Check if the wiring connector is correct 3. Check if the motor parameters are correct
	0004h	Over-current	1. Instantaneous current is too high 2. Motor power cable is loose
	0008h	Overload	1. Check if the motor cable is loose 2. Check if the wiring and motor parameters are correct 3. Motor is stall 4. Motor or driver's problem
	0020h	Encoder value is out of tolerance	1. Motor is stall 2. Encoder's problem
	0080h	Reference voltage error	Reference voltage circuit issue
	0100h	EEPROM read and write error	1. Firmware is upgraded (needs to make factory settings) 2. EEPROM circuit is damaged
	0200h	Hall error	1. Check if the motor cable is loose 2. Motor's problem 3. Driver's problem
	0400h	motor temperature is too high.	1. The motor current is too high (it is recommended to monitor motor's actual current and temperature, and reduce the current in real-time control) 2. Motor's thermistor is damaged 3. Driver's circuit is damaged
	0800h	Encoder error	1. Check if the motor encoder cable is loose 2. Check if the motor encoder cable is disconnected

八、ADDRESS DIRECTORY

Index	Name	Description	Type	Property	Default
2000h	Communication offline time	Driver and host communication offline time setting. Unit: ms Range: 0-32767;	U16	RW/S	1000
2001h	Motor default rotation direction	Motor default rotation direction(from shaft side): 0: CW; 1: CCW.	U16	RW/S	0
2003h	Input signal status	2 input signal level status Bit0-Bit1: X0-X1 input level status	U16	RO	0
2004h	Out signal status	2 output signal level status Bit0-Bit1: Y0-Y1 output status;	U16	RO	0

2005h	Reset feedback position	Used to clear feedback position in Profile Position Mode. 0: invalid; 1: Clear the feedback position; Not saved.	U16	RW	0
2006h	In absolute Profile Position Mode, clear the current position	Used to clear the current position in absolute Profile Position Mode. 0: invalid. 1: The current position is cleared. Not saved.	U16	RW	0
2007h	Limit parking method	0: stop. 1: Emergency stop. 2: invalid.	U16	RW/S	0
2008h	Initial speed	The initial speed when motion begins. Unit: r/min. Range: 1-300 r/min.	U16	RW/S	1r/min
2009h	Register parameter settings	0: invalid. 1: Restore factory settings. 2: Save all RW attribute parameters to EEPROM.	U16	RW	0
200Ah	Motor Max speed	Max operating speed of motor. Unit: r/min. Range: 1-1000 r/min.	U16	RW/S	1000
200Bh	Encoder wire number setting	0-4096	U16	RW/S	1024
200Ch	Motor pole pairs	4-64	U16	RW/S	15
200Dh	CAN custom drive node number	When the external dial switch is 0, 4 ~ 127 can be set; When the external dial switch is 1-3, this bit is invalid.	U16	RW/S	4
200Eh	High bit of CAN custom communication baud rate	0: 1000 Kbit/s 1: 500 Kbit/s 2: 250 Kbit/s 3: 125 Kbit/s 4: 100 Kbit/s	U16	RW/S	1
200Fh	Lock shaft method when power-on	0: Not enable, not lock the shaft. 1: Not enable, lock the shaft.	U16	RW/S	0
2010h	Whether store RW / S parameters in EEPROM synchronously	Whether the communication write function code value is updated to EEPROM. 0: Parameters with attribute RW/S are updated to EEPROM synchronously; 1: Not updated;	U16	RW	0
2011h	Offset angle of motor	Unit: 1 °;	I16	RW/S	0

	and Hall	Range: -360~ +360.			
2012h	Overload factor	Range: 0-300,.Unit: %;	U16	RW/S	200
2013h	Motor temperature protection threshold	Unit: 0.1 °C; Rang: 0-1200 (* 0.1).	U16	RW/S	800
2014h	Rated current	The rated current output by driver. Unit: 0.1A; Range: 0-150.	U16	RW/S	150
2015h	Max current	Max current output by driver. Unit: 0.1A; Range: 0-300.	U16	RW/S	300
2016h	Overload protection time	Driver overload protection time. Unit: 10ms; Range: 0-6553.	U16	RW/S	300
2017h	Out of tolerance alarm threshold	Encoder out-of-tolerance threshold. Unit: *10counts; Range: 1-6553.	U16	RW/S	409
2018h	Velocity smoothing factor	0-30000	U16	RW/S	1000
2019h	Current loop proportional coefficient	0-30000	U16	RW/S	600
201Ah	Current loop integral gain	0-30000	U16	RW/S	300
201Bh	Feedforward output smoothing coefficient	0-30000	U16	RW/S	100
201Ch	Torque output smoothing factor	0-30000	U16	RW/S	100
201Dh	Speed proportional gain Kp	0-30000	U16	RW/S	500
201Eh	Speed integral gain Ki	0-30000	U16	RW/S	100
201Fh	Speed feedforward gain Kf	0-30000	U16	RW/S	1000
2020h	Position proportional gain Kp	0-30000	U16	RW/S	50
2021h	Position feedforward gain Kf	0-30000	U16	RW/S	200
2022h	RS485 custom drive node number	When the external dial switch is 0, 4-127 can be set; When the external dial switch is 1-3, this bit is invalid.	U16	RW/S	4
2023h	High bit of RS485 custom communication baud rate	1: 128000bps 2: 115200bps 3: 57600bps 4: 38400bps	U16	RW/S	2

		5: 19200bps 6: 9600bps			
2024h	Reserved	Reserved	Reserved	Reserved	Reserved
2025h	Software version	Factory default	U16	RO	-
2026h	Motor temperature	Unit: 0.1 °C; Range: 0-1200 (* 0.1).	U16	RO	-
2027h	Motor status register	Driver control motor status: 00 00: Release shaft 00 40: Lock shaft 00 80: Emergency stop 00 C0: Alarm Motor running status: bit0 0: Stop 1: Running	U16	RO	0
2028h	Hall input status	0-7; If 0 or 7 appears, there exists Hall error.	U16	RO	0
2029h	Bus voltage	Unit: 0.01V	U16	RO	0
202Ah	Actual position feedback high 16 bit	Actual position feedback, unit: counts.	I32	RO	0
202Bh	Actual position feedback low 16 bit				
202Ch	Actual speed feedback	Current motor speed, unit: 0.1r/min	I16	RO	0
202Dh	Real-time torque feedback	Unit: 0.1A Range: -300~300.	I16	RO	0
202Eh	The last error code of driver	Manufacturer-defined driver error conditions. 0000h: no error; 0001h: over-voltage; 0002h: under-voltage; 0004h: over-current; 0008h: overload; 0010h: current is out of tolerance (reserved); 0020h: encoder is out of tolerance; 0040h: speed is out of tolerance (reserved); 0080h: reference voltage error; 0100h: EEPROM read and write error; 0200h: Hall error; 0400h: motor temperature is too high; 0800h: encoder error	U16	RO	0

202Fh	The connection bit between host computer and driver				
2030h	Reserved	Reserved	Reserved	Reserved	Reserved
2031h	Control word	Control word 0x06: alarm clear 0x07: stop 0x08: enable 0x10: start (required in Profile Position Mode)	U16	RW	0
2032h	Operating mode	0: undefined; 1: Profile Position Mode (absolute Profile Position Mode); 2: Profile Position Mode (relative Profile Position Mode); 3: Profile Velocity Mode; 4: Profile Torque Mode.	U16	RW	0
2033h	Target torque	Unit: mA Range: -30000 ~30000;	I16	RW	0
2034h	High 16 bits of target position	Range of total pulses in Profile Position Mode operation: -1000000~1000000	I16	RW	0
2035h	Low 16 bits of target position		I16	RW	0
2036h	Max speed	Max speed in Profile Position Mode; Range: 1-1000 r/min.	U16	RW	120r/min
2037h	S-type acceleration time	acceleration time; Range: 0-32767ms.	U16	RW	500ms
2038h	S-type deceleration time	deceleration time; Range: 0-32767ms.	U16	RW	500ms
2039h	Emergency stop deceleration time	deceleration time; Range: 0-32767ms.	U16	RW	10ms
203Ah	Target speed	Target speed in Profile Velocity Mode; Range: -1000-1000 r/min.	I16	RW	0
203BH	Torque slope	Current/1000/second; Unit: mA/s;	U16	RW	300ms
203Ch	Emergency stop code	Driver processing mode after quick stop command. 5: Normal stop, maintain quick stop status; 6: Sudden deceleration stop, maintain quick stop state; 7: Emergency stop, maintain quick stop state.	U16	RW	5
203Dh	Close operation code	Driver processing method after close	U16	RW	1

		command. 0: invalid; 1: normal stop, turn to ready to switch on state;			
203Eh	Disable operation codes	Driver processing mode after disabling operation command 0: invalid; 1: normal stop, turn to switched on state.	U16	RW	1
203Fh	Halt control register	Driver processing mode after control word Halt command. 1: Stop normally and maintain Operation Enabled state; 2: Sudden deceleration stop, maintain Operation Enabled state; 3: Emergency stop, maintain Operation Enabled state.	U16	RW	1
2040h	Profile Position Mode start / stop speed	Start/stop speed in Profile Position Mode; Range: 1-1000 r/min.	U16	RW	1r/min
2041h	Input terminal effective level	Bit0: input terminal X0 control bit; Bit1: input terminal X1 control bit; 0: default; 1: level reversal; The driver defaults input terminal level rising edge or high level is effective.	U16	RW/S	0
2042h	Input terminal X0 terminal function selection	0: undefined; 1-8: NC; 9: Emergency stop signal.	U16	RW/S	9
2043h	Input terminal X1 terminal function selection		U16	RW/S	0
2044h	Output terminal effective level	Bit0: output terminal Y0 control bit; Bit1: output terminal Y1 control bit; 0: default; 1: level reversal; The driver defaults input terminal level rising edge or high level is effective.	U16	RW/S	0
2045h	Output terminal Y0 terminal function selection	0: undefined; 1: alarm signal; 2: driver status signal; 3: NC;	U16	RW/S	1

		4: In position signal.			
2046h	Output terminal Y1 terminal function selection	Brake open/close 0: open; 1: close;	U16	RW	0
2054h	Alarm PWM processing method	0: close; 1: Open;	U16	RW/S	0
2055h	Overload processing method	0: close; 1: Open;	U16	RW/S	0
2056h	I/O emergency stop processing method	0: Lock shaft; 1: Release shaft;	U16	RW/S	0
2057h	Parking mode	0: close; 1: Open;	U16	RW/S	0
2058h	Set speed resolution	1-10 (1: 1RPM, 10: 0.1RPM)	U16	RW/S	1
Note: U16 means unsigned 16 bits; I16 means signed 16 bits; U32 means unsigned 32 bits; I32 means signed 32 bits.					

Note:

Alarm PWM processing method: After driver enters alarm state, the upper tube is closed and the lower tube is opened (short-circuit the 3 power cables of motor).

Overload processing method: for example, motor I^2t time is 20 seconds, the duration of double overload is 6 seconds, and the duration of triple overload is 4 seconds.