

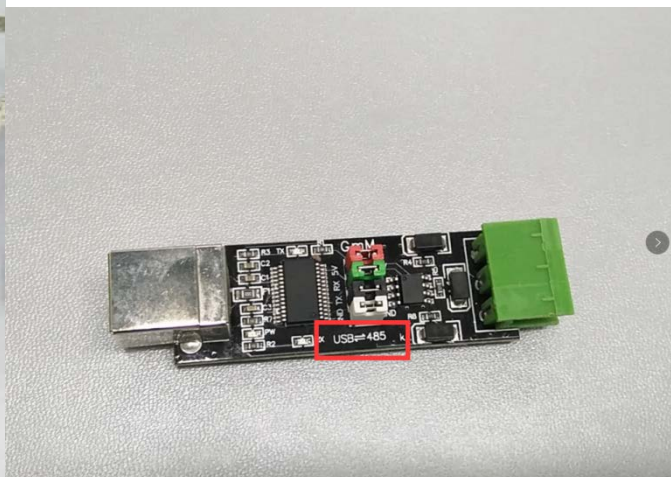
How to connect to PC and use ZLAC8015(D) software

1. Connection

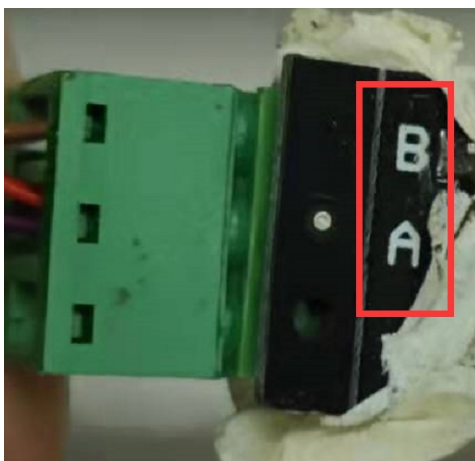
PC → USB to LPT cable → 485 module → debugging cable (A: Orange, B: Brown, provided by ZLTECH) → ZLAC8015(D) CAN&RS485 port (PIN 2, 4 correspond RS485 A, B signal, PIN 6, 8 correspond RS485 A, B signal)



USB to LPT cable



485 module

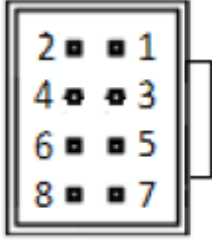


A: Orange B: Brown



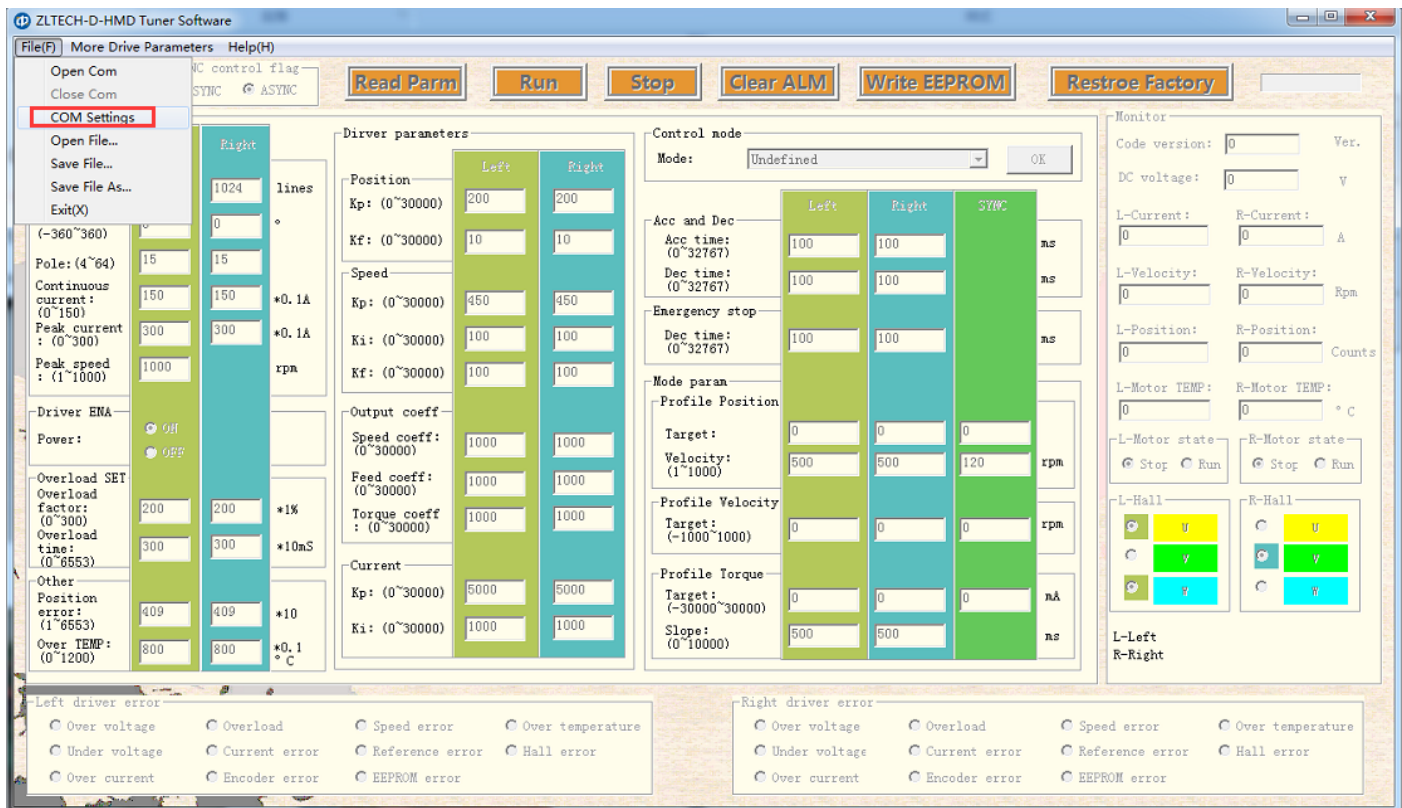
ZLAC8015(D) CAN&RS485 port

3.1.5 Communication port

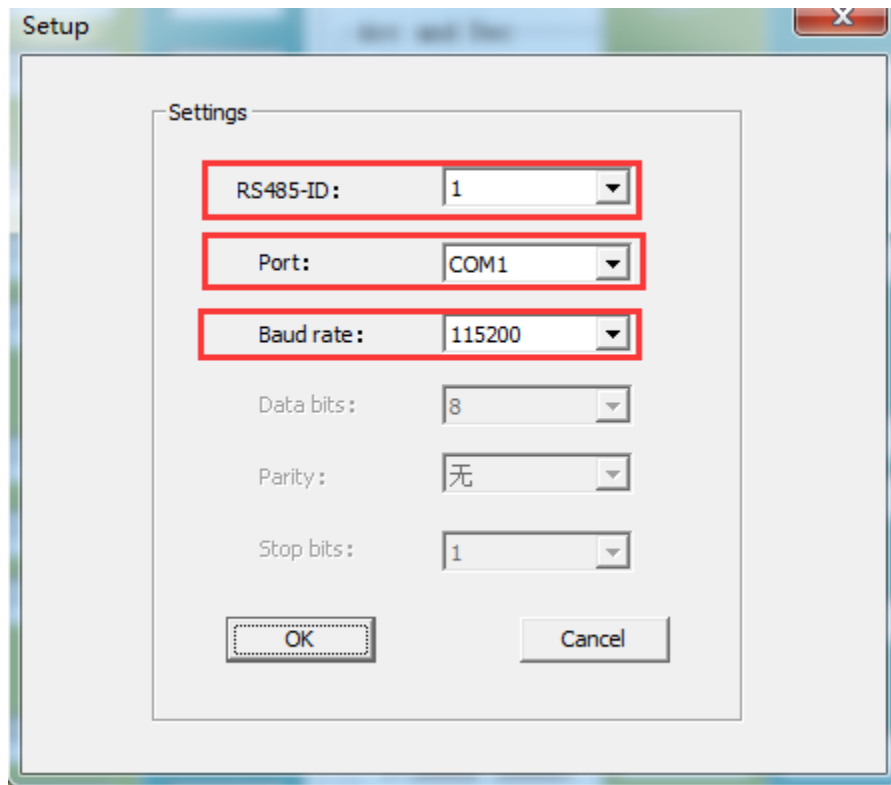
Port	Pin	Mark	Name	Function
	1	CANH	CANOPEN	
	3	CANL		
	2	A	RS485	
	4	B		
	5	CANH	CANOPEN	
	7	CANL		
	6	A	RS485	
	8	B		

2. How to set ZLAC8015(D) software

① File → COM Settings



② Setting port parameters



A. RS485-ID: the fault RS485-ID of ZLAC8015, ZLAC8030L is 4, the fault RS485-ID of ZLAC8015D is 1.

B. Port: select corresponding port.

(Right-click My Computer → Device Manager → USB Serial Port)



USB Serial Port: supports high frequency, high baud rate (no less than 115200).

USB SERIAL CH340: only supports low baud rate (9600), function is not stable.

Note: The Com port No. cannot exceed 15.

COM serial port cannot be recognized:

Please download a driver application to download drivers.

C. Baud rate:

The fault baud rate is: 115200.

③ Open Com



How to judge if the connection succeeds:

Connexion doesn't succeed:

ZLTECH-D-HMD Tuner Software

File(F) More Drive Parameters Help(H)

RS485_ID: 1 SYNC control flag: ☒ SYNC ☐ ASYNC

Read Parm **Run** **Stop** **Clear ALM** **Write EEPROM** **Restroe Factory**

Motor param

	Left	Right	
Encoder: (0~4096)	1024	1024	lines
PhaseShift: (-360~360)	0	0	°
Pole: (4~64)	15	15	
Continuous current: (0~150)	150	150	*0.1A
Peak current: (0~300)	300	300	*0.1A
Peak speed: (1~1000)	1000	1000	rpm

Driver ENA: ☒ ON ☐ OFF

Power: ☒ ON ☐ OFF

Overload SET: ☒ ON ☐ OFF

Overload factor: (0~300)

Left	Right	
200	200	*1%

Overload time: (0~6553)

Left	Right	
300	300	*10ms

Other:

Position error: (1~6553)

Left	Right	
409	409	*10

Over TEMP: (0~1200)

Left	Right	
800	800	*0.1 °C

Driver parameters

	Left	Right	
Position			
Kp: (0~30000)	200	200	
Kf: (0~30000)	10	10	
Speed			
Kp: (0~30000)	450	450	
Ki: (0~30000)	100	100	
Kf: (0~30000)	100	100	
Output coeff			
Speed coeff: (0~30000)	1000	1000	
Feed coeff: (0~30000)	1000	1000	
Torque coeff: (0~30000)	1000	1000	
Current			
Kp: (0~30000)	5000	5000	
Ki: (0~30000)	1000	1000	

Control mode: Mode: Undefined OK

Acc and Dec:

	Left	Right	SYNC	
Acc time: (0~32767)	100	100		ms
Dec time: (0~32767)	100	100		ms

Emergency stop:

	Left	Right	SYNC	
Dec time: (0~32767)	100	100		ms

Profile Velocity:

	Left	Right	SYNC	
Target: (-1000~1000)	0	0	0	rpm

Profile Torque:

	Left	Right	SYNC	
Target: (-30000~30000)	0	0	0	mA
Slope: (0~10000)	500	500		ms

Monitor

Code version: 0 Ver.

DC voltage: 0 V

L-Current: 0 A R-Current: 0 A

L-Velocity: 0 Rpm R-Velocity: 0 Rpm

L-Position: 0 Counts R-Position: 0 Counts

L-Motor TEMP: 0 °C R-Motor TEMP: 0 °C

L-Motor state: ☒ Stop ☐ Run R-Motor state: ☒ Stop ☐ Run

L-Hall: ☒ U ☐ V ☐ W R-Hall: ☒ U ☐ V ☐ W

L-Left R-Right

Left driver error

☐ Over voltage ☐ Overload ☐ Speed error ☐ Over temperature

☐ Under voltage ☐ Current error ☐ Reference error ☐ Hall error

☐ Over current ☐ Encoder error ☐ EEPROM error

Right driver error

☐ Over voltage ☐ Overload ☐ Speed error ☐ Over temperature

☐ Under voltage ☐ Current error ☐ Reference error ☐ Hall error

☐ Over current ☐ Encoder error ☐ EEPROM error

Connction succeeds:

ZLTECH-D-HMD Tuner Software

File(F) More Drive Parameters Help(H)

RS485_ID: 1 SYNC control flag: ☒ SYNC ☐ ASYNC

Read Parm **Run** **Stop** **Clear ALM** **Write EEPROM** **Restroe Factory**

Motor param

	Left	Right	
Encoder: (0~4096)	1024	4096	
PhaseShift: (-360~360)	240	0	°
Pole: (4~64)	10	15	
Continuous current: (0~150)	150	150	*0.1A
Peak current: (0~300)	300	300	*0.1A
Peak speed: (1~1000)	1000		rpm

Driver ENA: ☒ ON ☐ OFF

Power: ☒ ON ☐ OFF

Overload SET: ☒ ON ☐ OFF

Overload factor: (0~300)

Left	Right	
200	200	*1%

Overload time: (0~6553)

Left	Right	
300	300	*10ms

Other:

Position error: (1~6553)

Left	Right	
409	409	

Over TEMP: (0~1200)

Left	Right	
800	800	*0.1 °C

Driver parameters

	Left	Right	
Position			
Kp: (0~30000)	50	50	
Kf: (0~30000)	200	200	
Speed			
Kp: (0~30000)	500	500	
Ki: (0~30000)	1000	1000	
Kf: (0~30000)	1000	1000	
Output coeff			
Speed coeff: (0~30000)	50	50	
Feed coeff: (0~30000)	100	100	
Torque coeff: (0~30000)	100	100	
Current			
Kp: (0~30000)	1000	1000	
Ki: (0~30000)	300	300	

Control mode: Mode: Velocity Mode OK

Acc and Dec:

	Left	Right	SYNC	
Acc time: (0~32767)	15	15		ms
Dec time: (0~32767)	15	15		ms

Emergency stop:

	Left	Right	SYNC	
Dec time: (0~32767)	100	100		ms

Mode param:

Profile Position:

	Left	Right	SYNC	
Target:	0	0	0	
Velocity: (1~1000)	120	120	120	rpm

Profile Velocity:

	Left	Right	SYNC	
Target: (-1000~1000)	0	0	0	rpm

Profile Torque:

	Left	Right	SYNC	
Target: (-30000~30000)	0	0	0	mA
Slope: (0~10000)	300	300		ms

Monitor

Code version: 21323 Ver.

DC voltage: 26.08 V

L-Current: 0.30 A R-Current: 0.00 A

L-Velocity: 0.00 Rpm R-Velocity: 0.00 Rpm

L-Position: 0 Counts R-Position: 0 Counts

L-Motor TEMP: -28.00 °C R-Motor TEMP: -28.00 °C

Dirver TEMP: 25.00 °C

L-Motor state: ☒ Stop ☐ Run R-Motor state: ☒ Stop ☐ Run

L-Hall: ☒ 霍尔U ☐ 霍尔V ☐ 霍尔W R-Hall: ☒ 霍尔U ☐ 霍尔V ☐ 霍尔W

Left driver error

☐ Over voltage ☐ Overload ☐ Speed error ☒ Hall error

☐ Under voltage ☐ Current error ☐ Reference error ☐ EEPROM error

☐ Over current ☐ Encoder error ☐ Over temperature

Right driver error

☐ Over voltage ☐ Overload ☐ Speed error ☒ Hall error

☐ Under voltage ☐ Current error ☐ Reference error ☐ EEPROM error

☐ Over current ☐ Encoder error ☐ Over temperature

ZLTECH-D-HMD Tuner Software

File(F) More Drive Parameters Help(H)

RS485_ID: 1 SYNC: ☐ SYNC ☐ SYNC

Run Stop Clear ALM Write EEPROM Restore Factory

RS485 Help
CANopen Help
ZLAC8015D Help
About ZLTECH-D-HMD(A)...

Motor param

Encoder: (0~4096) Left: 1024 Right: 1024 lines

PhaseShift: (-360~360) Left: 0 Right: 0 °

Pole: (4~64) Left: 15 Right: 15

Continuous current: (0~150) Left: 150 Right: 150 *0.1A

Peak current: (0~300) Left: 300 Right: 300 *0.1A

Peak speed: (1~1000) Left: 1000 Right: 1000 rpm

Driver ENA

Power: ☒ ON ☐ OFF

Overload SET

Overload factor: (0~300) Left: 200 Right: 200 *1%

Overload time: (0~6553) Left: 300 Right: 300 *10ms

Other

Position error: (1~6553) Left: 409 Right: 409 *10

Over TEMP: (0~1200) Left: 800 Right: 800 *0.1 °C

Position

Kp: (0~30000) Left: 200 Right: 200

Kf: (0~30000) Left: 10 Right: 10

Speed

Kp: (0~30000) Left: 450 Right: 450

Ki: (0~30000) Left: 100 Right: 100

Kf: (0~30000) Left: 100 Right: 100

Output coeff

Speed coeff: (0~30000) Left: 1000 Right: 1000

Feed coeff: (0~30000) Left: 1000 Right: 1000

Torque coeff: (0~30000) Left: 1000 Right: 1000

Current

Kp: (0~30000) Left: 5000 Right: 5000

Ki: (0~30000) Left: 1000 Right: 1000

Control node

Mode: Undefined OK

Acc and Dec

Acc time: (0~32767) Left: 100 Right: 100 ns

Dec time: (0~32767) Left: 100 Right: 100 ns

Emergency stop

Dec time: (0~32767) Left: 100 Right: 100 ns

Mode paran

Profile Position

Target: Left: 0 Right: 0 SYNC: 0

Velocity: (1~1000) Left: 500 Right: 500 rpm

Profile Velocity

Target: (-1000~1000) Left: 0 Right: 0 rpm

Profile Torque

Target: (-30000~30000) Left: 0 Right: 0 nA

Slope: (0~10000) Left: 500 Right: 500 ns

Monitor

Code version: 0 Ver.

DC voltage: 0 V

L-Current: 0 R-Current: 0 A

L-Velocity: 0 R-Velocity: 0 Rpm

L-Position: 0 R-Position: 0 Counts

L-Motor TEMP: 0 R-Motor TEMP: 0 °C

L-Motor state: ☒ Stop ☐ Run R-Motor state: ☒ Stop ☐ Run

L-Hall: ☒ U ☐ V ☐ W R-Hall: ☒ U ☐ V ☐ W

L-Left R-Right

Left driver error

☐ Over voltage ☐ Overload ☐ Speed error ☐ Over temperature

☐ Under voltage ☐ Current error ☐ Reference error ☐ Hall error

☐ Over current ☐ Encoder error ☐ EEPROM error

Right driver error

☐ Over voltage ☐ Overload ☐ Speed error ☐ Over temperature

☐ Under voltage ☐ Current error ☐ Reference error ☐ Hall error

☐ Over current ☐ Encoder error ☐ EEPROM error

A. RS485 Help

Open RS485 communication routine.

B. CANopen Help

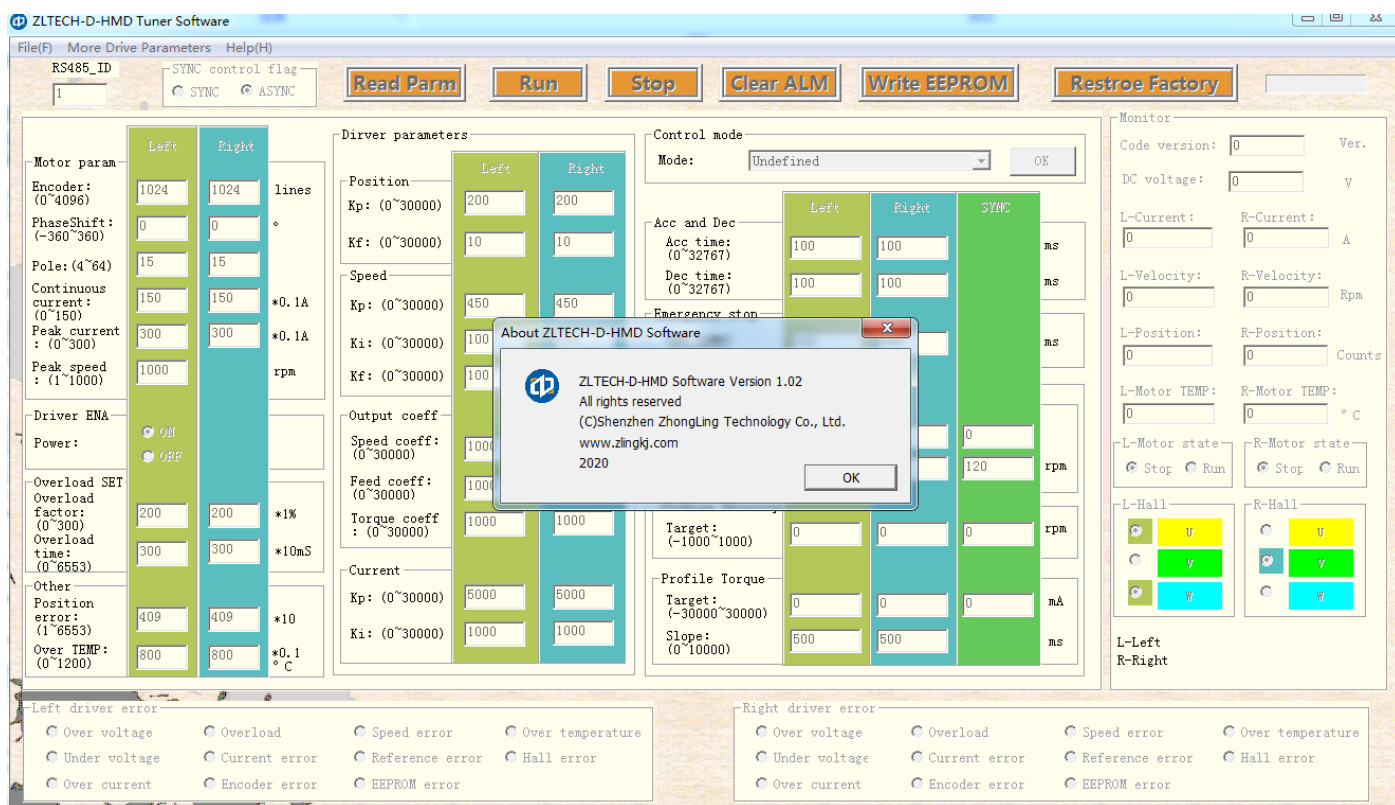
Open CANopen communication routine.

C. ZLAC8015(D) Help

Open ZLAC8015(D) manual.

D. About ZLTECH(-D)-HM

Software Version: 1.02



3. Software interface and function

File(F) More Drive Parameters Help(H)

RS485_ID: SYNC control flag: ☐ SYNC ☒ ASYNC

	Left	Right	
Motor param			
Encoder: (0~4096)	<input type="text" value="1024"/>	<input type="text" value="1024"/>	lines
PhaseShift: (-360~360)	<input type="text" value="0"/>	<input type="text" value="0"/>	°
Pole: (4~64)	<input type="text" value="15"/>	<input type="text" value="15"/>	
Continuous current: (0~150)	<input type="text" value="150"/>	<input type="text" value="150"/>	*0.1A
Peak current: (0~300)	<input type="text" value="300"/>	<input type="text" value="300"/>	*0.1A
Peak speed: (1~1000)	<input type="text" value="1000"/>		rpm
Driver ENA			
Power:	<input checked="" type="radio"/> ON		
	<input type="radio"/> OFF		
Overload SET			
Overload factor: (0~300)	<input type="text" value="200"/>	<input type="text" value="200"/>	*1%
Overload time: (0~6553)	<input type="text" value="300"/>	<input type="text" value="300"/>	*10mS
Other			
Position error: (1~6553)	<input type="text" value="409"/>	<input type="text" value="409"/>	*10
Over TEMP: (0~1200)	<input type="text" value="800"/>	<input type="text" value="800"/>	*0.1 °C

	Left	Right
Dirver parameters		
Position		
Kp: (0~30000)	<input type="text" value="200"/>	<input type="text" value="200"/>
Kf: (0~30000)	<input type="text" value="10"/>	<input type="text" value="10"/>
Speed		
Kp: (0~30000)	<input type="text" value="450"/>	<input type="text" value="450"/>
Ki: (0~30000)	<input type="text" value="100"/>	<input type="text" value="100"/>
Kf: (0~30000)	<input type="text" value="100"/>	<input type="text" value="100"/>
Output coeff		
Speed coeff: (0~30000)	<input type="text" value="1000"/>	<input type="text" value="1000"/>
Feed coeff: (0~30000)	<input type="text" value="1000"/>	<input type="text" value="1000"/>
Torque coeff: (0~30000)	<input type="text" value="1000"/>	<input type="text" value="1000"/>
Current		
Kp: (0~30000)	<input type="text" value="5000"/>	<input type="text" value="5000"/>
Ki: (0~30000)	<input type="text" value="1000"/>	<input type="text" value="1000"/>

Left driver error

☐ Over voltage ☐ Overload ☐ Speed error ☐ Over temperature
☐ Under voltage ☐ Current error ☐ Reference error ☐ Hall error
☐ Over current ☐ Encoder error ☐ EEPROM error

① 3 main motor parameters:

Encoder, Phase Shift, Pole (different motors have different parameters)

Motor	Encoder Line	Phase Shift	Pole Pair
ZLLG40ASM100	1024	-60	10
ZLLG45ASM200	1024	0	10
ZLLG50ASM200/ZLLG55ASM150	1024	240	10
ZLLG50ASM200 V2.0/ZLLG55ASM150 V2.0	4096	240	10
ZLLG65ASM250/ZLLG80ASM250	1024	0	15
ZLLG65ASM250 V3.0/ZLLG80ASM250 V3.0	4096	0	15
ZLLG65ASM250-L/ZLLG80ASM250-L	1024	0	15
ZLLG65ASM250-L V3.0/ZLLG80ASM250-L V3.0	4096	0	15
ZLLG65ASM250-4096 V2.0/ZLLG80ASM250-4096 V2.0	4096	0	15
ZLLG65ASM500 V1.0	1024	60	15
ZLLG65ASM500 V2.0	4096	60	15
ZLLG80ASM800 V1.0/ZLLG10ASM800(-R) V1.0	1024	0	20
ZLLG80ASM800 V2.0/ZLLG10ASM800(-R) V2.0/ZLLG13ASM800 V2.0/ZLLG14ASM800 V2.0/ZLLG15ASM800 V2.0/ZLLG16ASM800 V2.0	4096	0	20

② The relation among continuous current, peak current and overload factor:

$$\text{Continuous current} * \text{Overload factor} = \text{Peak current}$$

③ Driver Enable

ON: Shaft is locked when powered on

OFF: Shaft is released when powered on

④ Kp, Ki parameters in PID adjustment:

A. Kp (Scale coefficient): impulse the responding speed, increase the adjusting accuracy, adjust errors quickly. (Kp value cannot be too high, otherwise there will be current noise)

B. Ki (Integral coefficient): Eliminate residual errors, and adjust the rigidity of the motor at the same time.

C. How to find optimum value of Kp, Ki:

Adjust Kp from small value using scope 100, then adjust Ki from small value using scope 100

D. Empiric value of PID parameters under velocity mode

Velocity Kp: 200-300

Velocity Ki: 1000-1500

Current Kp: 600-800

Current Ki: 300-400

Stop
Clear ALM
Write EEPROM
Restroe Factory

Control mode

Mode: Undefined OK

	Left	Right	SYNC	
Acc and Dec				
Acc time: (0~32767)	100	100		ms
Dec time: (0~32767)	100	100		ms
Emergency stop				
Dec time: (0~32767)	100	100		ms
Mode param				
Profile Position				
Target:	0	0	0	
Velocity: (1~1000)	500	500	120	rpm
Profile Velocity				
Target: (-1000~1000)	0	0	0	rpm
Profile Torque				
Target: (-30000~30000)	0	0	0	mA
Slope: (0~10000)	500	500		ms

Monitor

Code version: 0 Ver.

DC voltage: 0 V

L-Current: 0 R-Current: 0 A

L-Velocity: 0 R-Velocity: 0 Rpm

L-Position: 0 R-Position: 0 Counts

L-Motor TEMP: 0 R-Motor TEMP: 0 °C

L-Motor state: ☒ Stop ☐ Run

R-Motor state: ☒ Stop ☐ Run

L-Hall

☒ U

☐ V

☐ W

R-Hall

☐ U

☒ V

☐ W

L-Left
R-Right

Right driver error

☐ Over voltage

☐ Overload

☐ Speed error

☐ Over temperature

☐ Under voltage

☐ Current error

☐ Reference error

☐ Hall error

☐ Over current

☐ Encoder error

☐ EEPROM error

⑤ Acceleration and deceleration time

We suggest customer to use their own acceleration and deceleration algorithm, as customer's own acceleration and deceleration algorithm could make the control effect better.

Note: the acceleration and deceleration time must be lower than the time interval the customer changes instructions.

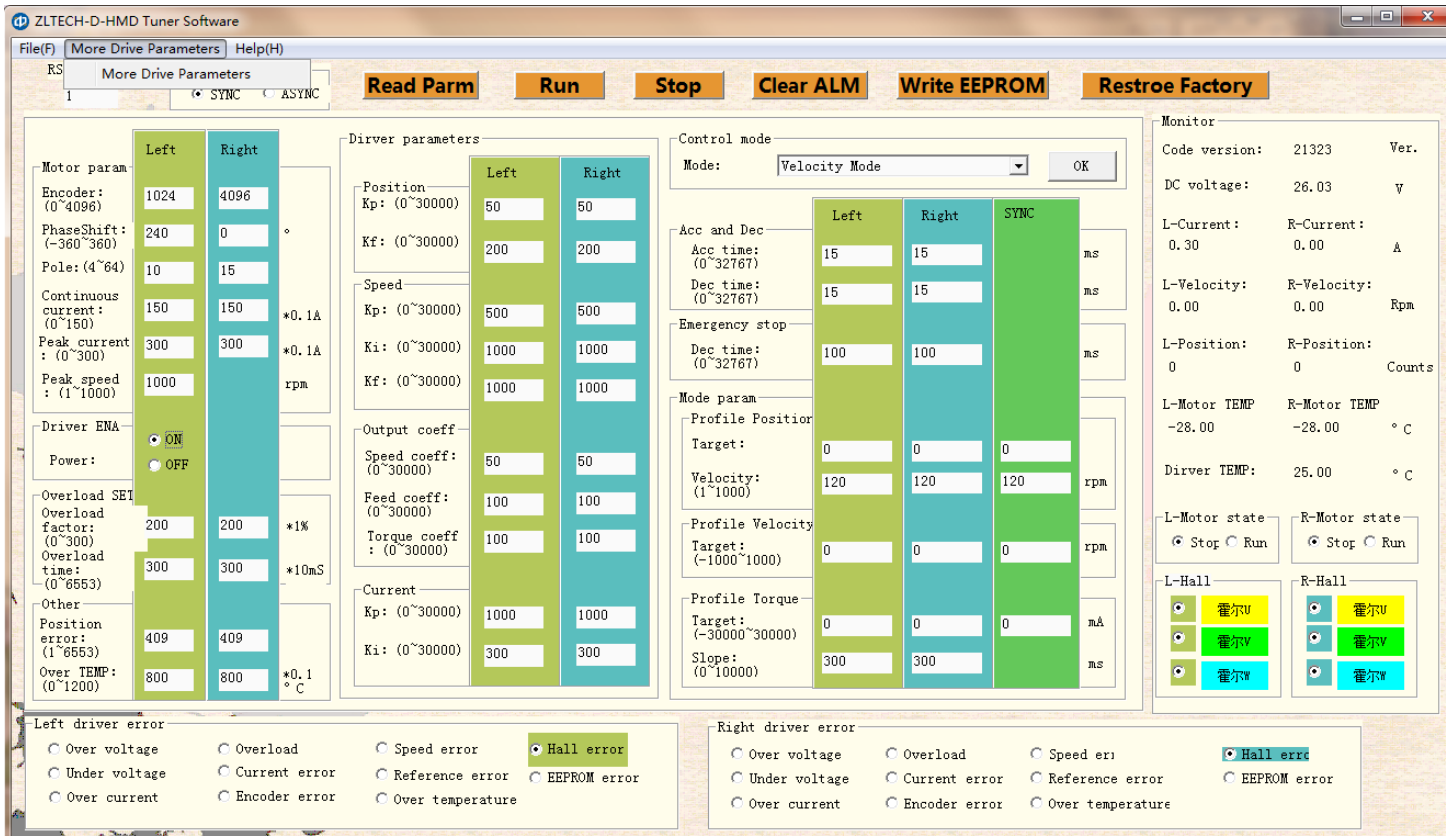
Eg: if the time interval the customer changes instructions is **50ms**, so the acceleration and deceleration time should be set to **25ms**.

4. Note for setting parameters

When setting CAN or RS485 ID, please note:

After filling in CAN or RS485 ID, press Enter → Select CAN or RS485 baud rate value, click

OK → click **Write EEPROM**



ZLTECH-D-HMD Tuner Software

File(F) More Drive Parameters Help(H)

RS More Drive Parameters

1 SYNC ASYNC

Read Parm Run Stop Clear ALM Write EEPROM Restroe Factory

Motor param	Left	Right
Encoder: (0~4096)	1024	4096
PhaseShift: (~360~360)	240	0
Pole: (4~64)	10	15
Continuous current: (0~150)	150	150
Peak current: (0~300)	300	300
Peak speed: (1~1000)	1000	
Driver ENA	ON	
Power:	OFF	
Overload SET		
Overload factor: (0~300)	200	200
Overload time: (0~6553)	300	300
Other		
Position error: (1~6553)	409	409
Over TEMP: (0~1200)	800	800

Dirver parameters

	Left	Right
Position		
Kp: (0~30000)	50	50
Kf: (0~30000)	200	200
Speed		
Kp: (0~30000)	500	500
Ki: (0~30000)	1000	1000
Kf: (0~30000)	1000	1000
Output coeff		
Speed coeff: (0~30000)	50	50
Feed coeff: (0~30000)	100	100
Torque coeff: (0~30000)	100	100
Current		
Kp: (0~30000)	1000	1000
Ki: (0~30000)	300	300

Control mode

Mode: Velocity Mode OK

Acc and Dec

	Left	Right	SYNC	
Acc time: (0~32767)	15	15		ms
Dec time: (0~32767)	15	15		ms
Emergency stop				
Dec time: (0~32767)	100	100		ms

Mode param

Profile Position

	Left	Right	SYNC	
Target:	0	0	0	
Velocity: (1~1000)	120	120	120	rpm

Profile Velocity

	Left	Right	SYNC	
Target: (-1000~1000)	0	0	0	rpm

Profile Torque

	Left	Right	SYNC	
Target: (-30000~30000)	0	0	0	mA
Slope: (0~10000)	300	300		ms

Monitor

Code version: 21323 Ver.

DC voltage: 26.03 V

L-Current: 0.30 A R-Current: 0.00 A

L-Velocity: 0.00 Rpm R-Velocity: 0.00 Rpm

L-Position: 0 Counts R-Position: 0 Counts

L-Motor TEMP: -28.00 °C R-Motor TEMP: -28.00 °C

Dirver TEMP: 25.00 °C

L-Motor state: Stop Run R-Motor state: Stop Run

L-Hall: 霍尔V 霍尔V 霍尔V R-Hall: 霍尔V 霍尔V 霍尔V

Left driver error

Over voltage Under voltage Over current Overload Current error Encoder error Speed error Reference error Over temperature Hall error EEPROM error

Right driver error

Over voltage Under voltage Over current Overload Current error Encoder error Speed error Reference error Over temperature Hall error EEPROM error

More Para Settings

Communication offline time : (0~32767)	0	r/min	Quick stop option code	5: slow down on slow down ramp and stay in
IO-input state : (0~65535)	0		Shutdown option code	1: Slow down with slow down ramp; go to re
IO-output state : (0~65535)	12		Disable operation option code	1: Slow down with slow down ramp; go to sv
Clear feedback position :	0: Invalid		Halt option code	1: slow down on slow down ramp and stay ir
In absolute position mode, clear the current position:	0: Invalid		Input effective level	0: default
Left start speed : (1~300)	1	r/min	X0-Input function selection	9: Emergency
Right start speed : (1~300)	1	r/min	X1-Input function selection	0: undefine
L-Initial speed in position mode : (1~1000)	1	r/min	Output effective level	0: default
R-Initial speed in position mode : (1~1000)	1	r/min	Y0-Output function selection	0: Brake On
			Y1-Output function selection	0: Brake On
			Driver Over TEMP: (0~1200)	0 *0.1°C

CANopen settings
 CAN_ID: (1~127) Baud rate:

RS485 settings
 485_ID: (1~127) Baud rate:

ZLTECH-D-HMD Tuner Software

File(F) More Drive Parameters Help(H)

RS485_ID: 1 SYNC control flag: ☒ SYNC ☐ ASYNC

Motor param		Driver parameters		Control mode			Monitor	
Encoder: (0~4096)	Left: 1024 Right: 4096	Position Kp: (0~30000)	Left: 50 Right: 50	Mode:	Velocity Mode	OK	Code version: 21323 Ver.	
PhaseShift: (-360~360)	Left: 240 Right: 0	Kf: (0~30000)	Left: 200 Right: 200	Acc and Dec	Left: 15 Right: 15 SYNC: 15	ms	DC voltage: 25.97 V	
Pole: (4~64)	Left: 10 Right: 15	Speed Kp: (0~30000)	Left: 500 Right: 500	Acc time: (0~32767)	Left: 15 Right: 15 SYNC: 15	ms	L-Current: -0.60 R-Current: 0.00 A	
Continuous current: (0~150)	Left: 150 Right: 150	Ki: (0~30000)	Left: 1000 Right: 1000	Dec time: (0~32767)	Left: 15 Right: 15 SYNC: 15	ms	L-Velocity: 0.00 R-Velocity: 0.00 Rpm	
Peak current: (0~300)	Left: 300 Right: 300	Kf: (0~30000)	Left: 1000 Right: 1000	Emergency stop	Dec time: (0~32767)	ms	L-Position: 0 R-Position: 0 Counts	
Peak speed: (1~1000)	Left: 1000 Right: 1000	Output coeff		Mode param	Target: 0 0 0		L-Motor TEMP: -28.00 R-Motor TEMP: -28.00 °C	
Driver ENA: <input checked="" type="radio"/> ON <input type="radio"/> OFF		Speed coeff: (0~30000)	Left: 50 Right: 50	Profile Position	Velocity: 120 120 120	rpm	Dirver TEMP: 25.00 °C	
Power: <input type="radio"/> ON <input checked="" type="radio"/> OFF		Feed coeff: (0~30000)	Left: 100 Right: 100	Target: 0 0 0			L-Motor state: <input checked="" type="radio"/> Stop <input type="radio"/> Run	R-Motor state: <input checked="" type="radio"/> Stop <input type="radio"/> Run
Overload SET		Torque coeff: (0~30000)	Left: 100 Right: 100	Profile Velocity	Target: 0 0 0	rpm	L-Hall: <input checked="" type="radio"/> 霍尔V <input type="radio"/> 霍尔V <input type="radio"/> 霍尔V	R-Hall: <input checked="" type="radio"/> 霍尔V <input type="radio"/> 霍尔V <input type="radio"/> 霍尔V
Overload factor: (0~300)	Left: 200 Right: 200	Current Kp: (0~30000)	Left: 1000 Right: 1000	Target: 0 0 0		ms		
Overload time: (0~6553)	Left: 300 Right: 300	Ki: (0~30000)	Left: 300 Right: 300	Slope: 300 300		ms		
Other								
Position error: (1~6553)	Left: 409 Right: 409							
Over TEMP: (0~1200)	Left: 800 Right: 800							

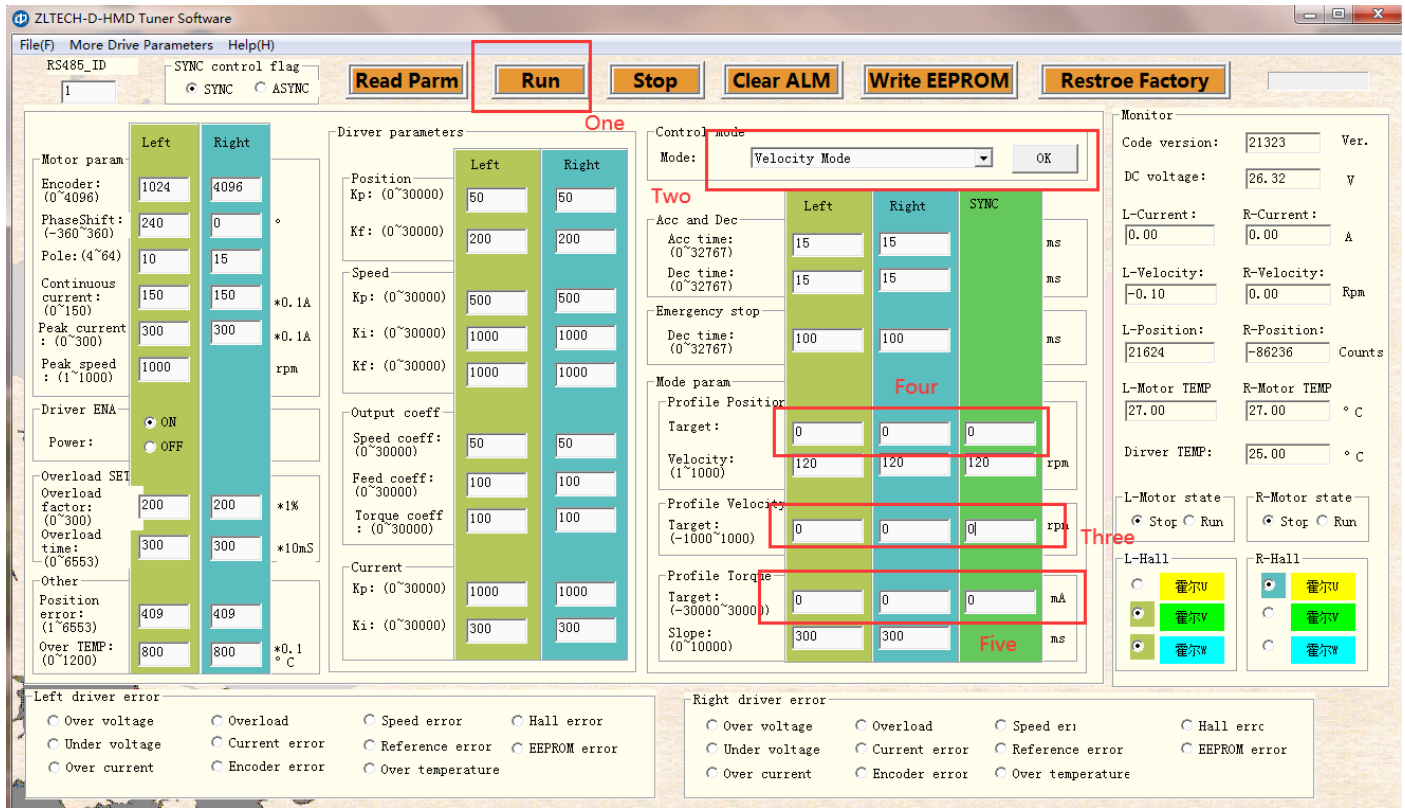
Left driver error

☐ Over voltage ☐ Overload ☐ Speed error ☒ Hall error
☐ Under voltage ☐ Current error ☐ Reference error ☐ EEPROM error
☐ Over current ☐ Encoder error ☐ Over temperature

Right driver error

☐ Over voltage ☐ Overload ☐ Speed error ☒ Hall error
☐ Under voltage ☐ Current error ☐ Reference error ☐ EEPROM error
☐ Over current ☐ Encoder error ☐ Over temperature

5. How to control motor using ZLAC8015(D) software



Please check if the motor parameters are matched with the motor P/N firstly.

- ① Click RUN
- ② Select control mode→click OK (if you need to save control mode, you need to click Write EEPROM→restart power)
- ③ Profile Velocity control mode: fill target velocity→press Enter
- ④ Profile Position control mode: fill target position and velocity→press Enter
- ⑤ Profile Torque control mode: fill target torque and slope→press Enter