

How to connect the SD500 servo drive to the host computer

Note:

The tools you need to prepare:



The wiring is as follows:





You need to find the pins corresponding to 485+, 485- in the cn6 segment and connect the wire corresponding to 485+ to T/R+ of usb to 485 and the wire corresponding to 485- to T/R- of usb to 485, and the functions of the pins

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of cn6 are as follows:



CN6 network port terminal pin definition:

CN6A / CN6B i	CN6A / CN6B interface definition									
Pin number	Signal name	Features		Pin number	Signal name	Features				
1	GND	Signal ground		6	-	-				
2	-	-		7	485-	485 data -				
3	GND	Signal ground		8	485+	485 data +				
4	+5V	External keyboard		shell	shield	shield				
5	+5V	power								

Step 1: Determine whether the driver of the device manager is successfully installed, the following driver has been successfully installed.



If not successfully installed, you can go to update the driver or use the driver software to update, generally speaking, click the right button, you can see the update driver, check to the manufacturer driver to update.





Action View Help		
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Microsoft Wi-Fi Direct Virtual	Adapter #2	
Realtek PCIe GbE Family Cont	roller	
Realtek RTL8852AE WiFi 6 802	11ax PCIe Adapter	
WAN Miniport (KEv2)		
WAN Miniport (P)		
WAN Miniport (Pv6)		
WAN Miniport (L2TP)		
WAN Miniport (Network Mon	nitor)	
WAN Miniport (PPPOE)		
WAN Miniport (PPTP)		
WAN Miniport (SSTP)		
Ports (COM & LPT)		
Silicon Labs CP210xLISB to U/	DT Beides (COMP)	
Print queues	Update driver	
Processors	Disable device	
Security devices	Uninstall device	
SIMATIC NET		
Software devices	Scan for hardware changes	
Sound, video and game controlle	Properties	
 Storage controllers 		
System devices		
Universal Serial Bus controllers		
 		
9 058 建接路管理器		
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Step 2: Open the inverter software , then choose the SD500 and create a new project of the relevant model



Step 3: Determine the local address, baud rate, and data format of the drive by the keyboard. The parameters for the SD500 are shown below:



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Step 4: Set F11.30=1 by the keyboard.

Step 5: Since the com port of the device manager is com3, the local address of the drive is 1, the data format is N-8-1, and the baud rate is 9600



Step 6: Power on the SD500 servo drive, click on the parameter setting to enter the parameter

munication configuration Con	nmunication discreted Parameter settin	ps Real-time mi	nitoring	Osciloscope Accident	details Motor	self-learning Pu	nction code imp	port Screenshots Exi	U system	
tion group selection	Read current page Read all pages Write		<u>ٿ</u>			Ontions				Function code comment
mon parameters Monitoring parameters	Dupition code name	current usine	unit	default value	minusha	maximality	addrare	attributer		
Fault monitoring parameter	F11.13 Read the function code of the cur	rent page	-	0002	0x0000	QxFFFF	0x0800	Set at any time		
Spindle feedback monitorin	P11.14 The first line of the keyboar	0011		0011	0x0000	OxTETT	0x080E	Set at any time		
Environmental application	F11.15 The second line of the keyb	0002		0002	Cx60000	0xFFFF	0x0B0F	Set at any time		
asic command	F11.16 The second line of the keyb	0004		0004	0x0000	OxFFFF	0x0810	Set at any time		
lotor 1 parameter group	F11.17 The second line of the keyb	0010		0010	0x0000	0xffff	0x0811	Set at any time		
/F control group	F11.18 The second line of the keyb	0012		0012	0x0000	OxFFFF	0x0812	Set at any time		
put terminal (X,AI,PUL)	F11.20 Keyboard display item settin	0002		0000	0x0000	Oxffff	0x0814	Set at any time		
utput terminal parameter	F11.21 Speed display coefficient	100.0	%	100.0	0.0	500.0	0x0815	Set at any time		
piliary control 1	F11.22 Power display coefficient	100.0	%	100.0	0.0	500.0	0x0816	Set at any time		
otection parameter group	F11.23 Monitor parameter group dis	0020	•	0000	0x0000	0xffff	0x0017	Set at any time		
serator parameter group	F11.24 C00.29 PG feedback monito	0:Whole p *		0	0	65535	0x0818	Set at any time		
mmunication control fun	F11.25 Display selection during mot	0:Show se *	v	0	0	65535	0x0619	Set at any time		
Iti-stage speed and simp	F11.26 EEPROM fault output selection	O:Pault E.E *	v	0	0	65535	0x081A	Set at any time		
4 Spindle special function par ferent parameters	F11.30 Serial port function selection	0:RS485 *	v	0	0	65535	0x0818	Set at any time		
	F11.31 Keyboard point device lower	0.50	v	0.50	0.00	65535.00	0x081F	Set at any time		
	F11.32 Keyboard point device lower	0.00	%	0.00	0.00	65535.00	0x0820	Set at any time		
	F11.33 Upper limit vokage of keybo	2-80	v	2.00	0.00	65535-00	0x0521	Set at any time		
	F11.34 Upper limit value of keyboar	100.00	%	100.00	0.00	65535.00	0x0822	Set at any time		
	Current total: 29 Total difference	s: 4 Cor	nmunicat	ion abnormal: 0					×	
023 3:48:25 PM Read function 023 3:48:25 PM Read function 023 3:48:25 PM Read function 023 3:48:25 PM Read function 023 3:46:25 PM Read function	code(F12.61 Reserved): 0001 code(F12.62 Reserved): 6 code(F12.62 Reserved): 0 code(F12.65 Reserved): 0 code(F12.65 Reserved): 0 code(F12.65 Reserved): 0									

Step 7: Click to read the parameters, the parameters are read successfully

nction group selection mmon parameters	Rei	ad current page Read all pages Vrite	Current page	Export	Import Open Comp	are Find Sav	Options			_	Function code comment
0 Monitoring parameters		Function code name	current val	ue unit	default value	min value	max value	address	attributes	^	
1 Fault monitoring parameter 4 Spindle foodback monitorin	\checkmark	F00.00 Parameter access level		•	0	0	8	0x0000	set at any time		
5 Position control monitoring	~	F00.01 Use selection	0:General	۰.	0	0	8	0×0001	set at any time		
0 Environmental application	~	F00.03 Initialization	O:No initia	۰.	0	0	65535	0x0003	Set at any time		
Basic command	~	F00.04 Keyboard parameter copy	0:No funct	۰.	0	0	65535	0x0004	Set at any time		
Motor vector control group	~	F00.05 User password	0000		0	0x0000	0×10000	0x0005	Set at any time		
V/F control group	~	F00.07 Free parameter 1	0	-	0	0	65535	0x0007	Set at any time		
Input terminal (X,AI,PUL)	~	F00.08 Free parameter 2	0		0	0	65535	0x0008	Set at any time		
Output terminal parameter	~	F00.10 Common parameter 1 addr	0100		0000	0x0000	0xFFFF	0x000A	set at any time		
Auxiliary control 1	~	F00.11 Common parameter 2 addr	0101		0000	0x0000	OxFFFF	0x0008	set at any time		
Protection parameter group	~	F00.12 Common parameter 3 addr	0102		0001	0x0000	0xFFFF	0x000C	set at any time		
Operator parameter group	~	F00.13 Common parameter 4 addr	0710		0002	0x0000	OxFFFF	0x000D	set at any time		
Process PID control parame	~	F00.14 Common parameter 5 addr	0122		0011	0x0000	OxFFFF	0x000E	set at any time		
Multi-stage speed and simp	~	F00.15 Common parameter 6 addr	0123		0002	0x0000	0×FFFF	0x000F	set at any time		
Spindle special function par	~	F00.16 Common parameter 7 addr	0110		0004	0x0000	0×FFFF	0x0010	set at any time		
erent parameters	~	F00.17 Common parameter 8 addr	0112		0010	0x0000	0×FFFF	0x0011	set at any time		
	~	F00.18 Common parameter 9 addr	0140		0012	0x0000	0xFFFF	0x0012	set at any time		
	~	F00.19 Common parameter 10 add	0730		0012	0x0000	0xFFFF	0x0013	set at any time		
	~	F00.20 Common parameter 11 add	0201		0000	0x0000	OxFFFF	0x0014	set at any time		
	~	F00.21 Common parameter 12 add	0202		0000	0x0000	OxFEFE	0x0015	set at any time	~	
	0	Current total: 38 Total difference	is: 31	Communie	cation abnormal: 0						
4/2023 4:06:09 PM Read function		(F24.37 Reserved): 0									
/2023 4:06:09 PM Read function	n code	(F24.38 Rserved): 0									
V2023 4:06:09 PM Read function V2023 4:06:09 PM Read function	n code n code	(F24.40 Swing angle): 45.0									
V2023 4:06:09 PM Read function	n code	(F24.41 Swing speed): 2.00									

