

# OK2D86BH Closed Loop Driver Instructions



#### Features:

It can drive NEMA 34 closed-loop stepper motors without complex

parameter adjustment. The motor will be automatically matched after

power-on.

Voltage input range: 18~70 VAC, 24-100VDC

Maximum peak current: 6A

Microstep (Steps/rev.) : 400~51200

Signal input: differential/single-ended, pulse/directional or dual pulse,

Compatible with signal level 5~24V.

Optically isolated signal input, strong anti-interference ability;



Max. Pulse Input (KHZ): 200KHz

Closed-loop vector control ensures that the motor outputs high speed

and high torque while ensuring that the motor does not lose steps.

Variable current control, automatically outputs matching current

according to load and speed, greatly reducing motor heating.

Ultra-low vibration and noise;

With overvoltage, overcurrent, position following error and other protection functions;

 $\equiv$  · Electrical Specification

#### 1. Specification

Parameters	BH86			
	Min	Typical	Max	Unit
Output Peak Current	-	-	8.2	A
Input Voltage	24	48	100	VDC
Logic Signal Current	7	10	20	MA
Pulse input frequency	-	300	-	KHZ
Isolation resistance	500			ΜΩ

2. Operating Environment and other Specifications



Cooling	Natural Cooling or Forced cooling		
Operating	Environment	Avoid dust, oil fog and corrosive	
Environment		gases	
	Storage Temperature	-20%~+80°C	
	Ambient Temperature	0°C - 70°C	
	Humidity	<80%RH, No-condensing and	
		No-frost	
Vibration	-	5.9m/s²,Max	
Weight	-	0.58kg	

### 3. Power and Motor Connector

PIN	Name	Description	Instruction
1	A +	Motor Phase A+	If the initial direction of the motor is opposite to
			what is required, you can set SW5.
2	A -	Motor Phase A-	
З	B +	Motor Phase B+	
4	В -	Motor Phase B-	
5	AC	Input AC power	18V~ 70VAC
6	AC	AC voltage	Direct current does not need to be divided into
			positive and negative poles



4. Encoder signal input port

Pin	Name	Description	Instruction
1	EB +	Encoder channel B+	
		input	
2	EB -	Encoder channel B-	
		input	
3	EA +	Encoder channel A+	
		input	
4	EA -	Encoder channel A-	
		input	
5	VCC	Encoder power supply +5V	
6	EGND	Signal ground 0V	

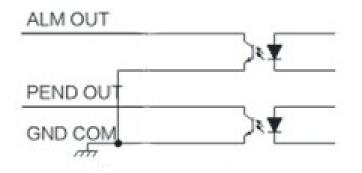
## 5. Control Signal Port

Name	Instruction
PUL +	Pulse input signal:
	Pulse Signal: In single pulse (pulse/direction) mode, this input represents pulse
PUL -	signal, each rising or falling edge active (software configurable, see Closed-loop



	Stepper software manual for more detail); In double pulse mode (software			
	configurable), this input represents clockwise (CW) pulse, active both at high level			
	and low level. The width of PUL signal is at least 1.2 $\mu s.$ 5-24V when PUL-HIGH,			
	0-0.5V when PUL-LOW. In Double pulse mode : CW			
DIR +	DIR signal: In single-pulse mode, this signal has low/high voltage levels,			
	representing two directions of motor rotation; In CW/CCW mode, this signal			
	is-counter-clock (CCW) pulse. For reliable motion response, DIR signal should be			
	ahead of PUL signal by 5us at least. 5-24V when DIR-HIGH, 0-0.5V when			
DIR -	DIR-LOW. Please note that rotation direction is also related to motor-driver			
	wiring match. Exchanging the connection of two wires for a coil to the driver will			
	reverse motion direction.			
ENA +	Enablesignal: This signal is used for enabling/disabling the drive. High level (NPN			
	control signal, PNP and differential control signals are on the contrary, namely			
	low level for enabling.)			
ENA -	For anabling the drive and low level for disabling the drive. Liquelly left			
	For enabling the drive and low level for disabling the drive. Usually left			
	UNCONNECTED			
Pend +	The in-position signal output is in the form of open collector.			
Pend -				
ALM +	The fault signal output is in the form of open collector.			
ALM -				







6. DIP Switch Settings

The driver uses a six-digit DIP switch to set the subdivision and motor rotation

direction. The detailed description is as follows:

Steps/rev	SW1	SW2	SW3	SW4
Default	on	on	on	on
800	off	on	on	on
1600	on	off	on	on
3200	off	off	on	on
6400	on	on	off	on
12800	off	on	off	on
25600	on	off	off	on
51200	off	off	off	on
1000	on	on	on	off
2000	off	on	on	off
4000	on	off	on	off

6.Microstep Setting:



5000	off	off	on	off
8000	on	on	off	off
10000	off	on	off	off
20000	on	off	off	off
40000	off	off	off	off

SW5:Motor DIR Initialize running direction, ,off=CC clockwise (Positive

direction) ,on=CW Counterclockwise (Reverse direction)

SW6:off; Standard mode on; Start acceleration assist (Not applicable to arc interpolation

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SW7	SW8	Motor Frame Size(mm)
on	on	Frame Size (60 x 60)
off	on	Frame Size (86-80), (86-118)
on	off	Frame Size (86-151)
off	off	Frame Size (86 x 86) open loop, current
		6.0A

7. Mechanical Specifications: (unit: mm [1inch=25.4mm])



