

---

## Table of Content

<b>1. Introduction</b> .....	1
1.1 Features.....	1
1.2 Applications.....	1
<b>2. Specifications</b> .....	2
2.1 Electrical Specifications.....	2
2.2 Environment.....	2
2.3 Mechanical Specifications.....	3
2.4 Heat Dissipation.....	3
3.1 Connector P1 – Control and Digital Output Connections.....	4
3.1.1 Pin Assignments of P1.....	4
3.1.2 Typical Control and Fault Output Connections.....	6
3.2 Connector P2 - Encoder Connection.....	7
3.3 Connector P3 - Motor Connection.....	7
3.4 Connector P4 – Power Supply Connection.....	7
3.5 Connector P5 – RS232 Connection.....	7
3.6 LED Light Indication.....	8
<b>4. Motor Selection</b> .....	8
<b>5. Power Supply Selection</b> .....	8
5.1 Regulated or Unregulated Power Supply.....	9
5.2 Power Supply Sharing.....	9
5.3 Selecting Supply Voltage.....	9
<b>6. DIP Switch Configurations</b> .....	9
6.1 Microstep Resolution (SW1-SW4).....	10
6.2 Other DIP Switch Settings (SW5-SW8).....	10
<b>7. Typical Connection</b> .....	11

---

<b>8. Sequence Chart of Control Signals</b> .....	11
<b>9. Fault Protections</b> .....	12
<b>10. Software Configuration</b> .....	13
<b>11. Accessories</b> .....	13
<b>12. Troubleshooting</b> .....	14

---

## 1. Introduction

KL-5080D4 is a closed loop stepper drive designed to solve the loss of step problem in open loop stepper control systems, thus increase system reliability at minimal cost increase. It implements advanced control algorithm of Leadshine based on its tens of years' experience in stepper and servo controls. The KL-5080D4 is highly reliable and affordable and performs excellent in many industrial applications such as CNC, medical, electronics, packaging...

The KL-5080D4 can power 2-phase NEMA 14, 17, 23, and 24 stepper motors with incremental encoders. Compared with traditional open loop stepper systems, a KL-5080D4 adopted closed loop step system can eliminate potential loss of step, make real-time position error correction, and do not need torque reservation (100% torque implementation). Also it can power the driven stepper motor with reduced heating, lower noise, low vibration...

### 1.1 Features

- No loss of step
- No torque reservation
- No hunting or overshooting
- No tuning for easy setup
- A configurable digital output for the option of Fault Output, In Position, or Brake Control
- Low noise and vibration, smooth motion
- Enhance performance at low speed application( <60RPM)
- 20-50VDC supply voltage, max 8A output current
- Max 200 KHz input frequency
- 15 micro step settings of 800-51,200 via DIP switches, or 200-51,200 via software (increase by 200)
- Protections for over voltage, over current and position following error

### 1.2 Applications

When a KL-5080D4 closed loop stepper drive is implemented with a compatible stepper motor with encoder, the closed stepper system can be adopted in many small to median speed applications such as CNC routers, CNC mills, CNC laser cutters, CNC plasma, lab automation instruments, plotters, medical equipment, electronic equipment, small packaging machines, etc.

## 2. Specifications

### 2.1 Electrical Specifications

Parameters	Min	Typical	Max	Unit
Output Current	0.5	-	8.0(Peak)	A
Operating Voltage	20	24, 36, 48	50	VDC
Logic signal current	7	10	16	mA
Pulse input frequency	0	-	200	kHz
Minimal pulse width	2.5	-	-	μS
Minimal direction setup	5.0	-	-	μS
Isolation resistance	500			MΩ

### 2.2 Environment

Cooling	Natural Cooling or Forced Cooling	
Operating Environment	Environment	Avoid dust, oil fog and corrosive gases
	Ambient Temperature	0°C — 65°C (32°F - 149°F)
	Humidity	40%RH—90%RH
	Operating Temperature	0°C — 50°C (32°F - 122°F)
	Vibration	10-50Hz / 0.15mm
Storage Temperature	-20°C — 65°C (-4°F - 149°F)	
Weight	Approx. 280 g (9.9 Oz)	

---

## 2.3 Mechanical Specifications

(unit: mm [1inch=25.4mm])

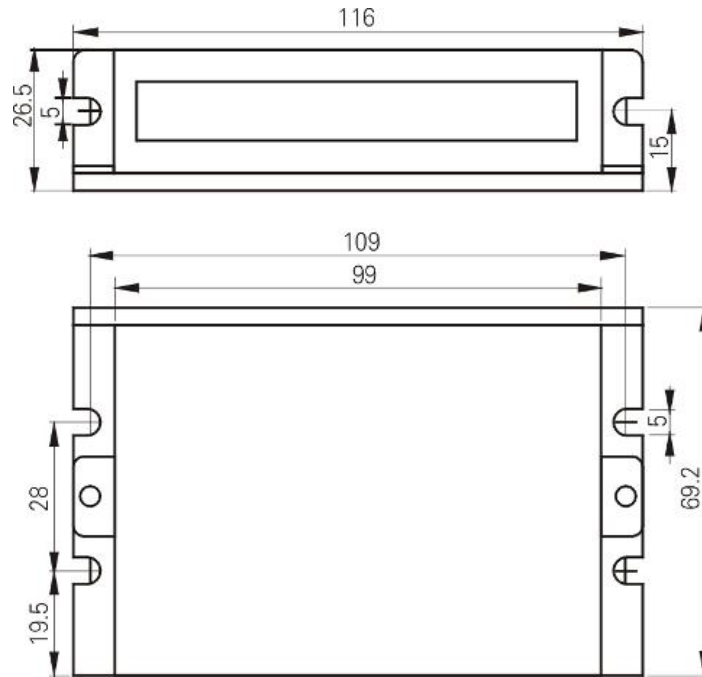


Figure 1: Mechanical specifications

## 2.4 Heat Dissipation

- KL-5080D4 reliable working temperature should be no more than 60°C (140°F)
- It is recommended to mount the drive vertically to maximize heat dissipation. Mount a cooling fan nearby if necessary.
- If multiple KL-5080D4 drives are installed, it is suggested to keep a minimal 30mm (1.2 inches) between two of them.

---

### 3. Connections and LED Indication

A KL-5080D4 closed loop stepper drive has 5 connection blocks from P1 to P5 (see figure 2).

#### 3.1 Connector P1 – Control and Digital Output Connections

##### 3.1.1 Pin Assignments of P1

The P1 connector in Figure 2 contains connections for control signals and a configurable digital output.

##### a) Pinout Definitions

There are 3 control signals for pulse, direction, and enable. See the following table for details.

Pin Name	I/O	Details
PUL+	I	<u>Pulse signal:</u> <b>(1)</b> . In single pulse (pulse & direction) control mode, this input represents pulse signal. A pulse signal is active at the rising or falling voltage edge (set by DIP switch SW8).
PUL-	I	<b>(2)</b> . In double-pulse (CW/CCW) control mode (set by DIP switch SW7), this signal input represents clockwise (CW) pulse, and is active at both high voltage level and low voltage level. <b>(3)</b> . 4.5-5V for voltage HIGH, 0-0.5V for voltage LOW (same for DIR and ENA signals). <b>(4)</b> . Pulse width should be set to 2.5 $\mu$ s or longer.
DIR+	I	<u>Direction signal:</u> <b>(1)</b> . In single pulse (step & direction) control mode, this signal's low and high voltage levels represent the two directions of motor rotation (e.g. clockwise and counterclockwise). <b>(2)</b> . In double-pulse (CW & CCW) control mode, this signal represents counterclockwise (CCW) rotation. It is active at both voltage high level and low level. <b>(3)</b> .
DIR-	I	

		Minimal DIR signal setup time should be at least 5 $\mu$ s. <b>(4)</b> . You can reverse the default rotation direction by toggling the SW5 DIP switch.
ENA+	I	<u>Enable signal</u> : This signal is used for enabling/disabling the drive. High voltage level of 4.5-5VDC (NPN control signal) for enabling the drive and low voltage level of 0-0.5VDC for disabling the drive. PNP and Differential control signals are on the contrary, namely Low level for enabling. By default this signal is left <b>UNCONNECTED &amp; ENABLED</b> .
ENA-	I	
ALM+	O	<u>Configurable Digital Output Signal</u> : A configurable OC output signal. It takes a sinking or sourcing 20mA current at 5-24V. It can be configured as one of the 3 types, <i>ALARM</i> (default), <i>IN POSITION</i> , or <i>BRAKE CONTROL</i> .
ALM-	O	

**Notes:** (1) Shielding control signal wires is suggested; (2) to avoid/reduce interference, don't tie control signal cables and power wires together.

**b) Fault Output, In Position, or Brake control Output Configuration**

The digital output on the P1 connector, marked as ALM+ & ALM-, is software configurable. It can be configured as one of the available 3 options - Fault Output”, “In Position”, and “Brake Control”. Read KL-5080D4 closed loop software manual for how to configure this output.

- Fault Output

FAULT output is the default configuration. This output signals a fault condition including over-voltage, over-current, or position following error. This output can be used to drive devices such as a relay, a LED, etc.; or as an input signal to electronic devices like a PLC.

For example, in a multi-axis system like a CNC machine when one of the axes fails such a fault output signal can be feedback to the motion controller for a followed action (e.g., auto machine shutdown, auto error clearing, etc.).

- In Position

Use software to configure this output as an IN POSITION output. In this case, an output signal can be sent out when the targeted position is in the “Target” range (see *parameter Distance to Send "In position" Output Signal* in software manual) to external devices such as relays, motion controllers, PLCs, IO boards, etc.

- Brake Control

Use software to configure this output as a BRAKE CONTROL output. In this case,

this signal can be used for automatic brake control while system power failure. It is recommended to connect a fly-wheel diode in parallel to a 24VDC relay and brake coil connection. Refer to the following figure for brake connection.

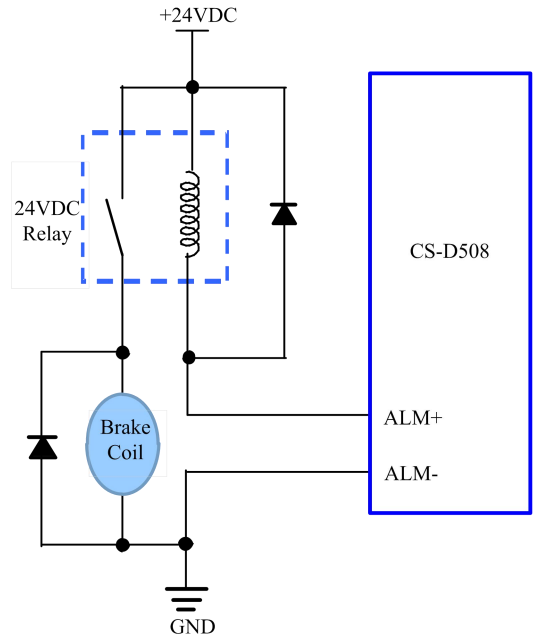


Figure 3: Brake Output Connection

### 3.1.2 Typical Control and Fault Output Connections

The KL-5080D4 can accept differential and single-ended control signal inputs (open-collector and PNP output). A KL-5080D4 has 3 optically isolated control inputs, PUL, DIR, and ENA. Refer to the following two figures for connections of open-collector and PNP signals.

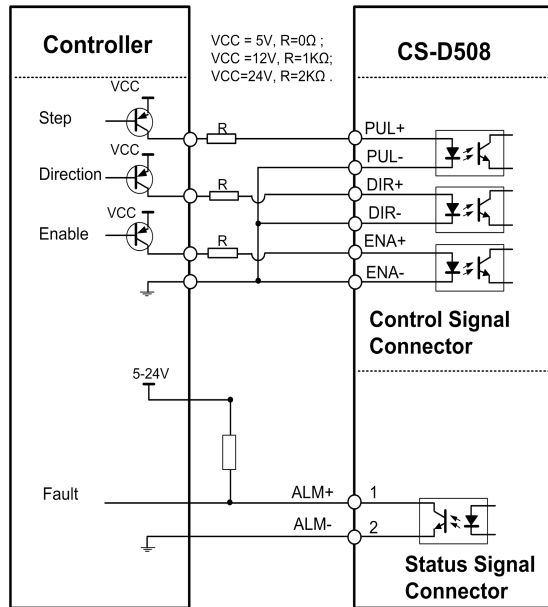


Figure 4: Connections to PNP signal

(Common-cathode)

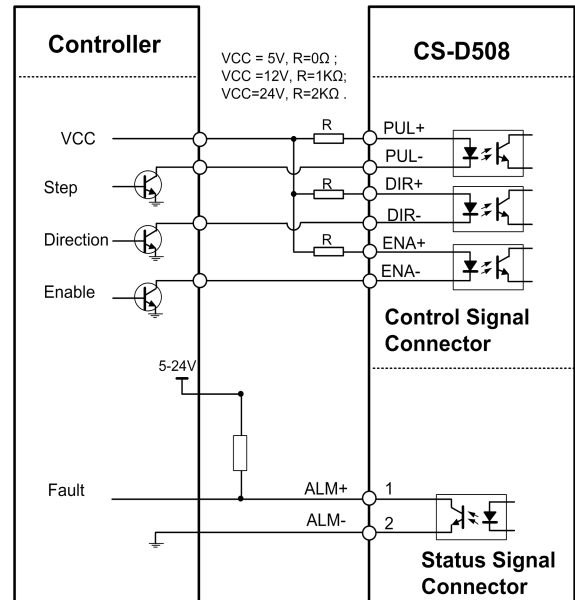


Figure 5: Connections to open-collector signal

(Common-anode)



---

### 3.2 Connector P2 - Encoder Connection

The P2 connector in Figure 2 is for encoder signal connection. Refer to the following table for details.

Drive Pin Name	Description
EB+	Encoder B+ input connection
EB-	Encoder B- input connection
EA+	Encoder A+ input connection
EA-	Encoder A- input connection
VCC	Encoder +5V voltage output connection
EGND	Power ground connection

### 3.3 Connector P3 - Motor Connection

The P3 connector in Figure 2 is for motor connection. Refer to the following table for details.

Pin Name	Details
A+	Stepper motor A+ connection. Connect motor A+ wire to this pin
A-	Stepper motor A- connection. Connect motor A- wire to this pin
B+	Stepper motor B+ connection. Connect motor B+ wire to this pin
B-	Stepper motor B- connection. Connect motor B- wire to this pin

### 3.4 Connector P4 – Power Supply Connection

The P4 connector in Figure 2 is for power supply connection. Refer to the following table for details.

Pin Name	Details
+Vdc	Power supply positive connection. 20-50VDC power supply voltage
GND	Power supply ground connection.

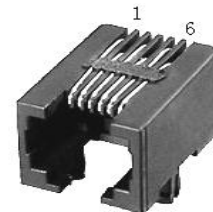
**Notes:** see [Appendix B for compatible Leadshine power supplies](#)

### 3.5 Connector P5 – RS232 Connection

The P5 connector in Figure 2 is a RS232 communication port for PC connection. Refer to the following pin definitions.

## RS232 Communication Port – RJ11

Pin	Name	I/O	Description
1	NC	-	Not connected.
2	+5V	O	+5V power output.
3	TxD	O	RS232 transmit.
4	GND	GND	Ground.
5	RxD	I	RS232 receive.
6	NC	-	Not connected.



**Notes:** RS232 connection of CS-D508 is for tuning purpose only, not for RS232 command controls.

### 3.6 LED Light Indication

There are two LED lights for KL-5080D4, one red and one green. The GREEN one is the power indicator which will be always on generally. The RED one is a protection indicator. It is off always when a KL-5080D4 operates normally, but will flash 1, 2 or 7 times in a 5-second period when error protection is enabled. Different number of flashes indicates different protection type (read Section 9).

## 4. Motor Selection

The KL-5080D4 is designed to power 2-phase (or 4-phase 0.9 degree) NEMA 17/23/24 stepper motors under 10000-line incremental encoders (recommend 1000-line). Leadshine offers many high performance stepper motors compatible with the KL-5080D4 which you can find in the Appendix A of this document. The KL-5080D4 can also power similar stepper motors with incremental encoders from third-party suppliers.

**Notes:** Contact with Leadshine for stepper motor with 2000-line, 2500-line, 5000-line encoders.

## 5. Power Supply Selection

The KL-5080D4 can power small and medium size closed loop stepper motors (frame size from NEMA17 to 24) from Leadshine (see Appendix A) or other motor manufacturers. To get good system performance, it is important to select proper supply voltage and output current. Generally speaking, supply voltage determines the high speed performance of the motor, while output current determines the output torque of the driven motor (particularly at lower speed). Higher supply voltage will allow higher motor speed to be achieved, at the price of more noise and heating. If the motion speed requirement is low, it's better to use lower supply voltage to decrease noise, heating and improve reliability.

**Notes:** See Appendix B at the end of this document for KL-5080D4 compatible switching power supplies specially designed for stepper & servo controls.

---

## 5.1 Regulated or Unregulated Power Supply

Both regulated and unregulated power supplies can be used to supply the drive. However, unregulated power supplies are preferred due to their ability to withstand current surge and fast response for current change. If you prefer to a regulated power supply, it is suggested to choose such a power supply specially designed for stepper/servo controls such as Leadshine RPS series (<http://www.leadshine.com/producttypes.aspx?producttype=regulated-switching>). Or, in the case when only normal switching power supplies are available, it is important to use “OVERSIZE” high current output rating power supplies (for example, using a 4A power supply for 3A stepper motor) to avoid problems such as current clamp. On the other hand, if unregulated supply is used, one may use a power supply of lower current rating than that of motor (typically 50%-70% of motor current). The reason is that the drive draws current from the power supply capacitor of the unregulated supply only during the ON duration of the PWM cycle, but not during the OFF duration. Therefore, the average current withdrawn from power supply is considerably less than motor current. For example, two 3A motors can be well supplied by one power supply of 4A rating.

## 5.2 Power Supply Sharing

Multiple KL-5080D4 drives can share one power supply to save space and reduce cost, if that power supply has enough power capacity. To avoid cross interference, connect each stepper drive directly to the shared power supply separately. To avoid cross interference, DO NOT daisy-chain connect the power supply input pins of the Drivers. Instead connect them to power supply separately.

## 5.3 Selecting Supply Voltage

The KL-5080D4 is designed to operate within 20-50VDC voltage input. When selecting a power supply, besides voltage from the power supply power line voltage fluctuation and back EMF voltage generated during motor deceleration needs also to be taken into account. Ideally it is suggested to use a power supply with the output of 20-48VDC, leaving room for power line voltage fluctuation and back-EMF.

Higher supply voltage can increase motor torque at higher speeds, thus helpful for avoiding losing steps. However, higher voltage may cause bigger motor vibration at lower speed, and it may also cause over-voltage protection or even drive damage. Therefore, it is suggested to choose only sufficiently high supply voltage for intended applications.

## 6. DIP Switch Configurations

The KL-5080D4 has a built-in 8-bit DIP switch to set microstep resolution, motor direction, auto tuning switch and so on.

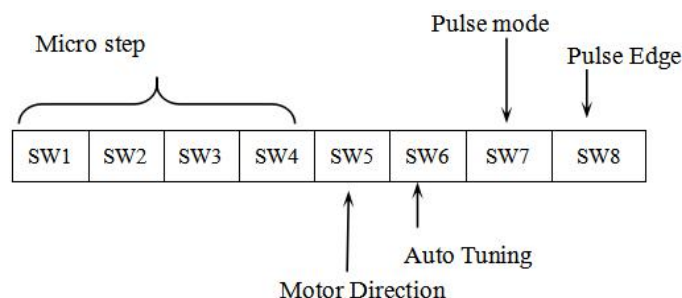


Figure 6 DIP switch Setting

### 6.1 Microstep Resolution (SW1-SW4)

Microstep resolution is set by SW1, 2, 3, 4 of the DIP switches as shown in the following table:

Steps/Revolution	SW1	SW2	SW3	SW4
Software Configured (Defaulted to 1600)	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
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

### 6.2 Other DIP Switch Settings (SW5-SW8)

	Function	On	Off
SW5	Default Direction	CW (clockwise)	CCW (counterclockwise)
SW6	Auto Tuning	No	Yes

<b>SW7</b>	Pulse Model	CW/CCW (double pulse)	PUL/DIR (single pulse)
<b>SW8</b>	Pulse Edge	Falling	Rising

## 7. Typical Connection

A complete closed loop stepper system should include a stepper motor with encoder, KL-5080D4 drive, power supply and controller (pulse generator). A typical connection is illustrated in figure 6.

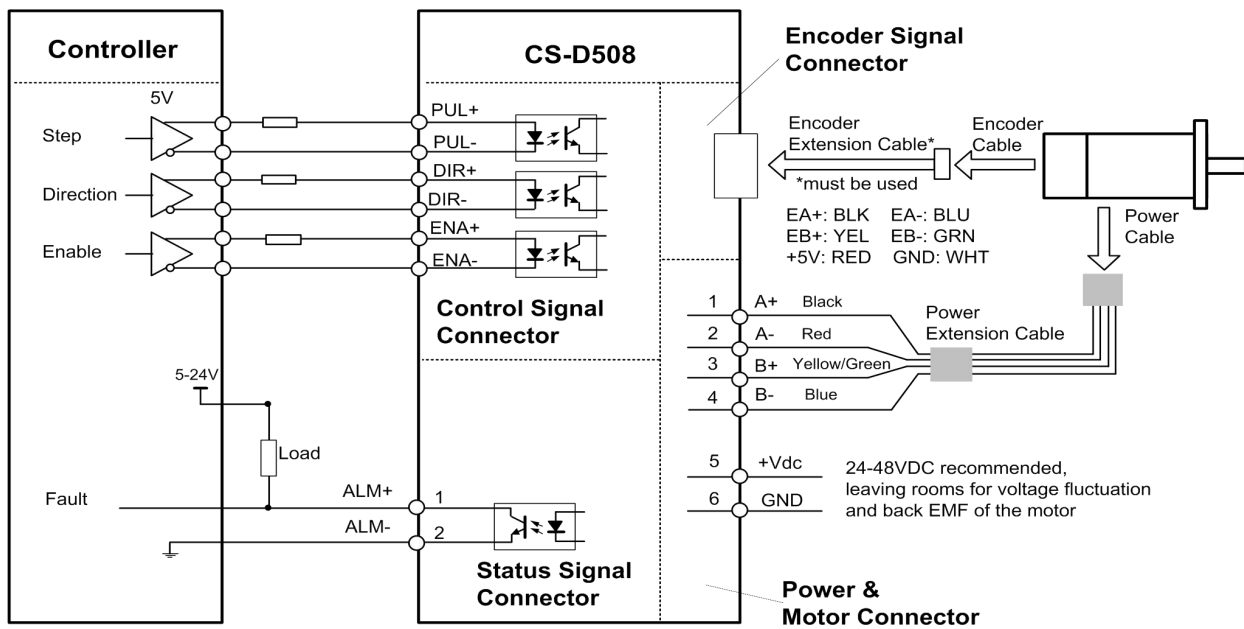


Figure 7: Typical connection

## 8. Sequence Chart of Control Signals

In order to avoid some fault operations and deviations, PUL, DIR and ENA should abide by some rules, shown as following diagram:

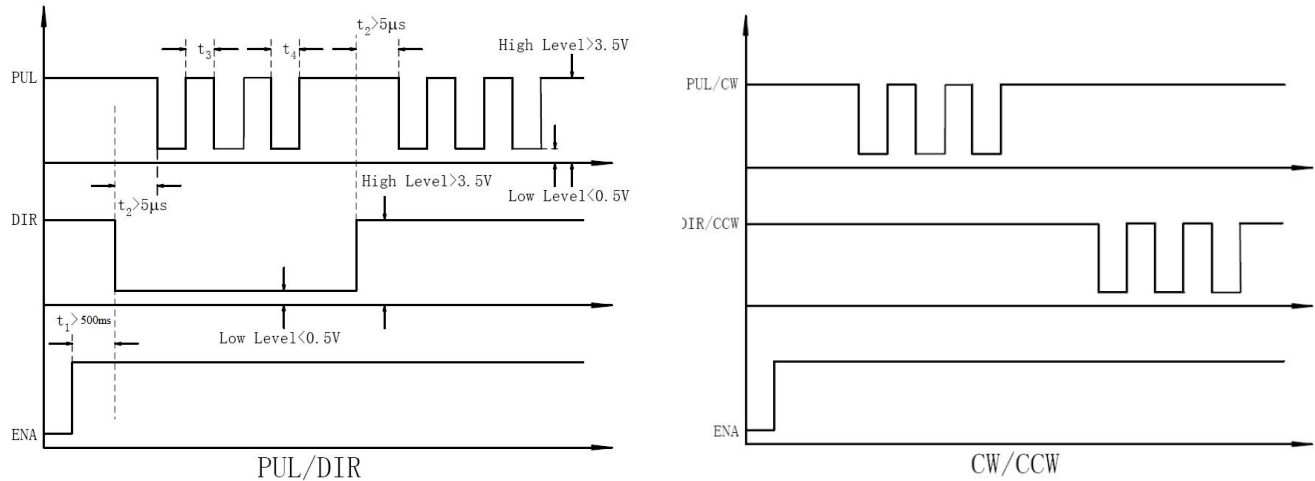


Figure 8: Sequence chart of control signals




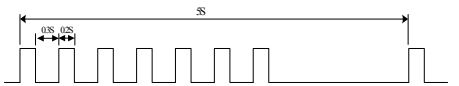
**Remark:**

- a) t1: ENA must be ahead of DIR by at least 500ms. Usually, ENA+ and ENA- are NC (not connected). See “Connector P1 Configurations” for more information.
- b) t2: DIR must be ahead of PUL effective edge by 5μs to ensure correct direction;
- c) t3: Pulse width not less than 2.5μs;
- d) t4: Low level width not less than 2.5μs.

**9. Fault Protections**

To improve reliability, the drive incorporates some built-in protection features.

Blink time(s)	Sequence wave of red LED	Description	Trouble shooting
1		Over-current	Turn off the power immediately. a) Check wiring is short-circuited or not; b) Check motor is short-circuited or not.
2		Over-voltage	Turn off the power immediately. a) Check if the power voltage is higher than 90VDC
3		Chip error	Restart the power supply, if the drive is still alarm, please contact after-sale

4		Fail to lock motor shaft	a) The drive is not connected to a motor; b) If alarm is occurred when connect a motor , set DIP switch SW6 to 'on' and restart power supply; If it still alarm, please check the motor power cable.
5		EEPROM error	Restart the power supply, if the drive is still alarm, please contact after-sale
6		Fail to auto tuning	Set DIP switch SW6 to 'on'
7		Position following error	a) The value of position following error is set too small; b) Motor torque is not enough or motor speed is too high; c) Motor wiring error, check wiring
Always	-	PCB board is burned out	Contact after-sale a) Power supply connection is wrong

When above protections are active, the motor shaft will be free or the red LED blinks. Reset the drive by repowering it to make it function properly after removing above problems.

## 10. Software Configuration

The KL-5080D4 is designed for simple setup and implementation. For most applications no software configuration or tuning is needed especially when driving Leadshine stepper motors with encoders (see Appendix A). If you want to do fine tuning or custom configurations such as micro-step, current percentage change..., you can use Leadshine's free ProTuner software to make the changes.

## 11. Accessories

If you plan to use the ProTuner software, contact your supplier to purchase the RS232 cable with part number [CABLE-PC](#) for connecting the KL-5080D4 to a computer with Windows 7/8/10 installed. In the case of using USB to RS232 conversion, contact your supplier or Leadshine for such a cable with part number [USB2.0-232](#) which has been verified working fine.



## 12. Troubleshooting

In the event that your drive doesn't operate properly, the first step is to identify whether the problem is electrical or mechanical in nature. The next step is to isolate the system component that is causing the problem. As part of this process you may have to disconnect the individual components that make up your system and verify that they operate independently. It is important to document each step in the troubleshooting process. You may need this documentation to refer back to at a later date, and these details will greatly assist our Technical Support staff in determining the problem should you need assistance.

Many of the problems that affect motion control systems can be traced to electrical noise, controller software errors, or mistake in wiring.

Symptoms	Possible Problems	Solutions
<b>Motor is not rotating</b>	No power	Connect power supply correctly
	Microstep resolution setting is wrong	Setting appropriate microstep
	Fault condition exists	Check wiring and restart power
	The drive is disabled	Drive restore factory setting, and keep ENA+, ENA- input signals unconnected.
<b>Wrong motor rotation direction</b>	The Direction signal level is reverse	Toggling the SW5 DIP switch
<b>The drive in fault</b>	Red light flashes once in a 5-second period	The motor coil may short circuit or exiting the wrong wiring
	Red light flashes twice in a 5-second period	The power supply exceeds Max. operation voltage
	Red light flashes 7-times in a 5-second period	If using Leadshine's motor, refer to motor wiring in datasheet; If using 3 <sup>rd</sup> motor, need to swap the wiring of motor phase A+ and phase A-
	Red light is always on after power on	The drive is burned
<b>Erratic motor motion</b>	Control signal is too weak	Ensure the current of control signal is within 7-16mA



	Control signal is interfered	Don't tie the control signal cable with power cable together
	Wrong motor connection	Refer to user manual of drive and motor datasheet
	Something wrong with motor coil	Check the motor is normal
<b>Motor stalls during acceleration</b>	Current setting is too small	Choose another power supply with larger power or increase the output current of drive
	Motor is undersized for the application	Choose another motor with higher torque
	Acceleration is set too high	Reduce the acceleration
	Power supply voltage too low	Choose another power supply with large voltage output
<b>Excessive motor &amp; drive heating</b>	Inadequate heat sinking / cooling	Refer to chapter 2.4
	Motor peak current setting is too high	Reduce the current value refer to motor datasheet
<b>Motor vibration when power on</b>	Speed loop Kp is too high	Reduce the speed loop Kp value