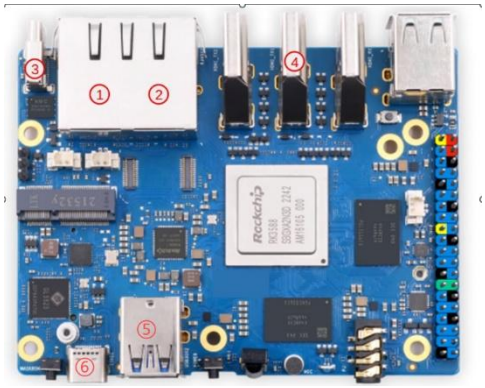


Port 1 is the **EtherCAT communication interface**.

- This port can be connected to the motor IN port or an **EtherCAT branch coupler**.
- Port 2 is a normal network interface and is not used for the EtherCAT real-time control link.
- Port 3 is the **power interface** and requires a **5V power supply**.
- Port 4 is the **HDMI interface** for connecting a display.
- Port 5: Two **USB 3.0** interfaces, which can be connected to vision (equipment).
- Port 6: One **USB 3.0 Type-C** interface, which can be connected to vision (equipment).

2. Motor Alias Must Be Updated to Match YAML

- The alias of each motor slave must be set according to the actual on-site devices.
- The alias values must match the values in the motor configuration file; otherwise, device identification or control may fail.
- Motor configuration file
  path: /home/raybot/raybot_motors_config/ethercat_motors.yaml.
- Default alias range: 1100-1119.
- Alias configuration command: ethercat alias -p x xxxx.
- Notes: x is the slave position index (following the EtherCAT topology order), and xxxx is the alias value to be written. It must match the YAML configuration.

3. Raybot Studio and Documentation Entry

- Shortcuts for Raybot Studio motor management software and related documents are on the desktop.
- Access to Raybot Studio is supported within the same LAN: run ifconfig on the controller to get its IP address, then open DeviceIP:5173 in a browser on another device (for example, 192.168.1.100:5173).

Raybot Smart Works