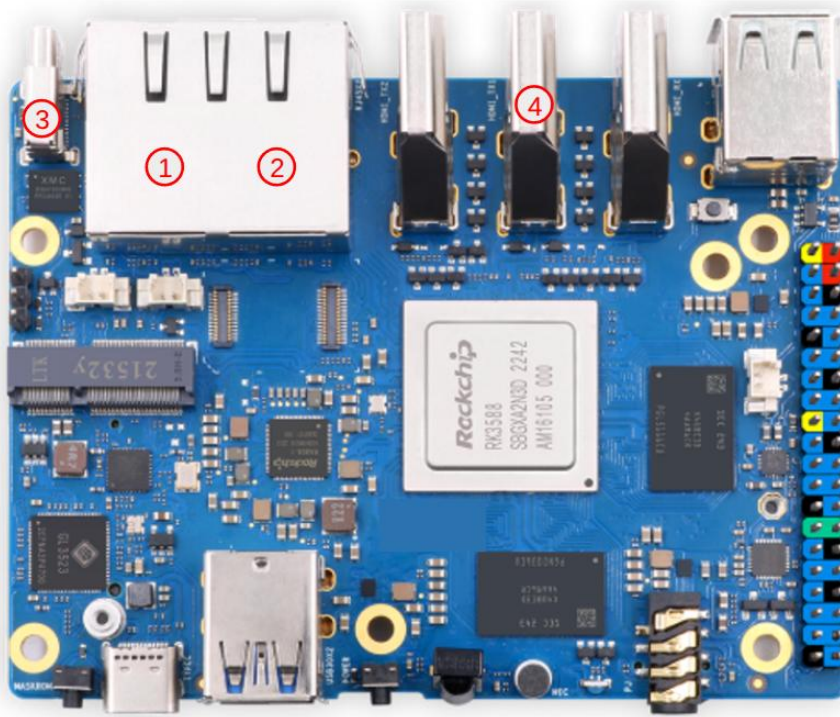


Raybot Controller Quick Start Guide

1. Hardware Interface Locations



- Port 1 is the EtherCAT communication interface.
- This port can be connected to a motor drive's IN port or to an EtherCAT junction (branch) device.
- Port 2 is a standard network port and is not used for the real-time EtherCAT control link.
- Port 3 is the power input; it requires a 5V power supply.
- Port 4 is an HDMI port for connecting a display.

2. Motor Alias Must Be Changed to Match the YAML Configuration

- The alias of each motor slave must be set according to the actual equipment on site.
- The alias value must be consistent with the settings in the motor configuration file; otherwise, device identification errors or control failures may occur.
- 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`
- Note: x is the slave position number (based on the EtherCAT topology order), and xxxx is the alias value to be written, which must match the YAML configuration.

3. Raybot Studio and Documentation Access

- Shortcuts to the Raybot Studio motor management software and related documentation are located on the desktop.
- Raybot Studio can be accessed within the same local area network: first, run `ifconfig` on the controller to obtain the device's IP address, then enter the IP address followed by `:5173` (e.g., `192.168.1.100:5173`) in a browser on another device to access Raybot Studio.