

Robot Hand Software Instructions

文档版本 V1.1.1.0

软件版本 V1.1.1.0

协议 RS485

版本	状态	修订日期	人员
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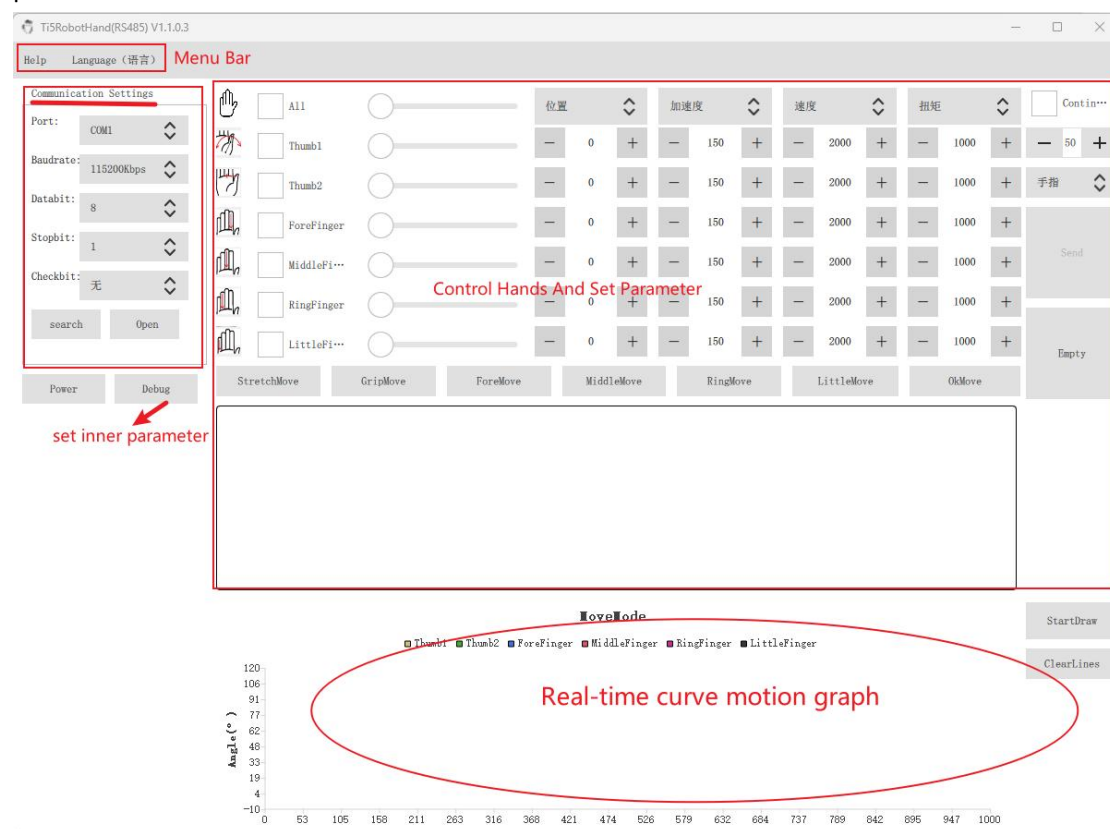
1The installation and operation of the upper computer

Ensure supply voltage 7V, current 3A. Users can send the executable file to the desktop for subsequent operations

2Functions Of The System

2.1System Interface

The software is mainly composed of six parts, 1. Menu bar, 2. Communication setting bar, 3. Control hand and setting parameters, 4. Real-time curve motion chart. 5. Set internal parameters.

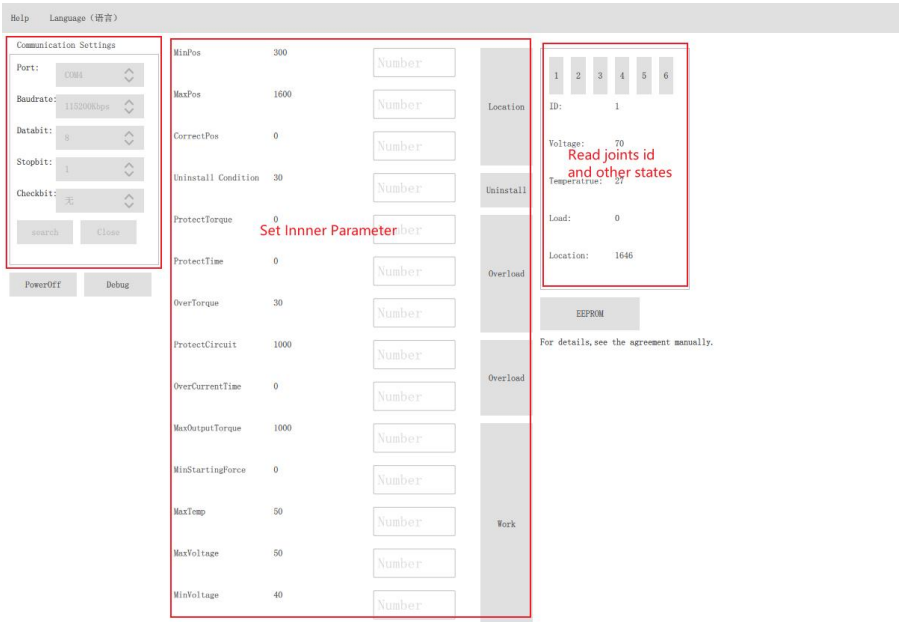


2.2 Internal Status Settings interface

Click the "Stop painting" button, and then click the "Parameter setting" button to switch back and forth.

See Section 4 for details.

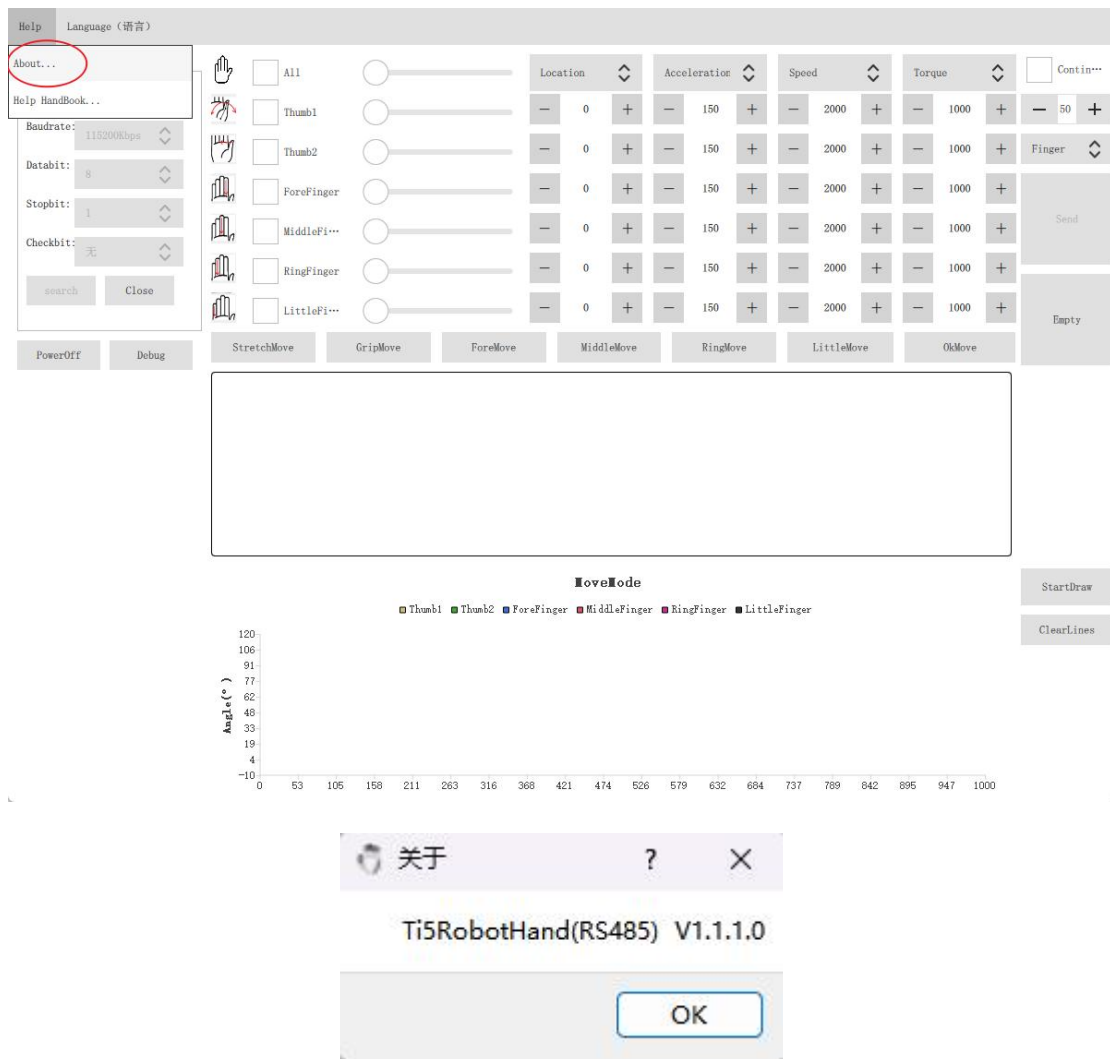
The Meaning Of Each Joint	6	The upper joint of the thumb
	5	The lower joint of the thumb
	4	Index finger
	3	Middle finger
	2	Ring finger
	1	Little finger



2.3 Menu Bar Interface

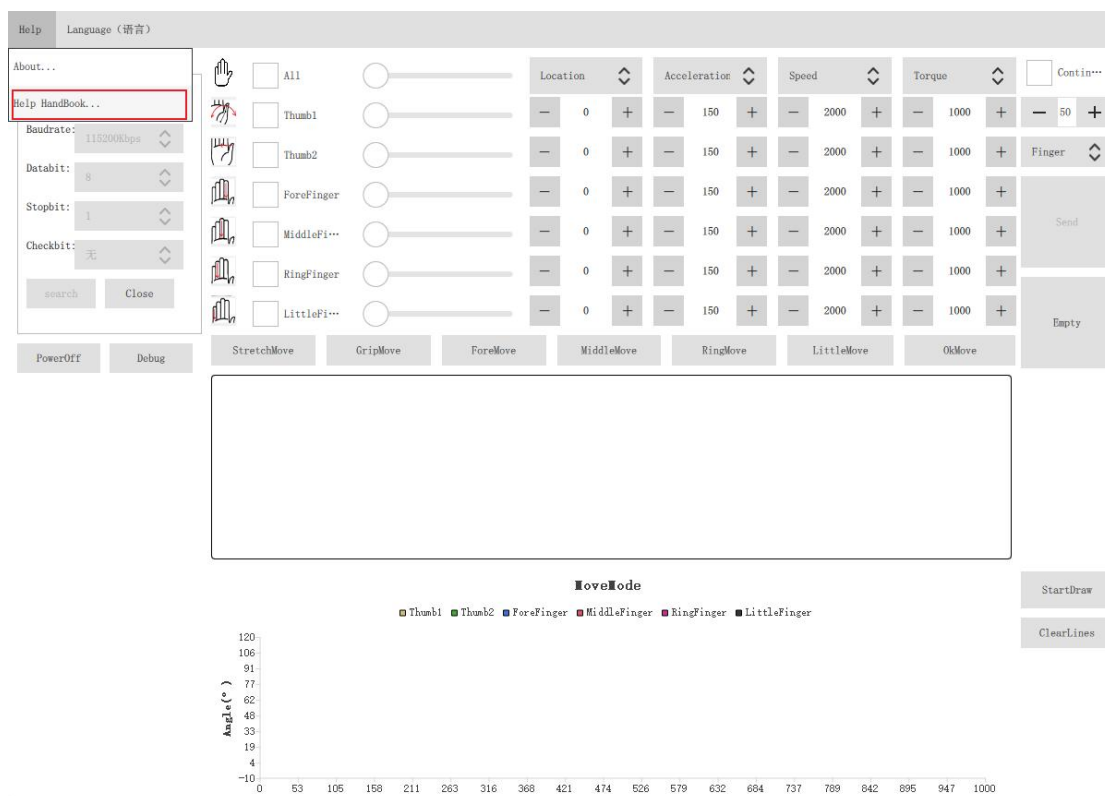
2.3.1 About

Click the "About" button to view the version number.

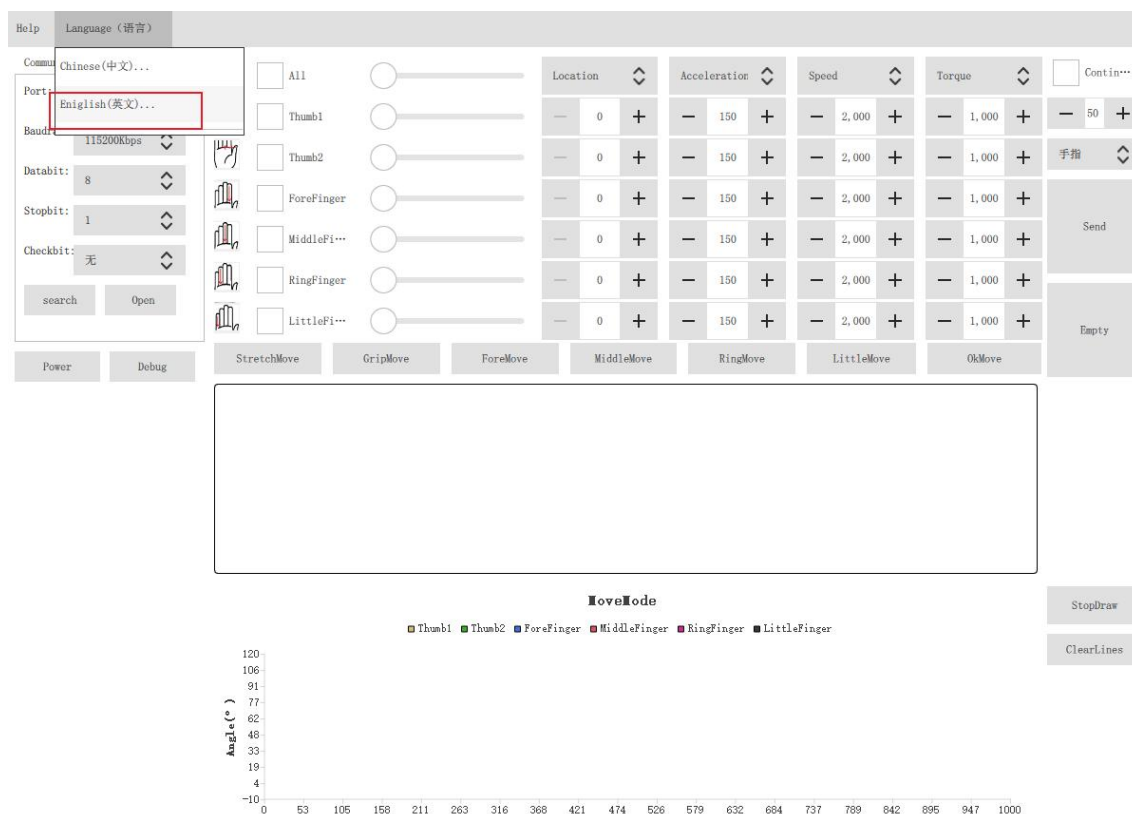


2.3.2 Help Manual

Check the user manual.



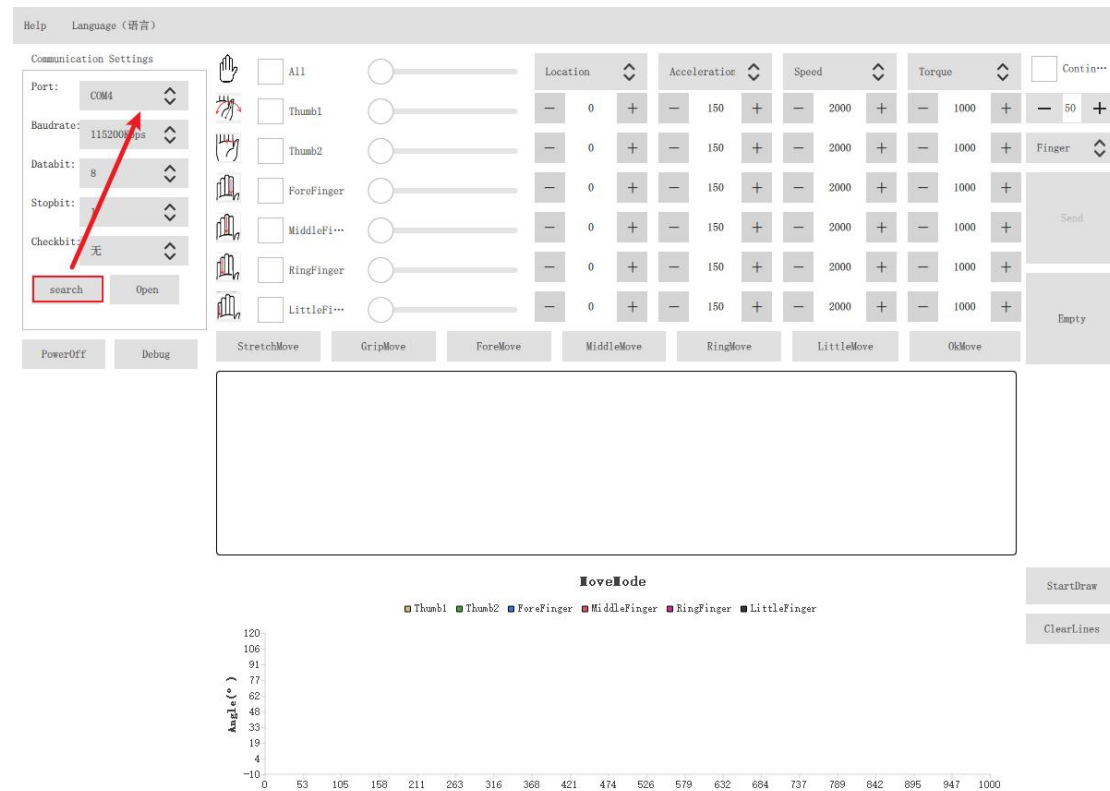
2.4Chinese-English version



3 Basic operation

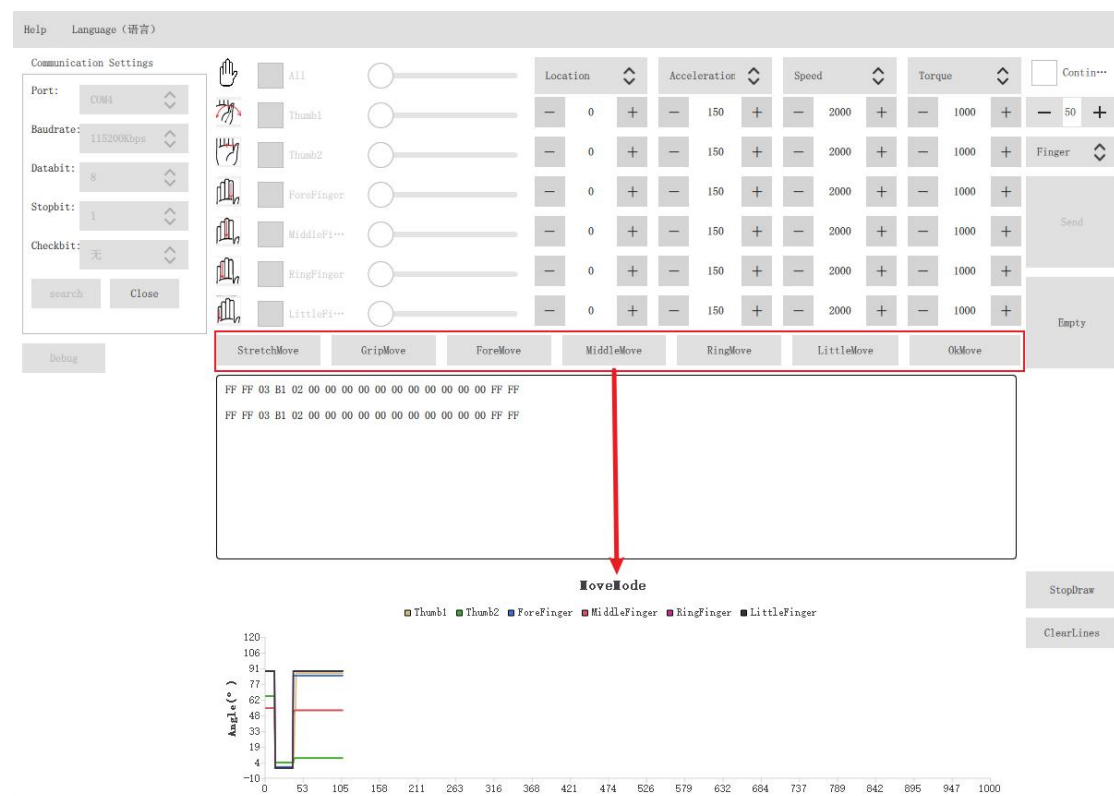
3.1 Open the serial port

Make sure to turn on the power, click the "search" button, the port number found will be added to the list in the main window, select the actual connected serial port, click open.



3.2 Six Movement Modes And Curve Display

Click the button in the box to move, and the curve will be drawn automatically. Click the "Stop Drawing" button to stop the curve. The horizontal coordinate indicates the time of drawing, and the vertical coordinate indicates the angular value of the movement of the six joints.

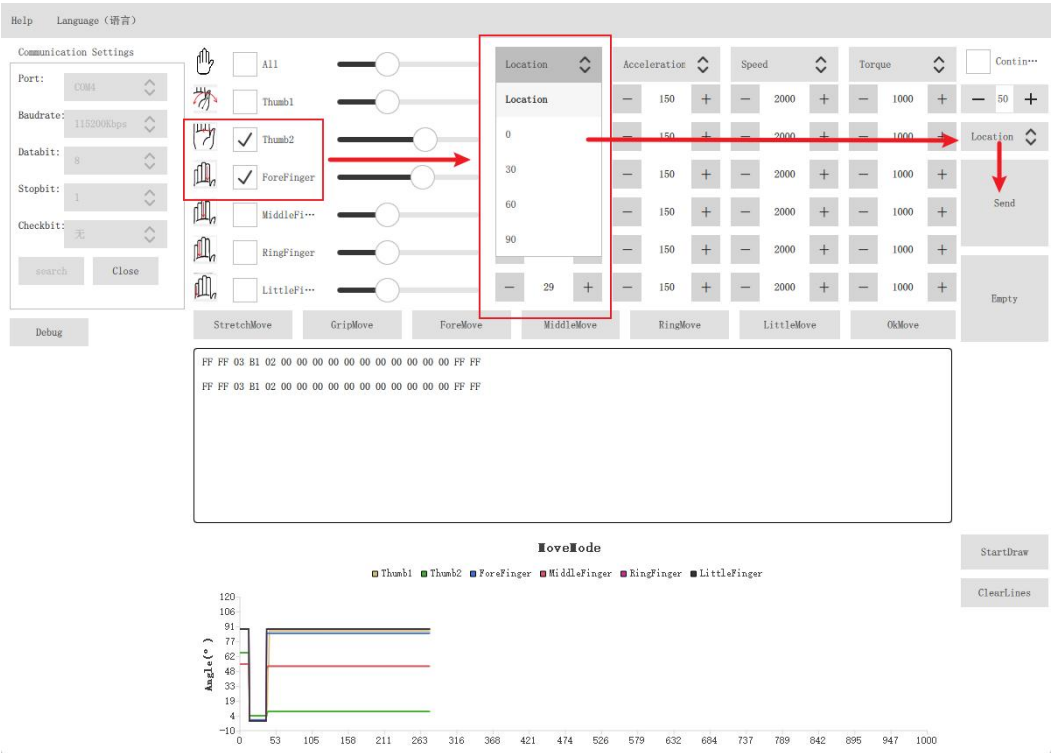


3.3Set Parameters

The operation process is shown in the following figure:The user can select the joint, parameter type and parameter value that need to be set to configure the manipulator.

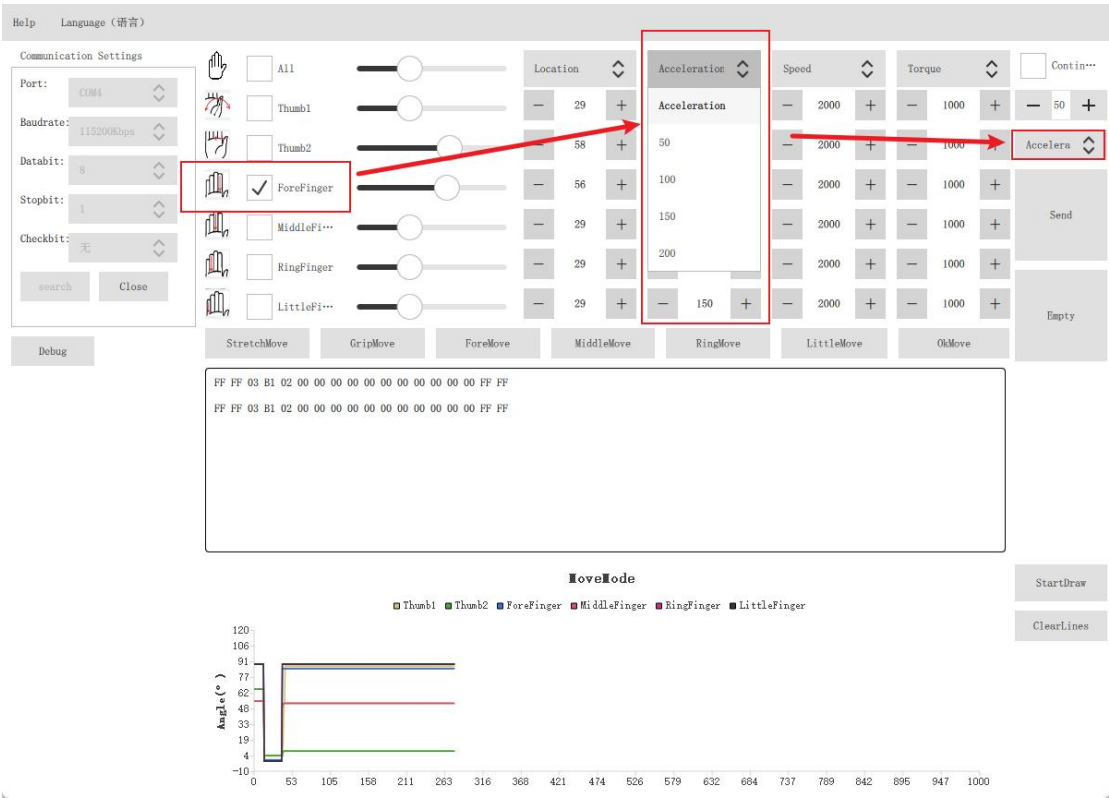
3.3.1 Location Setting

Check the joint to be set and set the Angle value, usually the Angle of the joint is from 0-90



3.3.2 Acceleration Setting

Select the joint to be set, the acceleration includes 1-200, and the default is 150 after power-on.



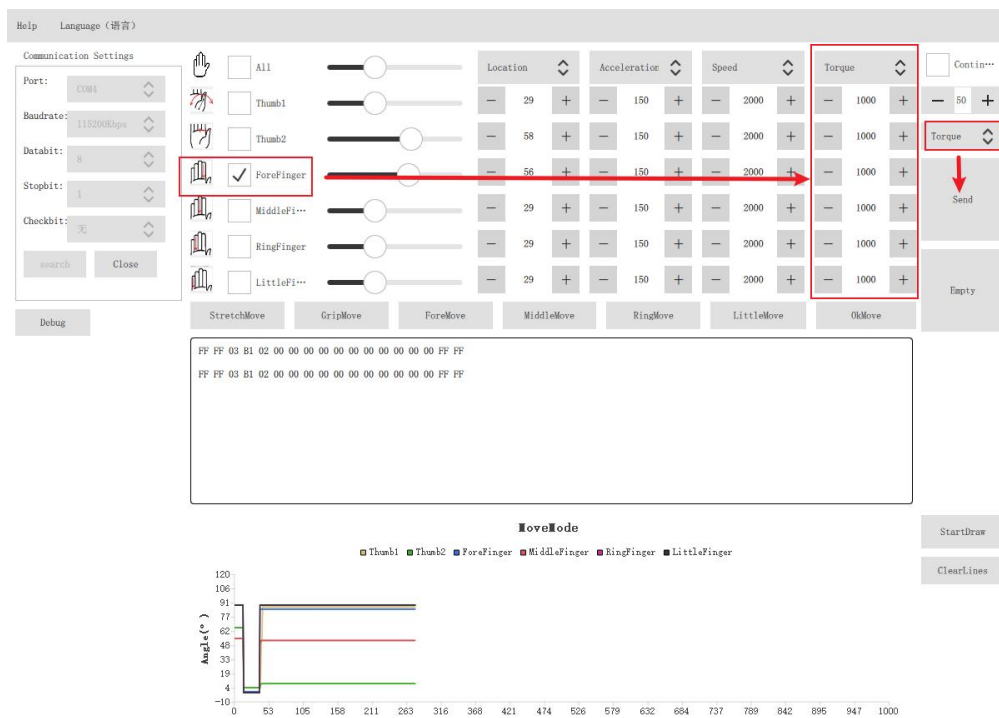
3.3.3 Speed Setting

Select the joint to be set. The speed ranges from 1 to 5000. The default startup time is 2000 after power-on.



3.3.4 Torque Setting

Check the joint to be set, the torque contains 1-1000, here the default power on after 1000.



3.3.5 Finger Mode Setting

The user selects the corresponding mode to define the setting parameters. The specific parameters are shown in the following figure.

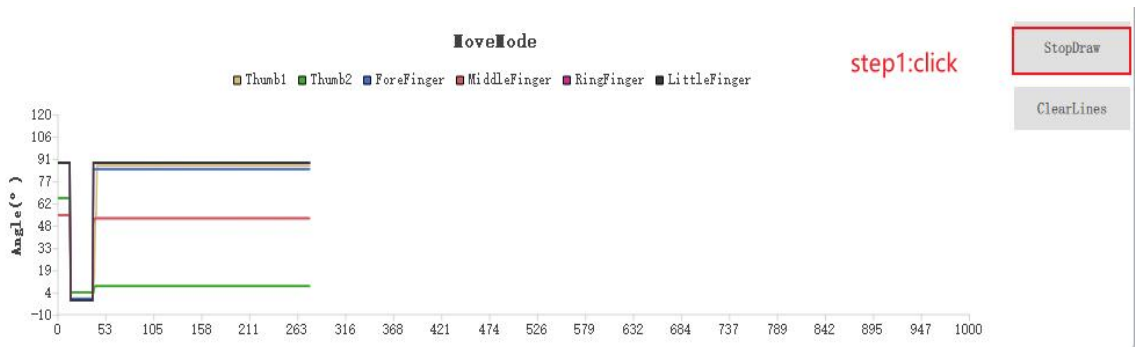


4 Set Internal Parameters

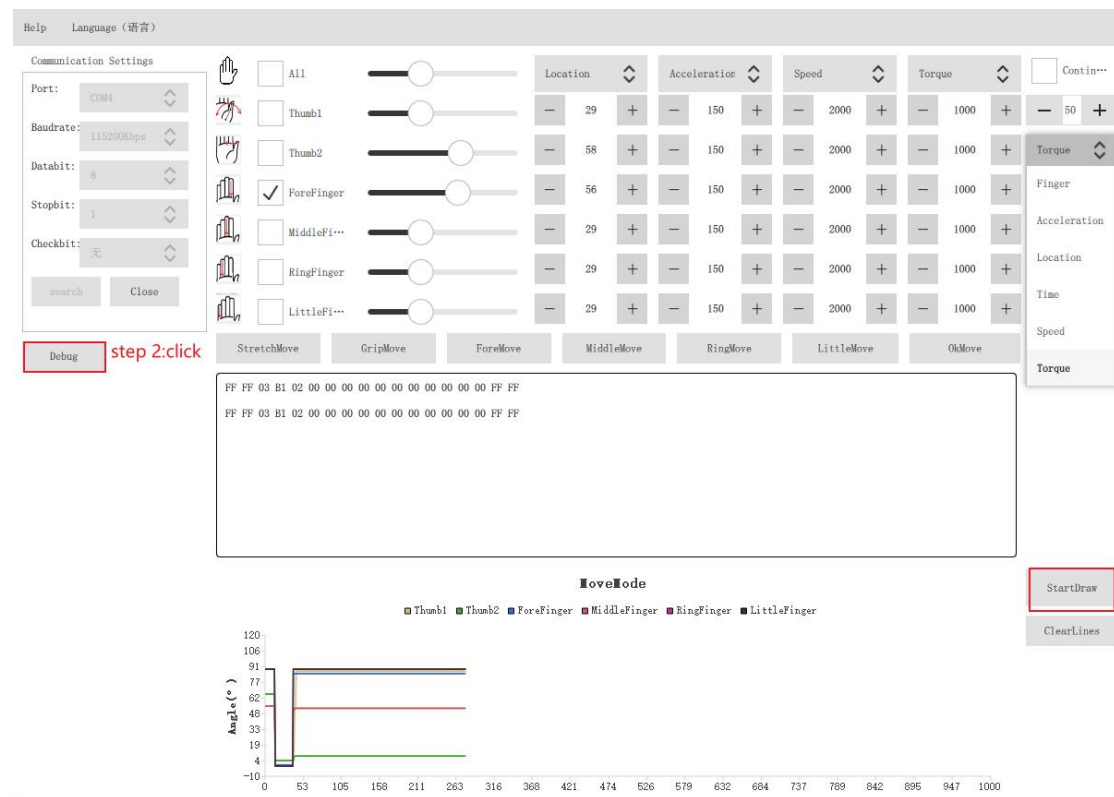
Users can modify other parameters such as manipulator motion limit and current.

4.1 Modification Procedure Description

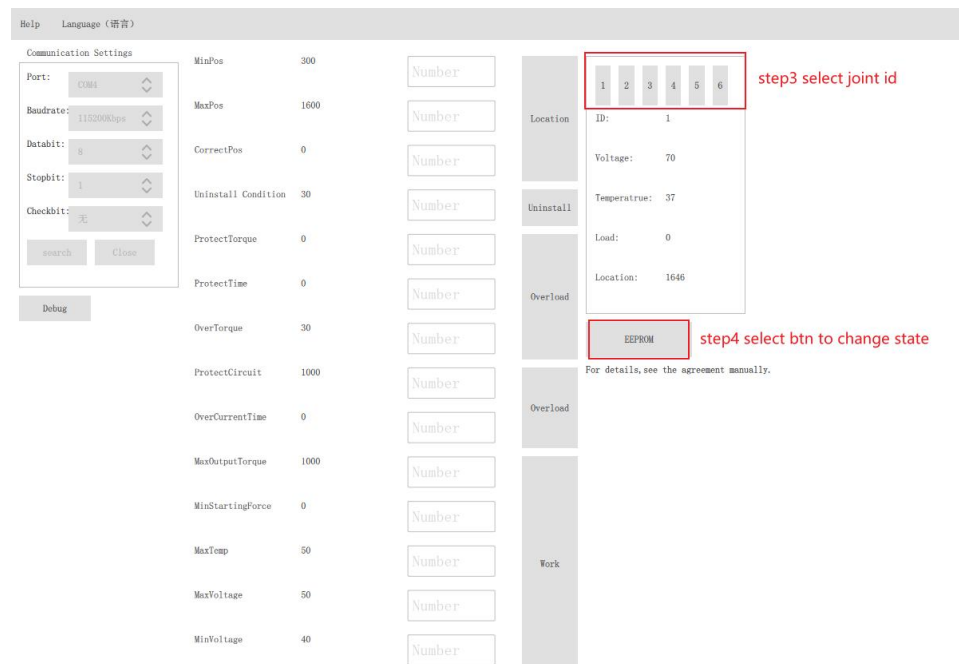
Step1 Click the "Stop Painting" button



Step2.Click the "Parameter Settings" button



Step3 Select the ID you want to set



Step4 Modify the internal status parameter values by module

HelpLanguage (语言)

Communication Settings

Port:COM4

Baudrate:115200bps

Databit:8

Stopbit:1

Checkbit:无

searchClose

PowerOffDebug

MinPos300300

MaxPos16001600

CorrectPos0

Uninstall Condition30

ProtectTorque0

ProtectTime0

OverTorque30

ProtectCircuit1000

OverCurrentTime0

MaxOutputTorque1000

MinStartingForce0

MaxTemp50

MaxVoltage50

MinVoltage40

Location

Uninstall

Overload

Overload

Work

123456

ID:1

Voltage:55

Temperatrue:49

Load:0

Location:309

Unable

Now you can write.

Step5 Modify value

1, reference value description: indicates 1-6 joints, see 2.2 for specific instructions

123456

ID:1

Voltage:70

Change reference values in real time

Temperatrue:37

Load:0

Location:1646

Angle value Resets the reference value

