

Setup Software Instruction Manual



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1. Preparation

Before starting the setup software, the following needs to be done : (1)Connection of hardware devices; (2)The configuration of the operating environment of the setup software.

1.1. Hardware Connection

As shown in table 1-1.

wn in table 1-1. Table 1-1 Hardware devices list
Devices Name
Windows PC (1) Profession
Type-C cable (1pc)
CAN-USB conversion device (1set)
Motor (≥1set)
DC power supply (24V/48V)

After the hardware device is ready, connect the CAN-USB conversion device and Type-C cable, the connection is shown in position 1, Figure 1-1; position 2 is the matching resistance, turn it to the left and keep it on.



Figure 1-1 CAN-USB and Type-C connection diagram

Please note that the appearance of the CAN-USB conversion device is different after upgrading, keep the matching resistance connected when using, and the connection method of the communication cable will not change.



Setup software use CAN0 channel, connect the CANH line and CANL line of the motor to the H and L of the CAN0 channel in turn. As shown in Figure 1-2, the CANH line is yellow and the CANL line is white in this example. The color of the CAN line may be different for different models of motors, so please follow the actual situation. In addition, multiple motors can be connected to the CAN bus as long as you make sure that the motor IDs are not the same.



Figure 1-2 Motor and CAN-USB connection diagram

With the DC power supply turned off, connect the motor to the DC power supply, and the black wire of the motor connected to the negative terminal and the red wire connected to the positive terminal, as shown in Figure 1-3.



Figure1-3 Hardware devices connection complete diagram

1.2. Running Environment

When you use the setup software for the first time, please install the necessary running environment-drivers and common Microsoft runtime libraries in the same





directory of the setup software, as shown in Figure 1-4, download link:Downloads | MyActuator. Running the program after the installation is completed, otherwise, a pop-up window will report an error, indicating that a file is missing.

📒 必备运行环境	x +		
$\leftarrow \rightarrow \uparrow C$	🖵 > 此电脑 > 系統 (D:) > V3S3上位机 6.11 > V3S3 > 必备运行环境 >		
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▲ 主文件夹	2篇 ^	修改日期	类型 大小
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> 📥 OneDrive	國 微软常用运行库合集 (Microsoft Common Runtime Libraries Collection)	2024-05-07 20:53	ZIP 文件 35,886 KB
<mark>11</mark> 桌面	9		
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🔤 文档	1		
🛃 图片	*		
🕜 音乐	*		
🛃 视频	*		
늘 参数			

Figure 1-4 Installing Drivers and Common Microsoft Runtime Libraries

2. Basic Parameters Interface

Basic parameters interface includes communication connections, encoder calibration, motor information and PID adjust parameters. In addition, the communication connection status and current communication ID are instantly displayed at the bottom of the screen.

2.1. Communication Connection

After the hardware is correctly connected, turn on the power switch and the setup software, enter the specified communication ID, click the "Set Communication ID" button, and a pop-up window prompts "Successfully set communication ID.", as shown in Figure 2-1. If the communication ID is empty, clicking the "Set communication ID" button will not take effect.





A MYACTUATOR Setup Software V	/4.0	OFTU		_		- 🗆 X
		SETU	PSOFTWARE			
Basic Parameters	Advanced Parameters	Motor Runing		Cont	act Us	
Communication	ID:	2 Set ID		Connect		Disconnected
Calib	1st Encoder	Calibrated 3		Calibrat	2nd Encoder	librated
Set Zero	Point	Succes	×	it Zero Point		
Motor Informati	on		ОК			
Motor ID:			Position Loop	Speed Loop	Q-Axis Current	D-Axis Current
Motor Nunber:						
Motor Name:						
FW Version:				-		
Factory lime:		R (Slope)				
Read	Save	T (Filter)	Read		Save	
Connection status:Dis	connected	4	MYACTUATOR		Gurrent	t Communication ID:

Figure 2-1 Communication ID setting diagram

Click on the "Connect" button to connect successfully, then this button can not be used, and display "Connected", display encoder calibration, the current position, motor information and the current communication ID, as shown in Figure 2-2.

	SETUP	SOFTWARE			
Basic Parameters Advanced Parameters	Motor Runing		Conta		
Communication ID: 1	Set ID		Connected		Disconnect
Ist Encoder Calibrat Set Zero Point	l i brated -1. 16		Calibrat iet Zero Point	2nd Encoder	librated
Motor Information Motor ID: 1 Motor Number: 0 Motor Name: AMAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA	PID Paramet P I D R(Slope) T(Filter)	ers Position Loop	Speed Loop	0-Axis Current	D-Axis Current
Read		Read		Save	

Figure 2-2 Setup software connection successfully diagram

Click on the "Disconnect" button, operate the setup software to close the CAN-USB conversion device, then displays "Disconnected", and the connection status changes to "Not connected...", the current communication ID is cleared.

2.2. Encoder Calibration

Click the "Encoder Calibration" button of the first encoder to bring up the main



encoder interface, read the encoder parameters, and a pop-up window prompts "Successfully read calibration parameters.", as shown in Figure 2-3.

asic Parameters	Advanced Parameters	Motor Runing		Contact Us	
Communication I	D: 1	2 Set In Master Encoder	Connect: - : ×	Disconnect	
1 Cailb Set Zero Motor Informatic Motor ID: Motor Number:	1st Encoder rat	Master Encoder: Enabled Powerdown Save Pole-Paris: 3 Sing A Tip Calli Successfully read of Exch Change Encoder Callibrat Value: Encoder Accuracy:	Nul tTurn: 10 15 15 15 15 10 10 10 10 10 10 10 10 10 10	2nd Encoder Cal ibrated	nt
Motor Name: FW Version: Factory Time: Reduction Rati	AAAAAAAAAAAAAAA 2024033001 0 0: B1 Save	Cellbrat Encoder Read	Calibrated	Save	

Figure 2-3 Main encoder calibration interface

Explanation of encoder parameters, as shown in Table 2-1.

Table 2-1 Explanation of encoder parameters

	1 1	
Parameters	Explanation	Range
Power off to save	When switched on, power down to saves	0,1
multi-turn values	multi-turn values	
Pole pair	Number of pole pairs of a motor	2~40
Number of motor	Increased encoder value after 1 revolution of	0~262144
encoder lines (PPR)	motor operation	
Encoder calibration	Motor torque current during calibration	0~Rated current
current (A)	INTOR	
Motor exchange	Automatic calibration according to encoder	0,1
phase sequence	direction and motor wiring direction	
Change motor	When switching on, change the direction of	0,1
direction	motor operation	
Encoder zero point	Zero bias of electrical angle	0~PPR
Encoder accuracy	Assess the accuracy of calibration results	<1000



0



The criteria for determining the accuracy of the encoder are shown in Table 2-2. Table 2-2 The criteria for determining the accuracy of the encoder

Encoder Accuracy	970~1000	0~970	<0
Calibration Results	Success	Failure	Failure

Adjust the encoder parameters to ensure that the value is correct, click on the "Save" button to save all parameters to the motor program, and the pop-up window prompts "Successfully saved calibration parameters .", as shown in Figure 2-4.



Figure 2-4 Master encoder parameters adjustment and save

In order to prevent operational errors, as long as there is no value for any one parameter, click the "Save" button, the setup software will not perform any operation. Further click on the "Zero Calibration" button, you can control the motor calibration, as shown in Figure 2-5.









After calibration, re-read all data in the "Master Encoder" interface and display the calibration result. If the calibration is unsuccessful, the resolution is shown in Table 2-3. In addition, some motors will automatically open the "Exchange phase" option after calibration, which is a normal phenomenon.

	Table 2-5 Encoder canoration problems and solutions
Results	Solutions
Failure	Check that the number of pole pairs, the number of encoder lines and
	the encoder calibration current and re-calibrate them.
Unavailability	Re-calibrate MACION Innovative

Table 2-3 Encoder calibration problems and solutions

2.3. Motor Information Professional R

Click the "Read" button of the motor information, the setup software will read the parameters in the motor information, refresh the current position, and pop-up window prompts "Successfully read motor information.", as shown in Figure 2-6.

A MYACTUATOR Setup Software V4.0				- 🗆 X
	SE	TUP SOFTWARE		
Basic Parameters Advanced	Parameters Motor Runing	Settings		
Communication ID:	1 Set ID		Connected	Disconnect
	st Encoder	4	2nd Encod	ter
Galibrat Set Zero Point	Galibrated 3 -4.45	Successfully read motor info	rmation. pint	Galibrated
Motor Information 2	PID	Parameters		
Motor ID: 1		Position Loop	Speed Loop Q-Axis	Current D-Axis Current
Motor Name: AAAAA	AAAAAAAAAA			
FW Version: 20240	33001			
Factory Time: 0	R (SI	ope)		
Reduction Ratio: 81	T (Fil	ter)		
1 Read	Save	Read		Save
Connection status:Connected		MYACTUATOR		Current Communication ID:1

Figure 2-6 Diagram for reading motor information

Explanation of motor information parameters, as shown in Table 2-4

 Table 2-4
 Explanation of motor information parameters

Parameters	Explanation	Range
Motor ID	Addressing the motor's identity on the CAN bus	0~32
Motor code	Distinguishing motors	NULL





Motor name	Motor model	NULL
Firmware version	Date of firmware version	NULL
Factory date	Factory date and it cannot be modified	NULL
Reduction ratio	Motor's reduction ratio	1~121

Except for the firmware version in the motor information, other parameters can be modified and saved. Click "Save" button to save all parameters to the motor program, and a pop-up window prompts "Successfully saved motor information.", as shown in Figure 2-7. In order to prevent operation errors, as long as there is no value for any parameter, click "Save" button, the setup software will not carry out any operation.

A MYACTUATOR Setup Software	V4.0				-	
		SETUP S	SOFTWARE			
D. 1. D						
Basic Parameters	Advanced Parameters	Motor Runing	Settings	Contact Us		
Communication	ID: 1	Set ID		Connected	Disconnect	
	1st Encoder			2nd E	ncoder	
0.11		Calibrated		alibrat	Calibrated	
		2			Caribiaceu	
Set Zer	o Point	- 4. 45 🆾 Tip	×	Zero Point		
		Successfully s	aved motor information.			
	e 19		ОК			
Motor Informati	ion					
Motor ID:	1		Position Loop	Speed Loop Q-	Axis Current D-Axis Curre	nt
Motor Nunber:	0					
Motor Name:	*****					
FW Version:	2024033001					
Factory Time:	0	R (Slope)				
Reduction Rat	:io: 81	T(Filter)				
Read	1					
			Kead		Save	
Connection status:Cor	nnected	MYACTL Professional Association	MATOR		Current Communication	D:1

Figure 2-7 Diagram for saving motor information

2.4. PID Parameter Adjustment

Click on the "Read" button of PID parameter to set the software to read the PID parameters, and at the same time, a pop-up window prompts "Successfully read PID parameters.", as shown in Figure 2-8.









Figure 2-8 Read PID parameters

Click the "Save" button of PID parameter, it save all PID parameters to the motor program, and the pop-up window prompts "Successfully saved PID parameters.", as shown in Figure 2-9. In order to prevent operational errors, as long as there is no value for any parameter, the setup software will not perform any operation when clicking the "Save" button.

		SETUP	SOFTWARE			
asic Parameters	Advanced Parameters	Motor Runing	Settings			
Communication ID		Set ID		Connected		Disconnect
	1st Encoder				2nd Encoder	
Calibra		Calibrated 2		Calibrat	Ca	librated
Set Zero F	Point	-4. 45 🎑 Tip	×	t Zero Point		
		Successf	ully saved PID parameters.			
Motor Information			OK			
Motor ID:	1		Position Loop	Speed Loop	Q-Axis Current	D-Axis Current
Motor Nunber:	0		0.0500	0. 1000	1.0000	1.0000
Motor Name:	*****		0.0000	0.0010	0. 1000	0. 1000
FW Version:	2024033001		5.0000	0.0000	0.0000	0.0000
Factory Time:	0	R (Slope)	0.0000	0.0000	0.0000	0.0000
Reduction Ratio	81	T(Filter)	0.0000	0.0000	0.0000	0.0000
Read	Save		Read		1 Save	

Figure 2-9 Save PID parameters





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3. Advanced Parameters Interface

The Advanced parameters interface displays protection parameters, planning parameters, motor parameters, export parameters and import parameters.

3.1. Protection Parameters

Click on the protection parameters of the "Read" button, the setup software read the protection parameters, while the pop-up window prompts "Successfully read protection parameters.", as shown in Figure 3-1.

A MYACTUATOR Setup Software V4.0		– 🗆 X
	SETUP SOFTWARE	
Basic Parameters Advanced Parameters	Motor Runing Settings	Contact Us
Protect Parameters Deer Voltage (V): Lew Voltage (V): Stall Time Limit(a): E-Brake Start Duty Oycle (N): Durrent Samole Res (mO): E-Brake Mold Duty Oycle (N): Brake Mold Duty Oycle (N): Commentation E-Brake Mold Duty Oycle (N): Commentation Export parameters	Plan Parameters Max Positive Position(Deg): Min Negative Position(Deg): Position Plan Max Acc (Dps/s) Position Plan Max Acc (Dps/s) Position Plan Max Doce(Dps/s) Spect Spect Successfully read protection parameters Spect Spect Successfully read protection parameters Notor Cox	Wotor Parameters Max Current(A): Stall Gurrent(A): Shutdown Temp(C): Resume Temp(C): Max Speed(RPM): Nominal Speed(RPM): Enable Znd Encoder: Enable Znd Encoder: Read
Connection status:Connected	MYACTUATOR	Current Communication ID:1

Figure 3-1 Read protection parameters

The explanation of protection parameters, as shown in table 3-1

Table 3-1	The explanation	of protection	parameters
-----------	-----------------	---------------	------------

Parameters	Unit	Explanation	Range
Over-voltage		If the operating voltage exceeds this	
protection	V	parameter, the motor stops and an error is	0~60
voltage		reported: over-voltage	
Low-voltage		If the operating voltage is lower than this	
protection	V	parameter, the motor stops and an error is	0~60
voltage		reported: low-voltage	







Time limit of blocking turns	S	If the blocking time exceeds this parameter, the motor stops and an error is reported: motor blocking	0~600
Duty cycle	%	Duty cycle of the holding brake circuit when the	0~100
for braking		holding brake is activated	
Current sampling resistors	mΩ	Resistor resistance value when sampling three-phase current by the main control	Base on the situation
Holding brake maintenance	%	Duty cycle of the holding circuit when holding brake is maintained	0~100
Duty Cycle for Brake Function Selection	_	Selection of braking function: holding brake or braking resistor	NULL

Click the "Save" button of the protection parameters, it can save all protection parameters to the motor, and at the same time, a pop-up window prompts "Successfully saved protection parameters .", as shown in Figure 3-2.



Figure 3-2 Save protection parameters

In order to prevent operation errors, as long as there is no value for any parameter,

click "Save" button, the setup software will not carry out any operation.





3.2. Planning Parameters

Click the "Read" button of the planning parameters, the setup software will read the planning parameters, and a pop-up window prompts "Successfully read planning parameters .", as shown in Figure 3-3.



Figure 3-3 Read planning parameters

The explanation of planning parameters, as shown in Table 3-2.

Table 3-2	The explanation	of planning parameters

Parameter	Explanation	Range
Max. positive angle(Deg)	Maximum positive angle for position mode	0~4.2E+9
Min. negative angle(Deg)	Minimum negative angle for position mode	0~4.2E+9
Max.acceleration for position	Maximum acceleration for position mode	0~60000
Max.deceleration for position	Maximum deceleration for position mode	0~60000
Max.speed for location	Maximum speed for position mode	0~Rated
Max.acceleration for velocity	Maximum acceleration for speed mode	0~60000
Max.deceleration for speed	Maximum deceleration for speed mode	0~60000
Motor position zero(Pulse)	Select an encoder value to mark as motor	0~PPR

Click on the "Save" button of the planning parameters, it can save all planning parameters to the motor, and at the same time, a pop-up window prompts "Successfully

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saved planning parameters .", as shown in Figure 3-4.

A MYACTUATOR Setup Software V4.0	0				- 0 ×
		SETUP S	OFTWARE		
Basic Parameters	Advanced Parameters	Motor Runing		Contact Us	
Protect Parameters Over Voltage(V): Low Voltage(V): Stall Time Limit(e): E-Brake Start Duty Cy Ourrent Sample Res(m E-Grake Hold Duty Brake Mode: Read Export parameters	55.00 20.00 0.00 (x): 0 0): 2 5.00 3.1p Successfully awed planning part	Plan Parameters Max Positive Position Min Negative Position Position Plan Max Acc Position Plan Max Spe eed Plan Max Acc(Dp meters deed Plan Max Doc(Dp or Position Zero: Read	(Deg): 65535 (Deg): 66535 (Dps/s) 5000 edRN0: 2500 s/s) 5000 n/s00 1000 1 Save	Motor Parameters Max Current(A): Stall Current(A): Shutdown Temp('C): Resume Temp('C): Max Speed(RPM): Nominal Speed(RPM): Enable 2nd Encoder: Enable 2nd Encoder: Enable CAN Filter: Head	Save
Connection status:Conne	ected	-MYACTUR Province Protocol	NTOR 0	Current	t Communication ID:1

Figure 3-4 Save planning parameters

In order to prevent operation errors, as long as there is no value for any parameter, click "Save" button, the setup software will not carry out any operation.

3.3. Motor Parameters

Click the "Read" button of the motor parameter, use the setup software to read the motor parameter, at the same time, the pop-up window prompts "Read motor parameter successfully.", as shown in Figure 3-5.



Figure 3-5 Read motor parameters

The explanation of motor parameters, as shown in table 3-3.





		Table 3-3 The explanation of motor parameters	
Parameter	Unit	Explanation	Range
Max phase current limit	А	The motor stops when the phase current exceeds this parameter and an error is reported: phase current over-current.	Base on the situation
Blocking current limit	A	When the torque current exceeds this parameter, the motor still cannot rotate, and the blocking time exceeds the time limit, then the motor stops and an error is reported: the motor is blocked.	Base on the situation
Over-tempe rature protection temperature	°C	The motor stops when the temperature exceeds this parameter and an error is reported: over temperature.	0~100
Over-tempe rature recovery temperature	°C	Cancels the over-temperature error when the temperature falls below this parameter.	0~100
Max speed	RPM	Max speed of motor running in current mode	0~6000
Rated speed	RPM	Motor speed at rated power	Base on the situation
Enabling second encoder	_	Whether to switch on the second encoder.	0、1
CAN filter enable	_	Whether to enable the CAN filter.	0, 1

Table 3-3 The explanation of motor parameters

Click the "Save" button of the motor parameters, it can save all motor parameters to the motor, and at the same time, a pop-up window prompts "Successfully saved motor parameters.", as shown in Figure 3-6.

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A MYACTUATOR Setup Software V4.0		- • ×
	SETUP SOFTWARE	
Basic Parameters Advanced Parameters	Motor Runing Settings	Contact Us
Protect Parameters Over Voltage(V): 55.00 Low Voltage(V): 20.00 Stall Time Limit(a): 0.00 E-Brake Start Duty Gycle(%): 0 Current Sample Res(mQ): 5.00 E-Brake Hold Duty Cycle(%): 0 Brake Mode: E-Brake Read Save Export parameters Import parameters	Plan Parameters Max Positive Position(Deg): 65535 Min Negative Position(Deg): 65535 Position Plan Max Acc(Dps/s) 5000 Position Plan Max SpeadDML Speed Speed Notor Read Save	Motor Parameters Max Current(A): Stall Current(A): Shutdown Temp(C): 100.00 Resume Temp(C): 90.00 Max Speed(RPM): 6000.00 Nominal Speed(RPM): Enable 2nd Encoder: Enable CAM Filter: Pread
Connection status:Connected	-MYACTUATOR 9®	Current Communication ID:1

Figure 3-6 Save the planning parameters

To prevent operational errors, the setup software does not perform any operation when the "Save" button is clicked as long as there is no value for any of the motor parameters.

3.4. Export Parameters

Click the "Export Parameters to XLSX File" button in the Advanced Parameters to bring up the export parameters dialogue box, the default path is the Windows desktop, as shown in Figure 3-7.

MYACTUATOR Setup Software V4.0				- 0
	SETUP	SOFTWARE		
Basic Parameters Advances	d Parameters 2 Motor Runing			
	A Export parameters.			×
Protect Parameters	← → ∽ ↑ 🛄 > 夏回 >		✓ C 在桌面中搜索	Q
Over Voltage(V):	55.0			= - 0
Low Voltage(V):	20.0) OpeDrive 名称	^	修改日期	美型 .
Stall Time Limit(s):	0. 0	oader上位机	2024-03-28 16:34	文件夹
E-Brake Start Duty Cycle(%):	0 🚛 桌面 🥜 📩 CEM系列	产品技术资料	2024-07-12 9:49	文件夹
Current Sample Res(mΩ):	5.0 👱 下载 💉 🔭 ICOlogo		2024-05-23 17:37	文件夹
E-Brake Hold Duty Cycle(%):	0 📄 文档 🍃 🎦 itek		2024-06-12 10:07	文件夹
Brake Mode:	E-Brake 🔀 图片 🌧 🎦 MT6825_	20230413	2023-04-14 10:15	文件夹
Read	Save 🔮 音乐 📌 🚞 QT		2024-04-29 12:24	文件夹
	N 和 Raytank.	Servo 20240108-MODBUS_S3	2024-04-15 21:02	文件夹
	🔊 app	数	2024-07-13 10:32	文件夹
	÷/#≲/Ni			
	保存类型①: Excel Files (*.xlsx)			~
	. 隐藏文件女		保存(5)	EV:M
	T PENEALTYC			
Export parameters				
Import parameters				
onnection status:Connected	-MYAC		Current Communi	cation ID:1

Figure 3-7 Export parameters dialog box





A MYACTUATOR Setup Software V4	1.0						- 0 ×
		SETUP	SOFTWARE				
Basic Parameters	Advanced Parameters	Motor Runing	Settings	Contact U			
	A (xport parameters. 1					×
Protect Parameter	s ←	→ ~ ↑ 🚬 > 桌面 > 参数	2		~ C	在 参数 中搜索	م
Over Voltage(V):	55.0	R ▼ 新建文件夹					■ • 0
Low Voltage(V): Stall Time Limit(s)	20.0 >	● OneDrive 名称	^	修改日期	类型	大小	
E-Brake Start Duty (Ourrent Sample Res() E-Brake Hold Duty C Brake Mode: Read	Sycte(%): 0 n(2): 5.00 ycte(%): 0 E-Brake Save	■ 重雨 ● 天阪 ● 天阪 ● 武浩 ● 西子 ● 田子 ● 田 ● 田		OR POSSAGE PERSON	×	3	
Export parameter	۲ م. ۵	發藏文件类				保存(5)	取消
Connection status:Conr	nected	-MYACT	UATOR [®]		Ċ	urrent Communica	tion ID:1

Specify a path, enter a filename, and click save, as shown in Figure 3-8.



The software will read all parameters in the motor, in the specified path to the specified file name to create a xlsx file, write all parameters to this file, and pop-up window prompts "Parameters exported successfully.", as shown in Figure 3-9.

MYACTUATOR Setup Software V4	4.0				- 0 :
		SETUP S	OFTWARE		
Basic Parameters	Advanced Parameters	Motor Runing	Settings	Contact Us	
Protect Parameter Over Voltage(V): Low Voltage(V): Stall Time Limit(a) E-Brake Start Duty (Current Sample Res (E-Brake Hold Duty C) Brake Mode: Read	S 55.00 20.00 Cycle(%): 0 nO): 5.00 cole(%): 0 E-Brake v Save	Plan Parameters Max Positive Position() Min Negative Position () Position Plan Max Acc() Position Plan Max Sener Speed P Parameters ex Motor P Read	heg):: 65535 heg):: 65535 pps/s): 5000 pps/s): 5000 pps/s): 5000 00 00 00 00 00 00 00 00 00	Motor Parameters Max Current(A): Stall Current(A): Shutdown Temp(CC): Resume Temp(CC): Max Speed (RPM): Nominal Speed (RPM): Enable 2nd Encoder: Enable 2nd Encoder: Read	15.00 15.00 100.00 90.00 6000.00 4000.00
Export parameter	5				
Import parameter	8				
Connection status:Conr	nected	MYACTUAT		Current	Communication ID:1

Figure 3-9 Export parameters

After exporting the parameters successfully, you can find the xlsx file storing the parameters in the specified path and open it to see all parameters, as shown in Figure 3-10.

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\$\$\$\$\$\$\$ 15	字体 5		R1777	277			数字			
26 VIX & D-Avi	is Current T(Filter)									
A	B	с	D	E	F	G	н			
Parameter	value									
Motor ID	1									
Motor Name										
Eactory Time	ANNONONOLAAAAAAA									
Pactory Time	0									
Reduction Ratio	0.00000001									
Position Loop KP	0.03000001									
Position Loop Ki	0									
Position Loop R(Slope)										
Position Loop T(Siltor)	0									
Position coop ((niter)	0 100000000									
Speed Loop Kr	0.001									
Speed Loop Ki	0.001									
Speed Loop R/Slopp)	0									
Speed Loop Malopej	0									
O-Avis Current KP	1									
O-Axis Current KI	0 10000001									
O-Axis Current KD	0									
Q-Axis Current R(Slope)	0									
Q-Axis Current T/Eilter)	0									
D-Avis Current KP	1									
D-Axis Current KI	0.100000001									
D-Axis Current KD	0									
D-Axis Current B(Slope)	0									
D-Axis Current T(Filter)										
Enabled Powerdown Save MultTurn	FAISE									
Pole-Paris	10									
Single-Resolution Value (Pulses)	65535									
Calibrat Current(A)	3									
Exchange phase	FALSE									
Change Motor Direction	FALSE									
Encoder Calibrat Value	2050									
Over Voltage(V)	55									
Low Voltage(V)	20									

Figure 3-10 The xlsx file that stores the parameters

It is not recommended to modify the contents of the xlsx file, which may cause errors in the import parameters.

3.5. Import Parameters

Click the advanced parameters in the "Import parameters" button, pop-up import parameters dialogue box, the default path to the Windows system desktop, shown in Figure 3-11.

MYACTUATOR Setup Software V4.0		SETUP	SOFTWARE	/		- □ >
Basic Parameters Advance	ed Parameters <mark>2</mark> Moto	r Runing	Settings	Contact Us		
	🌲 Import paramete	rs.				×
Protect Parameters	$\leftarrow \rightarrow \lor \uparrow$	🧾 > 桌面 >		~ C	在 桌面 中搜索	Q
Over Voltage(V):	55.0 细织 ▼ 新建文	"仕事			= •	
Low Voltage (V) : Stall Time Limit(s) : E-Brake Start Duty Dycle(%) : Current Sample Res (mD) ; E-Brake Hold Duty Cycle(%) : Brake Mode: Read	20.0 0.0 0 5.0 E-Brake Save 2 3 2 2 3 2 3 3 2 3 3 3 3 3 3 3 3 3 3	名称 anbootic CEM展列F ICOlogo itek MT6825 2 QT RaytankS RH展列参	へ 高速大波料 の230413 な な 20240108-MODBUS_53 文	博 22 22 22 22 22 22 22 22 22 22 22 22 22	XEI ## 24-03-28 16:34 24-07-12 9:49 24-05-23 17:37 24-06-12 10:07 23-04-14 10:15 24-04-29 12:24 24-04-12 10:02 24-04-12 10:22	契型 文件块 文件块 文件块 文件块 文件块 文件块 文件块 文件共 文件共 文件共 文件共 文件共 文件共 文件共 文件共 文件共
	► Exe	SourceCo 文件名(<u>N</u>):	inter	~	22-10-09 16:12 Excel Files (*.xlsx) 打开(Q)	文件疾 ~ 取消
Export parameters						
Connection status:Connected		-MYACT	HATOR [®]	Ci	irrent Communica	tion ID:1

Figure 3-11 Import Parameters dialog box

Specify a destination file and click Open, as shown in Figure 3-12.



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							- 0
		SETUP S	SOFTWARE				
Basic Parameters Advanced Pa	arameters Mo	tor Runing					
	🙈 Import param	eters.					×
Protect Parameters	$\leftarrow \rightarrow \vee$	↑ 🚬 > 桌面 > 参数			~ C	在 参数 中搜索	Q
Over Voltage(V):	55. 0	文件本				= •	
Low Voltage(V):	20. 0	· 1 _{名称}	^	修改日期	类型	大小	
Stall Time Limit(s):	0.00	parameters	,	2024-07-13 11:20	Microsoft Ex	cel 7 KB	
E-Brake Start Duty Cycle(%):	0 三直	*	-				
Current Sample Res(mΩ):	5.00 🛓 下載	*					
E-Brake Hold Duty Cycle(%):	0 📑 文档	*					
Brake Mode: E-E	Brake 🔀 图片	*					
Read	ve 🕑 音乐	*					
	12 视频	*					
	app 🦻						
	Exe						
		文件名(N): parameters			~	Excel Files (*.xlsx)	~
					2	打开(2)	取消
Export parameters							
Import parameters							
			uron [®]				

Figure 3-12 Select the target file

The setup software will read all parameters in the file, write all parameters to the motor, and pop-up window prompts "Parameters were imported to the motor successfully", as shown in Figure 3-13.

A MYACTUATOR Setup Software V4.0		- 🗆 X
	SETUP SOFTWARE	
Basic Parameters Advanced Parameters	Motor Runing Settings	Contact Us
Protect Parameters Over Voltage (V): 55.00 Low Voltage (V): 20.00 Stall Time Limit(a): 0.00 E-Brake Start Duty Oyole (N): 0 Current Sample Res (mO): 5.00 E-Brake Hold Duty Oyole (N): 0 Brake Mode: E-Brake Read Save Export parameters Import parameters	Plan Parameters Max Positive Position (Deg) : 65535 Min Negative Position (Deg) : 65535 Position Plan Max Acc (Dps/s) : 5000 Position Plan Max Dec (Dps/s) : 5000 Position Plan Max SenndRPM) : 2500 Top X Parameters were imported to the motor successfully Read Save	Motor Parameters Max Current(A): Stall Current(A): 15.00 Stall Current(A): 15.00 Shutdown Temp(C): 100.00 Resume Temp(C): 90.00 Max Speed (RPM): 4000.00 Enable 2nd Encoder: Enable 2nd Encoder: Read Read Save
Connection status:Connected		Current Communication ID:1

Figure 3-13 Import parameters to the motor

4. Motor Running Interface

The motor running interface is divided into three parts, running part, real-time status curve part and status display part, as shown in Figure 4-1.



MYACTUATOR Setup Software V4.0						-	D X
		SETUP	SOFTWARE				
				_			
Basic Parameters Advanced Para	meters Mk	otor Runing	Settings	Conta	ct Us		
Run	Real Time Sta	tus Curve				Status Display	
Operation mode: Position 🔻						Absolute Angle(Deg)	: -2. 99
		urrent				Speed (RPM) :	-0. 00
Absolute Angle(Deg):		peed				Bus Voltage(V):	48.00
Increment Angle(Deg):	100	OSITION				Q-Axis Voltage(V):	
Speed (RPM) :						Q-Axis Current(A):	0.00
Current (A) :						D-Axis Voltage(V):	
Alternat Motion:						D-Axis Current(A):	
Target Pos 1(Deg):						Motor Temp("C):	31
Run Speed 1 (RPM) :						PCB Temp(C):	
Run Time 1 (ms):						Motor Status:	
Target Pos 2(Deg):							
Run Speed 2 (RPM) :							
Run Time 2(ms):							
Start Motor Stop Motor							
	-150 L	00-00-15	00.00.30	00-00-45	00:01:00		
Reset			Time				
Connection status Connected		MYAC	TUATOR		0.	rent Communication ID	.1
Connection status:Connected		ndana an			60	irrent communication ID	

Figure 4-1 Motor operation interface

The motor can be controlled to run in a certain mode, as shown in Table 4-1. Table 4-1 The explanation of control mode

Control mode	Explanation
Position mode	Specify the speed and position to control the motor to run at the
	specified speed to the specified position.
Incremental	Specify the incremental angle and speed to control the motor to run
mode	the specified incremental angle from the current position.
Speed mode	Specify the speed to control the motor to run at the specified speed.
Current mode	Specify the current to control the motor to run at the specified
	torque current.
	Specify the target position 1, running speed 1, running time 1,
Reciprocating	target position 2, running speed 2, running time 2 to control the
motion mode	motor reciprocating.

Click the "Stop Motor" button to stop the motor. In addition, when switching to the basic parameter screen and advanced parameter screen, the control motor is stopped to prevent accidents. Click the "Reset" button to restart the motor master controller.

The real-time status curve part collects data in real time and draws dynamic line graphs, so you can view the curve changes within one minute, and the specific meaning

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of the line is shown in Table 4-2.

Table 4-2 The explanation of real-time status curve

Curve Colour	Orange	Blue	Red
Meaning	Current (A)	Speed (RPM)	Position (Deg)

4.1. Position Mode

Select the position mode as the working mode, enter the position and speed, click the "Start Motor" button, you can control the motor to run at the specified speed to the specified position and hold, as shown in Figure 4-2. If any item of position and speed is empty, the setup software will not perform any operation.



Figure 4-2 Schematic diagram of position mode operation

4.2. Incremental Mode

Select the working mode as incremental mode, enter the incremental angle and speed, click the "Start Motor" button, you can control the motor to the current position as the starting point to run the specified incremental angle, as shown in Figure 4-3. If any of the incremental angle and speed is empty, the setup software will not perform any operation.





A MYACTUATOR Setup Software V4.0							• ×
		SETUP	SOFTWARE				
Basic Parameters Advanced Para	meters M	otor Runing	Settings	Contac			
Run 1	Real Time Sta	tus Curve				Status Display	3
Operation mode: Increment	350 m					Absolute Angle(Deg)	120. 01
		Current				Speed (RPM) :	0.00
Absolute Angle(Deg):		Speed				Bus Voltage(V):	48.00
Increment Angle(Deg): 30		osition				Q-Axis Voltage(V):	-
Speed (RPM) : 1000						Q-Axis Current(A):	0.30
Current (A) :						D-Axis Voltage(V):	-
Alternat Motion:						D-Axis Current(A):	-
Target Pos 1(Deg):						Motor Temp(°C):	31
Run Speed 1 (RPM) :					0	PCB Temp(°C):	0
Run Time 1 (ms) :						Motor Status:	Normal
Target Pos 2(Deg):							
Run Speed 2(RPM):							
Run Time 2(ms):							
2 Start Motor Stop Motor							
	-150						
Reset	00:03:00	00:03:15	00:03:30 Time	00:03:45			
Connection status:Connected		-MYAC			Cu	rrent Communication ID	:1

Figure 4-3 Schematic diagram of incremental mode operation

4.3. Speed Mode

Select the speed mode as working mode, input the speed, click the "Start Motor" button, you can control the motor to run at the specified speed, as shown in Figure 4-4. If the speed is empty, the setup software will not perform any operation.

A MYACTUATOR Setup Software V4.0				- 🗆 ×
	SE	TUP SOFTWARE		
Basic Parameters Advanced Para	ameters Motor Runing	Settings	Contact Us	
Run Image: Speed Operation mode: Speed Absolute Angle (Deg): Image: Deg): Increment Angle (Deg): Image: Deg): Speed (RPM): Image: Deg): Ourrent (A): Image: Deg): Alternat Motion: Image: Deg): Target Pos 1 (Deg): Image: Deg): Run Time 1 (ms): Image: Deg): Target Pos 2 (Deg): Image: Deg): Run Speed 2 (RPM): Image: Deg): Run Time 2 (ms): Image: Deg): 2 Stop Motor Reset	Real Time Status Curve	00.05:15 00:05:30 Time		Status Display 3 Absolute Angle(Deg):342.79 Speed (BPM): 100.54 Speed (BPM): 100.54 Speed (BPM): - O-Axis Voltage(V): - - - O-Axis Voltage(V): 0.35 - - D-Axis Voltage(V): - - - D-Axis Voltage(V): - - - D-Axis Ourrent(A): - - - D-Axis Ourrent(A): - - - Motor Temp(C): 31 POB Temp(C): 0 Motor Status: Buenel - -
Connection status:Connected		MYACTUATOR 0		Current Communication ID:1

Figure 4-4 Schematic diagram of speed mode operation

4.4. Current Mode

Select the current mode as working mode, input the current, click the "Start Motor"



button, you can control the motor to run at the specified current, as shown in Figure 4-5. If the current is empty, the setup software will not perform any operation.

Because of safety considerations, for the brake motor, the current mode of the setup software cannot directly open the brake, and the position mode, increment mode and speed mode can directly open the brake.



Figure 4-5 Schematic diagram of current mode operation

4.5. Alternate Motion Mode

Turn on the "Alternate Motion" switch, enter the target position 1, running speed 1, running time 1, target position 2, running speed 2, running time 2, click on the "Start Motor" button, you can control the motor to run at running speed 1 to the target position 1, then the motor will run at running speed 2 to the target position 2, the cycle is repeated, as shown in Figure 4-6. If any of the data is empty, click the "Start Motor" button, the setup software will not perform any operation.

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Figure 4-6 Schematic diagram of alternate motion mode operation The following three points about the running time are explained :

(1) Regardless of whether the target position is reached or not, as soon as the run time is exceeded, the motor will immediately proceed to the next stage of motion.

(2) When the target position is reached, if the running time is not exhausted, the motor will enter the waiting state, and after exhausting the running time the motor will enter the next stage of movement.

(3) After switching on the "Alternate motion" switch, even if an operating mode is selected and the required data is entered, clicking on the "Start motor" button, the setup software will prioritize running the motor in alternate motion mode.

4.6. Motor Status

The status bar displays the current motor status in real time, as shown in Table 4-3. Table 4-3 The explanation of protection parameters

Status	Significance
Normal	The motor is operating normally
Hardware over-current	The motor current exceeds the limit value
Motor stallod	The motor current exceeds the stall current and lasts
WIOTOT Staticu	longer than the stall time

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Under-voltage	The operating voltage is lower than the under-voltage protection voltage			
Over-voltage	The operating voltage exceeds the over-voltage protection voltage			
Phase current over-current	The phase current of the motor exceeds the limit value			
Power overrun	The motor power exceeds the limit value			
Calibration parameters are	Calibration parameters are incorrectly written			
incorrectly written	MYAO usble Innovau			
Speeding	The motor speed exceeds the limit value			
On-board device overheated	The temperature of the on-board device of the motor			
	exceeds the limit value			
Motor overheated	The motor temperature exceeds the over-temperature			
	protection temperature			
Stall time limit	When the stalled rotor time exceeds this parameter, the			
	motor stops and the error is reported: Motor stalled			
Encoder calibration error	Encoder calibration error			
Without receiving motor	The host computer communicates with the motor, but			
message	the host computer does not receive the required message			

5. Set Up the Interface

In the setting interface, you can choose the language: Chinese or English, and the setup software will automatically obtain the local language of the current Windows system when it starts, if it is Chinese, it will be displayed in Chinese, and if it is not Chinese, it will be displayed in English.

6. Upgrade the Firmware

Before upgrading the firmware, you need to make the following preparations: (1)

(0)



The connection of hardware device; (2) The configuration of operating environment of the setup software, the specific operation process is the same as that of using the setup software, see the first part of the manual: Preparation.

The process of writing the upgrade firmware to the motor is described separately depending on whether the motor has an operating program. The judging method is: when the hardware connection is correct, turn on the power switch, and the green light flashing of the motor indicates that there is no operating program; otherwise, there is an operating program.

6.1. Motor without Operating Program

Turn off the power switch, open the update setup software, enter the motor ID, you don't need to set the port and baud rate, directly click the "Connect Device" button to connect CAN-USB conversion device, then the button changes to "Disconnect", as shown in Figure 6-1.

1	Myactuator Updata			00
Parameter	setting]		
O CAN-EN	ICP 🕢	Port	~	Disconn
	D 1 🗧	Bps 9600	~	ect

Figure 6-1 Update setup software connection to the conversion device

Click the "Open file" button to select the required bin file in the file dialogue box, if it opens successfully, the basic information of the bin file will be displayed in the "Upgrade file information" module, as shown in Figure 6-2.







Figure 6-2 The "Upgrade file information" module displays basic information of bin files.

Click the "Updata" button, for motors with operating program, the setup software can directly write the upgrade firmware into the motor without re-powering. After successful download, as shown in Figure 6-3, you can directly close the update setup software.

	100 %	
Downloading Download success!	4	Start ownl adino
		4-110-

Figure 6-3 Firmware upgrade completed

6.2. Motor with Operating Program

Open the setup software, enter the advanced settings, read motor parameters, turn off the CAN filter enable, as shown in Figure 6-4, and click save.

A MYACTUATOR Setup Software V4.0	- 🗆 X
SETUP SOFT	WARE
Basic Parameters Advanced Parameters Motor Runing Sett	ings Contact Us
Protect Parameters Over Voltage(V): Low Voltage(V): Stall Time Limit(a): Ourrent Sample Res(mC): Brake Mode: Read	65535 65535 5000 5000 5000 5000 5000 5000 5000 5000 5000 5000 5000 5000 66535 5000 5000 Source Temp (C): 90.00 Max Speed (RPM): 60000.00 Enable 2nd Encoder: CK Save
Export parameters	
Connection status:Connected	Current Communication ID:1

Figure 6-4 Reading motor parameters in the setup software

Close the setup software, open update software, input the motor ID, do not need to set the port and baud rate, directly click on the "Connect Device" button, you can open the CAN-USB conversion device, the button changes to "Disconnect", as shown in Figure 6-5.



3	Myact		00	
Paramet	er setting]		
O CAN-E	мср 🕢	Port	~	Disconn
	ID 1 🗧	Bps 9600	~	ect

Figure 6-5 Update setup software connection to the conversion device

Click the "Open file" button, select the bin file required for upgrading the firmware in the file dialogue box, and click "Open". If you open it successfully, the basic information of the bin file will be displayed in the "Upgrade file information" module, as shown in Figure 6-6.



Figure 6-6 The "Upgrade file information" module displays basic information of bin files

Click the "Updata" button, for motors with operating program, update setup software can directly write the upgrade firmware into the motor without re-powering, as shown in Figure 6-7. After successful download, you can directly close the Update setup software.



Figure 6-7 Firmware upgrade completed

7. Common Problems and Solutions

This subsection provides solutions to common problems during the use of setup software and firmware upgrades. If you still can't solve the problem, please contact us.





7.1. Common Problems and Solutions for Using Setup Software

7.1.1. Failure to Open CAN Device

If the pop-up window "Failed to open CAN device, please check the CAN device!"

appears, as shown in Figure 7-1.

Basic Parameters	Advanced Parameters	Notor Runing	Settings	Contact		
Communication	ID: 1	Set ID		Connect		Disconnected
Cal	1st Encoder	Calibrated		Calibrat	2nd Encoder	librated
Set Zer	ro Point	C 🏔 Tip		× Point		
		Hailed to open CAI	N device, please check the	CAN device!		
Motor Informat				ок		
Motor ID:				Speed Loop	Q-Axis Current	D-Axis Current
Motor Nunber	: 0		0. 0100	0. 0200	1.0000	1.0000
Motor Name:	RH-17-P100		0.0000	0. 0001	0. 1000	0. 1000
FW Version:	2024033001		2.0000	0.0000	0.0000	0.0000
Factory Time	: 0	R(Slope)	0.0000	0.0000	0.0000	0.0000
Reduction Ra	tio: 101		0.0000	0.0000	0.0000	0.0000
Read	Save		Read		Save	

Figure 7-1 Failed to open the CAN device

Please check if the situation described in table 7-1 exists and deal with it.

Table 7-1 Troubleshooting the failure to open the CAN device

Situation	Methods of handling
Other software occupancy	Close the software that may be occupied and reconnect it.
Unconnected	Check the connection between the conversion device and
	computer.
Faulty connection	Observe the green light of the conversion device'CAN1
Faulty connection	channel, if it doesn't light up, reconnect the hardware.

7.1.2. Failure to Send Data

TUATOR If the pop-up window "Sending message failed, please check if the motor status, CAN device, and wiring are correct!" appears, as shown in Figure 7-2.

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		_	SETU	P SOFTWAR	E		
Basic Parameters Adv	anced Parameters	Notor		Settings	Contact		
Communication ID:			Set ID		Connect		Disconnected
0.1 ibert	1st Encoder	Onlike			2.13k-st	2nd Encoder	liberted
Set Zero Point		Sending n	nessage failed, plea	se check if the motor status	; CAN device, and		
Motor Information					ОК		
Motor ID:					Speed Loop	Q-Axis Current	D-Axis Current
Motor Number:				0.0100	0. 0200	1.0000	1.0000
Motor Name:	RH-17-P100			0.0000	0. 0001	0. 1000	0. 1000
FW Version: 2	024033001			2.0000	0.0000	0.0000	0.0000
Factory Time: ()		R (Slope)	0. 0000	0. 0000	0.0000	0.0000
Reduction Ratio:	101			0.0000	0.0000	0.0000	0.0000
Read	Save			Read		Save	

Figure 7-2 Failure to send data

Please check if the situation described in Table 7-2 exists and deal with it.

Table 7-2 Troubleshooting	the failure	to send data
---------------------------	-------------	--------------

Situation	Methods of Handling
No power	Check the power supply, whether the motor indicator is normal,
/Under voltage	and whether the DC power supply voltage is correct.
Wrong motor CAN	Check whether the CAN line is connected to the CAN0 channel, and whether the CANH line and CANL line are connected to the
lines connection	H and L of the CAN0 channel in turn.

7.1.3. No Response Received from Motor

If the pop-up window "We have not received a response from the motor. Please check if the motor status, connection ID, and wiring are correct!" appears, as shown in Figure 7-3.







A MYACTUATOR Setup Software V4.0				-	\square \times
	SETUP	SOFTWARE			
Basic Parameters Advanced Parameters	Motor Runing	Settings	Contact Us		
Communication ID: 2	Set ID		Connect	Disconnected	
1st Encoder			2nd	Encoder	
Galibrat	Calibrated		Calibrat	Calibrated	
	🚕 Tip		×		
Set Zero Ponit	We have not received a respons	e from the motor. Please ch	eck if the motor		
	status, connection ID, and wiring	are correct!			
Nator Information			ок		
		Desition Lass	Saved Lana		
Motor ID: Motor Number:			Sheed Loop	PAXIS CUITERIC D-AXIS CUITERIC	
Motor Name:					5
FW Version:	D D				6 I I
Factory Time:	R (Slope)				
Reduction Ratio:			-		
Read		Read		Save	
		~			
Connection status:Disconnected	A			Current Communication ID	
	10115	elenne delably researce			

Figure 7-3 No response received from motor

Please check if the situation described in table 7-3 exists and deal with it.

Table 7-3 Troubleshooting the failure to response received from motor

Situation	Methods of Handling
The motor that matches the set communication	Check if the communication ID is
ID could not be found on the CAN bus	correct
Problems with connection	Check hardware device connections

7.1.4. Incorrect File Data

When importing parameters, if the pop-up window "The file data is incorrect.", as shown in Figure 7-4.



Figure 7-4 Incorrect file data





Replace a properly formatted motor parameter file with complete data.

7.2. Common Problems and Solutions for Firmware Upgrades

7.2.1. Failure to Open CAN Device

If the pop-up window "Failed to open the device, please check that the device type and device index number are correct" appears, as shown in Figure 7-5.

Pa	Myactuator Updata	••
0 1	CAN-EMCP O Port MBUF ID 0 + Bps 9600	V Connect device
Up	grade file information	
Fail ind	led to open the device, please check that the d ex number are correct	evice type and device
		确定
	0.0/	

Figure 7-5 Failure to open CAN device

Please check if the situation described in table 7-4 exists and deal with it.

	Table 7-4	Troubleshooting	the failure to	open CAN	device
--	-----------	-----------------	----------------	----------	--------

Situation	Methods of Handling	
Other software occupancy	Close the software that may be occupying it and reconnect	
Unconnected	Check the connection between conversion device and	
	computer	
Faulty connection	Observe the green light of the conversion device'CAN1	
Taulty connection	channel, if it doesn't light up, reconnect the hardware	

7.2.2. Power Failure during Firmware Upgrades

If there is a sudden power failure during the firmware upgrade process, the progress bar will stop. Recharging the motor, when the green light of the motor is blinking, follow the method that writing the upgrade firmware to the motor with no operating program to perform the firmware upgrade.

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7.2.3. Firmware Selection Error

If the wrong firmware is selected and written to the motor, a pop-up window "The firmware does not match the hardware version, please re-select the correct firmware!", this means the firmware is wrong, as shown in Figure 7-6, please replace the correct firmware.

Param	eter setting	
O CAN	-EMCP 🕥 Port	Disconn
	JF ID 1 - Bps 9600	~ Eet
Upgra	de file information	
File na	me: C:\Nsers\HP\Nesktop\谐波	固件 一一一一
		>
he firmware doe	s not match the bardware version ple	>
he firmware doe rmware!	s not match the hardware version, ple	ase re-select the correct
he firmware doe rmware!	s not match the hardware version, ple	> ase re-select the correct
he firmware doe rmware!	s not match the hardware version, ple	ase re-select the correct 确定
he firmware doe rmware!	s not match the hardware version, plea	ase re-select the correct 确定

Figure 7-6 Firmware error



