

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
V1.1.0.2	初始状态	2023.12	
V1.1.0.3	更新	2024.1	
V1.1.1.0	增加英文版本	2024.7	

Contents

Robot Hand Software Instructions	1
1The installation and operation of the upper computer	4
2Functions Of The System	4
2.1System Interface	4
2.2Internal Status Settings interface	5
2.3 Menu Bar Interface	5
2.3.1 About	5
2.3.2 Help Manual	6
3 Basic operation	8
3.1 Open the serial port	8
3.2 Six Movement Modes And Curve Display	8
3.3Set Parameters	9
3.3.1 Location Setting	11
3.3.2 Acceleration Setting	12
3.3.3 Speed Setting	12
3.3.4 Torque Setting	13
3.3.5 Finger Mode Setting	14
4 Set Internal Parameters	14
4.1Modification Procedure Description	14
4.2Power On And Off	17

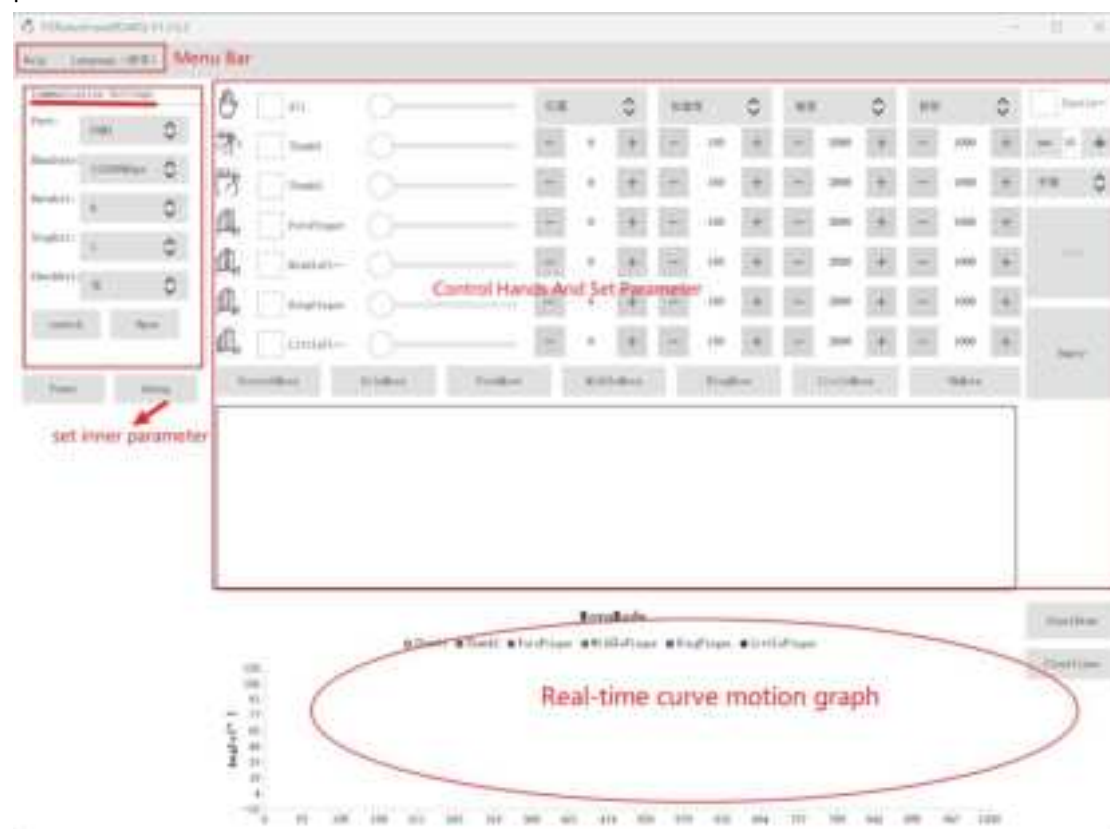
1The installation and operation of the upper computer

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.

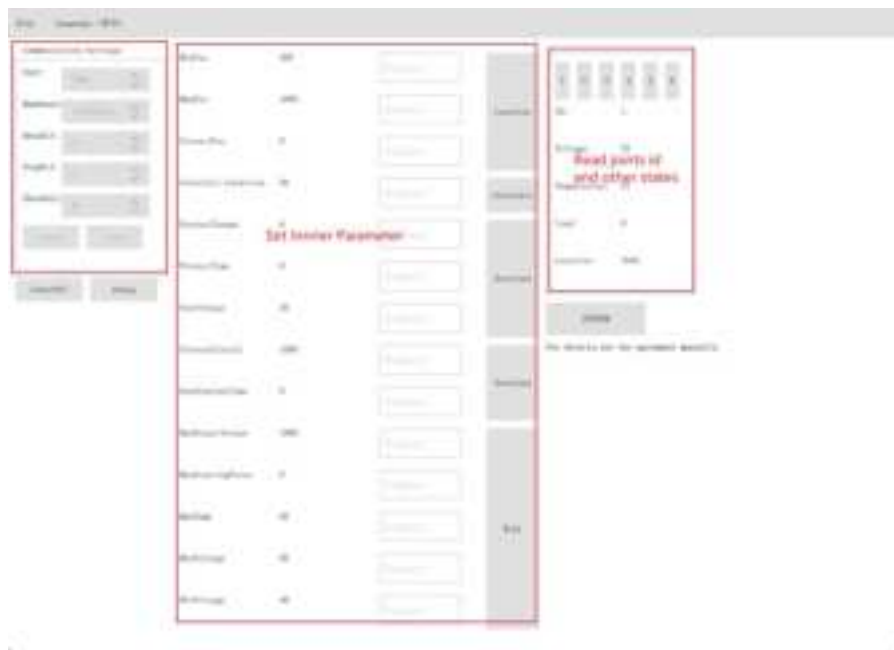


2.2 Internal Status Settings interface

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.



2.4 Chinese-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.



3.3.1 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

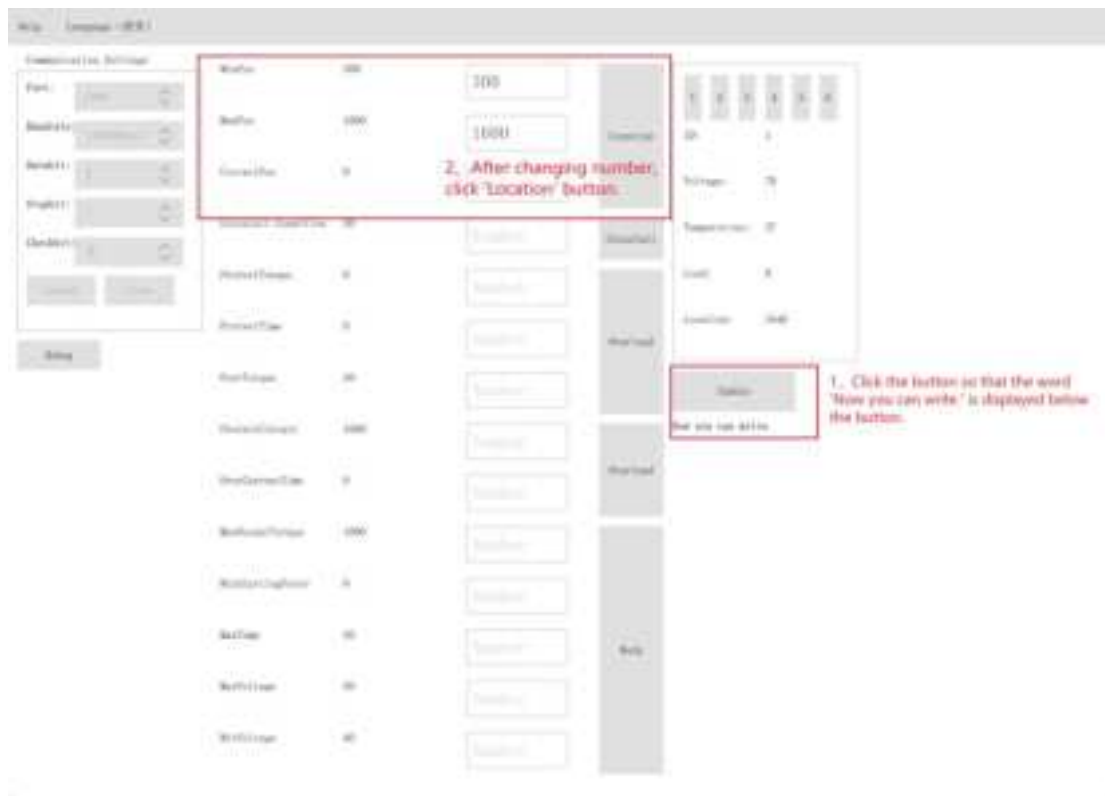


Step5 Modify value

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

	1	2	3	4	5	6
ID:	1					
Voltage:	70					
Change reference values in real time						
Temperature:	37					
Load:	0					
Location:	1646					

Angle value Resets the reference value



4.2 Power On And Off

1、Power on and off: indicates the working state of the internal manipulator. The user is powered on by default.

