

# Robot Hand Software User Guide

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## Robot Hand

### Robot Hand Software

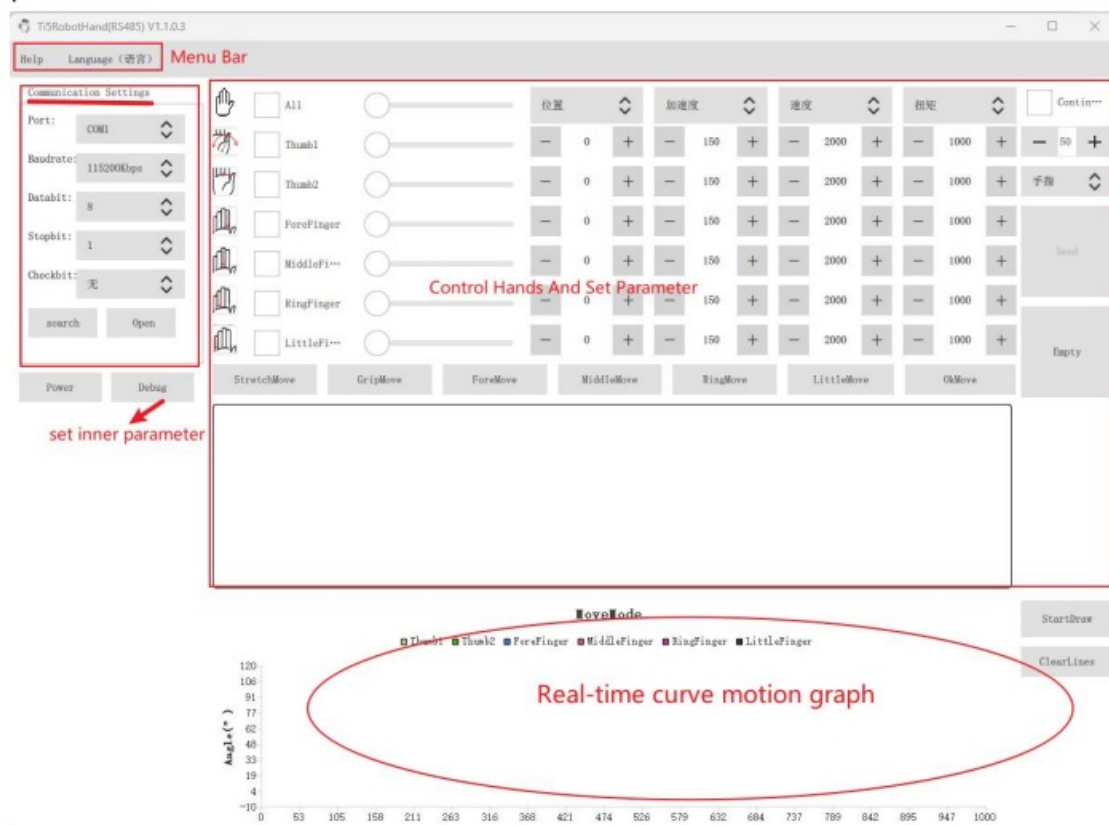
#### The installation and operation of the upper computer

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

#### Functions Of The System

##### System 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.



### 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

HelpLanguage (语言)

Communication Settings

Port:COM4

Baudrate:115200bps

Databit:8

Stopbit:1

Checkbit:无

searchClose

PowerOffDebug

MinPos300Number

MaxPos1600Number

CorrectPos0Number

Uninstall Condition30Number

ProtectTorque0Number

ProtectTime0Number

OverTorque30Number

ProtectCircuit1000Number

OverCurrentTime0Number

MaxOutputTorque1000Number

MinStartingForce0Number

MaxTemp50Number

MaxVoltage50Number

MinVoltage40Number

Location

Uninstall

Overload

Overload

Work

123456

ID:1

Voltage:70

Read joints id and other states

Temperatruer:27

Load:0

Location:1646

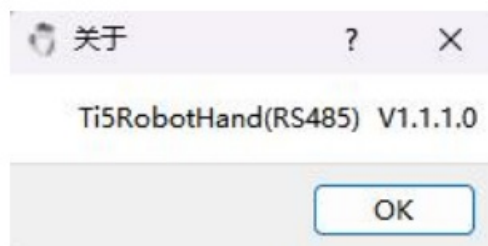
EEPROM

For details, see the agreement manually.

Menu Bar Interface

About

Click the “About” button to view the version number.

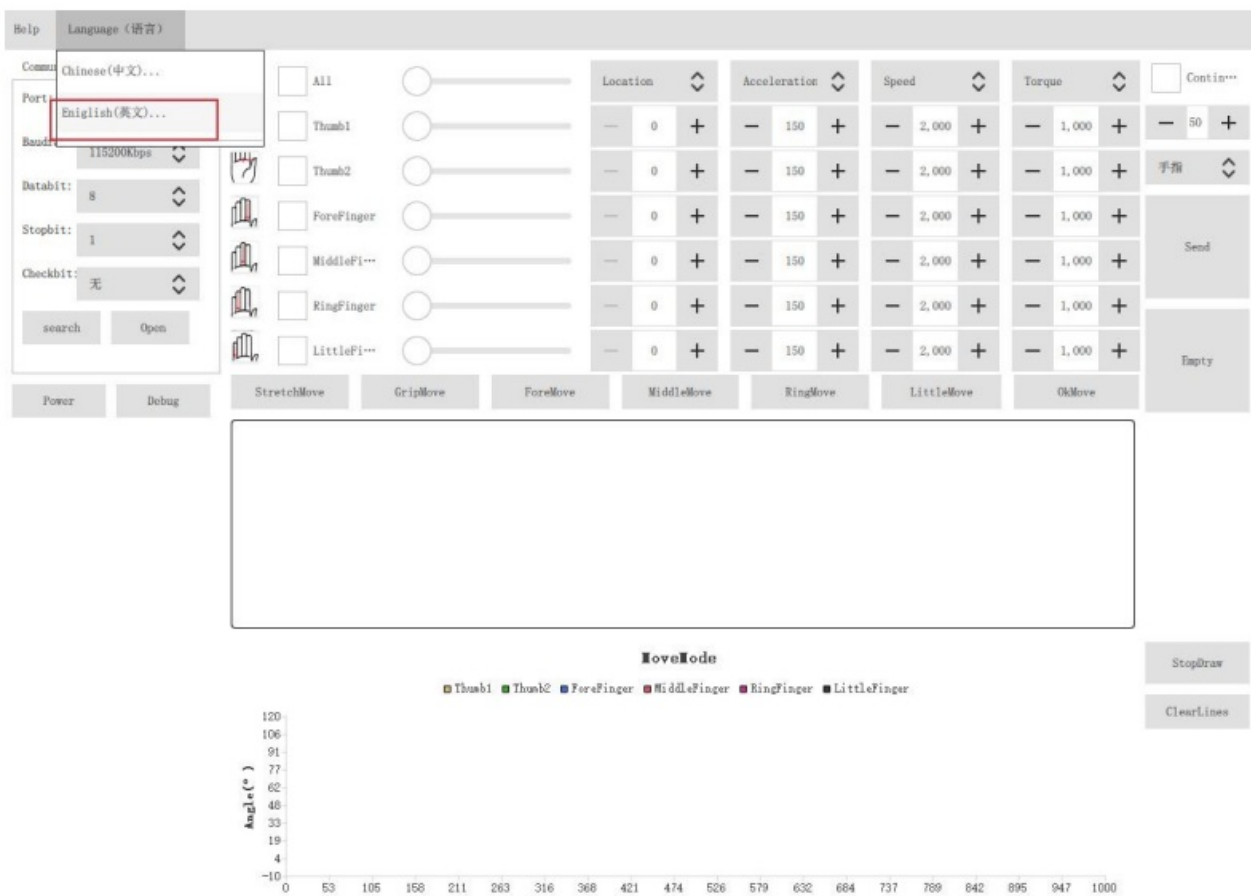


## Help Manual

Check the user manual.



## Chinese-English version



## Basic operation

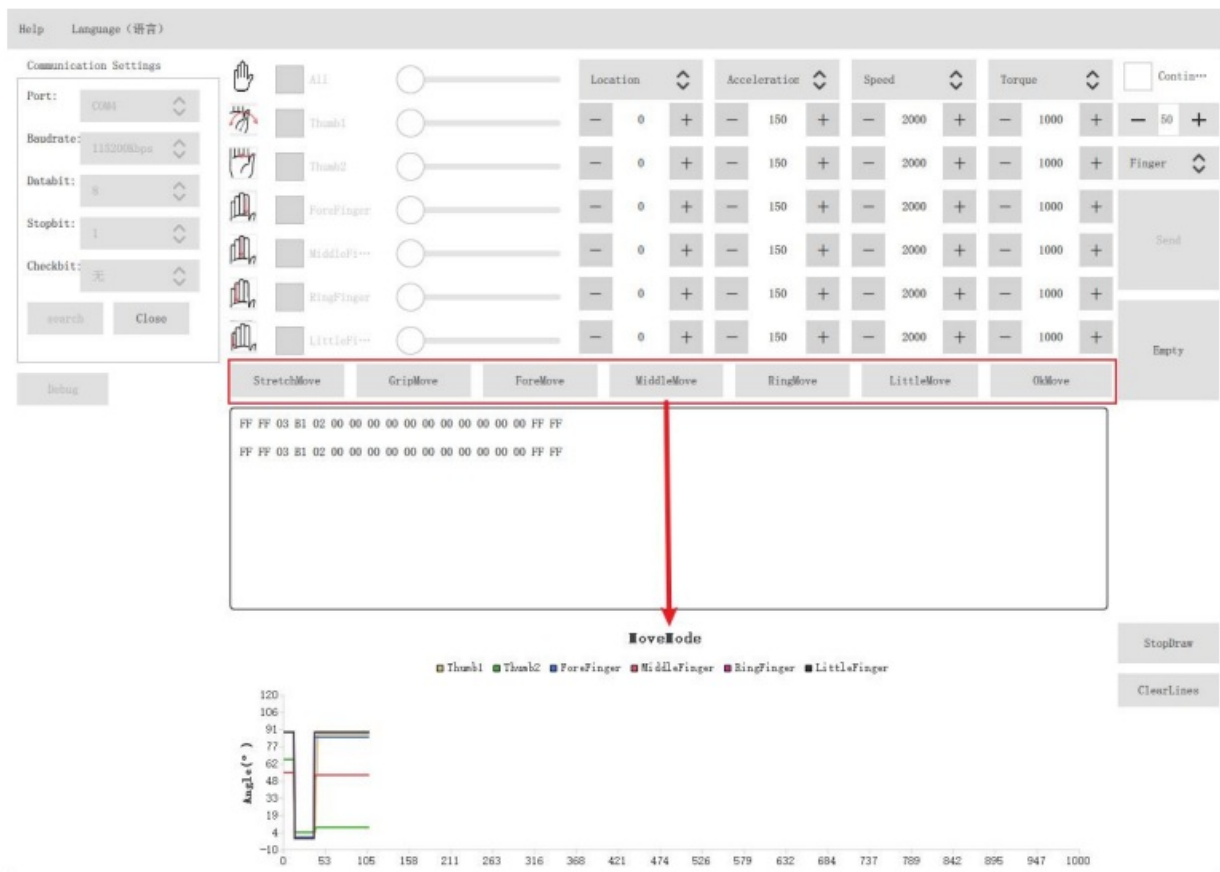
## Open the serial port

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.



## 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.



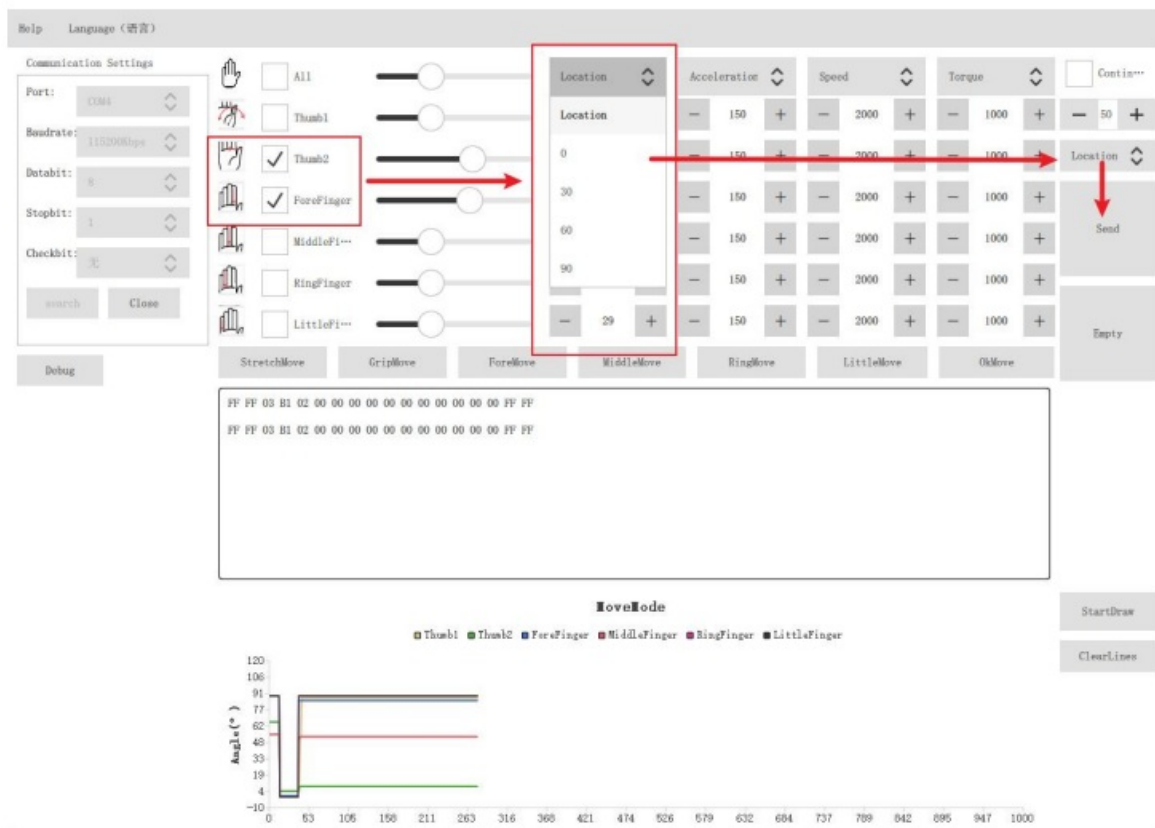
## Set Parameters

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.



## Location Setting

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



## Acceleration Setting

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



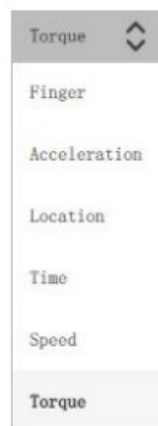


Check the joint to be set, the torque contains 1-1000, here the default power on after 1000.



## Finger Mode Setting

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



## Set Internal Parameters

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

## Modification Procedure Description

Step :1 Click the “Stop Painting” button



Help

Language (语言)

Communication Settings

Port: COM1

Baudrate: 115200bps

Databit: 8

Stopbit: 1

Checkbit: 无

search

Close

Debug

MinPos: 300

MaxPos: 1600

CorrectPos: 0

Uninstall Condition: 30

ProtectTorque: 0

ProtectTime: 0

OverTorque: 30

ProtectCircuit: 1000

OverCurrentTime: 0

MaxOutputTorque: 1000

MinStartingForce: 0

MaxTemp: 50

MaxVoltage: 50

MinVoltage: 40

Number

Number

Number

Number

Number

Number

Number

Number

Number

Number

Number

Number

Location

Uninstall

Overload

Overload

Work

1 2 3 4 5 6

ID: 1

Voltage: 70

Temperature: 37

Load: 0

Location: 1646

EEPROM

For details, see the agreement manually.

step3 select joint id

step4 select btn to change state

Step4 Modify the internal status parameter values by module

Help

Language (语言)

Communication Settings

Port: COM1

Baudrate: 115200bps

Databit: 8

Stopbit: 1

Checkbit: 无

search

Close

PowerOff

Debug

MinPos: 300

MaxPos: 1600

CorrectPos: 0

Uninstall Condition: 30

ProtectTorque: 0

ProtectTime: 0

OverTorque: 30

ProtectCircuit: 1000

OverCurrentTime: 0

MaxOutputTorque: 1000

MinStartingForce: 0

MaxTemp: 50

MaxVoltage: 50

MinVoltage: 40

300

1600

Number

Number

Number

Number

Number

Number

Number

Number

Number

Number

Number

Location

Uninstall

Overload

Overload

Work

1 2 3 4 5 6

ID: 1

Voltage: 55

Temperature: 49

Load: 0

Location: 309

Unable

Now you can write.

Enter the value you want to modify

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						
Temperatrue:	37					
Load:	0					
Location:	1646					

Angle value Resets the reference value

Help

Language (语言)

Communication Settings

Port: COM4

Baudrate: 115200bps

Databit: 8

Stopbit: 1

Checkbit: 无

search

Close

Debug

MinPos: 300

MaxPos: 1600

CorrectPos: 0

Uninstall Condition: 30

ProtectTorque: 0

ProtectTime: 0

OverTorque: 30

ProtectCircuit: 1000

OverCurrentTime: 0

MaxOutputTorque: 1000

MinStartingForce: 0

MaxTemp: 50

MaxVoltage: 50

MinVoltage: 40

300

1600

Number

Number

Number

Number

Number

Number

Number

Number

Number

Number

Number

Location

Uninstall

Overload

Overload

Work

1

2

3

4

5

6

ID: 1

Voltage: 70

Temperatrue: 37

Load: 0

Location: 1646

1. Click the button so that the word 'Now you can write.' is displayed below the button.

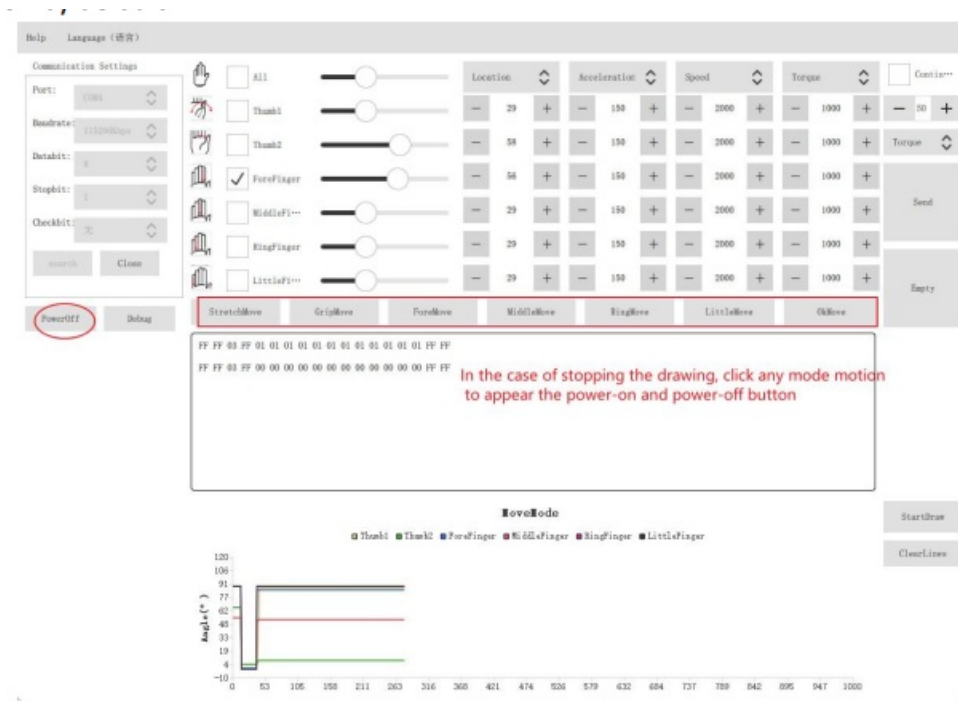
Unable

Now you can write.


2. After changing number, click 'Location' button.

## Power On And Off

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



## Documents / Resources

	<p><a href="#">Robot Hand Robot Hand Software [pdf] User Guide</a> b6394cd9, 485, Robot Hand Software, Hand Software, Software</p>
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## References

- [User Manual](#)

[Manuals](#), [Privacy Policy](#)

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