

(*) Reduction ratio of harmonic driver inside of the motor shell. (Directly effects rpm value)

(**) Value of targeted angle intervals. Driver divides the target angle into intervals and executes them in order. Nominal interval is 100.

NOTE1: Canbus communication speed is 1Mbit/s.

NOTE2: Canbus Extended Id structure is shown below:

ID Structure: 0Xuuu000dd

uuu: Unit Number, this specifies the unit itself to gather related data from Bus. (uuu: 0X011000dd – 0XFFF000dd.)

dd: Data type, this block specifies the types of data like speed, angle or torque, received by the related unit. (dd, shown in the TABLE-1.)

TABLE-2

LED STATUS TABLE			
ERROR STATUS	LED STATUS		
	LED1 (G)	LED2 (R)	LED3 (Y)
ROTARY ENCODER	ON	ON	OFF
POSITION SENSOR	ON	OFF	ON
CURRENT SENSOR	ON	OFF	OFF
HALL EFFECT SENSOR	OFF	OFF	ON
24V POWER SUPPLY	OFF	ON	OFF
MOTOR MOTION	OFF	ON	ON
JOINT POSITION	BLINK	OFF	OFF
EEPROM READ / WRITE	OFF	BLINK	ON
MCU OSCILLATOR	OFF	OFF	BLINK
MCU TIMER	BLINK	OFF	BLINK
MCU ADC	OFF	BLINK	ON
MCU CANBUS	OFF	BLINK	BLINK

NOTE3: The above table shows the led status of errors. (TABLE-2)