

Servo Motor Controller Instructions for use

Ver 3.11

Parameters:

Hardware	32 channels	24 channels	16 channels
Operating Voltage	5V	5V	5V
Servo Motor Input Voltage	According to the servo	According to the servo	According to the servo
СРИ	32bit	32bit	32bit
Baud Rate (USB)	115200	115200	115200
Baud Rate	4800、9600、19200、	4800、9600、19200、	4800、9600、19200、
(Bluetooth、WIFI、UART)	38400、57600、115200	38400、57600、115200	38400、57600、115200
Flash Capacity	16M	16M	16M
Servo motor synchronous	22	24	16
quantity	52	24	10
Max Action Groups	255	255	255
control precision	1us	1us	1us
Servo Motor signal isolation	Yes	Yes	Yes
Current limiting protection	No	Yes	Yes
MPU6500	No	Yes	NO
External sensor support	No	No	Yes
3D Virtual	All	All	Part
	1.CPU power indicator	1.CPU power indicator	1.CPU power indicator
	led (red)	led (red)	led (red)
Indicator led	2.Servo motor power	2.Servo motor power	2.Servo motor power
	indicator led (green)	indicator led (green)	indicator led (green)
	3. wireless remote	3.wireless remote	3.wireless remote
	control (Yellow)	control (Yellow)	control (Yellow)
Size	64mm X 45mm	64mm X 47.5mm	58.5mm x 45mm
Communication Protocol	UART	UART	UART
	Windows XP or later,	Windows XP or later,	Windows XP or later,
Computer Software	Mac OS 10.8 or	Mac OS 10.8 or	Mac OS 10.8 or
	later ,Linux(kernel 3.0	later ,Linux(kernel 3.0	later ,Linux(kernel 3.0
	or later)	or later)	or later)
Low pressure alarm	Default Open	Default Open	Default Open
Servo motor initial value	Default 1500	Default 1500	Default 1500
Support The Servo motor Type	9G~55G	9G~55G	
	C51、Arduino、ARM、	C51、Arduino、ARM、	C51、Arduino、ARM、
Online Operations Support	MSP、DSP、WIFI、	MSP、DSP、WIFI、	MSP、DSP、WIFI、
	Bluetooth, Compute	Bluetooth, Computer	Bluetooth, Computer
	1. one servo motor	1. one servo motor	1. one servo motor
wireless remote control	2 action groups	2 action groups	2 action groups
	2. action groups	2. action groups	2. action groups
	control	control	control

32 channels:

24 channels:





16 channels:



Instruction:

Communication Protocol:

serial communication	baud rate	parity bit	data bits	stop bits
TTL	9600(default)	none	8	1

Instruction format:

name	Instruction	description
		Data 1 refers to the servo' s channel
		Data 1500 Refers to the servo' s location,
		in the range 500-2500
Controllor single convo	#1P1500T1000D800\r\p	Data 1000 refers to the time of execution
Controller single servo	#121200110000800\1\11	and represents the speed, in the range
		100-9999
		Data 800 refers to the Instruction interval of
		delay time, in the range 100-9999
		Data 1、2 refers to the servo's channel
	#1P1500#2P1500T1000D800\r\n	Data 1500 Refers to the servo' s location,
		in the range 500-2500
Controller multiple servo		Data 1000 refers to the time of execution
controller mattiple servo		and represents the speed, in the range
		0-9999
		Data 800 refers to the Instruction interval of
		delay time, in the range 0-9999
Run action groups	G1F3\r\r	Data 1 refers to the group' s channel
Run action groups		Data 3 refers to the frequency of runs
Stop action groups	~ST	Stop running action groups (Note: not
		pause)
Restart CPU	~RE	Restart CPU

Note: "\r\n" converted to hexadecimal is "0X0D 0X0A" ;All instruction is ASCII.

```
"0x0D" == "\r" == "CR"
"0x0A" == "\n" == "LF"
```

Tip: If the function or software used in the program has "rn", it is not necessary to add it at the end. When the instruction is completed Controller feedback "OK".

Wiring methods:

<image>

I. Power supply access method, *P.1* location:

VCC: Servo motor power input VCC, can be connected to 4.2 V ~ 7.2 V power

supply; plugged into power supply for the anode, please.

Note: The VCC interface of the controller is the power input of the servo motor. The VCC interface should be selected according to the requirements of the servo motor. For example, one servo motor needs 6V voltage peak 2A current, and 10 servo motor power supplies should be 6V voltage, 10A power supply.

GND: The overall GND of servo motor controller, can be connected to servo motor

power GND or CPU power GND; plugged into power supply for the cathode, please.

5V: Servo motor controller CPU power input, Voltage range:5V~8.5V.

USB(1): Servo motor controller CPU power input and data communication port.

Note: 5V interface and USB interface can not access the power supply at the same

time. Only one can be selected as the power interface

II. Servo motor access method, *P.2* location:

Yellow Pin: Servo motor I/O connected with the entrance, it usual be servo motor

yellow or yellow soil.

White Pin: Servo motor VCC connected with the entrance, it usual be servo motor

red or dark red.

Black Pin: Servo motor GND connected with the entrance, it usual be servo motor

brown or black.

III. UART access method, *P.3* location, with the *P.4* reading:



Green circle position: CPU power input of GND for servo motor controller.
Yellow circle position: CPU power input of VCC for servo motor controller.
Purple circle position: UART RX port for servo motor controller.
Orange circle position: UART TX port for servo motor controller.

IV. Bluetooth and WIFI sensor access method, *P.5* location:



P.5 location, use four lines to line the Bluetooth sensor, 5V-VCC, GND-GND, RX-TX,

TX-RX.

Pairing your phone with a Bluetooth module, and Install app.

Fill in WIFI module settings TCP address can be controlled.

first time use app must input "RTrobot".

V. Wiring method of potentiometer and servo motor, *P.6*



location:

P.6

Use potentiometer modules linked together with servo motor controllers as in

Figure 6, 1 linked to 1, 2 linked to 2, 3 linked to 3

Each potentiometer can be set individually via the host software to control which

channel servo motor

VI. wireless remote control access method, *P.7* location:



Using the wireless remote control receiver and servo motor controller linked together. like *P.7*,1-1、2-2、3-3....., don't forget the handle also need two batteries. (After the wiring is correct, turn on the power receiver and the remote LED will always be on and not flicker, indicating that the pairing has been completed.) Wireless remote control have two mode, mode one is one of the servo motor to control (LED ON), mode two is action groups operations(LED OFF). At different mode, the button have different function; but, have some buttons in both modes are same.

Note: After power-up, you must pass a "START" to start servo.



P.8

Same push buttons:

SELECT: Exchange modes

START: Start to work

One of the servo motor to control (32 Servo Mode):

Square: All servo motor moves to 2500

Cross: All servo motor moves to 1500

Round: All servo motor moves to 500

Triangle: None

健 robot Welcome

Hardware	32 channels	24 channels	16 channels				
Number of the first group of servo motors	1、3、5、7、9、11、13、15	1、3、5、7、9、11	1、3、5、7				
	L2: Exchange group one servo,	descending order					
The first group of push	R2: Exchange group one servo, ascending order						
button	L3-Left: Group one servo moto	or value increased					
	L3-Right: Group one servo mo	tor value reduced					
Number of the second group of servo motors	2、4、6、8、10、12、14、16	2、4、6、8、10、12	2、4、6、8				
	L1: Exchange group two servo,	descending order					
The second group of push	R1: Exchange group two servo, ascending order						
button	R3-Left: Group two servo motor value increased						
	R3-Right: Group two servo mo	tor value reduced					
Number of the third group of	17、19、21、23、25、27、29、	12 15 17 10 21 22	0 11 12 15				
servo motors	31	15, 15, 17, 19, 21, 25	9, 11, 15, 15				
	Left: Exchange group three ser	vo, descending order					
The third group of push	Right: Exchange group three se	ervo, ascending order					
button	L3-Up: Group three servo moto	or value increased					
	L3-Down: Group three servo motor value reduced						
Number of the fourth group	18、20、22、24、26、28、30、	14 16 19 20 22 24	10 12 14 16				
of servo motors	32	14, 10, 10, 20, 22, 24					
	Down: Exchange group four se	ervo, descending order					
The fourth group of push	Up: Exchange group four serve	o, ascending order					
button	R3-Up: Group four servo moto	r value increased					
	R3-Down: Group four servo me	otor value reduced					

one of the ser	vo motor to control	Action groups to control	
32 servo mo	tor Mode	•	
	Servo	Value	
Square	All 👆	2500 ÷	
Cross	All 👆	1500 🛨	
Round	All 👆	500 🛨	
Triangle	All 👆	1500 🛨	

Push Button	L2	L1	R2	R1	Up	Left:
action group	0	1	2	3	4	5
Push Button	Down	Right	L3-Up	L3-Left	L3-Down	L3-Right
action group	6	7	8	9	10	11
Push Button	R3-Up	R3-Left	R3-Down	R3-Right	Square	Cross
action group	12	13	14	15	16	17
Push Button	Round	Triangle				
action group	18	19				

Action groups to control:

e of the servo motor to control Action groups to control G0F1 R2 G2F1 G1F1 R1 G3F1 G4F1 Square G16F1 G5F1 Cross G17F1 m G6E1 Bound G18E1	
G0F1 R2 G2F1 G1F1 R1 G3F1 G4F1 Square G16F1 G5F1 Cross G17F1 m G6E1 Bound G18E1	
G1F1R1G3F1G4F1SquareG16F1G5F1CrossG17F1mG6E1BoundG18E1	
G4F1 Square G16F1 G5F1 Cross G17F1 m G6E1 Bound G18E1	
G5F1 Cross G17F1	
m G6E1 Bound G18E1	
t G7F1 Triangle G19F1	
JP G8F1 R3-UP G12F1	
.eft G9F1 R3-Left G13F1	
Own G10F1 R3-Down G14F1	
tight G11F1 R3-Right G15F1	

One of the servo motor to control (6 Servo Mode):

The value will be incremented or decremented each time the specified servo motor

is pressed.

Example: Pressing the "L2" button, the servo motor value of S1 will be reduced to

change the angle.

Push Button	L2	L1	R2	R1	Down	Up:
Number of servo motors	1-	1+	4-	4+	2-	2+
Push Button	Left	Right	Square	Round	Cross	Triangle
Number of servo motors	3-	3+	5-	5+	6-	6+



If you need a custom handle button function, please click "Setting" - > "Wireless controller" in the editor.

Overall Wiring example:

I. use of computer-controlled :



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Use the USB line to Computer and servo motor controller linked together.

The power of the servo motor access please reference Wiring methods: I (don't

use VDD interface).

II. Servo motor controller automatically :



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Before use, first with software Settings, and then open the power supply work.

if you want to use USB power supply, don not link red line for VDD.

Set up and restart the power supply will work automatically.

II. Using MCU to control

Servo motor controller of power supply to the MCU:

Here is an example with Arduino UNO, Other MCU can reference here. Servo motor controller 5V link Arduino UNO 5V, Servo motor controller GND link Arduino UNO GND, Servo motor controller TX link Arduino UNO RX, Servo motor controller RX link Arduino UNO TX. like *P.11:*

NOTE: Note: all of the power supply is powered by one battery.



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MCU power supply to the servo motor controller:

Servo motor controller 5V link Arduino UNO 5V, Servo motor controller GND link Arduino UNO GND, Servo motor controller TX link Arduino UNO RX, Servo motor controller RX link Arduino UNO TX.



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Note: the UNO Arduino and the Servo motor controller provide power through the

computer. The servo motor is an independent power supply.

Software Operation:

I. Software Settsing:

Click on the ":" in the servo motor window, you can set every one servo motor

for named, maximum, minimum, color and locked positions.

RTrobot Servo Controller Ver: 3.2.5	- 🗆 X
Setting Panel S1 1500++ S2 1500++ S4 1500++ S5 1500++ S5 1500++ S7 1500++ S8 1500++ S9 1500++ S150 1500++ S15 1500++ S	Interface COM O TCP Serial NO. COM26 Baud Rate 115200 DisConnect ONLINE Speed(ms) 500 Add Delete Import Clear Export Stop
All Channel:	Poin I Loop Read Action Groups Download Erase System Info System Initialized COM25 connected OK Thanks to use Servo Controller 0%

P.13

Check "Setting" -> "Software", You can set up the software, like P.14.

Software Panel: Set up software control panel.

Servo On/Off: Hide the servo motor are not used.

After completion of the software configuration will automatically restart the softw

are.

nel				Interface	
				COM	O TCP
S1 1500 ↔ S2 1500 ↔	S3 1500 ↔ S4 1500 ↔	S5 1500 ÷ S6 1500 ÷	S7 1500 ÷ S8	1500 ÷ Serial NO	COM51
-0-	🖶 Configuration		?	× Baud Rate	115200
	Servo Value	Software	Panel		IsConnect
\$9 1500 ÷ \$10 1500 ÷	Min Value 500 🖨	Panel	Default 👆		
	Max Value 2500 호	Themes	Light	Speed(ms)	500
S17 1500	Servo On/Off			Delay(ms)	500
	Servo 1 Servo 2	🗹 Servo 3 🗹 Servo 4	Servo 5 Servo 6	Add	Delete
	Servo 7 Servo 8	🗹 Servo 9 🗹 Servo 10	Servo 11 Servo 1	2 Import	Clear
S25 1500 ÷ S26 1500 ÷	Servo 13 Servo 14	Servo 15 Servo 16	Servo 17 Servo 1	3 Export	Stop
-0-	🗹 Servo 19 🗹 Servo 20	🗹 Servo 21 🗹 Servo 22	Servo 23 Servo 24	Run	Loop
	Servo 25 Servo 26	Servo 27 Servo 28	Servo 29 Servo 3	Read	Action Gro
Channel:	Servo 31 Servo 32		All ON ALL OFF	Download	d Erase
ruction Sender				System Info	
			OK Cano	el System Ini COM51 co Thanks to Controller	tialized nnected OK use Servo
				Clear	0%

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Software Panel: After selection interface can specify each position servo motor

serial number. like P.15.

Note: If there is a repeat of the servo motor serial number, can not be saved.

р нер			
nel			Interface
			● COM ○ TCP
S1 1500 ↔ S2 1500 ↔	🖶 Configuration		Serial NO COM51
	Santo Value		Raud Rata 115200
	Servo value	Software Panel	Baud Rate 115200
	Min Value 500 호	Panel 18-DOF Spider 👆	DisConnect
S9 1500 ÷ S10 1500 ÷	Max Value 2500 🔄	Themes Light	ONLINE
	18-DOE Spider		• Speed(ms) 500
			Delay(ms) 500
			Add Delete
\$17 1500 ÷ \$18 1500 ÷			Import Clear
	5 🖶	14	Export Stop
		13 🚽 15 🚽	Run Loop
			Read Action Grou
Channel:	8	11 🖶	Download Erase
ruction Sender	7 🔮 9		System Info
		2	System Initialized
		4 OK Cancel	COM51 connected OK
	L	5	Controller
		8	Closer 094

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II.Controller settings:

Check "Setting" -> "Hardware", You can set up the controller, like *P.16*(This option must link controller to display).

Servo initial value: Set the initial value of each servo motor start.

Servo Deviation Value: Set each deviation of servo motor(valid values: -99~99),like

P.17.

Uart Baud Rate: Set up **P.5** ④ the location of the serial port baud rate.

Buzzer: Low pressure alarm switch.

Start Automatic run: Turn on or off automatically run action group.

Automatic run group: Set up automatically run action group number, when the

"Start Automatic run" is set to "Only Group" mode, this option is invalid.

Automatic run times: Set up automatically run action group run times, when the

"Start Automatic run" is set to "Only Group" mode, this option is invalid.

Note: configure complete do not forget to click on the "Apply", waiting for the

settings to complete. Configured after the controller needs to restart will come into

effect.

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Hardware		? X	Hardware		?
Servo initial value Servo	deviation value		Servo initial value	Servo deviation value	
Servo 1 1500 🖨	Servo 2 1500 ≑	Servo 3 1500 🖨	Servo 1 0	Servo 2 0	Servo 3 0
Servo 4 1500 🖨	Servo 5 1500 ≑	Servo 6 1500 🖨	Servo 4 0	Servo 5 0	Servo 6 0
Servo 7 1500 🖨	Servo 8 1500 ≑	Servo 9 1500 🖨	Servo 7 0	Servo 8 0	Servo 9 0
Servo 10 1500 🖨	Servo 11 1500 🖨	Servo 12 1500 🖨	Servo 10 0	Servo 11 0	Servo 12 0
Servo 13 1500 🖨	Servo 14 1500 🖨	Servo 15 1500 🖨	Servo 13 0	Servo 14 0	Servo 15 0
Servo 16 1500 🖨	Servo 17 1500 🖨	Servo 18 1500 🖨	Servo 16 0	Servo 17 0	Servo 18 0
Servo 19 1500 🖨	Servo 20 1500 🖨	Servo 21 1500 🖨	Servo 19 0	Servo 20 0	Servo 21 0
Servo 22 1500 🗘	Servo 23 1500 🖨	Servo 24 1500 🖨	Servo 22 0	Servo 23 0	Servo 24 0
Servo 25 1500 🖨	Servo 26 1500 🖨	Servo 27 1500 🖨	Servo 25 0	Servo 26 0	Servo 27 0
Servo 28 1500 🖨	Servo 29 1500 🖨	Servo 30 1500 🖨	Servo 28 0	Servo 29 0	Servo 30 0
Servo 31 1500 🗘	Servo 32 1500 🔹	All Servo 1500 主	Servo 31 0	Servo 32 0	All Servo 0
JART Baud Rate 9600	Buzzer	Open 👆	UART Baud Rate	9600	Buzzer Open
Start automatic run No	automatic ru	n group 0	Start automatic rur	No 🔮	automatic run group 0
automatic run times(max:	254; loop:0;) 0	•	automatic run time	s(max:254; loop:0;)	D
Apply		Close	Ap	ply	Close

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P.17

II.3D Virtual:

Click "Setting" - > "3d Virtual" can display 3d Virtual.

🖶 RTrobot Servo Controller Ver: 3.2.0	– 🗆 🗙	🛞 RTrobot Servo Controller 4-DOF Robot —	
Setting Help			
Panel	Interface		
	● COM ◯ TCP		
	Serial NO. COM51 🛛		
	Baud Rate 115200		
SZ 1520÷ S3 1637÷	DisConnect		
	ONLINE	· · · · · · · · · · · · · · · · · · ·	
	Speed(ms) 500 👆		
S1 1755 ÷	Delay(ms) 500		
	Add Delete		
	Import Clear		
	Export Stop		
	Run Loop		
	Read Action Groups		
All Channel:	Download Erase		
Instruction Sender	System Info		
1	System Initialized		
	COM51 connected OK		
	Controller		
Group 0 🖶 Index 0 0	Clear 0%	Recourse the computer system can not achieve accurate microscoped limits	
		So if the speed is inaccurate, please try to modify the base here.	15 🗘

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Note: Need to be in the "Software" Settings panel select control interface after open the serial port to display 3d interface.

IV.Software control:

1. Select a suitable connection mode, and use the USB line to connect to the

computer.

2. Installation controller driver (Servos Controller Drive.exe).

Windows 10 does not require a driver to be installed.

NOTE: If the warning does not have a digital certificate signature, drive installation

fails. You need to put the computer "disable driver signature enforcement"

approach to start the computer, run the driver installation again

3. Open the software "ServoController.exe" .

4. Select serial number, and open the serial. If used WIFI mode, choose the "TCP",

write the Server IP and Port.

NOTE: In order to use all of the features only USB link.

1 Single servo motor operation:

like *P.19* drag or fill can change servo motor angle values.



② Multiple servo motor operation:

Under the instruction information box "Group" checkbox to select good to edit action Group of serial number, configure each servo motor first run value, And then configure the running speed of servo motor and waiting time after the completion. Check "Add" ,then configure each servo motor second run value, check "Add" .

All the preset run value were configure over, check "Run" to test.

running speed of servo motor: Finish the instruction at the specified time (not

exceeding the maximum physical speed of the servo motor).

waiting time of servo motor: After completing the current instruction, delay the

specified time, to perform the next instruction.



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③ Save instruction:

Click on the "Export" keep the motion Instructions to the text, in order to import

used next time.

Note: save the instruction for all action groups.

④ Using the file import operation:

Click on the "Import" save the past action in imported into the software.

Note: the import of all action group of instructions.

(5) Instructions edit:

At the Instructions information box, click the line need to Edit the instructions in





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⑥ Offline operate independently:

Staying all instructions to edit and then click the "Download" to Download all

action group's instructions.

In the "Setting" - > "Hardware" open interface controller automatically switch and

operation of action group number.

⑦ read the instructions:

Read all instructions have been downloaded to the controller.

(8) Erase all action groups

Click "Erase" to erase all the action groups instructions, erase time is about 30

seconds.

③Edit command

Click "Instruction" to manually enter or edit the instructions in the pop-up dialog.

-Instruction Sender				
1 #1P1500#2P1500#3P1500#4P 2 #1P2500#2P2500#3P2500#4P 3 #1P500#2P500#3P500#4P500	1500#5P1500#6P1500#7P1500#8P1500#9P15 1500#5P2500#6P2500#7P2500#8P2500#9P25 19P500#6P500#7P500#8P500#9P500#10P500	00#10P1500#11P1500#12P150 00#10P2500#11P2500#12P250 #11P500#12P500#13P500#14!	00#13P1500#14P1500#15P 00#13P2500#14P2500#15P; P500#15P500#16P500T500	1500#16P1500T500D500 2500#16P2500T500D500 D500
Group 0	Index 3 of 3	Alias		Instruction

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V. Password protection for instructions:

If you need to protect the instructions, so as not to modify or read the instructions to others, you can set password protection. Click "Setting" -> "Flash Password" to set the password. The password length is fixed to 8 digits. If you forget your password, you can reset your password.

Note 1: Setting a password will erase all instructions in the Flash.

Note 2: If the password is set successfully, the password will be saved in the

"config.ini. Please take care the configuration file.

Note 3: Do not enter any information in the input box will cancel the password.

VI. Pure action group instruction to edit:

Click "Action group" will appear action groups edit interface, like P.23.

G1F3		
G17F5		

G1: Action group 1

F3: run 3 times

After editing, can click "run" to test, if the test is correct, now you can download

to controller board. At the next time you open the software, you can use the

"Read" to read previously downloaded action group instructions. if you want to auto run at start; click "Setting" -> "Hardware", Change the "Start Automatic run" switch to "group only".

нер		
el	Interface	
	Сом	○ TCP
S2 150	- 🗆 🗙 ial NO. 🛛	COM30
1 G1F3	id Rate	115200
2 G17F5 3 G7	Delete	DisConnect
4 G254F1	Chart	
\$5 150	Clear	
	Download ONLINE	
S4 1500 <u>÷</u>		
	Read INE	
S8 150	Run ed(ms)	500
	ay(ms)	500
S7 1500 <u>→</u>	Add	Delete
-0-	Export	Clear
	Import	Stop
	Run	Loop
inanne:	Extended	Action Gro
uction Sender	ne	
		Erase
		Download
	0%	
	RT	robot
		1 222 2



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VI. MPU6500(only 24 channels):

Click the "Setting"-> "MPU6500" to open the MPU6500 setup interface, like *P.24*; Click the "Disable" button to change the status to "Enable" to boot MPU6500. Pitch、Roll、Yaw is value of MPU6500 XYZ; Fill in the allowable deviation value (no

more than 90), out of range after the need to run the action group and the number of runs. After placing the controller in the final operating state and click the "Apply" button to enable it and restart the controller boar. When the controller is tilted in any direction other than the set run value, the previously set action group and run count will triggered. (If you use the USB line to connect the computer and use the PC software debug,mpu6500 will not trigger.)



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Note: before performing the action group, the serial port will first feedback "TRIGGER".

After the completion of the specified action group feedback "OK".

III. 6 channel digital level sensors (only 16 channels):



The red circle section can be connected to 6 channel digital level sensors, each sensor can independently control 6 action groups or maintain the current position of the specified servo motor (Only support 3.3/5 v digital level sensor).

If you use the USB line to connect the computer and use the PC software debug, external sensors will not trigger.

Note: the GND of each digital level sensor needs to be connected to the GND of the servo controller.

When multiple "IN" is triggered at the same time, the smaller number of "IN" is val id.

IN1>IN2>IN3>IN4>IN5>IN6

Example1: IN2 and IN3 trigger at the same time, it will only perform IN2 specified action group, if IN2 release, IN3 trigger, execute IN3 specified action group.

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Example2: After the IN1 is triggered, the action group is started, and the IN6 is used to keep the current position of the servo motor. When both of them are triggered, the IN1 and the IN6 are both effective.

	IN 5 Disabl	
	All Server 1500	
	IN 4 Disabl ♥ ● Group ◯ Stop	
rvo 16 1500 🕏	Servo 5	
rvo 13 1500 🖻 Servo 14 1500 🕯	Je Servo 15 1500 C Group Stop	
nyo 10 1500 € Servo 11 1500 €	Group 211	
rvo 7 1500 🗘 Servo 8 1500 🕏	0 1 Servo 9 1500 € @ Group O Stop	
rvo 4 1500 🔹 Servo 5 1500 🕏	0 € Servo 6 1500 € a	
rvo 1 1500 🗘 Servo 2 1500 🕏	0 € Servo 3 1500 € ® Group O Stop	
rvo 1 1500 € Servo 2 1500 €	0 € Servo 3 1500 € IN 1 Low	

INx Three options:

- Disable: Disable (Trigger is invalid)
- High: High level trigger
- Low: Low level trigger

Group: Trigger the action group to be executed.

Stop: After the trigger the servo motor stops and remains the current position.

Note: Before performing the action group, the serial port will first feedback "TRIGGER".

After the completion of the specified action group feedback "OK".

Note: Invalid AC level sensor.

IX. Upgrade firmware

1. On "http://www.rtrobot.org/software/" website to download the latest PC

software

- 2. Open the latest PC software
- 3. Press and hold the key on the servo motor controller to release the USB cable

after releasing the key.



4. Open the latest PC software serial port, then the firmware began to upgrade,

after the upgrade will be mentioned "Update Success, Restart the controller,

Please."

- 5.Restart the servo motor controller
- 6. If is the latest firmware will prompt "ERROR Don 't need UPdate!"

Size chart:

32 channels:



24 channels:



16 channels:



X. About:

Thank you for using RTrobot of servo motor controller, have any questions about

the controller need to consult, mail to : admin@rtrobot.org