

AK Series Actuator Driver Manual

V1.0.1



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Notice

1. Ensure that the circuit is normal and the interface is correctly connected as required.
2. The driver board will be hot when output, please use it carefully to avoid burns.
2. Please Check whether the parts are in good condition before use. If any parts are missing or aging, please stop using and contact technical support in time.
3. Several optional control modes can't be switched when driver board is working, and different control mode have different communication protocol. If you need to switch, please reboot the power to the driver board then to change. Using the wrong protocol control may burn the driver board.
4. Please use it strictly in accordance with the working voltage, current, temperature and other parameters specified in this article, otherwise it will cause permanent damage to the product.

Feature

The AK series actuators' driver board adopts the driver chip with high-performance, uses the Field Oriented Control (FOC) algorithm, and is equipped with advanced active disturbance rejection control technology to control the speed and angle. It is matched with our modular motor to form a powerful power package. It can be used with CubeMars Tool assistant software for parameter setting and firmware upgrade.

Disclaimer

Thank you for purchasing the AK series actuators. Before using, please read this statement carefully. Once used, it is deemed to be an endorsement and acceptance of the entire content of this statement. Please strictly abide by the product manual and related laws, regulations, policies and guidelines to install and use the product. In the process of using the product, the user promises to be responsible for his actions and all consequences arising therefrom.

CubeMars will not be liable for any losses caused by improper use, installation, or modification by the user.



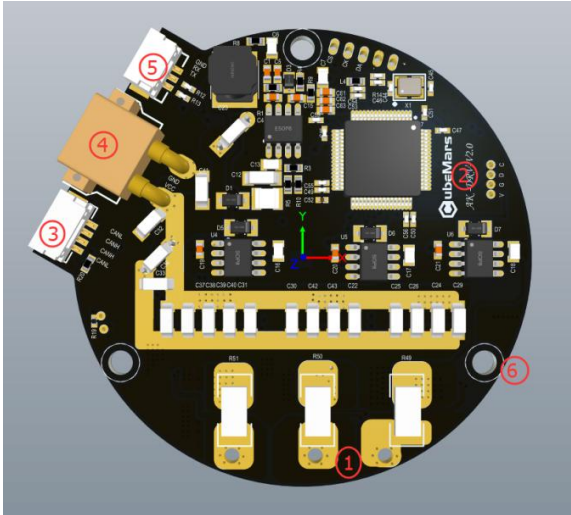
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Version Change Record

Date	Version	Change content
2021.9.1	Ver. 1.0.0	create version
2021.9.26	Ver.1.0.1	Correct the Can code of 5.3

1. Drive Product Information

1.1 Introduction of Drive' appearance & Specifications

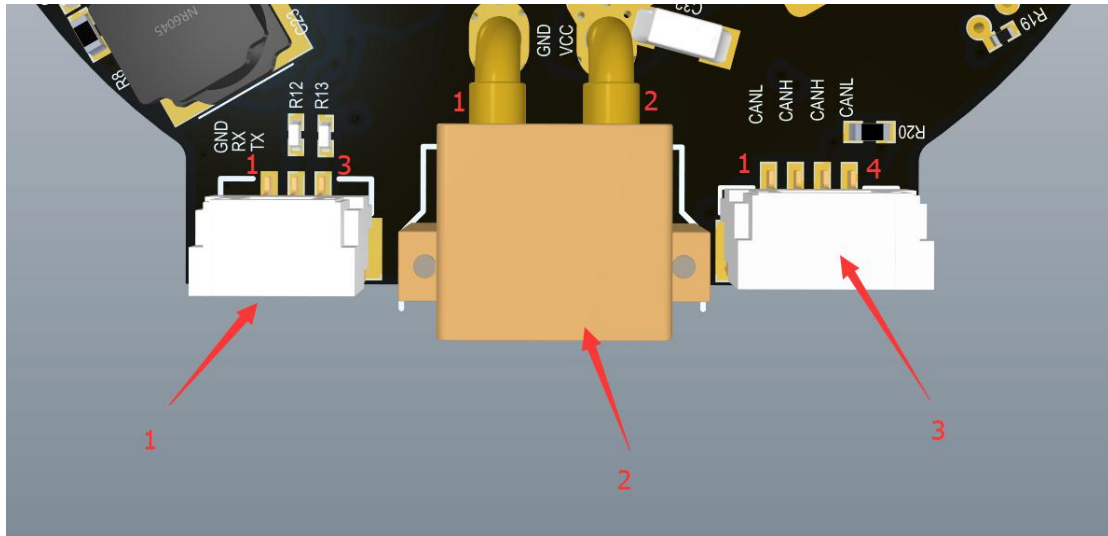


- ① Three-phase wires connection port
- ② Hardware version
- ③ CAN communication connection port
- ④ DC power port
- ⑤ Serial communication connection port
- ⑥ Mounting holes

Specifications	
Rated Voltage	48V
Peak Voltage	52V
Rated current	20A
Peak current	60A
Power consumption	≤50mA
Can bus bit rate	1Mbps (no change recommended)
Size	62mm×58mm
Working Environment temperature	-20℃-65℃
Maximum allowable temperature of driver board	100℃
Encoder Accuracy	14bit(single turn absolute)

1.2 Drive Interface and Definition

1.2.1 Drive Interface Diagram



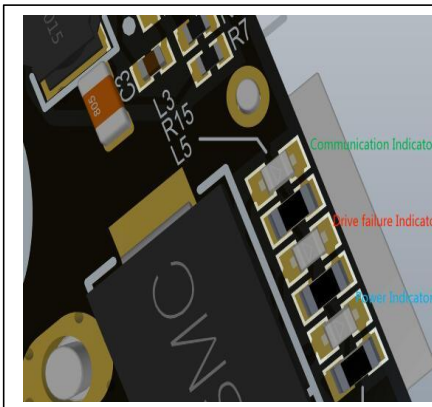
1.2.2 The Brand and Model of Drive Interface

No.	Onboard interface model	Brand	Wire interface model	Brand
1	A1257WR-S-3P	CJT	A1257H-3P	CJT
2	XT30PW-M	AMASS	XT30UPB-F	AMASS
3	A1257WR-S-4P	CJT	A1257H-4P	CJT

1.2.3 Drive Interface pin Definition

No.	Interface function	Pin	Explain
1	Serial communication	1	Serial signal ground (GND)
		2	Serial signal output (TX)
		3	Serial signal input (RX)
2	POWER INPUT	1	Negative pole (-)
		2	Positive pole (+)
3	Can communication	1	CAN communication low side (CAN_L)
		2	CAN communication high side (CAN_H)
		3	CAN communication high side (CAN_H)
		4	CAN communication low side (CAN_L)

1.3 Drive Indicator Definition



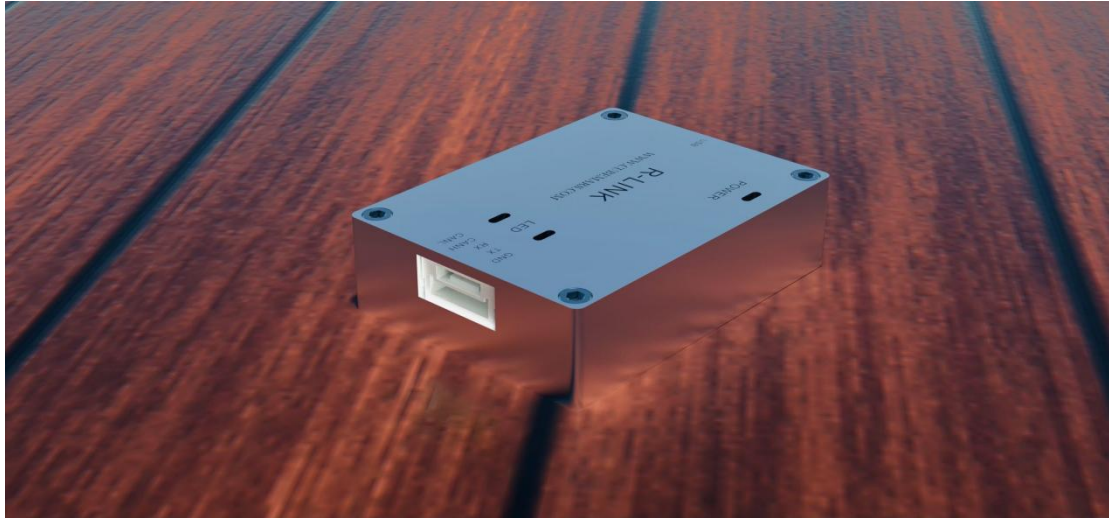
Indicator definition	
1. Power indicator (when blue light is on)	The power indicator is used to show the power supply of the driver board. Normally, it will light up blue when the power is plugged in. If the blue light is not on, please remove the power immediately and never turn on the power again.
2. Communication Indicator (when green light is on)	The communication indicator is used to show the communication status of the driver board. normally the driver board will light up green when the driver board communicates normally. If the green light is not on, please check whether the CAN communication wiring is normal.
3. Drive failure indicator (when red light is on)	The drive failure indicator is used to show the failure of the drive board. normally, it will light up in red only when the drive board fails, and it will usually go off under normal circumstances. When the drive failure indicator lights up, it means that the drive board has been damaged. The power supply should be turned off and no operation is allowed.

1.4 Main Accessories and Specifications

NO.	Item	Specification	QTY	Remark	
1	Serial communication line	wire rod	24AWG-300MM-Teflon silver-plated wire-black yellow green	Each 1PCS	±2MM
		pin	A1257H-3P	1PCS	
			A2541H-3P	1PCS	
2	power line	wire rod	16AWG-200MM-Silicone wire-red and black	Each 1PCS	±2MM
		pin	XT30UPB-M	1PCS	
			XT30UPB-F	1PCS	
3	CAN communication line	wire rod	24AWG-300MM-Teflon silver-plated wire-white and blue	Each 1PCS	±2MM
		pin	A1257H-4P	2PCS	
			A2541H-2P	1PCS	
4	Thermistor	MF51B103F3950-10K-3950	2PCS		
5	Electrolytic capacitor	120Uf-63V-10x12MM	2PCS	AK10-9 V2.0 standard	
6	MOS power	BSC026N08NS5-80V-2.6mΩ TPH2R608NH-75V-2.6mΩ	12PCS	Random	

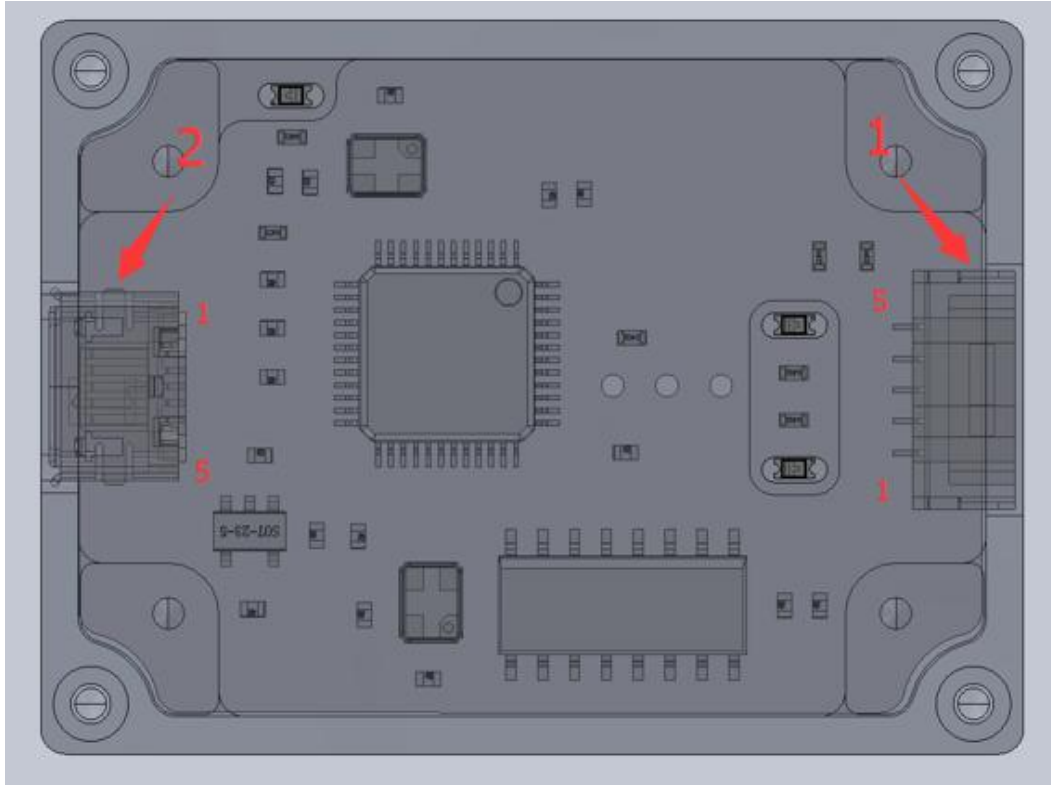
2. R-link produce information

2.1 Introduction of R-link' appearance&Specifications



Specification	
Rated Voltage	5V
Power consumption	≤30mA
Size	39.2x29.2x10MM
Working Environment temperature	-20°C -65°C
Maximum allowable temperature of board	85°C

2.2 R-link Interface and Definition

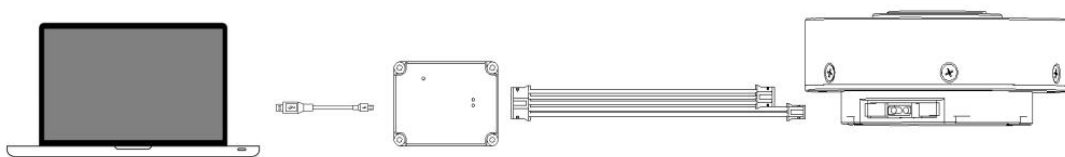


No.	Interface function	Pin	Definition
1	Communication Interface	1	CAN communication low side(CAN_L)
		2	CAN communication high side(CAN_H)
		3	Serial signal input (RX)
		4	Serial signal output (TX)
		5	Serial signal ground (GND)
2	USB interface	1	VBUS
		2	D-
		3	D+
		4	ID
		5	GND

2.3 R-link Indicator Definition

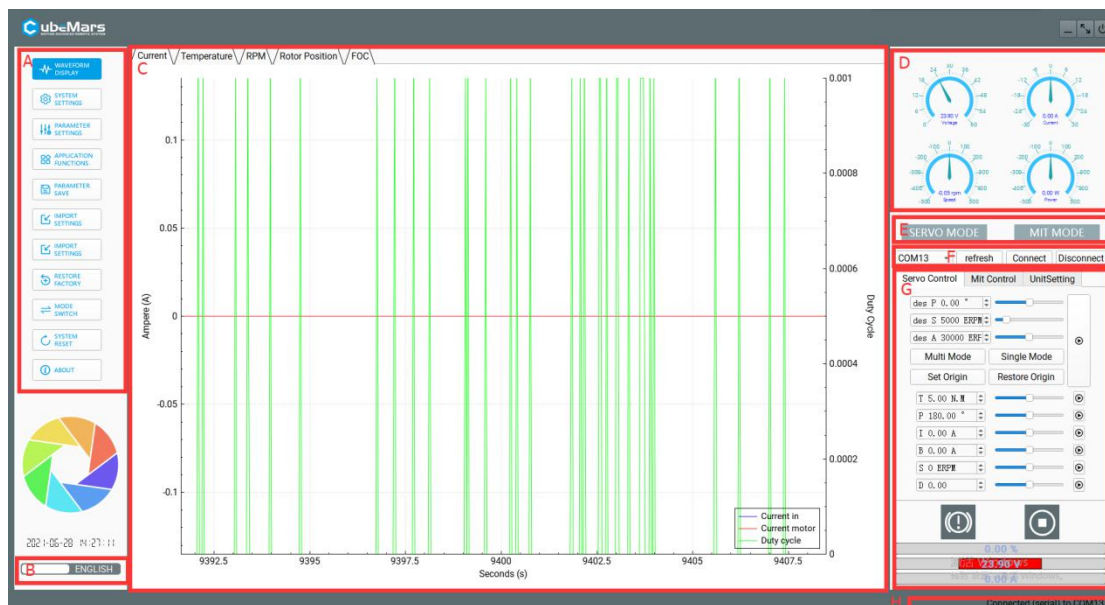
No.	Color	Definition
1	GREEN	The power indicator is used to indicate the power status of the R-link. Under normal circumstances, it will light up green when the power is plugged in. If the green light does not light up when the power is plugged in, please remove the power immediately and never turn on the power again
2	BLUE	Serial communication output (TX), always off, flashes when there is data output from the R-link serial port.
3	RED	Serial communication output (TX), always off, flashes when there is data input from the R-link serial port.

3. Actuator and R-link Connection and Notices



4. Instructions for use of the upper computer

4.1 PC interface and instruction



- A. Home
- B. Chinese and English Switching
- C. Main page
- D. Implement data display
- E. Current mode
- F. Serial port selection
- G. control parameter

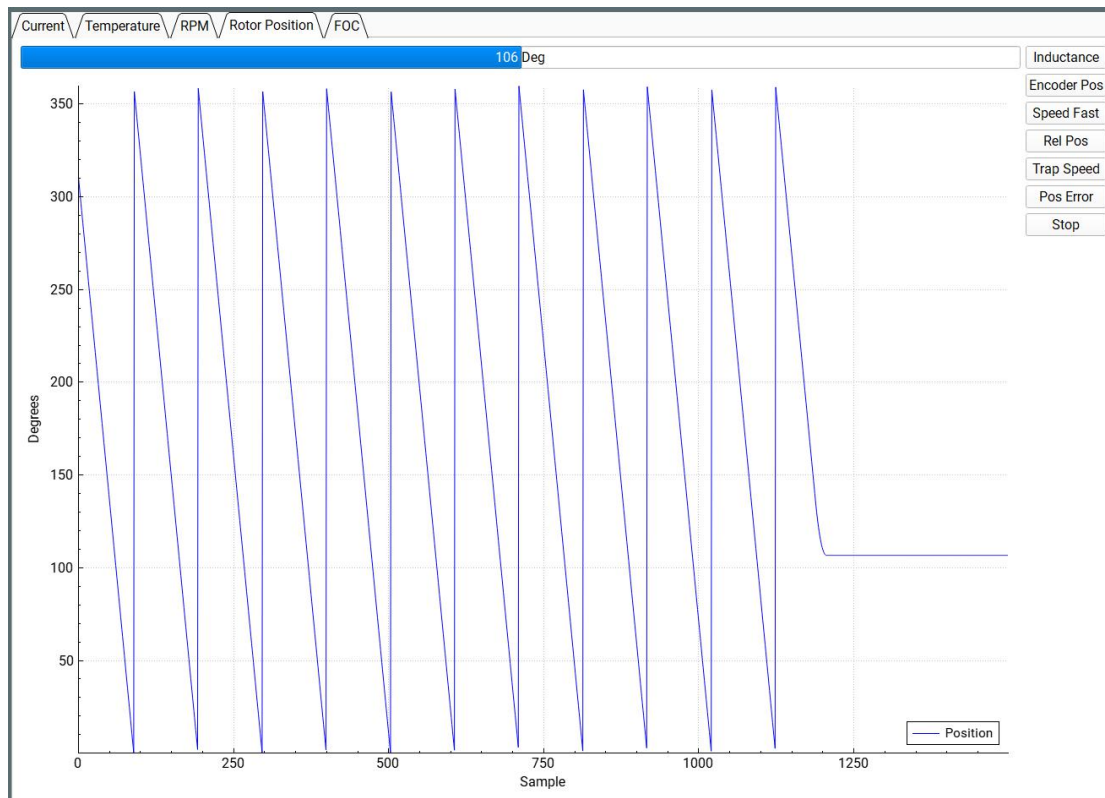
4.1.1 Home

4.1.1.1 waveform display



This page supports viewing real-time data feedback and drawing images.

Data includes: motor current, temperature, real-time speed, inner encoder position, outer encoder position, high-frequency speed, rotor position, path planning, position deviation, DQ current, etc.

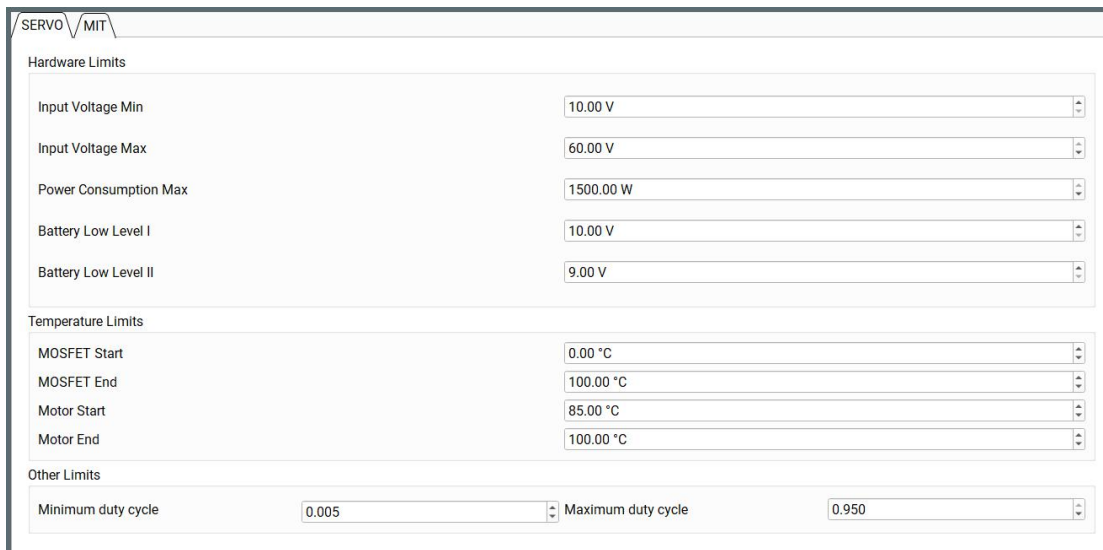


4.1.1.2 System Setting



This page is mainly about changing the hardware limitations of the drive board such as voltage, current, power, temperature, duty ratio, etc. It mainly protects the drive board and motors.

: Please use it strictly in accordance with the specified voltage, current, power, and temperature. Our company will not bear any legal responsibility if the operation of this product in violation of regulations causes injury to the human body or irreversible damage to the drive board and motor.



SERVO MIT

Hardware Limits

Input Voltage Min	10.00 V
Input Voltage Max	60.00 V
Power Consumption Max	1500.00 W
Battery Low Level I	10.00 V
Battery Low Level II	9.00 V

Temperature Limits

MOSFET Start	0.00 °C
MOSFET End	100.00 °C
Motor Start	85.00 °C
Motor End	100.00 °C

Other Limits

Minimum duty cycle	0.005	Maximum duty cycle	0.950
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4.1.1.3 Parameter Setting



This page is mainly about adjusting the parameters of the drive board, including but not limited to current loop Kp-Ki, encoder paranoia, maximum and minimum current, maximum and minimum speed, speed loop Kp-Ki-KD, reduction ratio and other parameters, as well as encoder calibration and motor parameter tuning.

: Please use it strictly in accordance with the specified voltage, current, power, and temperature. Our company will not bear any legal responsibility if the operation of this product in violation of regulations causes injury to the human body or irreversible damage to the drive board and motor.

Servo MIT

General

Current Control	Kp: 0.0334	Ki: 29.19
Encoder	Ofs: 139.60	Rat: 21.00
Switching Frequency	25.00	<input checked="" type="checkbox"/> Invert Encoder

Detect Encoder

I: 5.00 A Start Offset: 139.6 Ratio: 21.0 Inverted Update

Current Limits	ERPM Limits
Motor max: 60.00 A	Min ERPM: -100000.00
Motor min (regen): -60.00 A	Max ERPM: 100000.00
Batt max: 99.00 A	Max ERPM at full brake: 0.00
Batt min (regen): -60.00 A	Max ERPM at full brake in current control mode: 0.00
Absolute max: 0.00 A	

Speed control	Position control
KP: 0.00400	KP: 0.03000
KI: 0.00400	KI: 0.00000
KD: 0.00010	KD: 0.00040
	Gear Division: 1.00

Detect and Calculate Parameters

Measure R/L → Measure Lamba → Update

I: 20.00 A	D: 0.30	ω: 2000.0 ERPM/s
R: 29.24 mΩ	L: 33.42 μH	λ: 2.550 mH/b
Observer Gain (x11): 153.79	KP: 0.0334	KI: 29.24

4.1.1.4 Application Functions



This page is mainly about CAN ID setting, CAN communication rate and CAN communication sudden interruption setting.

Settings		<input type="checkbox"/> Send status over CAN	
Controller ID	<input type="text" value="0"/>	Rate (Hz)	<input type="text" value="0"/>
Timeout (when no control signal is received)			
Timeout (ms)	<input type="text" value="0"/>		
Brake current to use when a timeout occurs (A)	<input type="text" value="0.00"/>		

4.1.1.5 Parameter Save



Save the upper computer parameters to the actuator.

4.1.1.6 Export Settings



Save the upper computer parameters as two files with the suffixes ".McParams" and to the computer.



The ".McParams" file is:



AK10-9_设置参数.AppParams

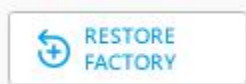
The ".AppParams" file is:

4.1.1.7 Import Settings



Upload the parameters of the two files with the suffix ".McParams" and ".AppParams" on the computer to the upper computer.

4.1.1.8 Restore Factory

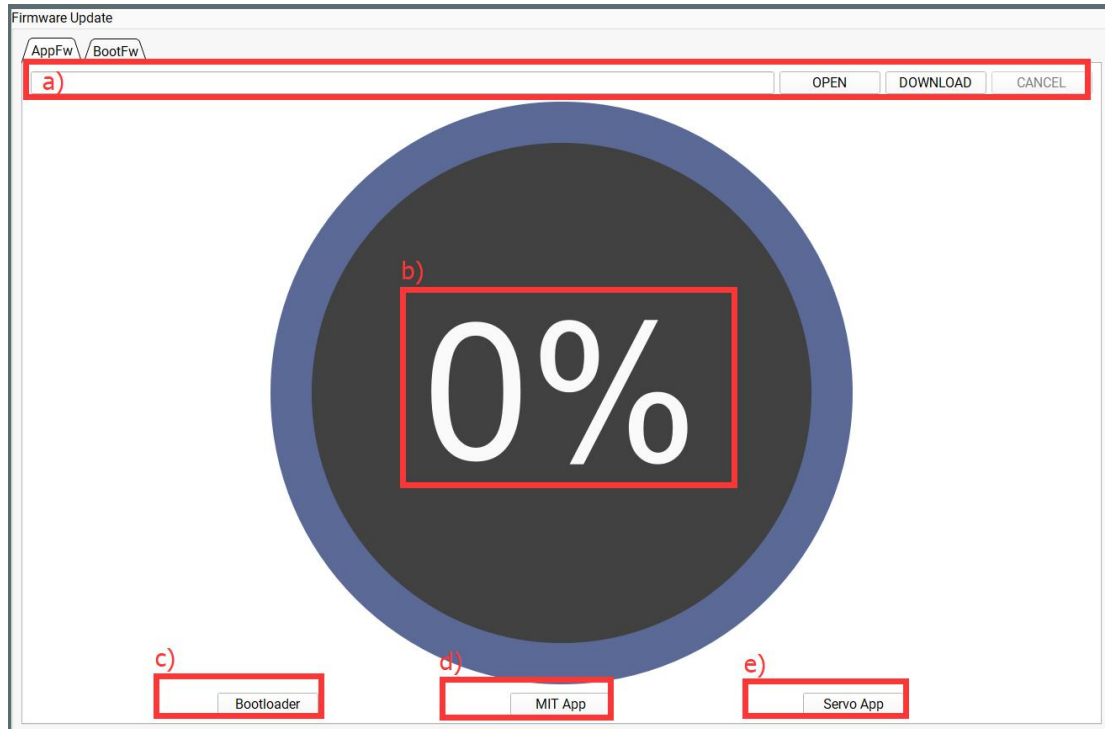


This feature is not currently enabled.

4.1.1.9 Mode Switch



This page is mainly about switching the control mode of the drive board, including "guide mode", "servo mode" and "MIT power mode", and update the driver board firmware.



A). Import firmware area: It can import files with the suffix ".bin" in the computer.

B). Firmware update progress bar

C). Enter boot mode

D). Enter MIT power mode

E). Enter servo mode

4.1.1.10 System reset



Stop the actuator and reset.

4.1.1.11 About

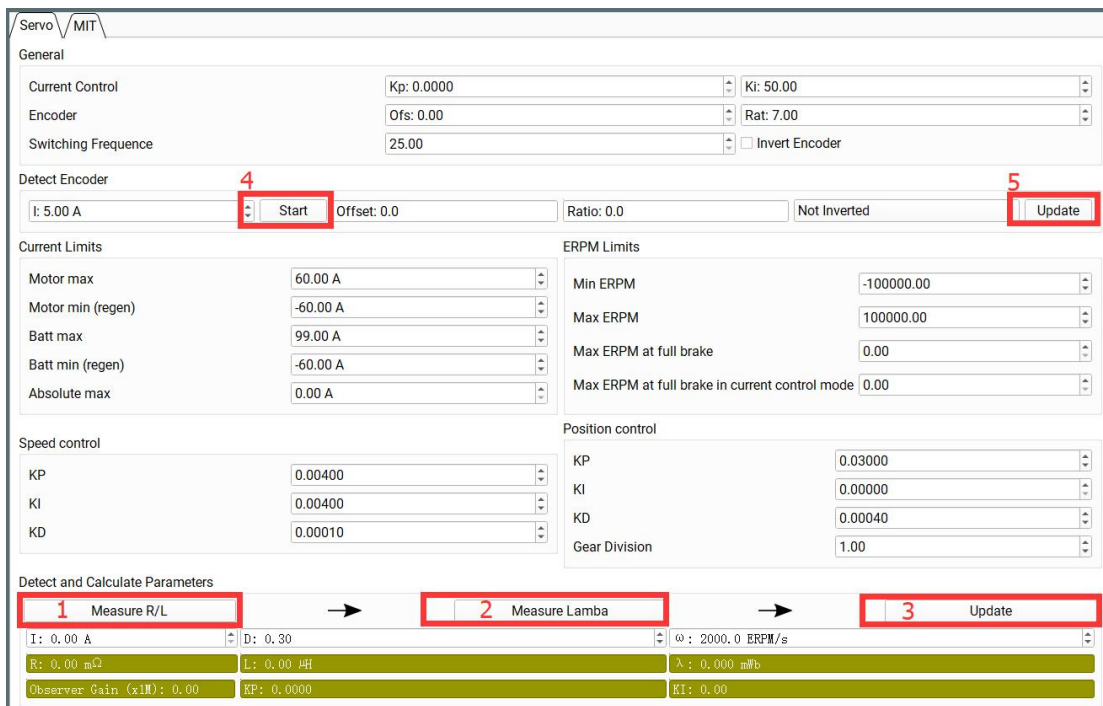
About the version number of the host computer and the official website of the company <https://www.cubemars.com/>

4.2 Driver board calibration

After you reinstall the driver board on the motor, or change the line sequence of the motor's three-phase line, or update the firmware, you must calibrate it. After calibration, the motor can be used normally.

4.2.1 Servo mode

Confirm that the motor input power is stable, the R-LINK connection is normal, and the motor is in servo mode, after successfully connecting with the host computer, enter the system setting page, and click "Electrical Parameters", "Identification Parameters", "Update Parameters", "Start calibration", "Update parameters" successively.



The screenshot shows the 'Servo' control interface with the following sections and highlighted elements:

- General:**
 - Current Control: Kp: 0.0000, Ki: 50.00
 - Encoder: Of: 0.00, Rat: 7.00
 - Switching Frequency: 25.00, Invert Encoder
- Detect Encoder:**
 - I: 5.00 A, **4** Start, Offset: 0.0, Ratio: 0.0, Not Inverted, **5** Update
- Current Limits:**
 - Motor max: 60.00 A
 - Motor min (regen): -60.00 A
 - Batt max: 99.00 A
 - Batt min (regen): -60.00 A
 - Absolute max: 0.00 A
- ERPM Limits:**
 - Min ERPM: -100000.00
 - Max ERPM: 100000.00
 - Max ERPM at full brake: 0.00
 - Max ERPM at full brake in current control mode: 0.00
- Speed control:**
 - KP: 0.00400
 - KI: 0.00400
 - KD: 0.00010
- Position control:**
 - KP: 0.03000
 - KI: 0.00000
 - KD: 0.00040
 - Gear Division: 1.00
- Detect and Calculate Parameters:**
 - 1** Measure R/L → **2** Measure Lamba → **3** Update
 - I: 0.00 A, D: 0.30, ω: 2000.0 ERPM/s
 - R: 0.00 mΩ, L: 0.00 μH, λ: 0.000 mfb
 - Observer Gain (x1M): 0.00, KP: 0.0000, KI: 0.00

4.2.2 MIT power mode

Confirm that the motor input power is stable, the R-LINK connection is normal, and the motor is in force control mode, after successfully connecting with the host computer, click "Debug Mode" on the "Motion Control" interface, and then input "calibrate" in the input field, Wait for about 30 seconds. At the same time, the output field will scroll the position value of the encoder in real time until the output field prints "Encoder Electrical Offset (rad)", the actuator will reboot and print the message from the driver board then the calibration is completed. When calibrating, the voltage is about 1A at 48V, and the current is restored to about 0.02A after the calibration.

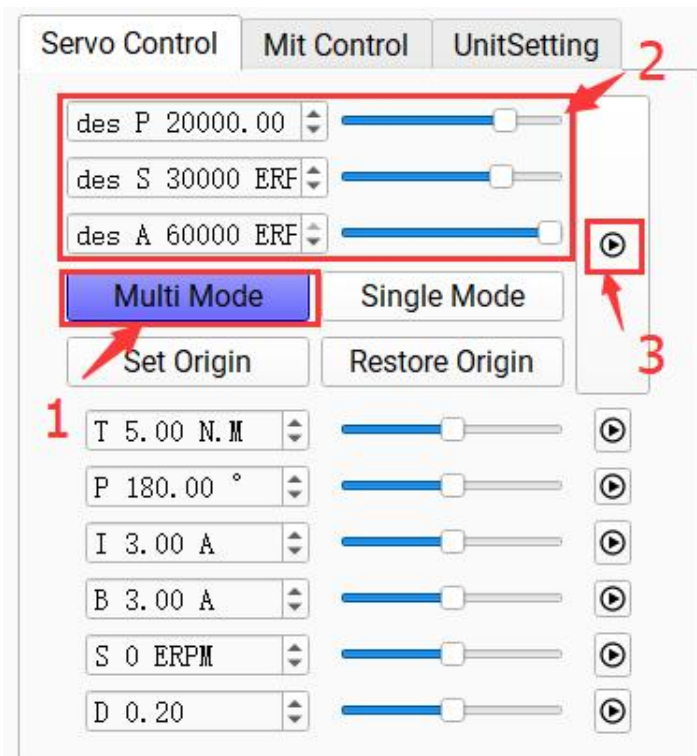


4.3 Control demo

4.3.1 Servo mode

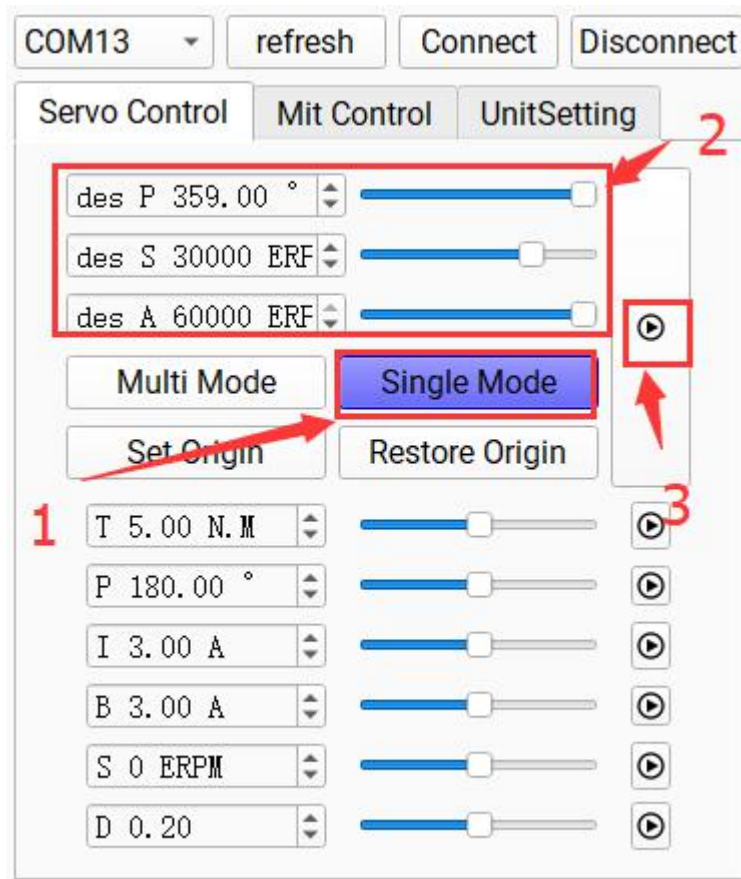
4.3.1.1 Multi-turn position velocity mode

Confirm that the motor input power is stable, the R-LINK connection is normal, and the motor is in servo mode, after successfully connecting with the host computer, click "multi-turn mode" on the "servo control" interface, and input the desired position (the position at this time is \pm After 100 revolutions, ie -36000° - 36000°), after the desired speed and acceleration, the motor will move at the desired speed until it reaches the desired position.



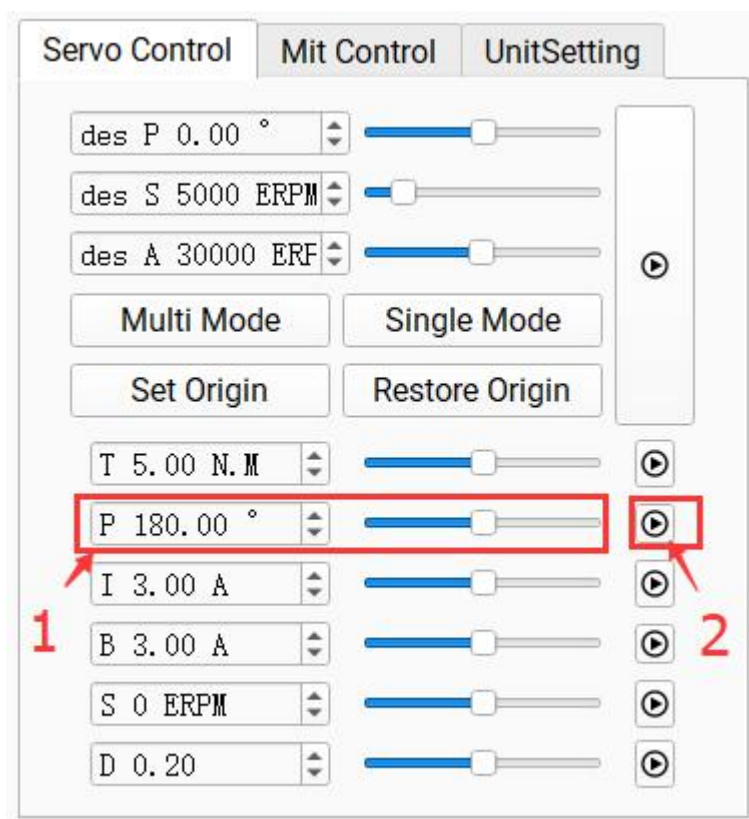
4.3.1.2 Single loop position velocity mode

Confirm that the motor input power is stable, the R-LINK connection is normal, and the motor is in servo mode, after successfully connecting with the host computer, click "single-turn mode" on the "servo control" interface, and after inputting the desired position (the position is only one at this time). Circle, ie 0°-359°), the desired speed and acceleration, the motor will move at the desired speed until it reaches the desired position.



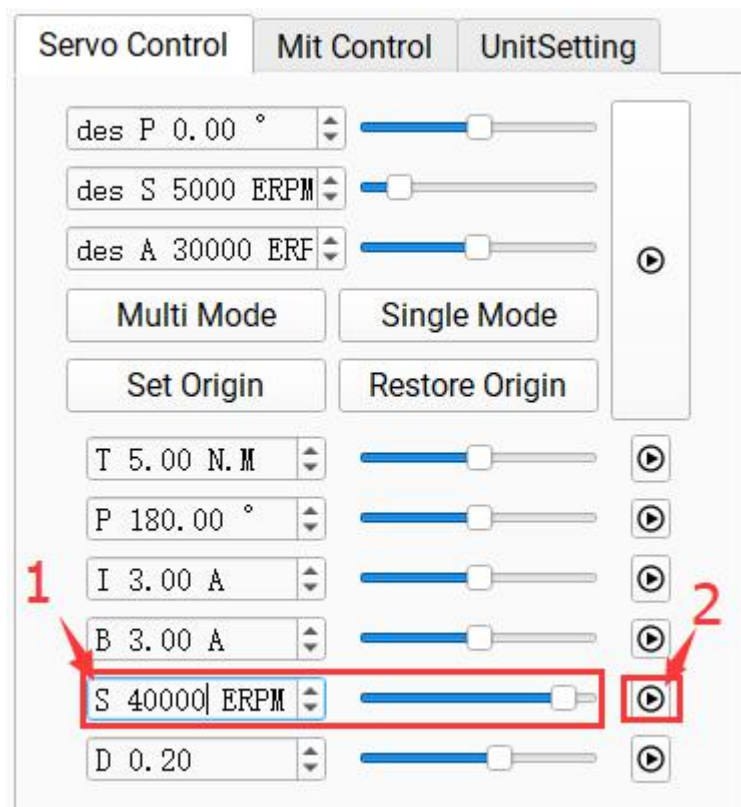
4.3.1.3 Position mode

Confirm that the motor input power is stable, the R-LINK connection is normal, and the motor is in servo mode, input the desired position in the "Servo Control" interface after connecting with the host computer successfully, and the motor will reach the desired position at the maximum speed.



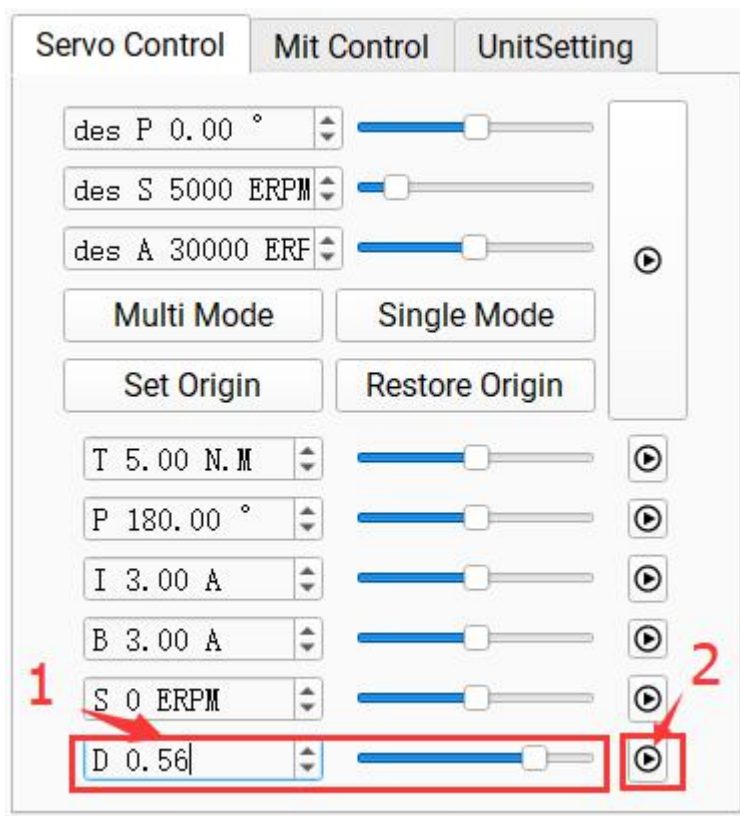
4.3.1.4 Velocity mode

Confirm that the motor input power is stable, the R-LINK connection is normal, and the motor is in servo mode, after connecting with the host computer successfully, input the desired speed (± 50000 ERPM) in the "Servo Control" interface, and the motor will move at the desired speed.



4.3.1.5 Duty cycle mode

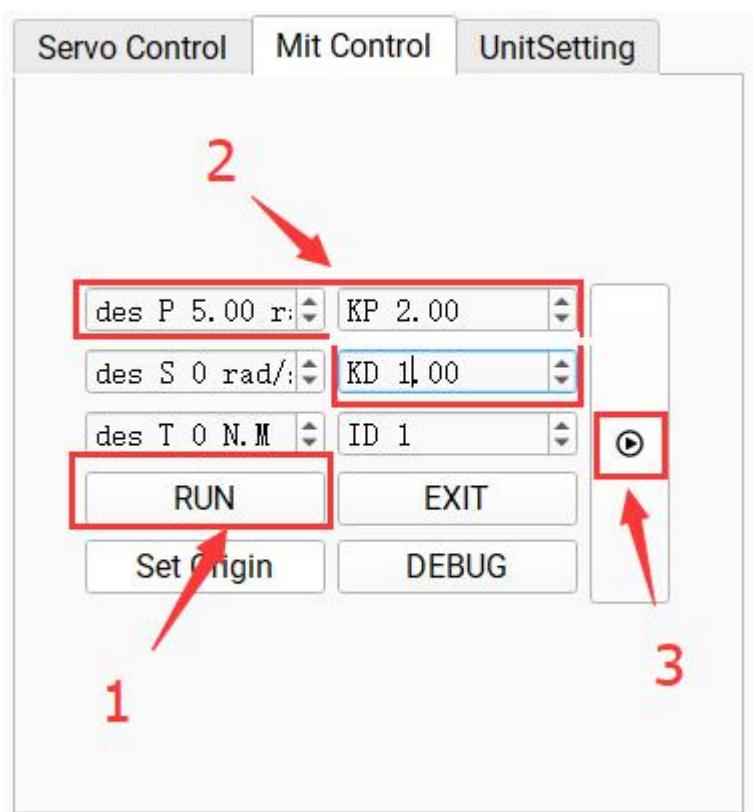
Confirm that the motor input power is stable, the R-LINK connection is normal, and the motor is in servo mode, input the desired duty ratio (default 0.005-0.95) in the "Servo Control" after connecting with the host computer, the motor will work at the desired duty ratio.



4.3.2 MIT power Mode

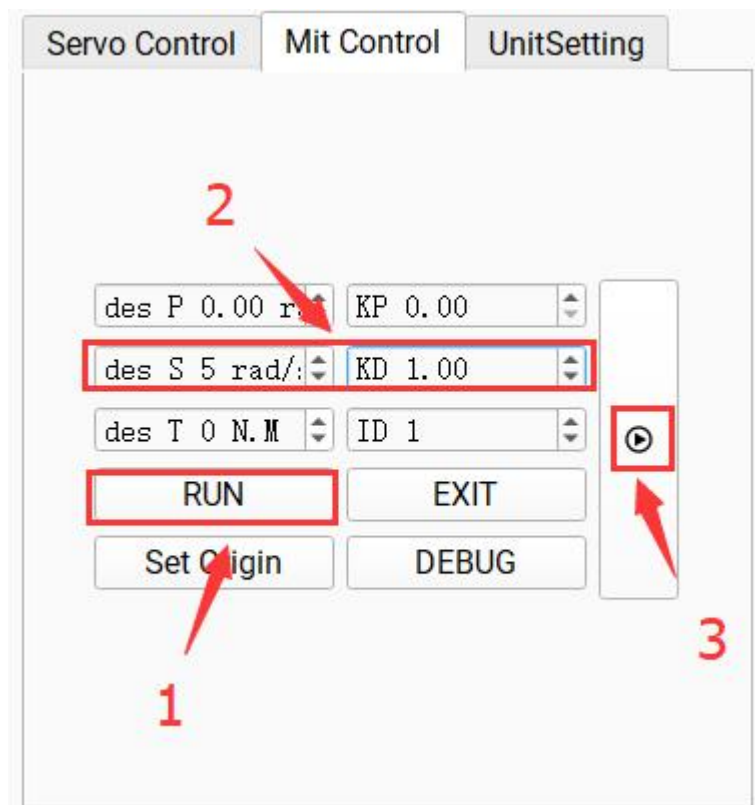
4.3.2.1 Position Mode

Confirm that the motor input power is stable, the R-LINK connection is normal, and the motor is in force control mode, after connecting with the host computer successfully, input corresponding “CAN ID” in the “Mit Control” interface and then click “RUN”, you can enter the motor mode. The motor will perform position movement (default speed 12000erpm, acceleration 40000erpm) after inputting desired position, KP and KD.



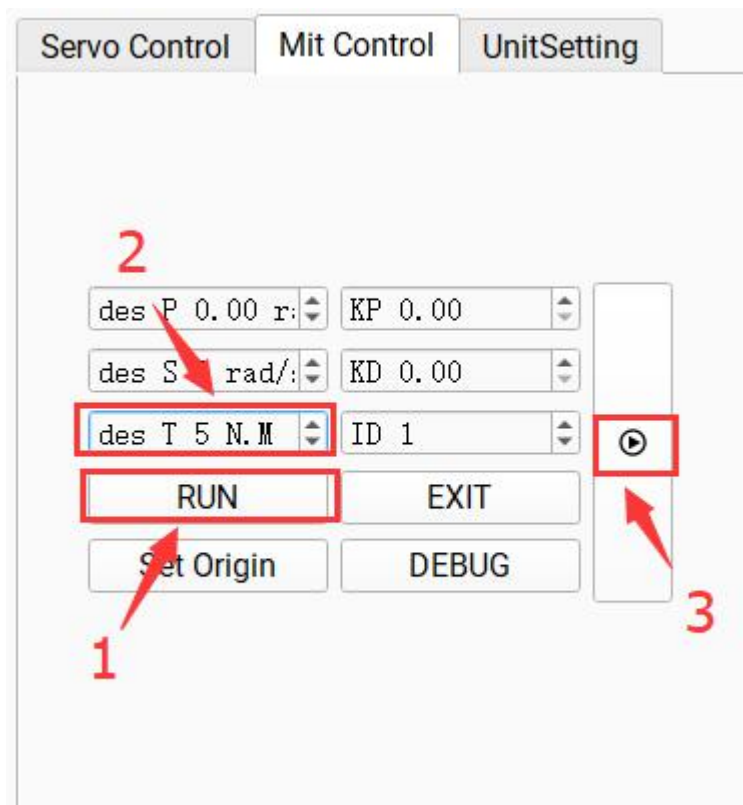
4.3.2.2 Velocity mode

Confirm that the motor input power is stable, R-Link connection is well, and the motor is in force control mode. After the motor is successfully connected with the upper computer, enter the corresponding "CAN ID" on the "Mit Control" interface and click "Enable Control" to enter the motor mode. After the expected speed and KD are input, the motor will running at speed.



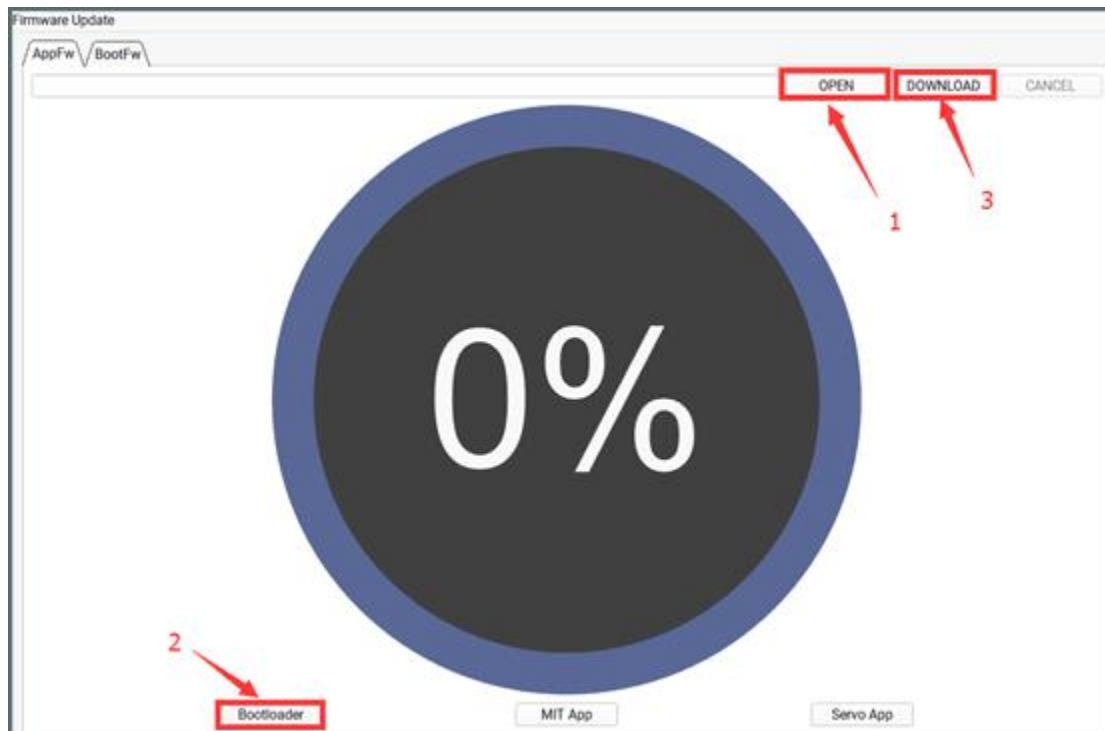
4.3.2.3 Torque mode

Confirm that the motor input power is stable, r-Link connection is normal, and the motor is in force control mode. After the motor is successfully connected with the upper computer, enter the corresponding "CAN ID" on the "Mit Control" interface and click "Enable Control" to enter the motor mode. After the expected torque is input, the motor will running accord to the torque.



4.4 Firmware update

1. Click Open File and select the firmware. The firmware name extension is .bin.
2. Click Bootloader.
3. Click download and wait for the progress bar to reach 100%. Then restart the power supply.



5. Driver board communication protocol and description

5.1 Servo mode and control mode description

Servo mode with six control modes

Duty cycle mode: duty cycle voltage is specified for a given motor, similar to square wave drive mode

Current loop mode: given the I_q current specified by the motor, the motor output torque = $I_q * K_T$, so it can be used as a torque loop

Current brake mode: the motor is fixed at the current position by the specified brake current given by the motor (pay attention to the motor temperature when using)

Velocity mode: the speed specified by the given motor

Position mode: Given the specified position of the motor, the motor will run to the specified position, (default speed 12000erpm acceleration 40000erpm)

Position velocity loop mode: the position, speed and acceleration specified by the given motor. The motor will run at a given acceleration and maximum speed to a specified position.

The servo motor protocol is CAN protocol, and the extended frame format is shown below

Can ID bits	[28]-[8]	[7]-[0]
Field name	Control mode	Source node ID

Control mode contain {0,1,2,3,4,39} Six eigenvalues correspond to six control modes respectively

Duty cycle mode: 0

Current loop mode: 1

Current brake mode: 2

Velocity mode: 3

Position mode: 4

Position velocity loop mode: 39

Examples of various mode control motors are provided below

The following are library functions and macro definitions for each instance

```
typedef enum {
    CAN_PACKET_SET_DUTY = 0, //Duty cycle mode
    CAN_PACKET_SET_CURRENT, // Current loop mode
```



```

    CAN_PACKET_SET_CURRENT_BRAKE, // Current brake mode:
    CAN_PACKET_SET_RPM,           // Speed mode:
    CAN_PACKET_SET_POS,           // Position mode
    CAN_PACKET_SET_ORIGIN_HERE,
    CAN_PACKET_SET_ADRC_GAIN,
    CAN_PACKET_SET_ENC_OFFSET,
    CAN_PACKET_SET_ELEC_ZERO,
    CAN_PACKET_SET_POS_SPD = 39, //39 Position speed loop mode 39
    CAN_PACKET_SET_ZESC = 40,
} CAN_PACKET_ID;

void comm_can_transmit_eid(uint32_t id, const uint8_t *data, uint8_t len) {
    uint8_t i=0;
    if (len > 8) {
        len = 8;
    }
    CanTxMsg TxMessage;
    TxMessage.StdId = 0;
    TxMessage.IDE = CAN_ID_EXT;
    TxMessage.ExtId = id;
    TxMessage.RTR = CAN_RTR_DATA;
    TxMessage.DLC = len;
    //memcpy(txmsg.data8, data, len);
    for(i=0;i<len;i++)
    TxMessage.Data[i]=data[i];
    CAN_Transmit(CHASSIS_CAN, &TxMessage);
}

void buffer_append_int32(uint8_t* buffer, int32_t number, int32_t *index) {
    buffer[*index++] = number >> 24;
    buffer[*index++] = number >> 16;
    buffer[*index++] = number >> 8;
    buffer[*index++] = number;
}

void buffer_append_int16(uint8_t* buffer, int16_t number, int16_t *index) {
    buffer[*index++] = number >> 8;
    buffer[*index++] = number;
}

```

5.1.1 Duty cycle mode:

Duty cycle mode sends data definitions

Data bits	Data[3]	Data[2]	Data[1]	Data[0]
Range	0~0xff	0~0xff	0~0xff	0~0xff
Corresponding variables	Duty cycle 25-32 bit	Duty cycle 17-24 bit	Duty cycle 9-16 bit	Duty cycle 1-8 bit

```
void comm_can_set_duty(uint8_t controller_id, float duty) {
    int32_t send_index = 0;
    uint8_t buffer[4];
    buffer_append_int32(buffer, (int32_t)(duty * 100000.0), &send_index);
    comm_can_transmit_eid(controller_id | ((uint32_t)CAN_PACKET_SET_DUTY << 8), buffer,
    send_index);
}
```

5.1.2 Current loop mode

Current loop mode sends data definition

Data bits	Data[3]	Data[2]	Data[1]	Data[0]
Range	0~0xff	0~0xff	0~0xff	0~0xff
Corresponding variables	Current 25-32 bit	Current 17-24 bit	Current 9-16 bit	Current 1-8 bit

Current loop mode sending routine

```
void comm_can_set_current(uint8_t controller_id, float current) {
    int32_t send_index = 0;
    uint8_t buffer[4];
    buffer_append_int32(buffer, (int32_t)(current * 1000.0), &send_index);
    comm_can_transmit_eid(controller_id |
        ((uint32_t)CAN_PACKET_SET_CURRENT << 8), buffer, send_index);
}
```

5.1.3 Current Brake Mode

Current brake mode sends data definition

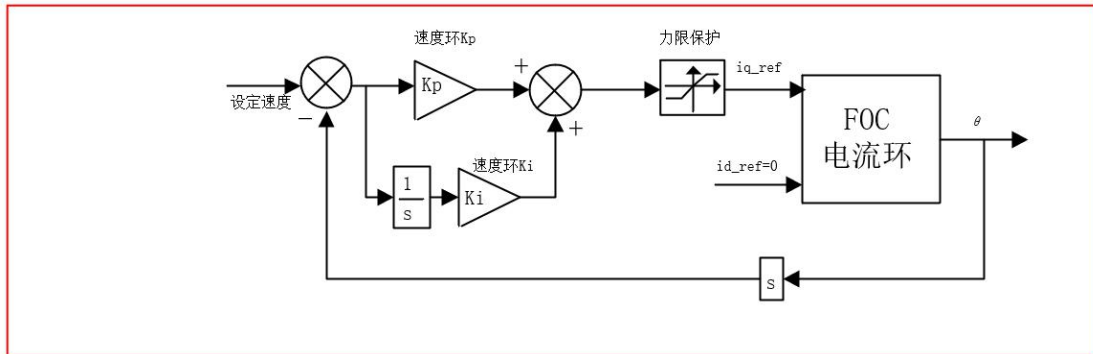
Data bits	Data[3]	Data[2]	Data[1]	Data[0]
Range	0~0xff	0~0xff	0~0xff	0~0xff
Corresponding variables	Brake current 25-32 bit	Brake current 17-24 bit	Brake current 9-16 bit	Brake current 1-8 bit

Current brake mode sending routine

```
void comm_can_set_current_brake(uint8_t controller_id, float current) {
    int32_t send_index = 0;
    uint8_t buffer[4];
    buffer_append_int32(buffer, (int32_t)(current * 1000.0), &send_index);
    comm_can_transmit_eid(controller_id |
        ((uint32_t)CAN_PACKET_SET_CURRENT_BRAKE << 8), buffer, send_index);
}
```

5.1.4 Velocity mode

Velocity loop simple control block diagram



Velocity loop mode sends data definition

Data bits	Data[3]	Data[2]	Data[1]	Data[0]
Range	0~0xff	0~0xff	0~0xff	0~0xff
Corresponding variables	Speed 25-32 bit	Speed 17-24 bit	Speed 9-16 bit	Speed 1-8 bit

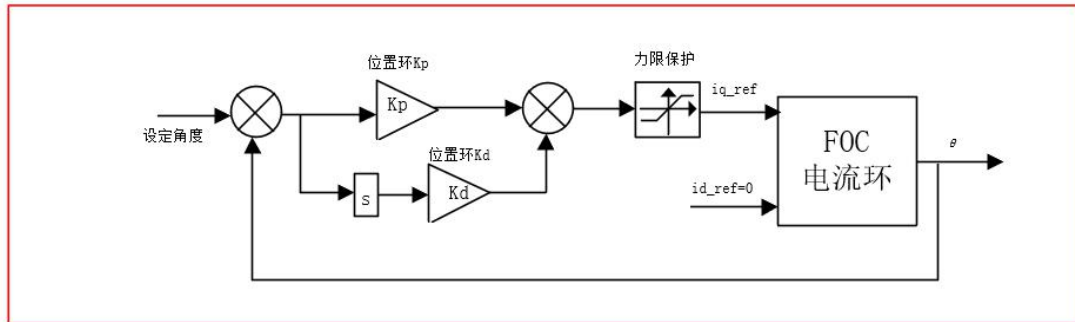
Velocity loop sending routine

```

void comm_can_set_rpm(uint8_t controller_id, float rpm) {
    int32_t send_index = 0;
    uint8_t buffer[4];
    buffer_append_int32(buffer, (int32_t)rpm, &send_index);
    comm_can_transmit_eid(controller_id |
        ((uint32_t)CAN_PACKET_SET_RPM << 8), buffer, send_index);
}
    
```

5.1.5 Position loop mode

Position loop simple control block diagram



Position loop mode sends data definitions

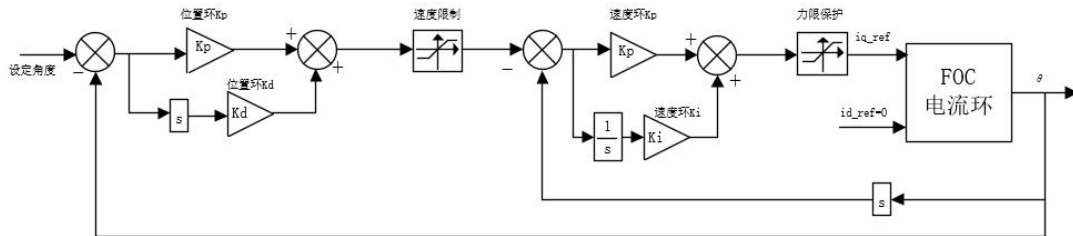
Data bits	Data[3]	Data[2]	Data[1]	Data[0]
Range	0~0xff	0~0xff	0~0xff	0~0xff
Corresponding variables	Position 25-32 bit	Position 17-24 bit	Position 9-16 bit	Position 1-8 bit

Position loop sending routine

```
void comm_can_set_pos(uint8_t controller_id, float pos) {
    int32_t send_index = 0;
    uint8_t buffer[4];
    buffer_append_int32(buffer, (int32_t)(pos * 1000000.0), &send_index);
    comm_can_transmit_eid(controller_id |
        ((uint32_t)CAN_PACKET_SET_POS << 8), buffer, send_index);
}
```

5.1.6 Position and Velocity Loop Mode

Simplified block diagram of position velocity loop



Position velocity loop mode sends data definition

Data bits	Data[0]	Data[1]	Data[2]	Data[3]	Data[4]	Data[5]	Data[6]	Data[7]
Range	0~0xff	0~0xff	0~0xff	0~0xff	0~0xff	0~0xff	0~0xff	0~0xff
Corresponding variables	Position 25-32 bit	Position 17-24 bit	Position 9-16 bit higher	Position 1-8 bit higher	Speed 8 bit higher	Speed 8 bit lower	Accelerated speed 8 bit lower	Accelerated speed 8 bit lower

*/

/* Pos is the specified position, SPD is the specified speed, and RPA is the self-determined acceleration

Pos range unit

SPD range unit

RPA range unit

```
void comm_can_set_pos_spd(uint8_t controller_id, float pos,int16_t spd, int16_t RPA ) {
    int32_t send_index = 0;
    Int16_t send_index1 = 0;
    uint8_t buffer[4];
    buffer_append_int32(buffer, (int32_t)(pos * 10000.0), &send_index);
    buffer_append_int16(buffer,spd, & send_index1);
    buffer_append_int16(buffer,RPA, & send_index1);
    comm_can_transmit_eid(controller_id |
        ((uint32_t)CAN_PACKET_SET_POS << 8), buffer, send_index);
}
```

5.2 Servo mode of motor message format

In servo mode, motor packets are uploaded in timing mode. The upload frequency can be set to 1-500Hz, and the upload byte is 8 bytes

Data bits	Data[0]	Data[1]	Data[2]	Data[3]	Data[4]	Data[5]	Data[6]	Data[7]
Range	0~0xff	0~0xff	0~0xff	0~0xff	0~0xff	0~0xff	0~0xff	0~0xff
Corresponding variables	Position 8 bit higher	Position 8 bit lower	Speed 8 bit higher	Speed 8 bit lower	Current 8 bit higher	Position 8 bit lower	Motor temperature	An error code

The following is an example of receiving a message

```
void motor_receive(float* motor_pos,float*
motor_spd,float* cur,int_8* temp,int_8* error,rx_message)
{
    &motor_pos= (float)((rx_message)->Data[0] << 8 | (rx_message)->Data[1]); //电机位置
    &motor_spd= (float)((rx_message)->Data[2] << 8 | (rx_message)->Data[3]); //电机速度
    &motor_cur= (float)((rx_message)->Data[4] << 8 | (rx_message)->Data[5]); //电机电流
    &motor_temp= (rx_message)->Data[6] ;
    &motor_error= (rx_message)->Data[7] ;
}
```

5.3 MIT power mode communication protocol

Special Can code

Enter motor control mode {0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0XFC }

Exit motor control mode {0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0XFD }

Set the current position of the motor to 0 {0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0xFF, 0XFE }

Note: motor control mode must be entered before using CAN communication control motor!

Force control mode drive board receives data definition

Identifier: set motor ID (default: 1)

Frame type: standard frame

Frame format: DATA

DLC: 8 bytes

Data fields	DATA[0]	DATA[1]	DATA[2]	DATA[3]	
Data bits	7-0	7-0	7-0	7-4	3-0
The data content	Motor position 8 bit higher	Motor position 8 bit lower	Motor speed 8 bit higher	Motor speed 4 bit lower	KP value 4 bit higher

Data fields	DATA[4]	DATA[5]	DATA[6]		DATA[7]
Data bits	7-0	7-0	7-4	3-0	0-7
The data content	KP value 4 bit lower	KD value 8 bit lower	KD value 4 bit lower	Current value 4 bit higher	Current value 8 bit lower

MIT power mode driver board sending data definition

Identifier: 0X00+ Drive ID

Frame type: standard frame

Frame format: DATA

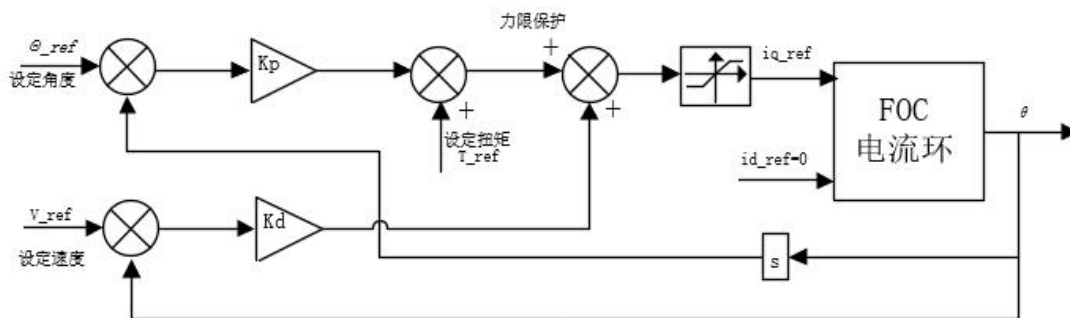
DLC: 6 bytes

Data fields	DATA[0]	DATA[1]	DATA[2]	DATA[3]	DATA[4]
Data bits	7-0	7-0	7-0	7-0	7-4
The data content	Driver board ID code	Motor position 8 bit higher	Motor position 8 bit lower	Motor speed 8 bit higher	Motor speed 4 bit lower

Data fields	DATA[4]	DATA[5]
Data bits	3-0	7-0
The data content	Current 4 bit higher	Current 8 bit lower

CAN Speed: 1 MHZ

Simple block diagram of MIT power mode



MIT power mode transceiver code routine

Sends routine code

```

void pack_cmd(CANMessage * msg, float p_des, float v_des, float kp, float kd, float t_ff){
  /// limit data to be within bounds ///
  float P_MIN =-95.5;
  float P_MAX =95.5;
  float V_MIN =-30;
  float V_MAX =30;
  float T_MIN =-18;
  float T_MAX =18;
  float Kp_MIN =0;
  float Kp_MAX =500;
  float Kd_MIN =0;
  float Kd_MAX =5;
  float Test_Pos=0.0;
  p_des = fminf(fmaxf(P_MIN, p_des), P_MAX);
  v_des = fminf(fmaxf(V_MIN, v_des), V_MAX);
  kp = fminf(fmaxf(Kp_MIN, kp), Kp_MAX);
  kd = fminf(fmaxf(Kd_MIN, kd), Kd_MAX);
  t_ff = fminf(fmaxf(T_MIN, t_ff), T_MAX);
  /// convert floats to unsigned ints ///
  int p_int = float_to_uint(p_des, P_MIN, P_MAX, 16);
  int v_int = float_to_uint(v_des, V_MIN, V_MAX, 12);
  int kp_int = float_to_uint(kp, KP_MIN, KP_MAX, 12);
  int kd_int = float_to_uint(kd, KD_MIN, KD_MAX, 12);

```

```

int t_int = float_to_uint(t_ff, T_MIN, T_MAX, 12);
/// pack ints into the can buffer ///
msg->data[0] = p_int>>8;          // Position 8 higher
msg->data[1] = p_int&0xFF;       // Position 8 lower
msg->data[2] = v_int>>4;         // Speed 8 higher
msg->data[3] = ((v_int&0xF)<<4)|(kp_int>>8); //
Speed 4 bit lower KP 4bit higher
msg->data[4] = kp_int&0xFF;      // KP 8 bit lower
msg->data[5] = kd_int>>4;       // Kd 8 bit higher
msg->data[6] = ((kd_int&0xF)<<4)|(kp_int>>8); //
                                                                    KP 4 bit lower torque 4 bit higher
msg->data[7] = t_int&0xff;      // torque 4 bit lower

}

```

When sending packets, all the numbers should be converted into integer numbers by the following functions and then sent to the motor.

```

int float_to_uint(float x, float x_min, float x_max, unsigned int bits)
{
/// Converts a float to an unsigned int, given range and number of bits ///
float span = x_max - x_min;
if(x < x_min) x = x_min;
else if(x > x_max) x = x_max;
return (int) ((x - x_min)*((float)((1<<bits)/span)));
}

```

Receive routine code

```

void unpack_reply(CANMessage msg){
/// unpack ints from can buffer ///
int id = msg.data[0]; //驱动 ID 号
int p_int = (msg.data[1]<<8)|msg.data[2];          //Motor position data
int v_int = (msg.data[3]<<4)|(msg.data[4]>>4);     // Motor speed data
int i_int = ((msg.data[4]&0xF)<<8)|msg.data[5];     // Motor torque data

/// convert ints to floats ///
float p = uint_to_float(p_int, P_MIN, P_MAX, 16);
float v = uint_to_float(v_int, V_MIN, V_MAX, 12);
float i = uint_to_float(i_int, -I_MAX, I_MAX, 12);
    if(id == 1){
postion = p;                                     //
                                                Read the corresponding data according to the ID code

```

```
speed = v;  
torque = i;  
    }  
}
```

All numbers are converted to floating-point by the following function.

```
float uint_to_float(int x_int, float x_min, float x_max, int bits){  
    /// converts unsigned int to float, given range and number of bits ///  
    float span = x_max - x_min;  
    float offset = x_min;  
    return ((float)x_int)*span/((float)((1<<bits)-1)) + offset;  
}
```