



Ardumower
connected

Overload Counter
0, 0

Power in Watt I, r
0.00, 0.00

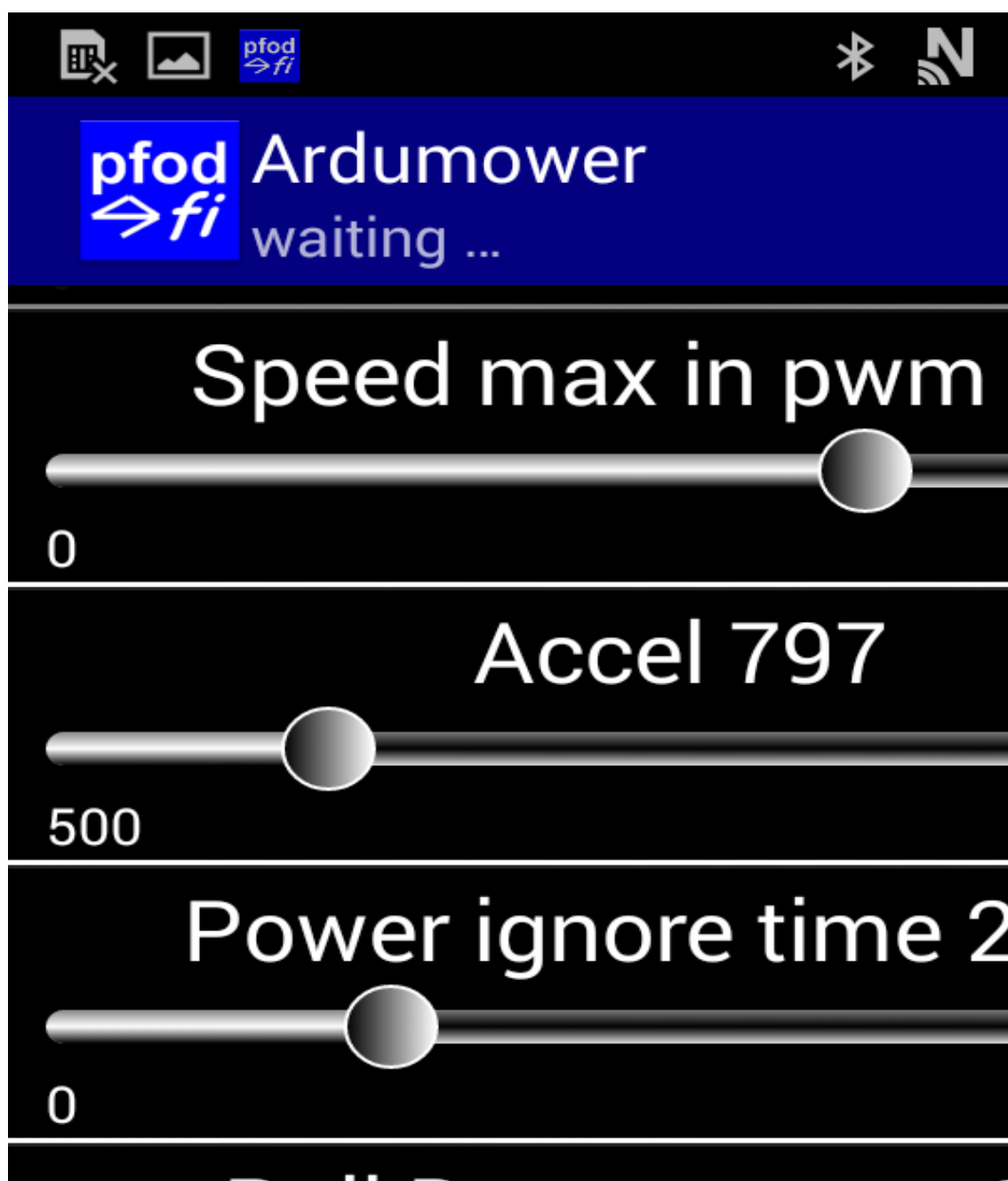
motor current in mA
0.00, 0.00

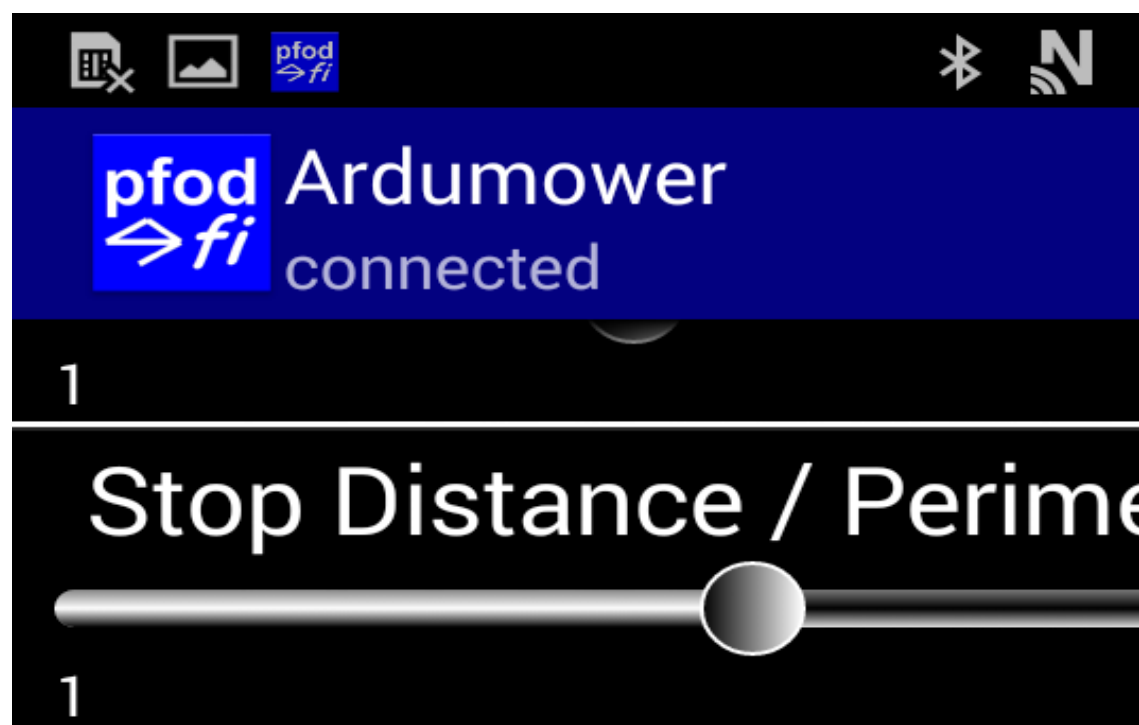
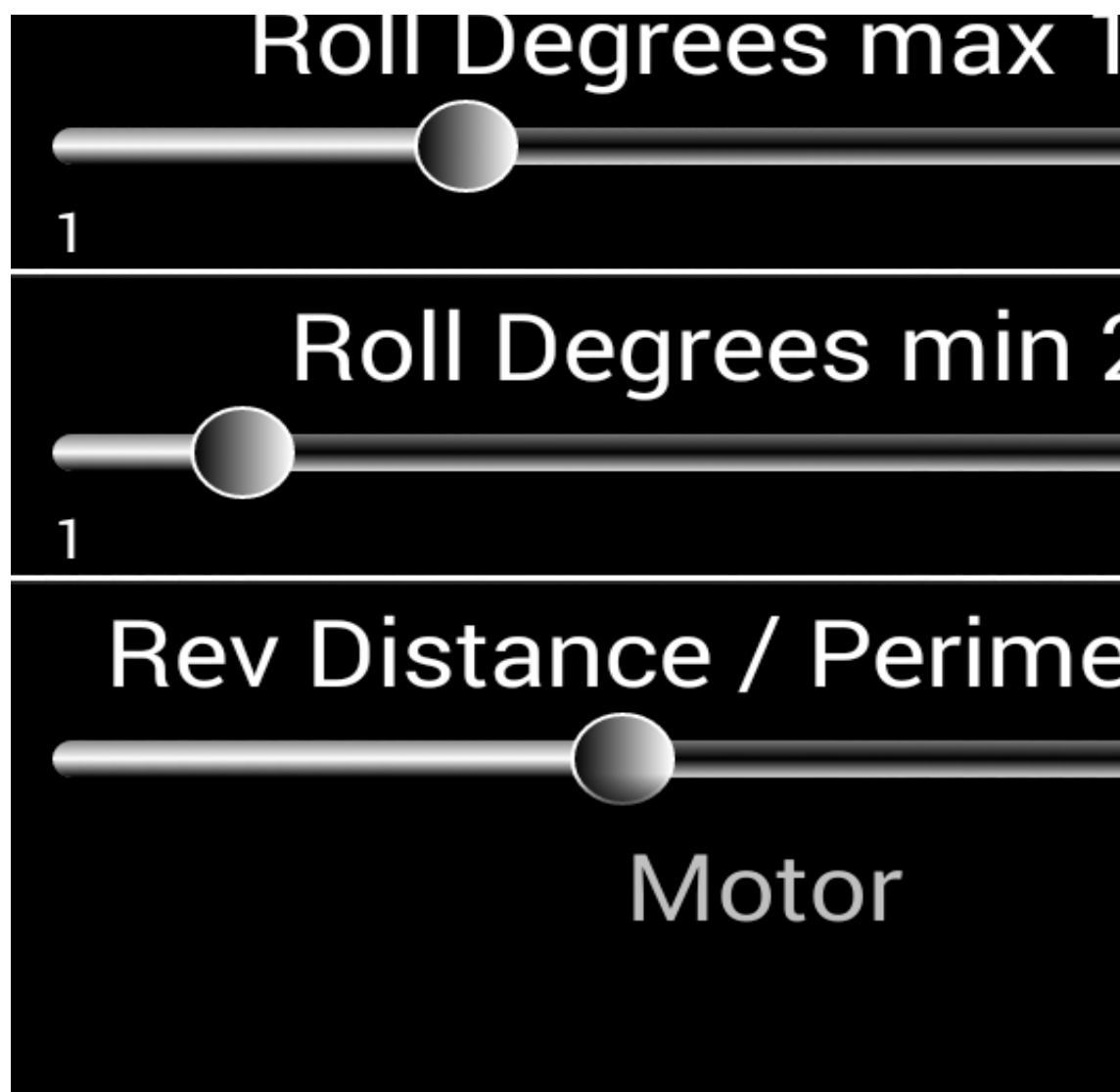
Power max 23,3

0.0

Speed I, r0, 0

Speed max in rpm



RPM_P 1,



0.0

RPM_I 0,4



0.0

RPM_D 0.0



0.0

Testing is
OFF

MotorSenseLeftScale



Motor





Ardumower
connected

MotorSenseLeftScale



0,1

MotorSenseRightScale



0,1

for config file: motorSen
l, r1.65, 1.87

Swap left direction

Swap right direction

PWM Right Forward off

0



-50

Motor

Orange F 21:23



ESP32_BT01denna

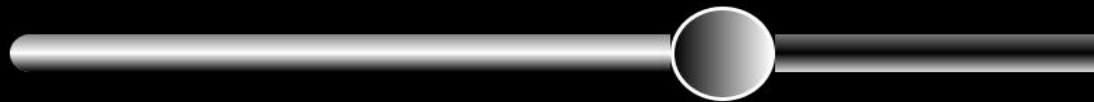
waiting ...

Swap left direction

Swap right direction

PWM Right Forward off

0



-50

PWM Right Reverse off

0



50

-50

Speed Odo Minimum



0

Speed Odo Maximum



100

Calib Ticks/Second

Motor



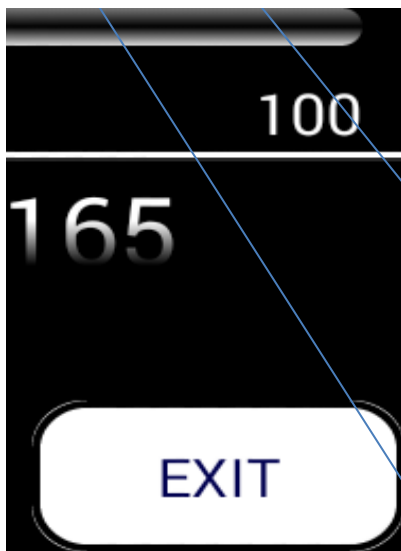


Counter of Overload

Actual Power of left
Watt

Electrical intensity of
with MotorSenseSca

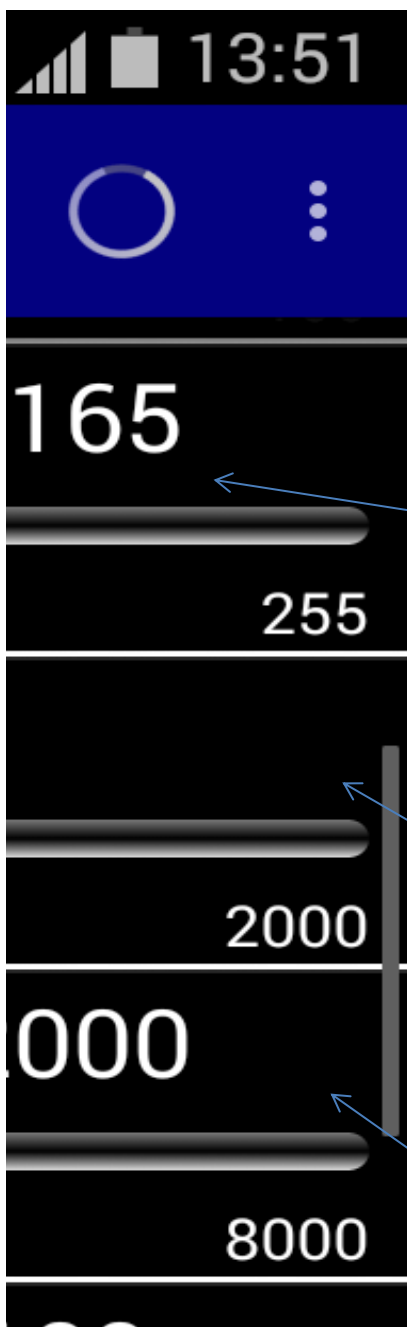
Max power (at 80% of
mower stop and rev
mower stop and it's
To find the best Valu
Manual and forward
until the subject is



until the wheels slip

Actual speed in RPM

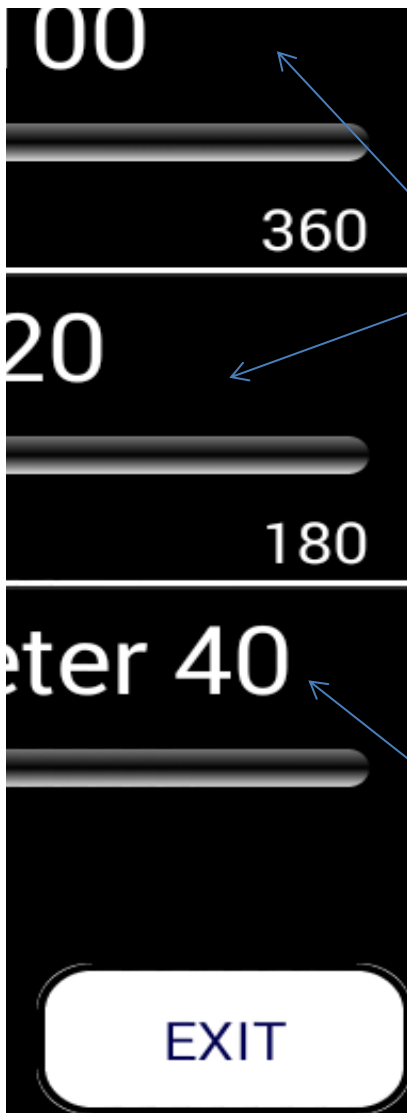
The Max wheels speed
Adjust with PWM, I
PWM is not at max
(See Odometry sett



Normal speed of the
mowing mode
Very Important sett

Wheel Acceleration

During this duration
motor is not manag

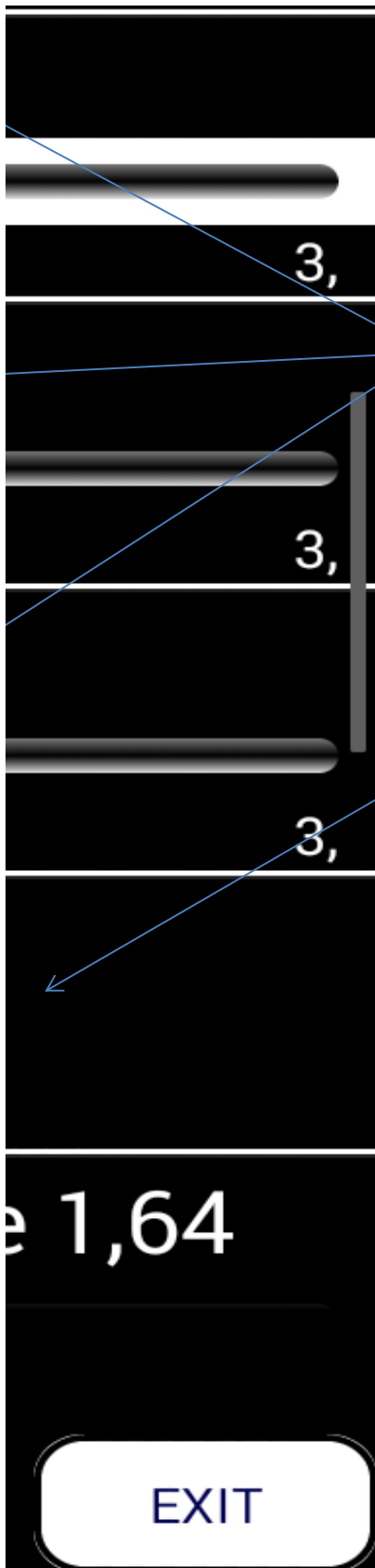


Into Random Mode
and maximum roll a
correct random path

After crossing wire it
distance in CM
need to be bigger th
Distance,



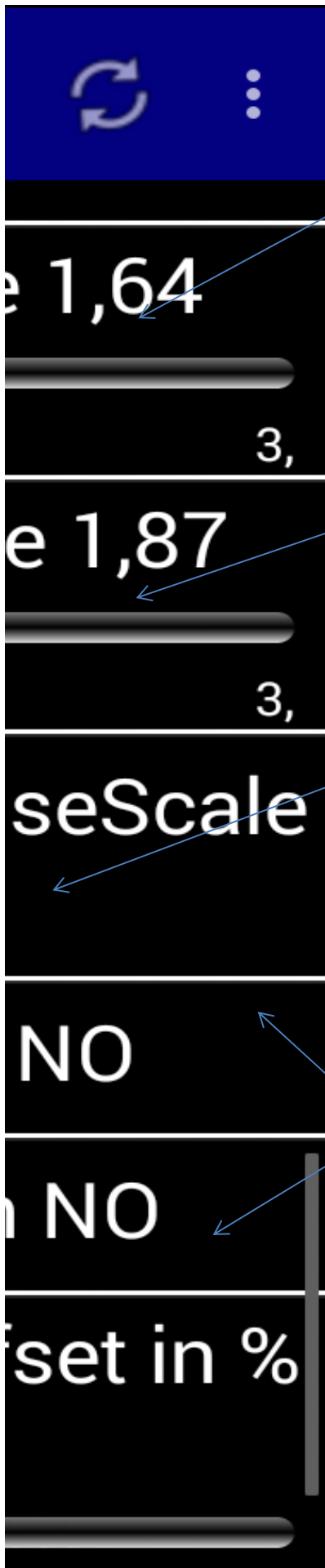
Brake distance after c
perimeter wire,
(The mower go over t
but help to brake and
Not too big to avoid p
error



P I D parameter

Use to go in straigh li
(when IMU is not use
mode)

Test of motor (remov
: there is a new men

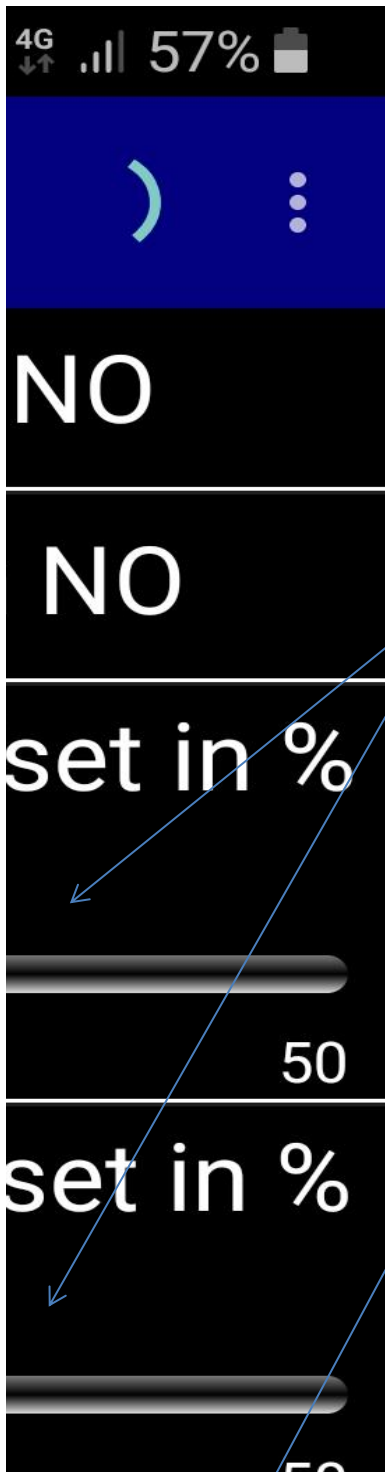
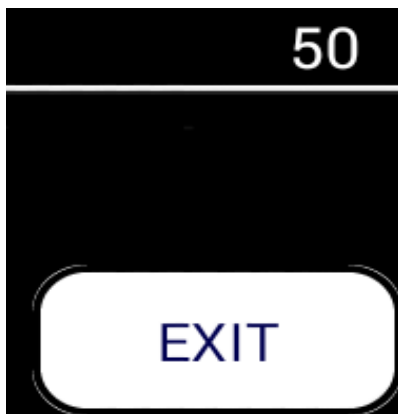


Use to perfectly set t
motor (Visible only in

Use to perfectly set
Right motor (Visible

I need to verify but r

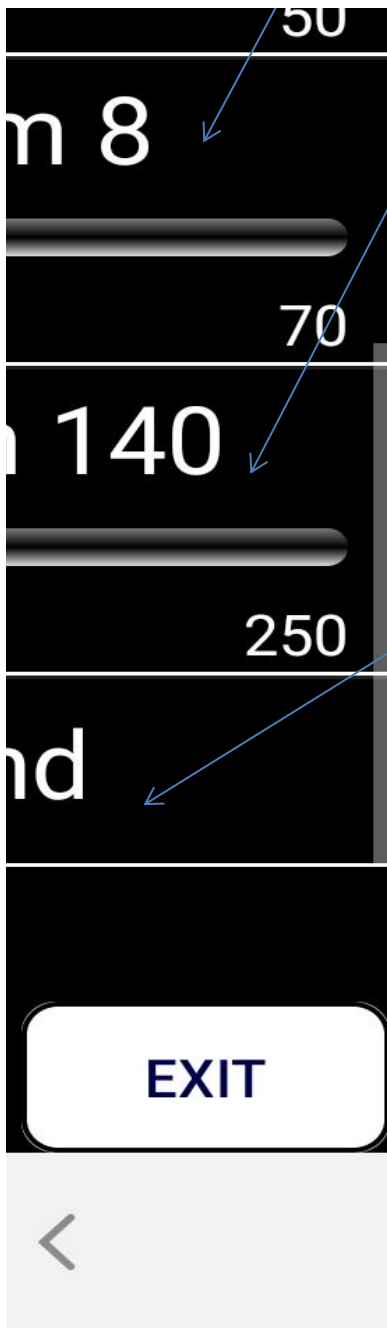
Swap is used to reve
INVERT THE WIRE DI



Offset to help the 2 r
same PWM,easy to c
need to stop at the s

Minimum PWM for tl
IMPORTANT to avoid

Maximum PWM Avoi



(need to be smaller t

Warning MOWER M
To do once into norr
all the state duratior
slope or big grass

d ,Not important in

: and Right Motor in

f Motor in Ma Adjust
le if not correct

of this value the
erse) at 100% the
ERROR.

ie, put the mower in
l ,Brake the mower

system and read value

or stop, and read max

1

eed in RPM
n manual check that
value on the 2 wheel
ting)

e mower when into
:ing

n Coeff (use into

n the Power of
e help when accel

it's the minimum
angle to have a
h

it's the reverse

an the Stop

crossing the

the wire in this case
(smooth movement)
perimeter timeout

ine with ODOmetry
ed or in Manual

/e in the futur version
u for that)

the intensity of left
in DEV mode)

the intensity of
only in DEV mode)

not use

use a motor but BETTER TO
DIRECTLY ON MOTOR

motor to go at exactly the same speed
check into test motor 5 turn the 2 n
ame time, Into forward and reverse

he motor to turn on small slope ,VE
long pause during mowing

id mower go too fast when adding

han MaxPWM)

OVE when click
nal grass to help the firmware to c
1 and avoid wait at the end of state

eed when
motors
e Mode,

ERY

the PID

.....

ompute
e on