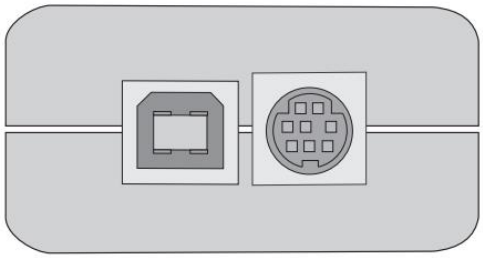
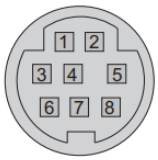
1. Torque series MD8 interface definition

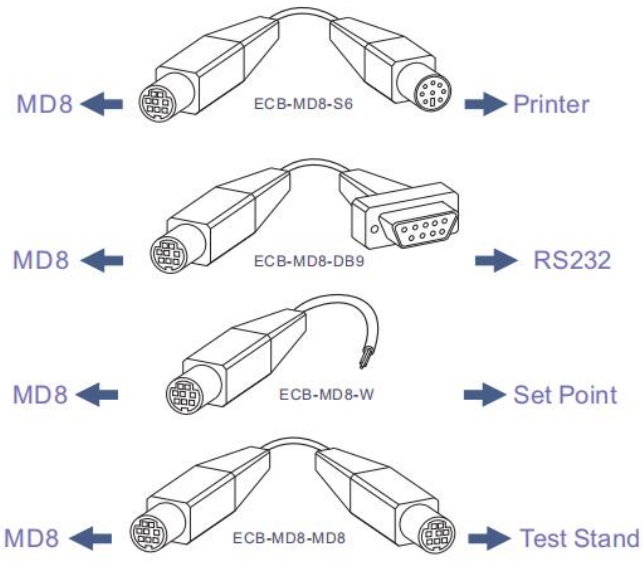




Pin	Description
1	RS232 Transmit(TX)
2	RS232 Receive(RX)
3	RS232 Ground
4	Output A+
5	Reserved
6	Output COM-
7	Output B+
8	Reserved

When RS232 is used for serial communication, refer to the above pin definition, where pin 1 is the sending end of the dynamometer, which can be connected to the receiving end of the user device RS232; pin 2 is the receiving end of the dynamometer, which can be connected to the sending end of the user device RS232; pin 3 is the GND of the dynamometer RS232, which is connected to the GND of the user device.

There are a variety of MD8 wire options:



2. Baud rate setting

The torque series uses 38400 bps by default, the other Settings are set to stop bit 1, data bit 8, and parity none.

3. Communication command

Communication command (hexadecimal)	Instruction effect
0x3F	Returns a real-time value
0x50 0x5A 0x00	Zero clearing, serial return 0x52 0x06
0x3F 0x43 0x01	Returns a display value
0x3F 0x43 0x02	Data is returned continuously at the rate of 10 times per second
0x3F 0x43 0x03	Data is returned continuously at the rate of 20 times per second
0x3F 0x43 0x04	Data is returned continuously at the rate of 50 times per second
0x3F 0x43 0x05	Data is returned continuously at the rate of 100 times per second
0x3F 0x43 0xff	Terminate continuous return instruction
0x53 0x50 0x01	Set the unit to N.m, serial return 0x52 0x50 0x01
0x53 0x50 0x02	Set the unit to N.cm, serial return 0x52 0x50 0x02
0x53 0x50 0x03	Set the unit to kgf.m, serial return 0x52 0x50 0x03
0x53 0x50 0x04	Set the unit to kgf.cm, serial return 0x52 0x50 0x04
0x53 0x50 0x05	Set the unit to lbf.ft, serial return 0x52 0x50 0x05
0x53 0x50 0x06	Set the unit to lbf.in, serial return 0x52 0x50 0x06
0x53 0x50 0x07	Set the unit to N.mm, serial return 0x52 0x50 0x07

The above table is the torque series communication commands, the left side is the command sent by the user device, and the right side is the status of the torque series after receiving the command.

For example, if the user device sends 0x3F, the torque series immediately returns the real-time value of the torque series after receiving the command, and the returned data is in the string format: for example, -2.3456 N.m.

For setting unit instructions, if there is no such unit in the current range, keep the current unit.