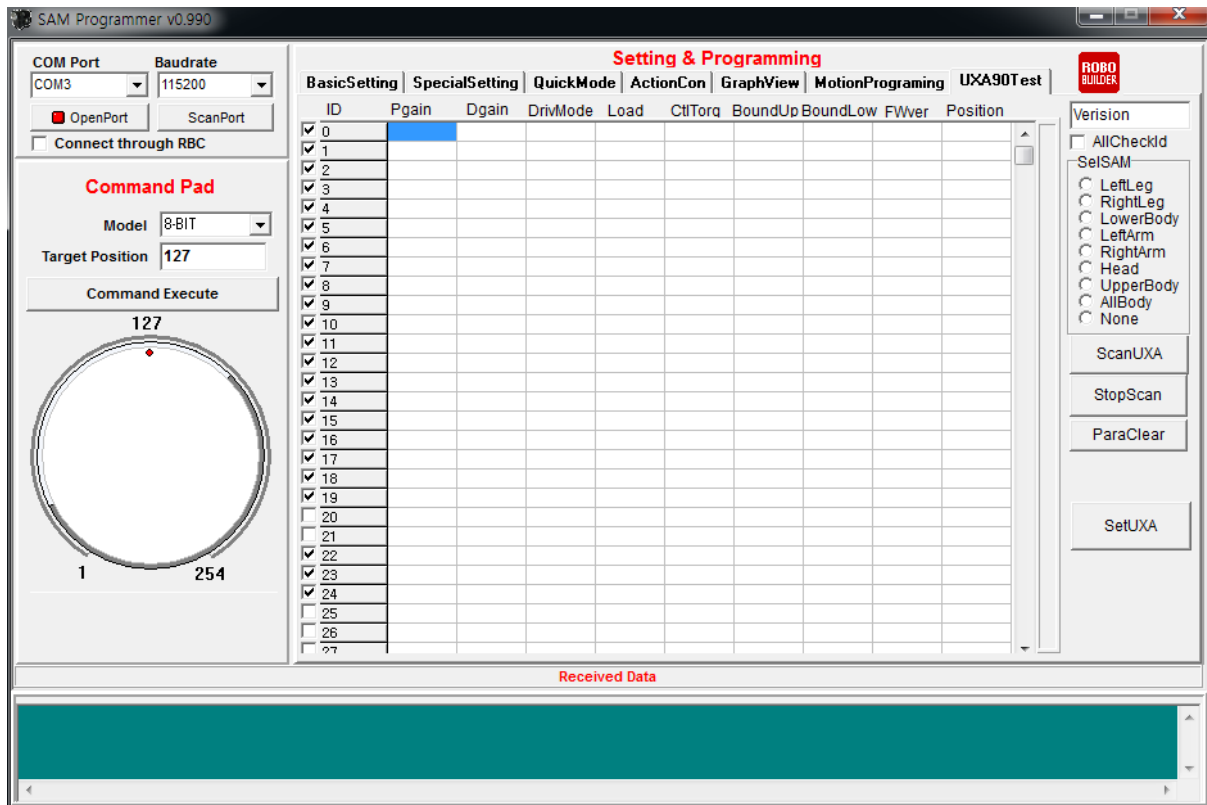


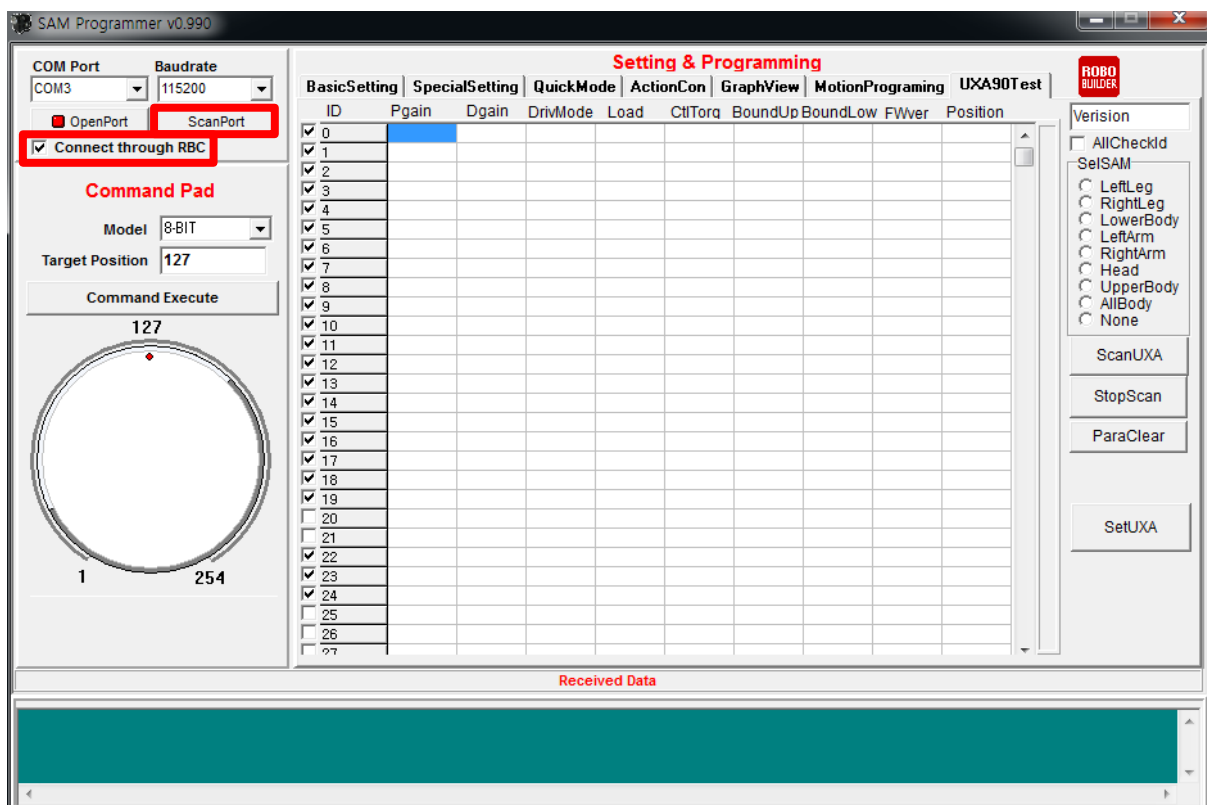
●SAM Programmer v0.990●

Preparation : ①UXA-90 and PC are connected by an USB cable. ②UXA-90 is in sitting position while power is on.

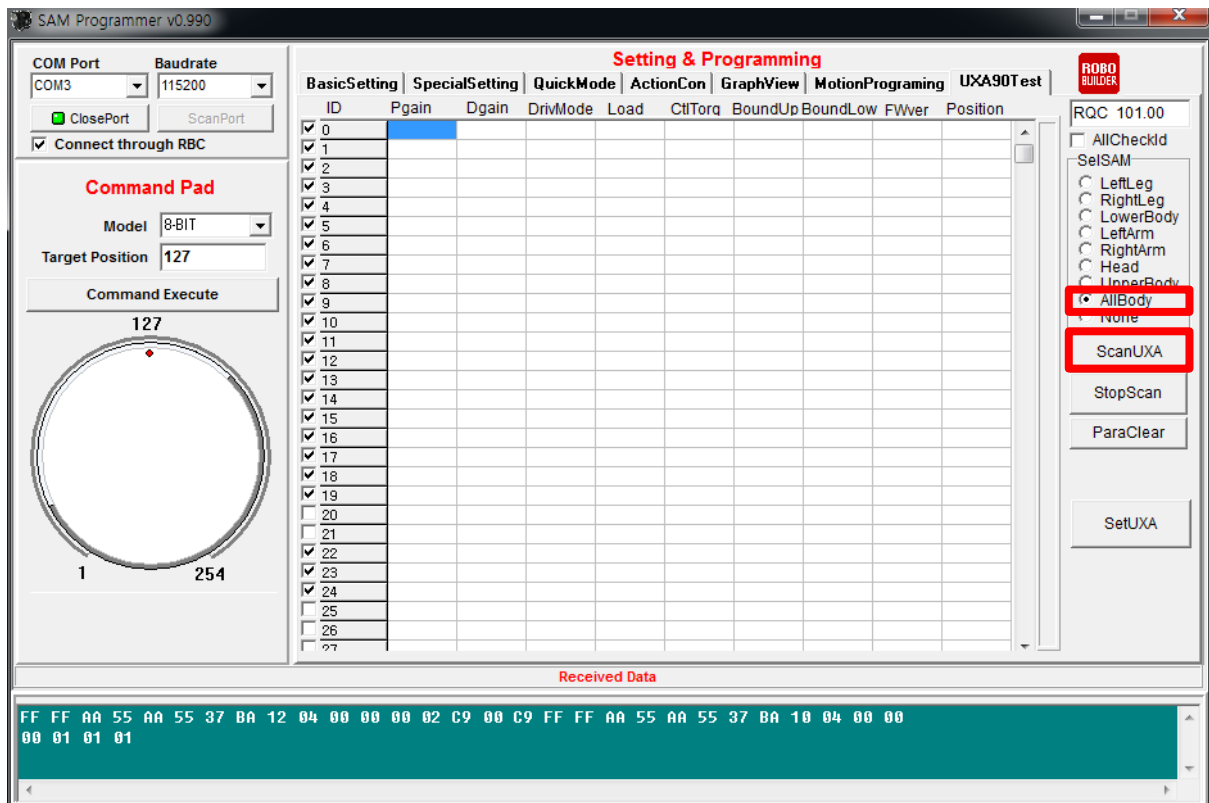
1. Run "SAM Programmer v0.990".



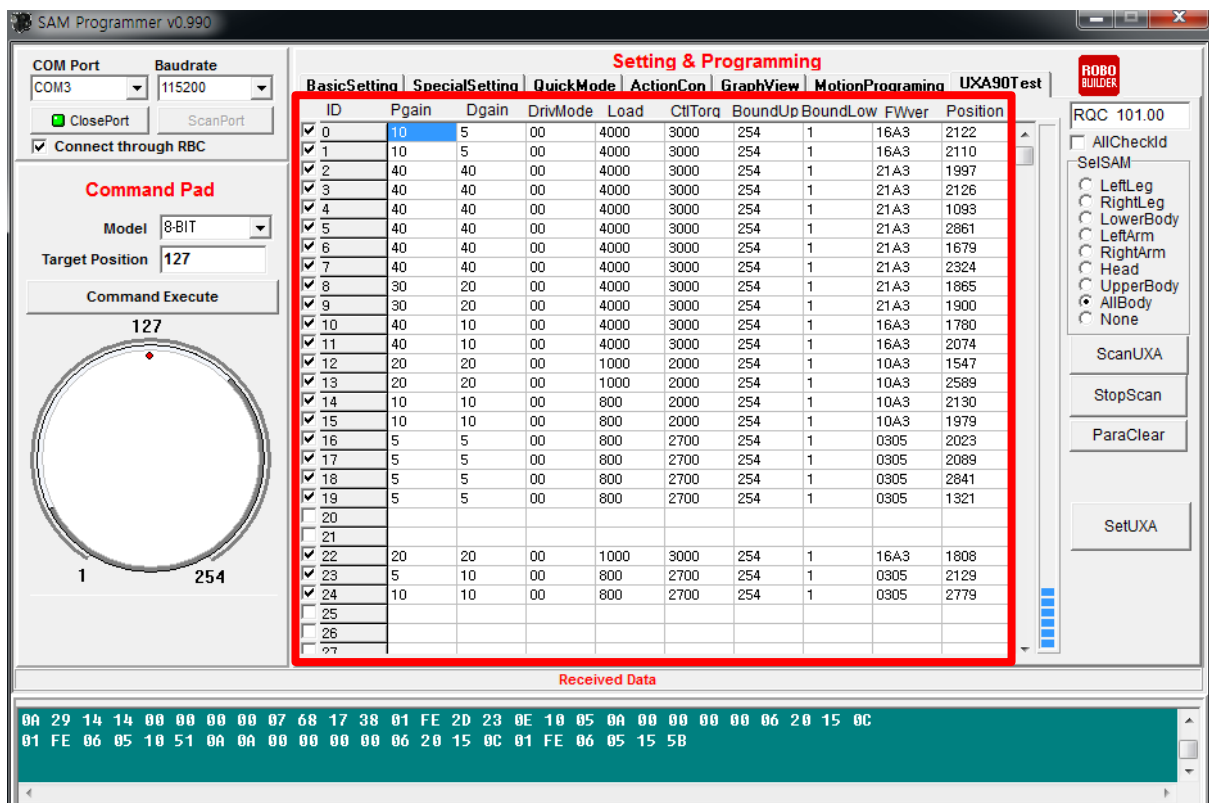
2. Check "Connect through RBC" and click "Scan Port" to connect with the robot.



3. "Closeport" will appear once the connection is successfully done. Check "AllBody" and click "Scan UXA" to scan all of UXA-90's servo motors.



4. You can scan all of the servo motors' data if UXA-90 is in a normal condition. (Please follow this process and send us a captured image of the scanned data as below).



5. But if UXA-90 is not in a normal condition, you will see pop-up message "Try Again", then if you press "OK", the scan will go on and will find servo motors that do not function.

The software interface is titled "SAM Programmer v0.990" and features a "Setting & Programming" tab. It includes a "Command Pad" on the left with a circular diagram and a "Received Data" section at the bottom.

Top Screenshot: A "Try Again" dialog box is displayed over the servo motor data table. The table lists 27 servos with columns for ID, Pgain, Dgain, DrivMode, Load, CtlTorq, BoundUp, BoundLow, FWver, and Position. The data for the first 19 servos is as follows:

ID	Pgain	Dgain	DrivMode	Load	CtlTorq	BoundUp	BoundLow	FWver	Position
0	10	5	00	4000	3000	254	1	16A3	2121
1	10	5	00	4000	3000	254	1	16A3	2108
2	40	40	00	4000	3000	254	1	21A3	2017
3	40	40	00	4000	3000	254	1	21A3	2110
4	40	40	00	4000	3000	254	1	21A3	1077
5	40	40	00	4000	3000	254	1	21A3	2914
6	40	40	00	4000	3000	254	1	21A3	1687
7	40	40	00	4000	3000	254	1	21A3	2346
8	30	20	00	4000	3000	254	1	21A3	1867
9	30	20	00	4000	3000	254	1	21A3	1895
10	40	10	00	4000	3000	254	1	16A3	1777
11	40	10	00	4000	3000	254	1	16A3	2046
12	20	20	00	4000	3000	254	1	10A3	1548
13	20	20	00	4000	3000	254	1	10A3	2588
14	10	10	00	4000	3000	254	1	10A3	2127
15	10	10	00	4000	3000	254	1	10A3	1978
16	5	5	00	4000	3000	254	1	0305	2022
17	5	5	00	4000	3000	254	1	0305	2106
18	5	5	00	4000	3000	254	1	0305	2816
19	5	5	00	4000	3000	254	1	0305	1351

Bottom Screenshot: The same interface is shown, but with a red box highlighting a row of data for a non-functional servo motor (ID 23):

ID	Pgain	Dgain	DrivMode	Load	CtlTorq	BoundUp	BoundLow	FWver	Position
23	5	10	00	800	2700	254	1	0305	2100
24	10	10	00	800	2700	254	1	0305	2780