地址 Address	功能 Function	读写 Read-write	初始值 Initial Value	备注 Note	模式 Mode
0x00	工作状态 Mode of operation	读 Read	0x00		状态信息 State information
0x01	电池电量 Battery level	读 Read	0xff	范围为0-100，线性对应电量最低值-最高值 Range: 0-100, linearly corresponding to the lowest-highest battey level	
0x02	XGO版本 XGO version	读 Read		0x00 MINI | 0x01 Lite | 0x02 PRO	
0x03	表演模式 Performance mode	写 Write	0x00	0x00正常控制模式 | 0x01循环做动作 0x00 normal control mode | 0x01 cyclic action	
0x04	标定模式 Calibration mode	写 Write	0x00	0x01进入标定模式 0x00退出标定模式完成标定 0x01 Enter the calibration mode 0x00 Exit the calibration mode and complete the calibration process	
0x10	蓝牙连接状态 Status of Bluetooth connection	读 Read	0x00	0x00本机无蓝牙设备或蓝牙模块故障 0x01支持蓝牙设备但未连接手机终端 0x02已连接手机终端 0x00 The appliance has no Bluetooth device or the Bluetooth module malfunctions 0x01 Bluetooth device is supported but the mobile terminal is not connected 0x02 The mobile terminal is connected	蓝牙信息 暂不支持 Bluetooth information Currently not supported
0x11	蓝牙串口波特率 Baud rate of Bluetooth serial port	读 Read	0x00		
0x12	蓝牙密码 Bluetooth password	读写 Read-write	1234	该寄存器为字符串类型，典型值占位可能超过一个字节，读取命令时将忽略指令中的字节数，返回数据包中按真实字节数，写入时数据包中请按真实字节数 This register is a string type and the space occupied by typical value may be more than one byte. Bytes in the instruction will be ignored when reading command, take actual bytes in the packet returned; when writing take actual bytes in the packet	

0x13	蓝牙名称 Bluetooth name	读写 Read-write	HC-05	该寄存器为字符串类型，典型值占位可能超过一个字节，读取命令时将忽略指令中的字节数，返回数据包中按真实字节数，写入时数据包中请按真实字节数 This register is a string type and the space occupied by typical value may be more than one byte. Bytes in the instruction will be ignored when reading command, take actual bytes in the packet returned; when writing take actual bytes in the packet	
0x20	卸载舵机 Unmount steering gear	读写 Read-write	0x00	0x00舵机处于正常工作状态，0x01卸载所有舵机，0x11-0x14依次卸载1-4号腿，0x21-0x24依次恢复1-4号腿 0x00 The steering gear is in normal operation, 0x01 Unmount all gears, 0x11-0x14 Unmount #1-4 leg in order, 0x21-0x24 Remount #1-4 leg in order	调试模式 Test mode
0x21	重置舵机零位 Reset the zero position of steering gear	写 Write	0x00	0x00舵机处于正常工作状态0x01所有舵机记录当前位置为零位 该寄存器设定为0x01后，会自动跳变为0x00 0x00 The steering gear is in normal operation, 0x01 All gears record the current position as the zero position. Once set as 0x01, the register will automatically jump to 0x00	
0x30	前后移动速度 Forward/backward movement speed	读写 Read-write	0x80	范围为0x00-0xff，线性对应反向最大值-正向最大值，正方向按机器人坐标系，下同 Range: 0x00-0xff, linearly corresponding to the revers max. value-forward max. value. The forward direction is the same as the robot coordinate system, the same below	整机模式 Whole unit mode
0x31	左右移动速度 Left/right movement speed	读写 Read-write	0x80		
0x32	顺逆时针旋转速度 Clockwise/counterclockwise rotation speed	读写 Read-write	0x80	迎着z轴射来方向顺时针对应最大值方向 The incidence direction along the z axis corresponds to the max. value direction clockwise	
0x33	身体沿x方向平移距离 Body shift distance along the x direction	读写 Read-write	0x80	足端与地面接触点不变而身体扭动，下同 The body twists with the area where the foot contacts the floor remains unchanged, the same below	
0x34	身体沿y方向平移距离 Body shift distance along the	读写 Read-	0x80		

	y direction	write		
0x35	身体高度 Body height	读写 Read-write	0x80	
0x36	身体绕x轴旋转角度 Angle at which the body rotates around the x axis	读写 Read-write	0x80	迎着坐标轴射来方向顺时针对应最大值方向 The incidence direction along the coordinate system corresponds to the max. value direction clockwise
0x37	身体绕y轴旋转角度 Angle at which the body rotates around the y axis	读写 Read-write	0x80	
0x38	身体绕z轴旋转角度 Angle at which the body rotates around the z axis	读写 Read-write	0x80	
0x39	以一定周期绕x轴旋转身体 A given period in which the body rotates around the x axis	读写 Read-write	0x00	0x00停止，0x01-0xff线性对应最小-最大旋转速度，该功能与直接设置位置寄存器不能同时起作用 0x00 stop, 0x01-0xff linearly corresponds to the min.-max. rotation speed, this function cannot work alongside with the direct setup of the position register
0x3A	以一定周期绕y轴旋转身体 A given period in which the body rotates around the y axis	读写 Read-write	0x00	
0x3B	以一定周期绕z轴旋转身体 A given period in which the body rotates around the z axis	读写 Read-write	0x00	
0x3C	原地踏步 Stepping	读写 Read-	0x00	0x00停止，0x01-0xff线性对应最小-最大踏步高度 0x00 stop, 0x01-0xff linearly corresponds to the min.-max. stepping height

		write		
0x3D	运动模式 Moving mode	读写 Read-write	0x00	0x00常速运动0x01慢速运动0x02高速运动 0x00 Move at normal speed 0x01 Move at slow speed 0x02 Move at high speed	
0x3E	动作指令 Action command	写 Write	0x00	动作指令表，0为默认站姿 1-N为各个动作(0-N为十进制)，1趴下，2站起，3匍匐前进，4转圈，5原地踏步，6蹲起，7转动Roll，8转动Pitch，9转动Yaw，10三轴转动，11撒尿，12坐下，13招手，14伸懒腰，15波浪，16左右摇摆，17求食，18找食物，19握手 List of action commands, 0 is the default stance 1-N means each action (0-N is decimal value), 1: lying down, 2: standing up, 3: creeping, 4: circling, 5: stepping, 6: squatting, 7: rolling , 8: pitching, 9: yawing, 10 three-axis rotation, 11 peeing, 12 sitting, 13 beckoning, 14: stretching, 15: waving, 16 swaying, 17 begging for food, 18 searching food, 19 shaking hands	
0x80	以一定周期沿X轴方向平移运动 A given period in which the body shifts along the X axis	读写 Read-write	0x00	0x00停止，0x01-0xff对应最小-最大旋转速度，移动幅度为位置限幅的一半 0x00 stop, 0x01-0xff corresponds to the min.-max. rotation speed, the extent of movement is a half of the position limit	
0x81	以一定周期沿Y轴方向平移运动 A given period in which the body shifts along the Y axis	读写 Read-write	0x00		
0x82	以一定周期沿Z轴方向平移运动 A given period in which the body shifts along the Z axis	读写 Read-write	0x00		
0x40	左前腿x方向足端位置 Foot position along the x direction of the left fore leg	读写 Read-write	0x80	范围为0x00-0xff，线性对应反向最大值-正向最大值，正方向按机器人坐标系 Range: 0x00-0xff, linearly corresponding to the reverse max. value-forward max. value, the forward direction is the same as the robot coordinate system	单腿模式 Single leg mode
0x41	左前腿y方向足端位置 Foot position along the y direction of the left fore leg	读写 Read-write	0x80		

0x42	左前腿z方向足端位置 Foot position along the z direction of the left fore leg	读写 Read-write	0x80	
0x43	右前腿x方向足端位置 Foot position along the x direction of the right fore leg	读写 Read-write	0x80	
0x44	右前腿y方向足端位置 Foot position along the y direction of the right fore leg	读写 Read-write	0x80	
0x45	右前腿z方向足端位置 Foot position along the z direction of the right fore leg	读写 Read-write	0x80	
0x46	右后腿x方向足端位置 Foot position along the x direction of the right rear leg	读写 Read-write	0x80	
0x47	右后腿y方向足端位置 Foot position along the y direction of the right rear leg	读写 Read-write	0x80	
0x48	右后腿z方向足端位置 Foot position along the z direction of the right rear leg	读写 Read-write	0x80	
0x49	左后腿x方向足端位置 Foot position along the x direction of the left rear leg	读写 Read-write	0x80	
0x4A	左后腿y方向足端位置 Foot position along the y direction of the left rear leg	读写 Read-write	0x80	

0x4B	左后腿z方向足端位置 Foot position along the z direction of the left rear leg	读写 Read-write	0x80		
0x50	左前腿肘，ID为11舵机位置 Left fore leg elbow, ID is the position of #11 gear	读写 Read-write	0x80	范围为0x00-0xff，线性对应反向最大值-正向最大值 Range: 0x00-0xff, linearly corresponding to the reverse max. value-forward max. value	舵机模式 Steering gear mode
0x51	左前腿臂，ID为12舵机位置 Left fore leg arm, ID is the position of #12 gear	读写 Read-write	0x80		
0x52	左前腿肩，ID为13舵机位置 Left fore leg shoulder, ID is the position of #13 gear	读写 Read-write	0x80		
0x53	右前腿肘，ID为21舵机位置 Right fore leg elbow, ID is the position of #21 gear	读写 Read-write	0x80		
0x54	右前腿臂，ID为22舵机位置 Right fore leg arm, ID is the position of #22 gear	读写 Read-write	0x80		
0x55	右前腿肩，ID为23舵机位置 Right fore leg shoulder, ID is the position of #23 gear	读写 Read-write	0x80		
0x56	右后腿肘，ID为31舵机位置 Right rear leg elbow, ID is the position of #31 gear	读写 Read-write	0x80		
0x57	右后腿臂，ID为32舵机位置 Right rear leg arm, ID is the position of #32 gear	读写 Read-write	0x80		

0x58	右后腿肩，ID为33舵机位置 Right rear leg shoulder, ID is the position of #33 gear	读写 Read-write	0x80	
0x59	左后腿肘，ID为41舵机位置 Left rear leg elbow, ID is the position of #41 gear	读写 Read-write	0x80	
0x5A	左后腿臂，ID为42舵机位置 Right rear leg arm, ID is the position of #42 gear	读写 Read-write	0x80	
0x5B	左后腿肩，ID为43舵机位置 Right rear leg shoulder, ID is the position of #43 gear	读写 Read-write	0x80	
0x5C	设置舵机速度 Set the speed of steering gear	读写 Read-write	0x80	范围为0x00-0xff，线性对应最小值-最大值（仅在该模式下有效） Range: 0x00-0xff, linearly corresponding to the min. - max. value (only applicable under this mode)
0x5D	舵机位置设置为站立姿态 The gear position is set as standing posture	写 Write	0x00	0x00不起作用0x01舵机位置恢复站立时位置 该寄存器设定为0x01后，会自动跳变为0x00 0x00 inactive. 0x01 The gear position returns to the standing position. Once set as 0x01, the register will automatically jump to 0x00
0x61	IMU状态 IMU state	读写 Read-write	0x00	0x00关闭 0x01自稳定模式 0x00 close 0x01 self-stabilizing mode