# Connection detection

Link test is a detection function that uses the motor in the robot arm and the connection state of **Atom**. The function allows the user to remove equipment faults easily.

During the link test, the connection state of the equipment for the robot arm, including the **connection of the servo** and the **communication state of Atom** can be seen. In **micro-controller devices**, the versions of their current firmwares are shown on M5Stack-basic.

**Different types of devices have different operating methods**. They have the approximate steps below:

- Burn the latest version of **atomMain** for **Atom**, and the **minirobot** for **M5Stack-basic.**
- Choose the **Information** function (It is unnecessary to burn **M5Stack-basic** for micro-CPU devices)
- press the detection key to detect the connection of the devices
- press the firmware view key to check the version of the current firmware
- press the exit button to exit this function.

In this chapter, we will learn how to use the detection function for different types of devices.

# Connection Detection

## 1 Applicable Robotic Arms

- myCobot 280 M5
- myCobot 320 M5
- myPalletizer 260 M5
- mechArm 270 M5

## 2 Steps to Operate the Arms

**Step 1:** Burn the latest version of **atomMain** for **Atom**.

**Step 2:** Burn the **minirobot** for **M5Stack-basic**, and press the **Information**.

**Step 3:** Press **A** to start connection detection.

`atom: ok` means that Atom is connected normally.

`servo x: ok` means that six motors are connected normally.

> **Notice:** Press **B** for the version information.

**Step 4:** Press **C** to exit this function.